

# Research Log - Week 00

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July 28, 2016

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March 30, 2016	Established research log after 3 hours of learning new $\text{\LaTeX}$
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April 2, 2016	Added some additional comments to the <b>Process</b>
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April 3, 2016	<p>Have been reading [Shum2007] [1].</p> <p><b>Question for Kamangar:</b> regarding [Shum2007] [1] about difference between:</p> <ul style="list-style-type: none"><li>• <b>Camera Plane</b> : Coordinates <math>u, v</math></li><li>• <b>Focal Plane</b> : Coordinates <math>s, t</math></li></ul>
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April 11, 2016	<p>Reviewing blog articles located at:</p> <ul style="list-style-type: none"><li>• <a href="https://erget.wordpress.com/2014/02/01/calibrating-a-stereo-camera-with-opencv/">https://erget.wordpress.com/2014/02/01/calibrating-a-stereo-camera-with-opencv/</a></li><li>• <a href="https://erget.wordpress.com/2014/02/28/calibrating-a-stereo-pair-with-python/">https://erget.wordpress.com/2014/02/28/calibrating-a-stereo-pair-with-python/</a></li><li>• <a href="https://erget.wordpress.com/2014/03/13/building-an-interactive-gui-with-opencv/">https://erget.wordpress.com/2014/03/13/building-an-interactive-gui-with-opencv/</a></li><li>• <a href="https://erget.wordpress.com/2014/04/27/producing-3d-point-clouds-with-a-stereo-camera-in-opencv/">https://erget.wordpress.com/2014/04/27/producing-3d-point-clouds-with-a-stereo-camera-in-opencv/</a></li></ul> <p>for process to get webcam up and running. Previous issues related to fine-tuning <i>block matching</i> parameters. Need to review sources at list at bottom of <a href="http://docs.opencv.org/2.4/modules/calib3d/doc/camera_calibration_and_3d_reconstruction.html">http://docs.opencv.org/2.4/modules/calib3d/doc/camera_calibration_and_3d_reconstruction.html</a> to understand.</p>
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April 19, 2016	<p>Made adjustments to python for image acquisition scripts (from blogs mentioned on April 11, 2016.)</p> <p><b>NOTE:</b> Consider creating rig with glue to keep stereo camera placement / direction constant.</p>
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April 19, 2016	<p><b>UPDATE:</b> Error with <code>calibrate_cameras</code> python code causing linux machine to crash. If can't be resolved switch over to MacBook.</p> <p><b>NOTE:</b> Package should be setup by calling <code>\$ python setup.py install</code>.</p>
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April 19, 2016	<p><b>UPDATE:</b> Crash due to recursive shell call and was fixed. OpenCV not detecting all chessboard corners. Will try a new board.</p>
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April 20, 2016	<p>Did small amount of work on <b>Change of Reference</b> section in the paper. Added a section to the intro containing a map of commonly used symbols and notation.</p>
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April 29, 2016      Read following sections of [Chen1993] [2]:

- Abstract
- Introduction
- Visibility Morphing

**SUMMARY:** Explicit Geometry is ignored (i.e. surface mesh and 3d-points). Geometry is kept in 2-d. Whereas Image Morphing interpolates between *pixel intensity values in fixed locations* the method in this article interpolates between *pixel locations with (relatively) fixed intensity values*. **Question:** Sections read mention that pixel positions are stored in 3d (3-tuple) data structure. I'm not sure I understand this correctly, since

1. This would effectively make this structure a point cloud (but no mention of it in the paper).
2. There is no mention of special "depth-based" hardware or cameras (Far as I know this is supposed to be a regular image).

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April 30, 2016      Checked understanding of *epipolar constraint* through reading of [Hartley2004] [3] and its derivation of

$$\begin{aligned} \mathbf{x}'^T \cdot \mathbf{E} \cdot \mathbf{x} &= \mathbf{x}'^T \cdot [\mathbf{t}]_{\times} \cdot \mathbf{R} \cdot \mathbf{x} \\ &= \mathbf{x}'^T \cdot \mathbf{l} \end{aligned}$$

and creation of MatLab code verifying this.

I may have been mistaken about relation of **Fundamental Matrix** and **Essential Matrix**.

My current understanding is the *Fundamental Matrix* describes point/epipolar line correspondance for images under **scale invariant** conditions (i.e. point correspondance and Fundamental matrix does not change when one image (or both images) are scaled (uniformly or omni-directionally).

*Essential Matrix* describes point/epipolar line correspondance for images under **normalized** conditions (i.e. unit-length is set equal to focal-length, and projection center is set at (0,0,1).

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May 2, 2016      Additional wording to Stereo-vision section. I am unsure of best order to present ideas related to *multi-view* geometry.

## References

- [1] Sing Bing Kang Heung-Yeung Shum, Shing-Chow Chan. *Image Based Rendering*. Springer Publishing, 1 edition, 2007. Available online at: <http://link.springer.com/content/pdf/10.1007%2F978-0-387-32668-9.pdf> Pages cited are **Book Page Numbers**. Formula for **PDF Page Number** is (**PDF Page Number** = **Book Page Number** + 17).
- [2] Shenchang Eric Chen and Lance Williams. View interpolation for image synthesis. In *Proceedings of the 20th Annual Conference on Computer Graphics and Interactive Techniques*, SIGGRAPH '93, pages 279–288, New York, NY, USA, 1993. ACM.
- [3] R. I. Hartley and A. Zisserman. *Multiple View Geometry in Computer Vision*. Cambridge University Press, ISBN: 0521540518, second edition, 2004.