

Computer Vision

Lecture 8 – Shape-from-X

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Robotics, Computer Vision, Deep Learning, Machine Learning, System Software



Agenda

8.1 Shape-from-Shading

8.2 Photometric Stereo

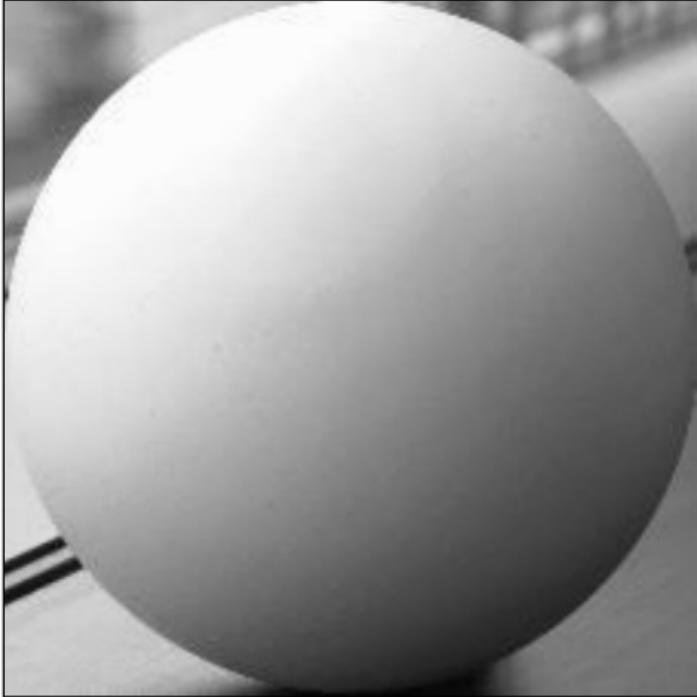
8.3 Shape-from-X

8.4 Volumetric Fusion

8.1

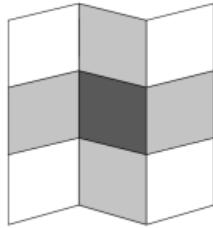
Shape-from-Shading

Can we recover shape from shading?

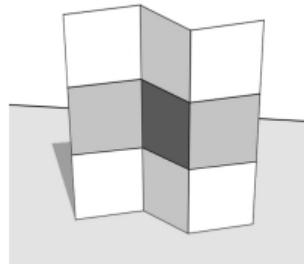


- What is the relation between **intensity** and **shape**? Can we recover shape?

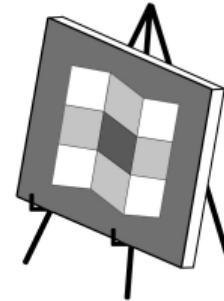
Adelson and Pentland's Workshop Metaphor



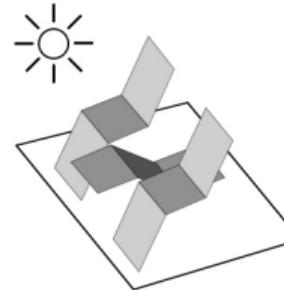
(a) an image



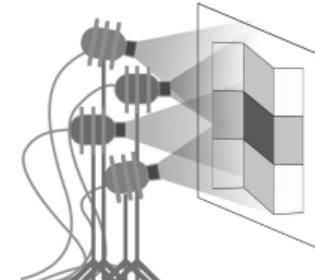
(b) a likely explanation



(c) painter's explanation



(d) sculptor's explanation

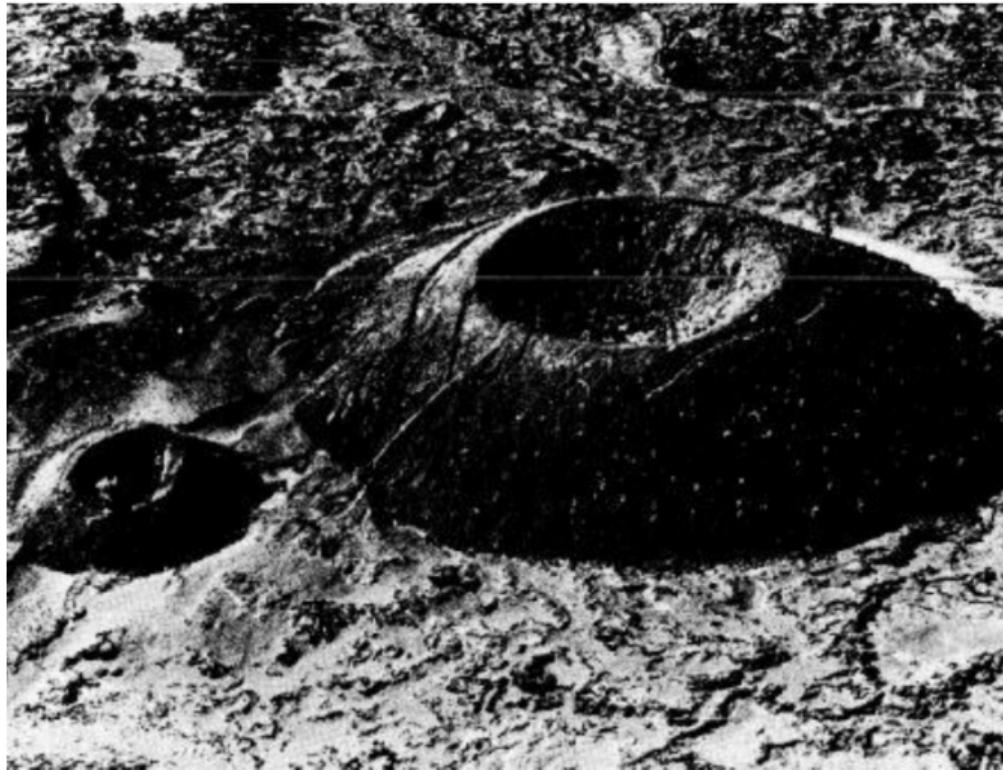


(e) gaffer's explanation

Can we recover **3D from a single image?**

- ▶ Inverting the graphics problem is very challenging
- ▶ The space of shapes, paint, and light that exactly reproduce an image is vast
- ▶ The image in (a) very likely corresponds to (b), but it could be a painting (c), sculpture (d), or an arrangement of lights (e)
- ▶ We are looking for a **simple explanation** and must use **prior knowledge**

Human Perception



Human Perception



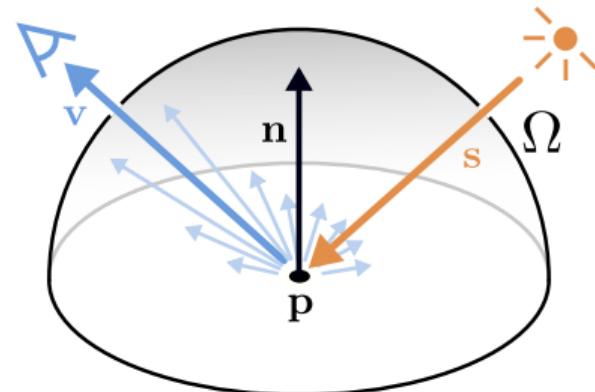
Recap: Rendering Equation

Rendering Equation

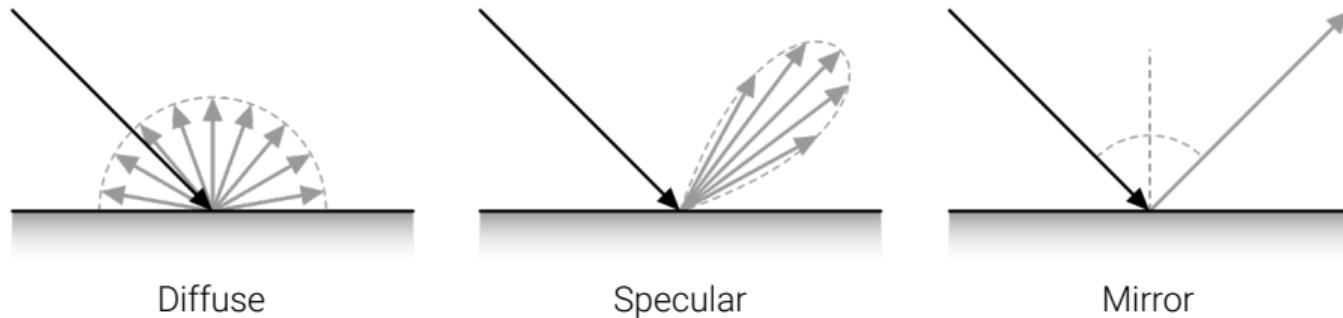
Let $\mathbf{p} \in \mathbb{R}^3$ denote a 3D surface point, $\mathbf{v} \in \mathbb{R}^3$ the viewing direction and $\mathbf{s} \in \mathbb{R}^3$ the incoming light direction. The **rendering equation** describes how much of the light L_{in} with wavelength λ arriving at \mathbf{p} is reflected into the viewing direction \mathbf{v} :

