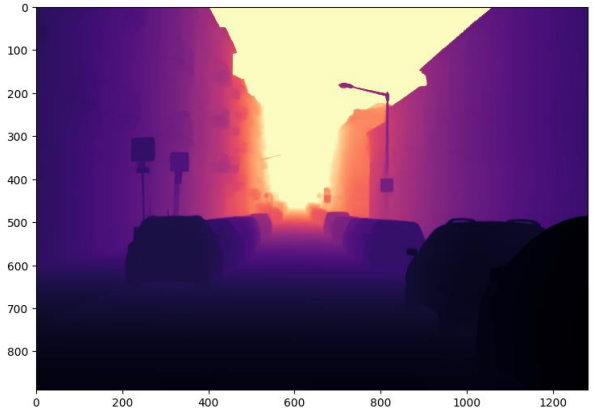
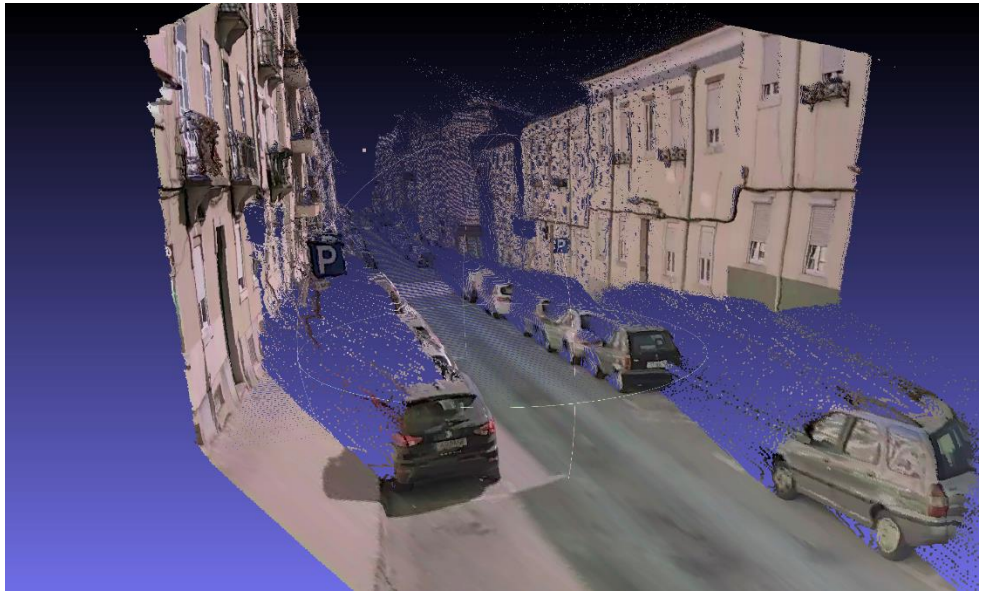
First Lab work (for next week)

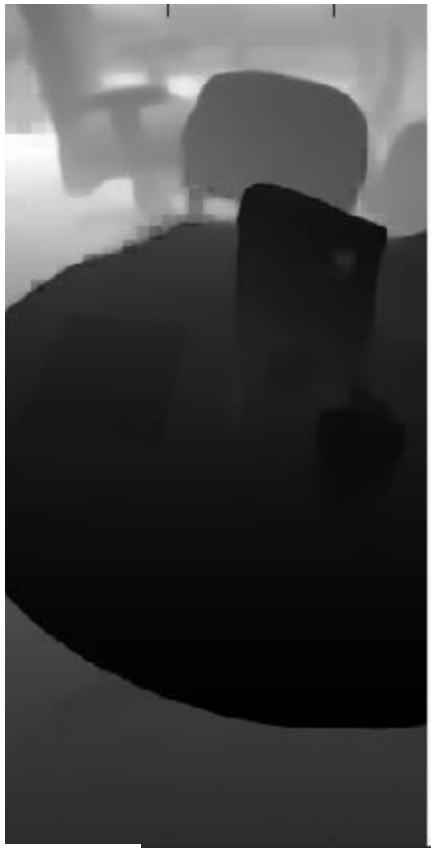
Meet the city from a car





Data Available Soon

Meet my office from my phone



struct with fields:

```
          rgb: [512×256×3 single]
        depth: [512×256 single]
         conf: [512×256 single]
focal_lenght: 415.4270
```

Download from GDrive

The Goal is:

From the depth image compute a 3D point cloud.
The depth is registered to the B&W image so you can not color the point cloud

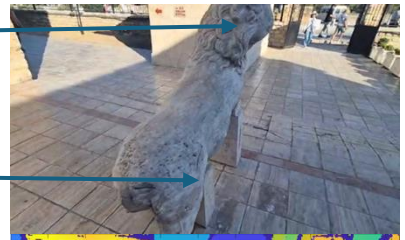
From matches between the B&W and the COLOR images (in a different position) find the color of all visible 3D points.

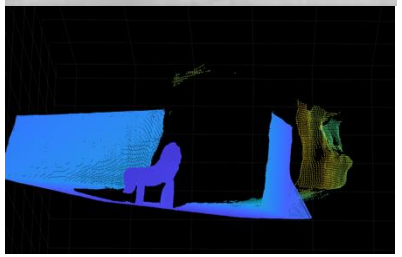
In the process compute the Camera Matrix of both images and the relative pose between the two images (cameras)

Matrix+camera+lse+derivative..
homogeneous or linear ???
I thought CV was…somethingelse

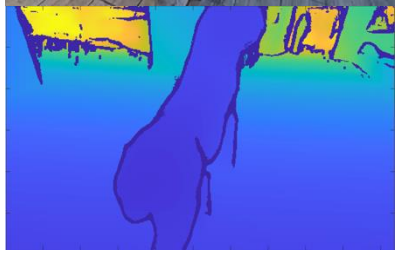
Except that … you have to choose depending on the dataset

Matches or maybe not





3D point cloud…
or not



Depth

Depth

K or maybe not

K or maybe not

Goal reshaped

Compute the K, R and T of images (no need to repeat similar cases)

Colored 3D point cloud of B&W images

- You may need to find the matches (click manually)