

To Flatten image, vertically Stack each channel

$$\begin{bmatrix} h_k \\ s_k \\ v_k \end{bmatrix} \quad \text{for each image } k \text{ in } I$$

- (4) For each ~~image~~ image k in I , ~~calculate~~ transpose the image, calculate mean of each column and subtract from original i.e. calculate deviation score

Let μ_m be the mean of the m th column

$$\begin{bmatrix} I_0 \\ I_1 \\ \vdots \\ I_{599} \end{bmatrix} - [\mu_0 \mu_1 \dots \mu_{599}] = a$$

$$\begin{bmatrix} I_0^T \\ I_1^T \\ I_2^T \\ I_3^T \\ \vdots \\ I_{599}^T \end{bmatrix} - [\mu_0 \mu_1 \dots \mu_{599}] = a$$

~~Let resulting score be a~~

Set resulting score to a

⑤ Calculate $A^T \cdot A$ and divide result by 216000

Result is a 657×657 ~~image~~ matrix

⑥ Compute Eigen values and Eigen vectors
of Covariance matrix

Let A be the covariance matrix

v = eigenvector

λ = eigenvalue

$$A v = \lambda v$$

$$A v = \lambda I_{657} v$$

$$|A - \lambda I_{657}| = 0$$

$$\text{This leads to } C_0 \lambda^{657} + C_1 \lambda^{656} + \dots + C_{656} \lambda + C_{657} = 0$$

where C_i is a constant i range from 0 to 657

This leads to 657 possible values for λ

Substitute each individual value back

to $A v = \lambda v$ and solve for v

- ① Order Eigen vectors based on numeric value of corresponding eigen values

Resulting $[V_0, V_1, V_2, \dots, V_{656}]$ where λ_0 and V_0 are the corresponding eigenvalues and eigenvector for the 0^{th} largest eigenvalue

Such that $\lambda_0 \geq \lambda_1 \geq \lambda_2 \geq \dots \geq \lambda_{656}$

- ② keep the first 6 eigen vectors and ~~get~~ get rid of rest

$$FM = [V_0, V_1, \dots, V_5] \quad \text{Size} = 657 \times 6$$

= Feature Vector

- ③ Recast original along PCA

~~New Matrix~~ $FM^T \cdot I$ size = 6×216000

- ④ Recover Original Image and stack vertically

$$\begin{bmatrix} I_1 \\ I_2 \\ \vdots \\ I_{599} \end{bmatrix} \quad \text{where } I_k \text{ where } k \text{ is the } k^{th} \text{ image in the recovered dataset}$$

394200
657x600

(11) Upload LIDAR Values

~~Let k_i be the~~ Let D_i be the i th distance in the LIDAR dataset

$$D = [D_0, D_1, \dots, D_{359}]$$

(12) ~~Let~~ Generate 1000 equidistant values between 0 and 360