$$L_{\text{out}}(\mathbf{p}, \mathbf{v}, \lambda) = L_{\text{emit}}(\mathbf{p}, \mathbf{v}, \lambda) + \int_{\Omega} \text{BRDF}(\mathbf{p}, \mathbf{s}, \mathbf{v}, \lambda) \cdot L_{\text{in}}(\mathbf{p}, \mathbf{s}, \lambda) \cdot (-\mathbf{n}^\top \mathbf{s}) d\mathbf{s}$$

- ▶ Ω is the unit hemisphere at normal \mathbf{n}
- ▶ The bidirectional reflectance distribution function $\text{BRDF}(\mathbf{p}, \mathbf{s}, \mathbf{v}, \lambda)$ defines how light is reflected at an opaque surface.
- ▶ $L_{\text{emit}} > 0$ only for light emitting surfaces

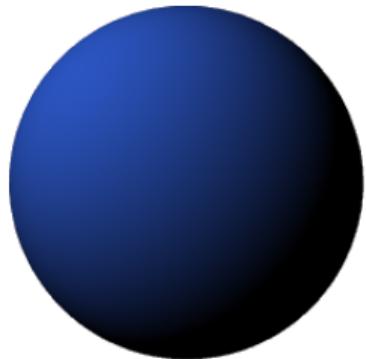


Diffuse and Specular Reflection

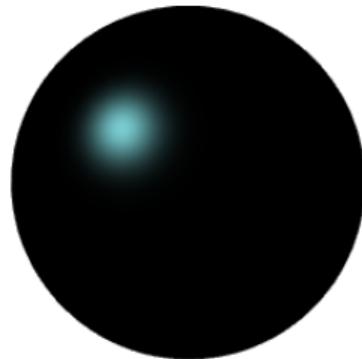


- ▶ Typical BRDFs have a **diffuse** and a **specular** component
- ▶ The diffuse (=constant) component scatters light uniformly in all directions
- ▶ This leads to shading, i.e., smooth variation of intensity wrt. surface normal
- ▶ The specular component depends strongly on the outgoing light direction

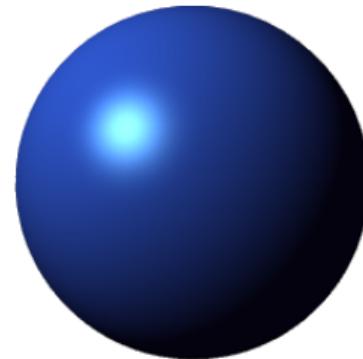
Diffuse and Specular Reflection



Diffuse



Specular



Combined

- ▶ Typical BRDFs have a **diffuse** and a **specular** component
- ▶ The diffuse (=constant) component scatters light uniformly in all directions
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- ▶ The specular component depends strongly on the outgoing light direction

Diffuse and Specular Reflection



Clay Pot



Cloud Gate (Kapoor, 2006)

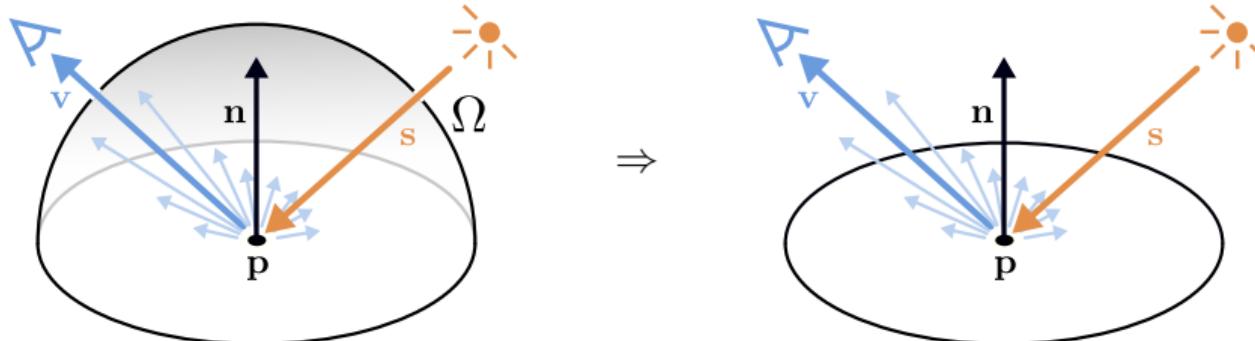
Simplifying the Rendering Equation

Dropping the dependency on λ and \mathbf{p} for notational simplicity, and considering a **single point light source** located in direction \mathbf{s} , the rendering equation

$$L_{\text{out}}(\mathbf{p}, \mathbf{v}, \lambda) = L_{\text{emit}}(\mathbf{p}, \mathbf{v}, \lambda) + \int_{\Omega} \text{BRDF}(\mathbf{p}, \mathbf{s}, \mathbf{v}, \lambda) \cdot L_{\text{in}}(\mathbf{p}, \mathbf{s}, \lambda) \cdot (-\mathbf{n}^T \mathbf{s}) d\mathbf{s}$$

simplifies as follows:

$$L_{\text{out}}(\mathbf{v}) = \text{BRDF}(\mathbf{s}, \mathbf{v}) \cdot L_{\text{in}} \cdot (-\mathbf{n}^T \mathbf{s})$$



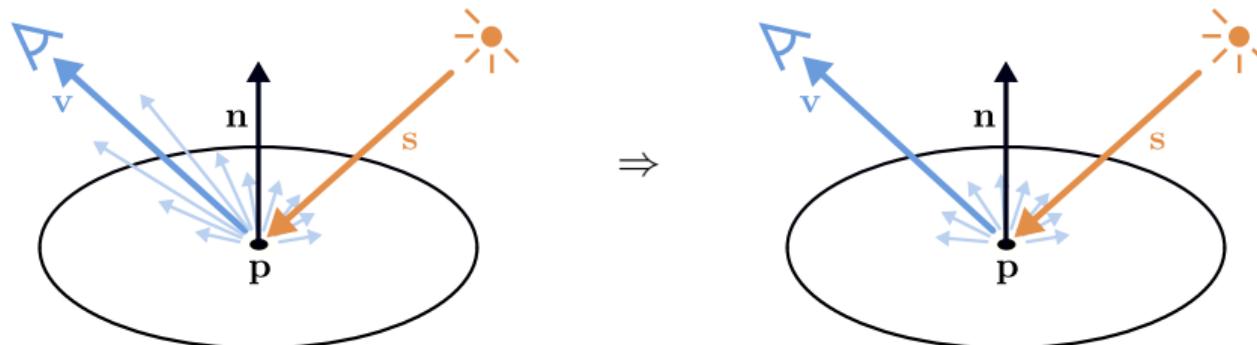
Simplifying the Rendering Equation

Assuming a purely **diffuse material** with albedo (=diffuse reflectance) $\text{BRDF}(\mathbf{s}, \mathbf{v}) = \rho$

