Master in
Computer Vision
Barcelona

Module: 3D Vision
Project: 3D recovery of urban scenes
Session 2

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Session 2

Goal: compute the homography that relates to images

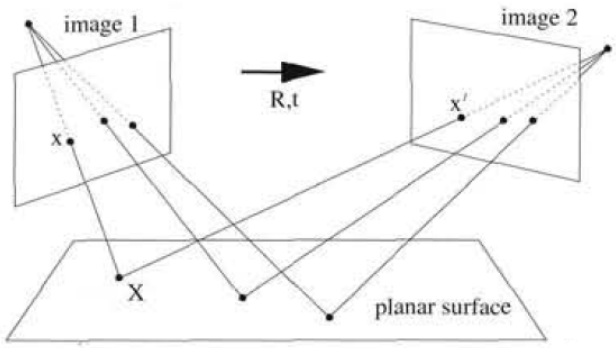
Algorithms:

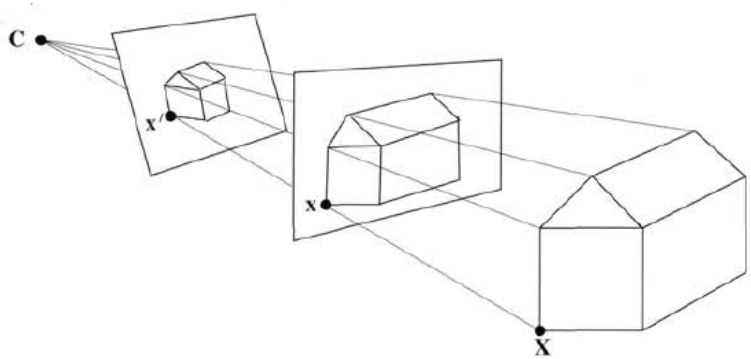
- Robust normalized DLT algorithm (algebraic method).
- Gold-Standard algorithm (geometric method).
- Camera calibration using a planar pattern.

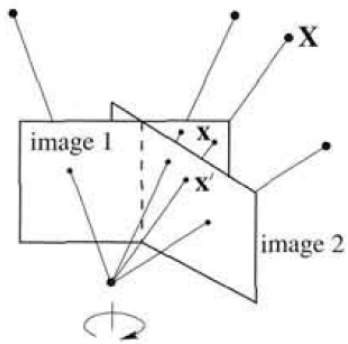
Applications:

- Image mosaics (panoramas).
- Augmented reality.
- Logo insertion in an image.