$$L_{\text{out}}(\mathbf{v}) = \text{BRDF}(\mathbf{s}, \mathbf{v}) \cdot L_{\text{in}} \cdot (-\mathbf{n}^T \mathbf{s})$$

further simplifies to the following equation (L_{out} becomes independent of \mathbf{v}):

$$L_{\text{out}} = \rho \cdot L_{\text{in}} \cdot (-\mathbf{n}^T \mathbf{s})$$



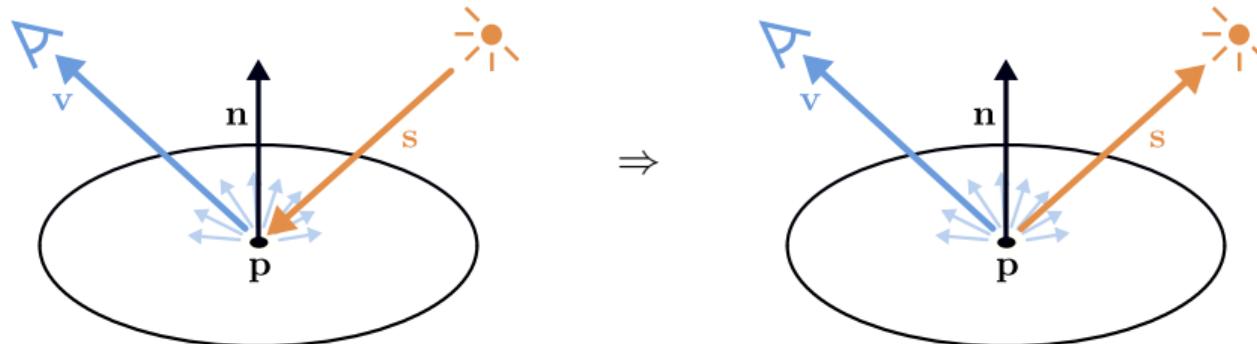
Simplifying the Rendering Equation

For simplicity, we further eliminate the **minus sign** in

$$L_{\text{out}} = \rho \cdot L_{\text{in}} \cdot (-\mathbf{n}^T \mathbf{s})$$

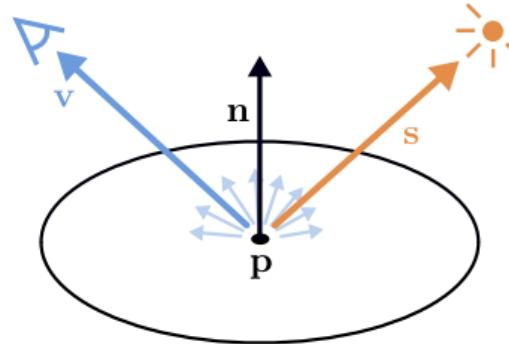
by reversing the orientation (definition) of the light ray \mathbf{s} and obtain:

$$L_{\text{out}} = \rho \cdot L_{\text{in}} \cdot \mathbf{n}^T \mathbf{s}$$



Simplifying the Rendering Equation

$$L_{\text{out}} = \rho \cdot L_{\text{in}} \cdot \mathbf{n}^\top \mathbf{s} = R(\mathbf{n})$$



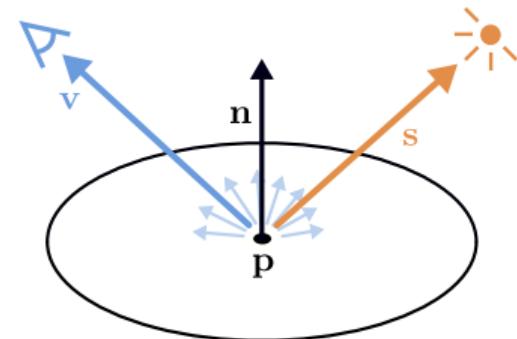
- ▶ For a fixed material and light source, the reflected light L_{out} is a function of \mathbf{n}
- ▶ This function $R(\mathbf{n})$ is called **reflectance map** (we will see examples)
- ▶ If we would know \mathbf{n} at each surface point, we can integrate the geometry
- ▶ Can we determine \mathbf{n} from the observation L_{out} for every pixel in an image?
- ▶ This problem is called **Shape-from-Shading** (Berthold Horn, 1970)

Shape-from-Shading

Shape-from-Shading (SfS)

Shape-from-Shading makes the following assumptions:

- ▶ **Diffuse material with spatially constant albedo ρ**
 - ▶ Reduces number of material parameters to 1
- ▶ **Known point light source at infinity**
 - ▶ Keeps light direction s constant across all pixels
 - ▶ Makes s independent of geometry/depth
- ▶ **Known camera at infinity (orthography)**
 - ▶ Keeps view direction v constant across all pixels
 - ▶ Makes v independent of geometry/depth



Gradient Space Representation

How should we **parameterize** the normal \mathbf{n} ?

- ▶ While $\mathbf{n} \in \mathbb{R}^3$, it has only 2 degrees of freedom
- ▶ Parameterize \mathbf{n} by **neg. gradients of depth map**:

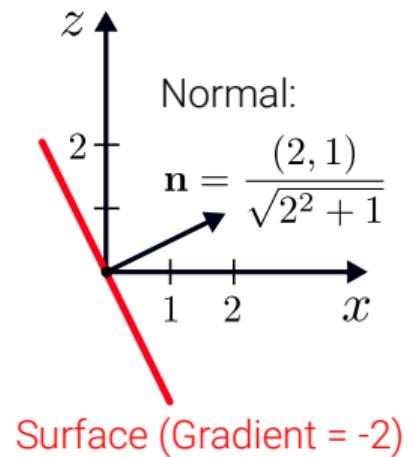
$$(p, q) = \left(-\frac{\partial z}{\partial x}, -\frac{\partial z}{\partial y} \right)$$

- ▶ The surface normal \mathbf{n} at pixel (x, y) is given by:

$$\mathbf{n} = \frac{(p, q, 1)^\top}{\sqrt{p^2 + q^2 + 1}}$$

- ▶ Assuming $\rho \cdot L_{in} = 1$, the **reflectance** becomes:

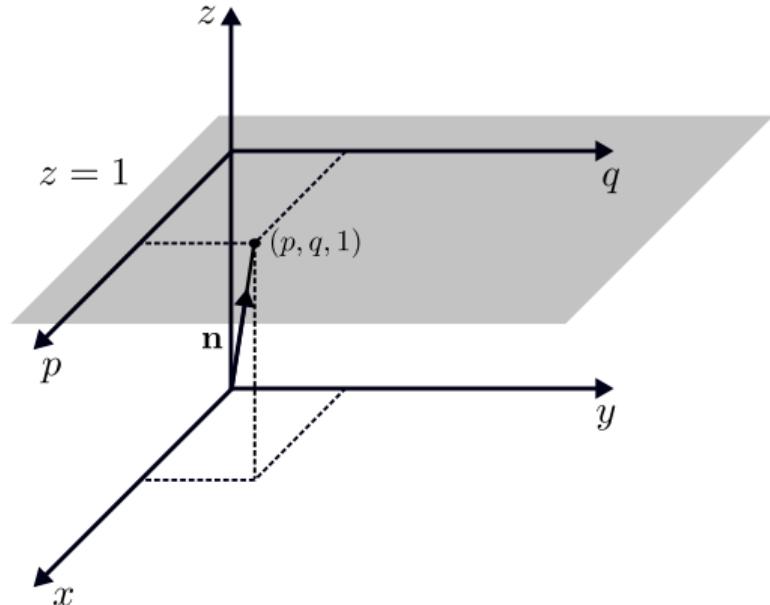
$$R(\mathbf{n}) = \mathbf{n}^\top \mathbf{s} = \frac{ps_x + qs_y + s_z}{\sqrt{p^2 + q^2 + 1}} = R(p, q)$$



Gradient Space Representation

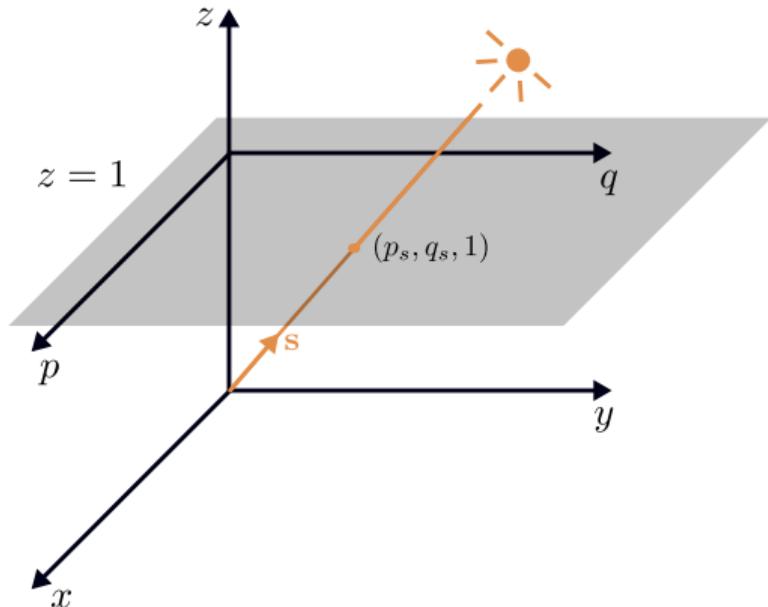
- ▶ Visualization of the **gradient space** (gray)
- ▶ Normal \mathbf{n} intersects $z = 1$ plane at $(p, q, 1)^\top$
- ▶ Unit normal given by:

$$\mathbf{n} = \frac{(p, q, 1)^\top}{\sqrt{p^2 + q^2 + 1}}$$



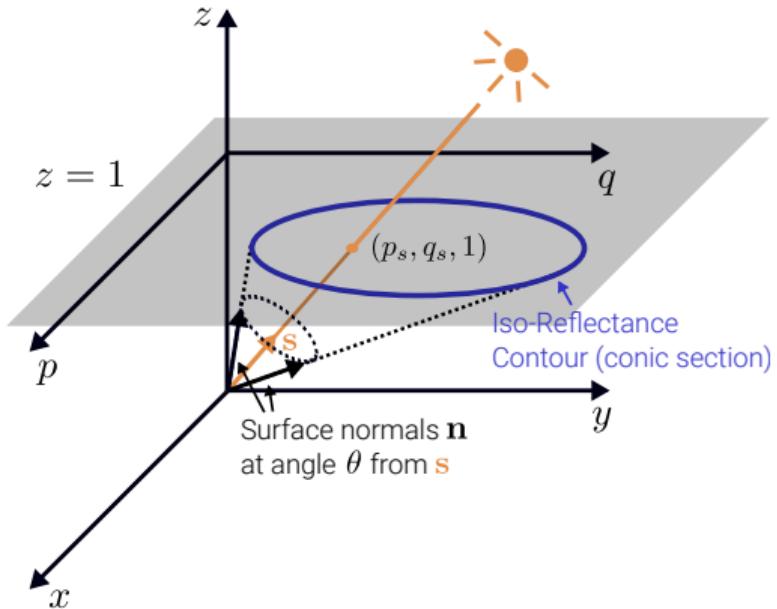
Gradient Space Representation

- ▶ The **gradient space** can also be used to represent the **light direction s**
- ▶ Light ray s intersects $z = 1$ plane at $(p_s, q_s, 1)^\top$
- ▶ For a given light ray s and observed reflectance R what is the normal \mathbf{n} ?

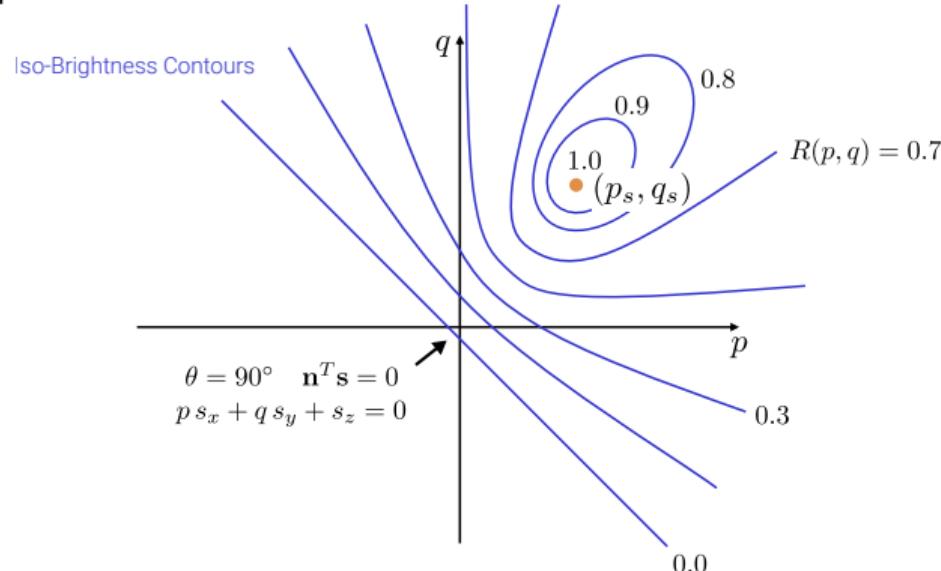


Gradient Space Representation

- ▶ For a given light ray \mathbf{s} and observed reflectance R what is the normal \mathbf{n} ?
- ▶ We have $R = \mathbf{n}^\top \mathbf{s} = \cos(\theta)$ with angle θ between \mathbf{n} and \mathbf{s}
- ▶ The set of solutions $\{\mathbf{n}\}$ is located on a **circle** around \mathbf{s}
- ▶ Projecting this set to the $z = 1$ plane yields a **conic section**



Reflectance Map



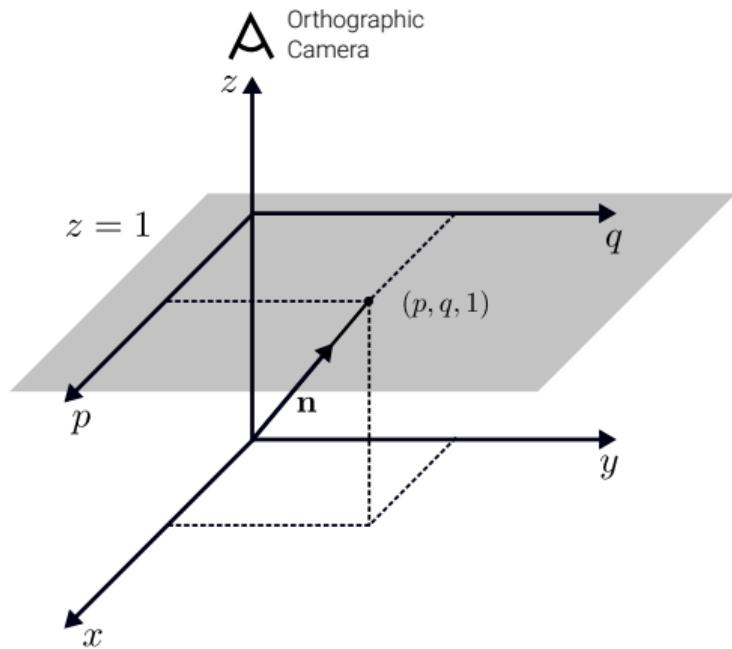
- ▶ Except for $R(p, q) = 1.0$, the normals consistent with R are **not unique**
- ▶ Inferring unique normals from a single image thus requires **further constraints**
- ▶ **Solutions:** Regularization (SfS), more observations (photometric stereo)