Homographies



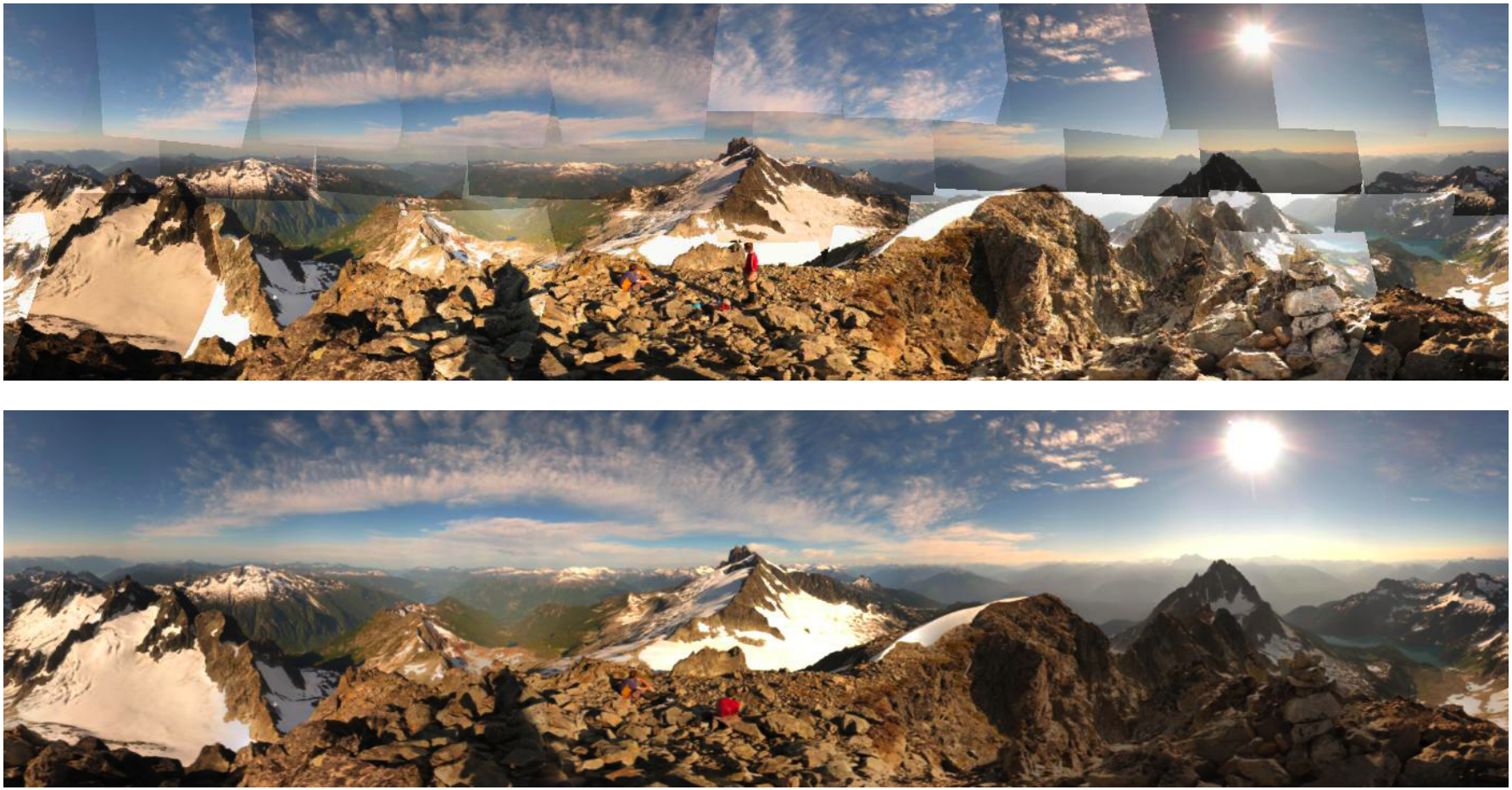




A homography relates two images:

- of the same plane in the 3D scene;
- taken with a camera rotating about its centre;
- taken with the same static camera varying its focal length;
- the whole scene is far away from the camera.

Image mosaics



Geometric algorithm: It minimizes the reprojection error

$$\min_{\hat{H},\hat{x}_i,\hat{x}'_i} \sum_i d([x_i],[\hat{x}_i])^2 + d([x'_i],[\hat{x}'_i])^2 \text{ s. t. } \hat{x}'_i = \hat{H}\hat{x}_i \forall i$$

where different matchings $x_i \longleftrightarrow x'_i$ are the data, [.] is the projectionn operator to Euclidean coordinates.

The above problem simplifies to the non-constrained minimization problem:

$$\min_{\hat{H},\hat{x}_i} \sum_i d([x_i],[\hat{x}_i])^2 + d([x'_i],[\hat{H}\hat{x}_i])^2$$

Session 2

Mandatory tasks:

- Function that estimates the homography with the normalized DLT algorithm given $n \geq 4$ image correspondences.
- Complete the RANSAC function and the lab2.m file.
- Compute an image mosaic with four different sets of data; compare and comment the results (why it works or it does not work in the different cases).
- Estimation of the homogaphy with the Gold-Standard algorithm.

Optional tasks:

- Complete the code on camera calibration using a planar pattern and answer (in the report) two questions raised in the file lab2.m.
- Change the virtual object (cube) by another simple geometric 3D object (e.g. pyramid).
- Add a logo to an image (flat surface).

Session 2

Language: MATLAB

Provided functions: lab2.m, apply_H_v2.m, euclid.m, optical_center.m, plot_camera, ransac_homography_adaptive_loop.m, vgg_gui_H.m, vgg_scatter_plot.m, view_direction.m, sift functions.
lab2.m is the guided file with the different steps of the lab session.

To Do:

- Complete the code in lab2.m as indicated in the same file
- Complete the code in ransac_homography_adaptive_loop.m as indicated
- Write the function homography2d.m
- (Write the function gs_errfunction.m)
- (Complete the code on camera calibration)
- (Add a logo to an image using the DLT algorithm)

Evaluation

To deliver **before 9am of the day before** the next lab session:

- **Code deliverable:**
  - READY TO BE LAUNCHED on the provided images
- **Short document (10 pages):**
  - Results
  - Problems and comments
  - Conclusions

Evaluation

Grading:

- Report(including answers to questions): **2.5 points**
- DLT function: **2.5 points**
- RANSAC: **1.5 points**
- 4 mosaics: **1 point**
- Gold-Standard algorithm: **2.5 points**
- Optional calibration: **+ 2 points**
- Optional change virtual object: **+ 0.2 points**
- Optional add logo to an image: **+ 0.6 points**