Reflectance Map

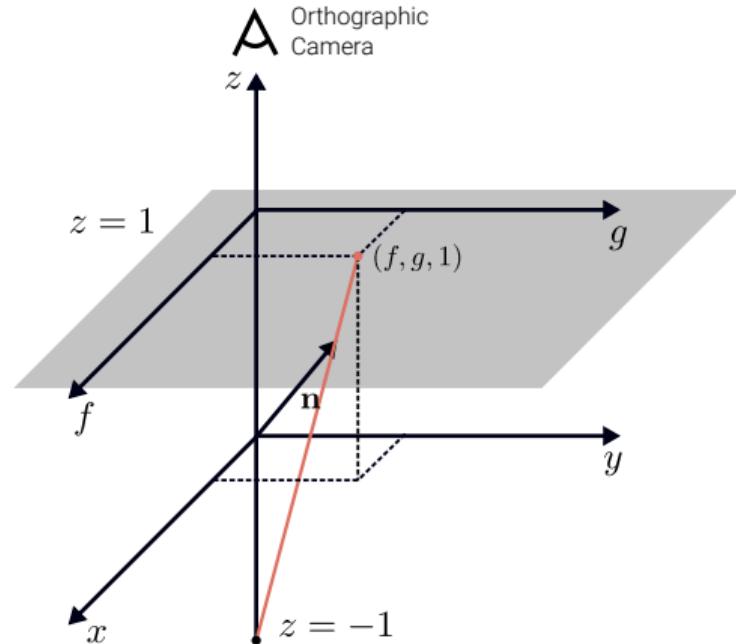
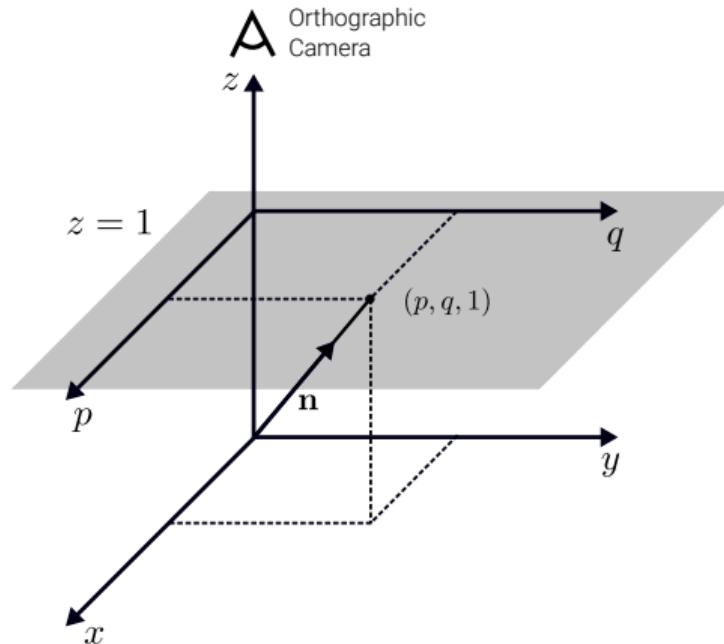
Under the assumptions of a known distant point light and observer, the variation in reflectance is a function of the local surface orientation:

$$R(\mathbf{n}) = \mathbf{n}^\top \mathbf{s} = \frac{p s_x + q s_y + s_z}{\sqrt{p^2 + q^2 + 1}} = R(p, q)$$

- ▶ $(p, q) = \left(-\frac{\partial z}{\partial x}, -\frac{\partial z}{\partial y} \right)$ are the negative **gradients** of the depth map
- ▶ $R(p, q)$ is called **reflectance map**
- ▶ What happens when \mathbf{n} becomes orthogonal to the viewing direction?



Stereographic Mapping



- Solution: **Change of representation** that bounds surface gradients ($\text{norm} < 2$)

Stereographic Mapping

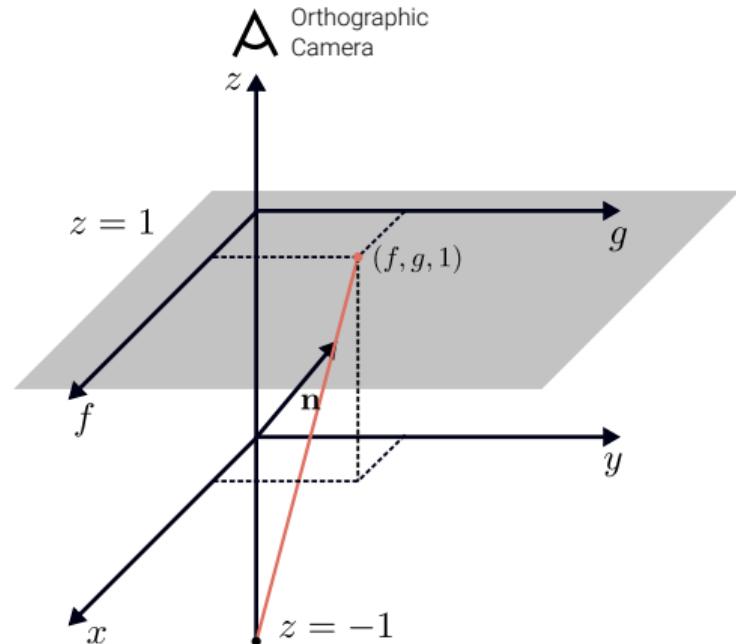
The following relationship holds:

$$f = \frac{2p}{1 + \sqrt{p^2 + q^2 + 1}}$$

$$g = \frac{2q}{1 + \sqrt{p^2 + q^2 + 1}}$$

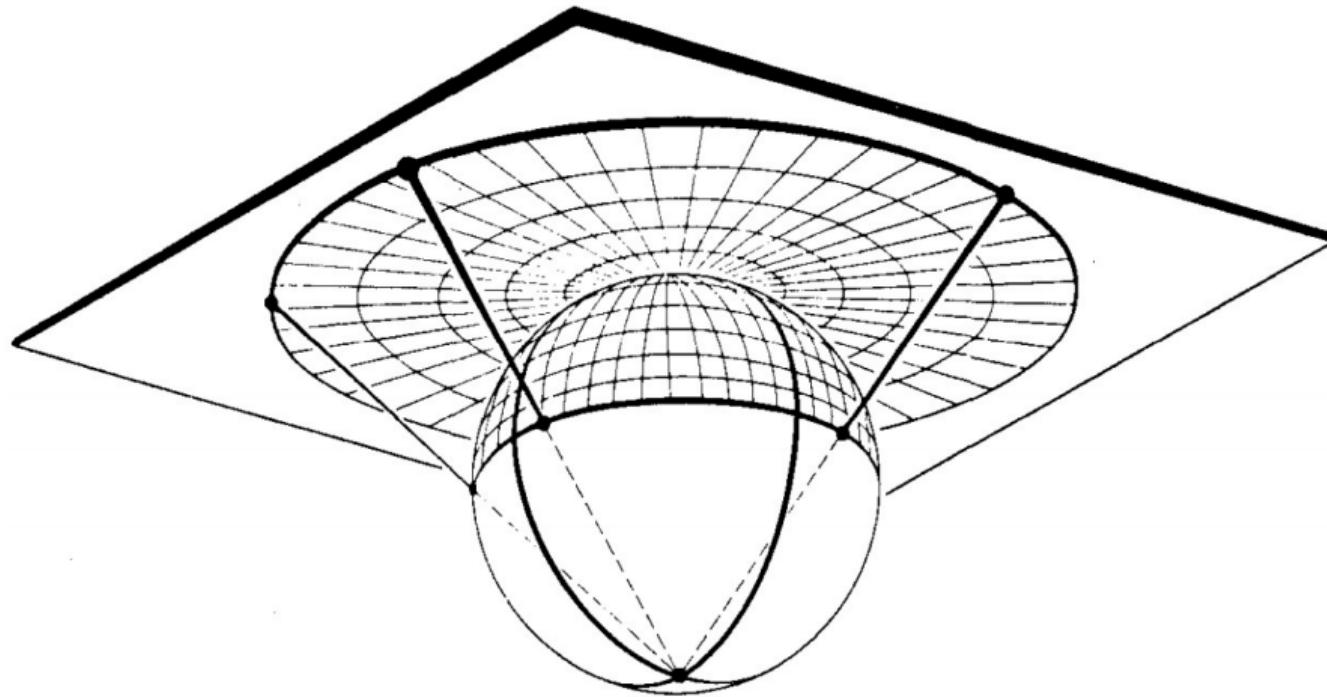
Now R depends on f and g :

$$R(f(x, y), g(x, y))$$



- Solution: **Change of representation** that bounds surface gradients (norm < 2)

Stereographic Mapping



Shape-from-Shading Formulation

Assumption: image irradiance (=intensity) should equal the reflectance map:

$$I(x, y) = R(f(x, y), g(x, y))$$

SfS thus minimizes:

$$E_{image}(f, g) = \int \int (I(x, y) - R(f, g))^2 dx dy$$

Goal: Penalize errors between image irradiance and reflectance map

However, as we have seen, this problem is ill-posed (#unknowns > #observations)

Numerical Shape-from-Shading

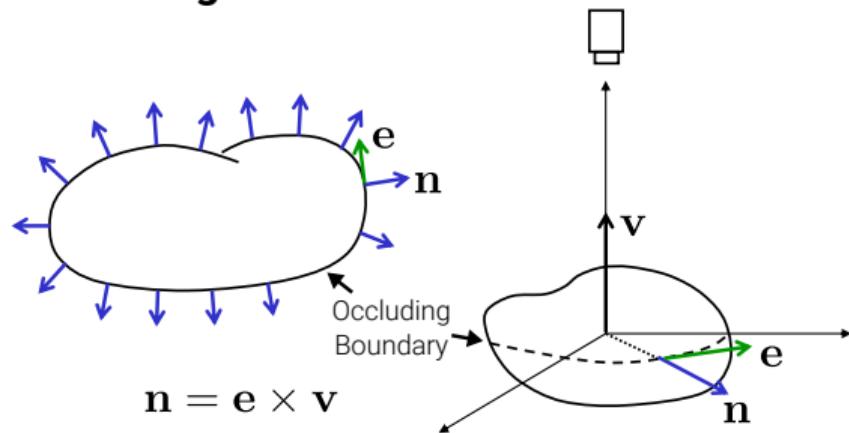
To constrain this ill-posed problem, SfS exploits two additional constraints:

Smoothness:

$$E_{smooth}(f, g) = \int \int f_x^2 + f_y^2 + g_x^2 + g_y^2 dx dy$$

with gradients $f_x = \frac{\partial f}{\partial x}$, $f_y = \frac{\partial f}{\partial y}$, ..

Occluding Boundaries:



- Goal: Penalize rapid changes in surface gradients f and g

- Goal: Constrain normals at occluding boundaries where they are known

Numerical Shape-from-Shading

In summary, we optimize the **variational energy**

$$E(f, g) = E_{image}(f, g) + \lambda E_{smooth}(f, g)$$

wrt. the gradient fields $f(x, y)$ and $g(x, y)$ subject to occluding boundary constraints.

Remarks:

- ▶ As images are spatially discrete, this problem is transferred to a spatially discrete problem similar to the Horn-Schunck optical flow algorithm discussed in lecture 6
- ▶ Iterative optimization required as R depends non-linearly on f and g
- ▶ We can use the known normals to fix f and g on the occluding boundary
- ▶ Initialize other variables to 0, see also: <https://fpcv.cs.columbia.edu/>

Surface Integration

Surface Integration

Given the **surface gradients**

$$(p, q) = \left(-\frac{\partial z}{\partial x}, -\frac{\partial z}{\partial y} \right)$$

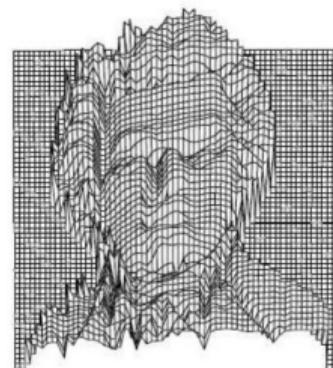
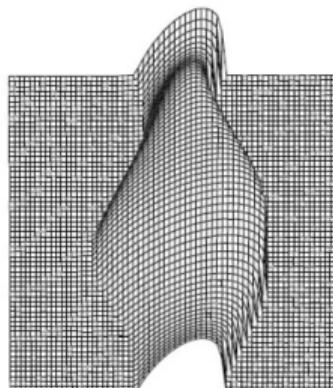
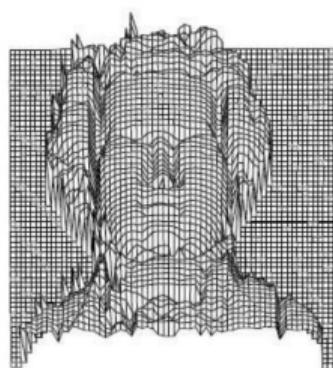
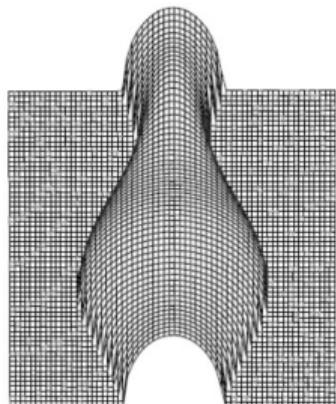
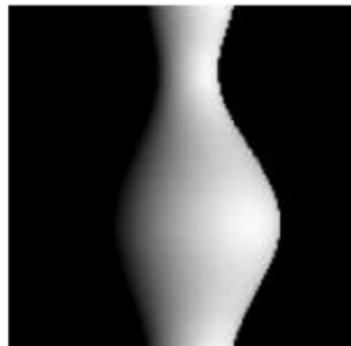
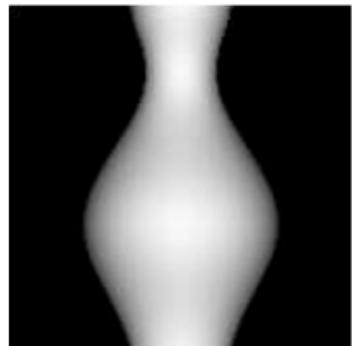
how can we **recover the 3D surface** / depth map?

Assuming a smooth surface, we can solve the following **variational problem**

$$E(z) = \int \int \left(\frac{\partial z}{\partial x} + p \right)^2 + \left(\frac{\partial z}{\partial y} + q \right)^2 dx dy$$

efficiently using the discrete **Fast Fourier Transform** (Frankot and Chellappa, 1988).

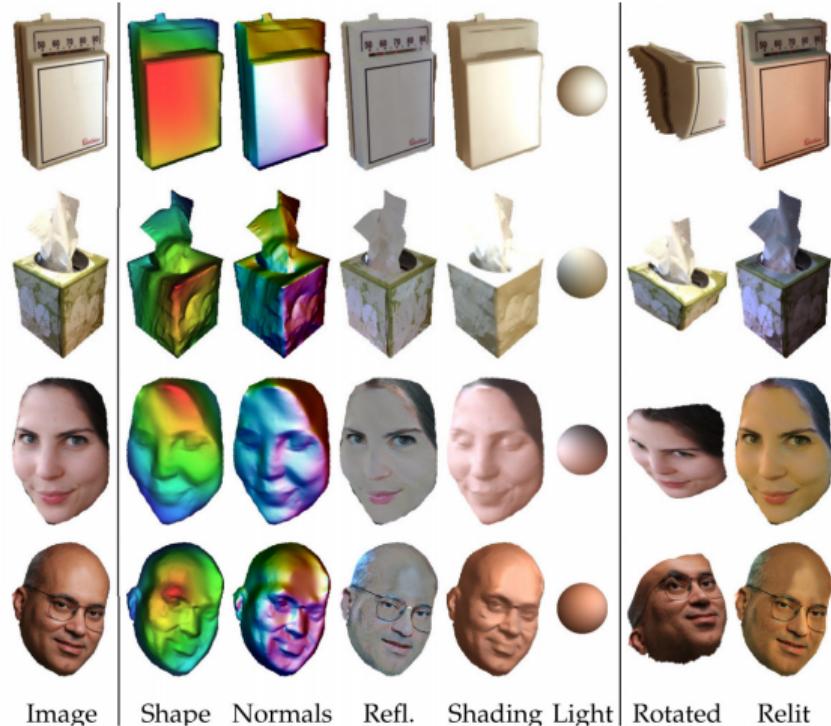
Results



SIRFS: Shape, Illumination, and Reflectance from Shading

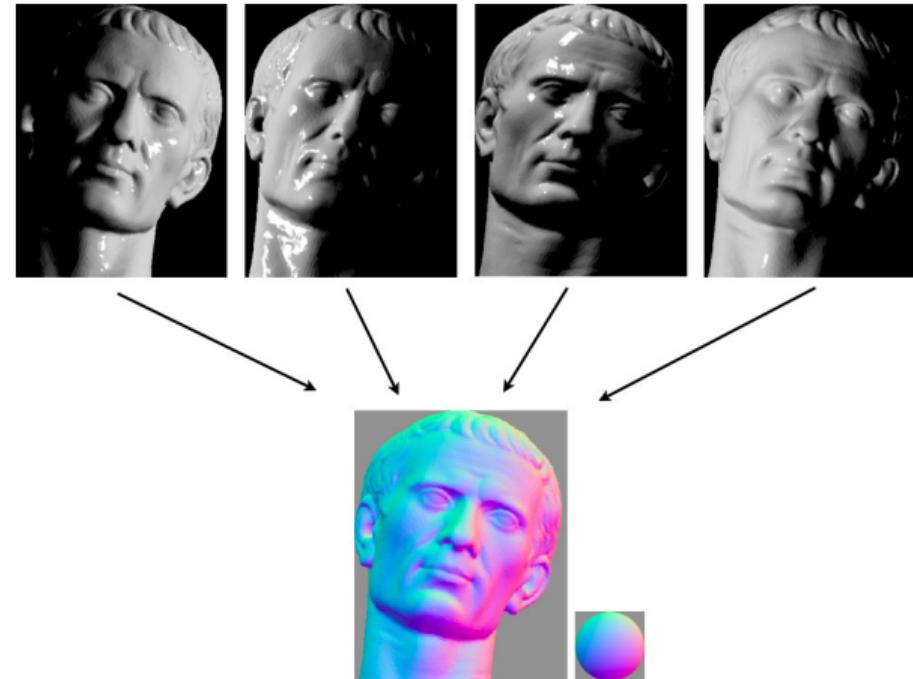
SIRFS:

- ▶ Modern version of SfS
- ▶ Input: Single masked RGB image
- ▶ Estimates depth, normals, reflectance, shading, lighting
- ▶ Doesn't assume known point light
- ▶ Doesn't assume constant color
- ▶ Much harder problem than SfS



Photometric Stereo

- ▶ Instead of smoothness constraints, add **more observations per pixel**
- ▶ Take **K images** of the object from **same viewpoint** (e.g., with a tripod) but with different (known) point light source each
- ▶ Per-pixel estimation of **normal** and **albedo** or **material**
- ▶ Also assumes far camera/light

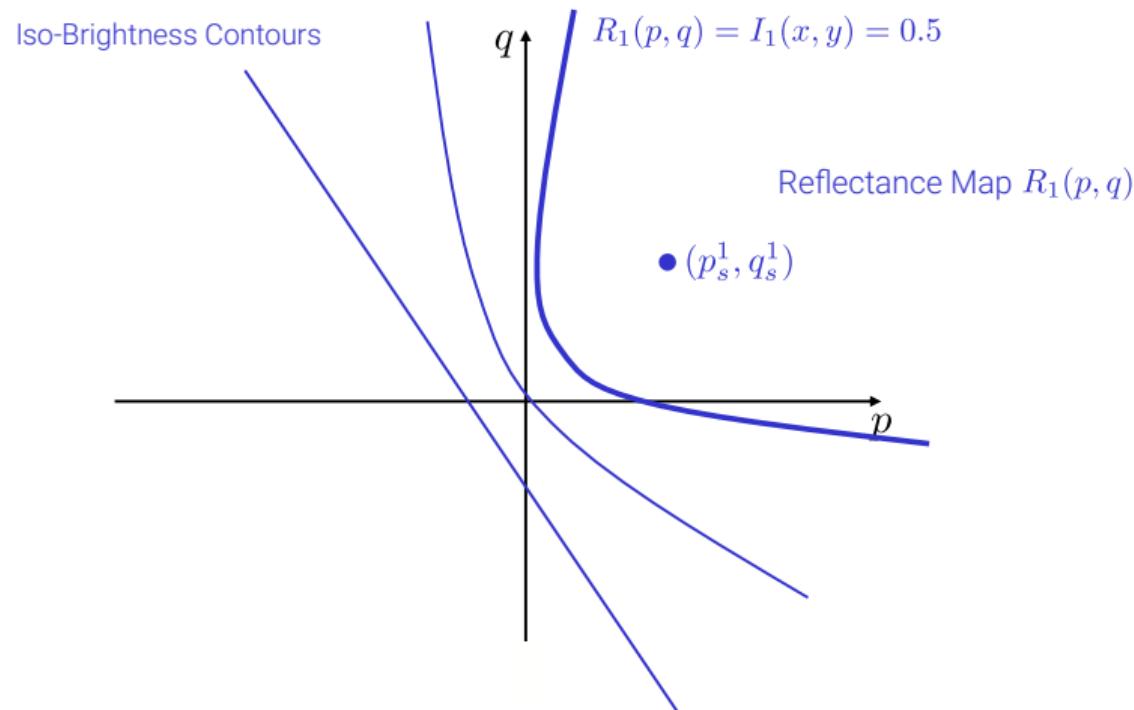


Light Stage



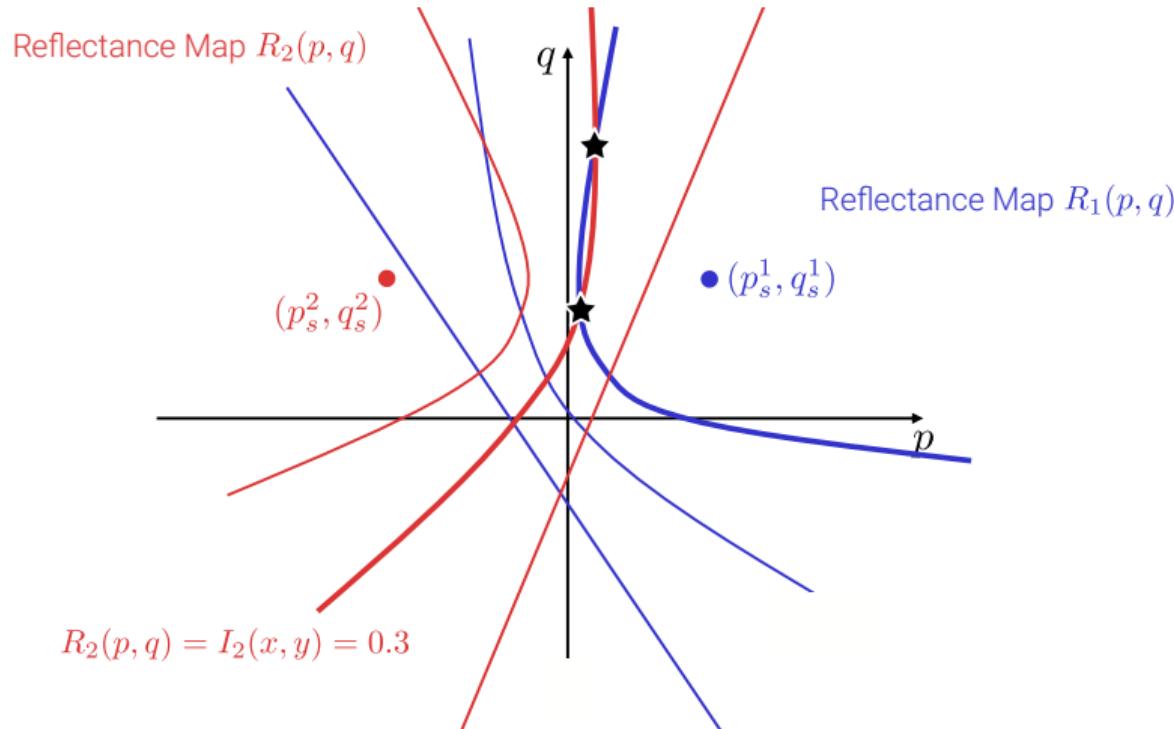
<https://www.esperhq.com/product/lightcage-scanning-rig/>

Reflectance Maps



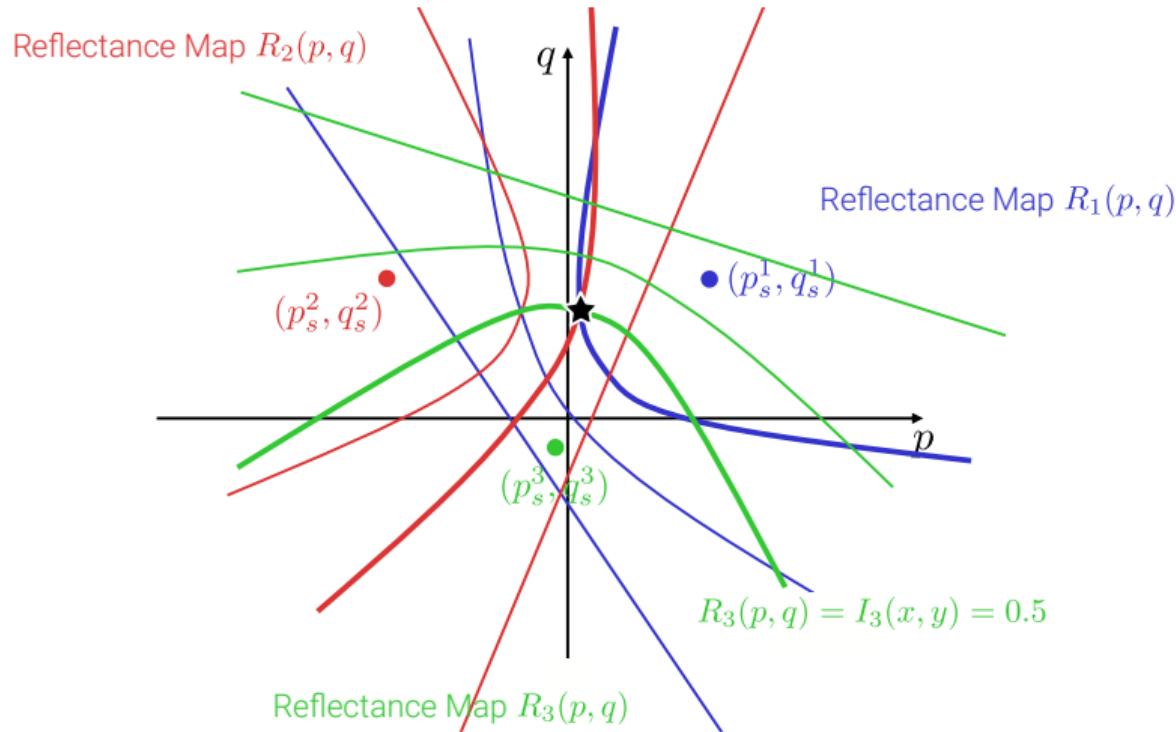
- ▶ Capture K images, construct reflectance maps/curves per pixel, find intersection

Reflectance Maps



- ▶ Capture K images, construct reflectance maps/curves per pixel, find intersection

Reflectance Maps



- ▶ Capture K images, construct reflectance maps/curves per pixel, find intersection

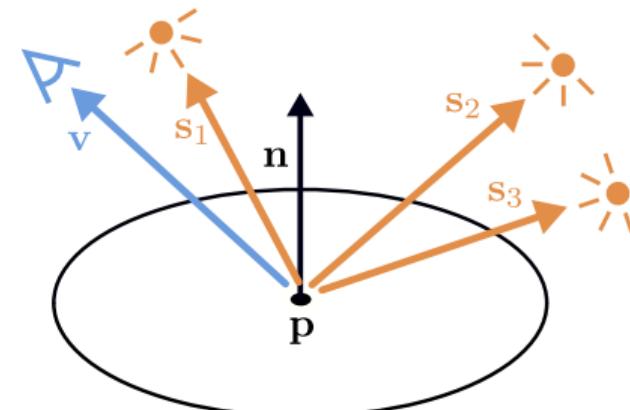
Photometric Stereo Formulation

Assuming **Lambertian reflectance** and $L_{in} = 1$, the image intensity / reflected light is:

$$I = L_{out} = \rho \cdot \mathbf{n}^\top \mathbf{s} = \rho \cdot \mathbf{s}^\top \mathbf{n}$$

Given **3 observations** (same \mathbf{v} , different \mathbf{s}),
we can express this in matrix form as follows:

$$\underbrace{\begin{pmatrix} I_1 \\ I_2 \\ I_3 \end{pmatrix}}_{\mathbf{I}} = \underbrace{\begin{pmatrix} \mathbf{s}_1^\top \\ \mathbf{s}_2^\top \\ \mathbf{s}_3^\top \end{pmatrix}}_{\mathbf{S}} \underbrace{\rho \mathbf{n}}_{\tilde{\mathbf{n}}}$$



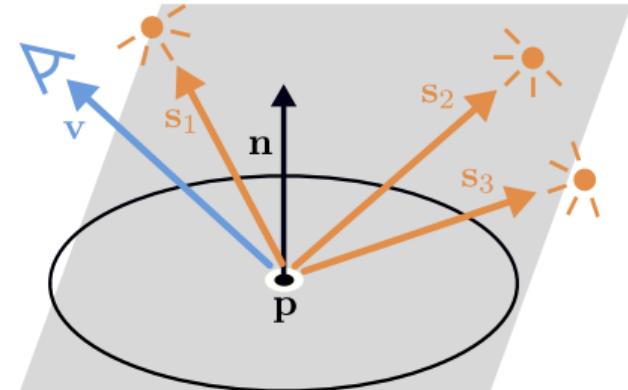
Solution given by $\tilde{\mathbf{n}} = \mathbf{S}^{-1}\mathbf{I}$, $\rho = \|\tilde{\mathbf{n}}\|_2$ and $\mathbf{n} = \tilde{\mathbf{n}}/\rho$.

Photometric Stereo

When does Photometric Stereo **not work?**

$$\underbrace{\begin{pmatrix} I_1 \\ I_2 \\ I_3 \end{pmatrix}}_{\mathbf{I}} = \underbrace{\begin{pmatrix} \mathbf{s}_1^\top \\ \mathbf{s}_2^\top \\ \mathbf{s}_3^\top \end{pmatrix}}_{\mathbf{S}} \underbrace{\rho \mathbf{n}}_{\tilde{\mathbf{n}}}$$

If $\mathbf{s}_3 = \alpha \mathbf{s}_1 + \beta \mathbf{s}_2$, i.e., if all three light sources $\mathbf{s}_1, \mathbf{s}_2, \mathbf{s}_3$ and the origin \mathbf{p} lie on a 3D plane, the linear system becomes rank-deficient and thus there exists no unique solution $\tilde{\mathbf{n}} = \mathbf{S}^{-1}\mathbf{I}$.



Photometric Stereo

Better results can be obtained by using **more images** (by averaging noise):

$$\underbrace{\begin{pmatrix} I_1 \\ \vdots \\ I_K \end{pmatrix}}_{\mathbf{I}} = \underbrace{\begin{pmatrix} \mathbf{s}_1^\top \\ \vdots \\ \mathbf{s}_K^\top \end{pmatrix}}_{\mathbf{S}} \underbrace{\rho \mathbf{n}}_{\tilde{\mathbf{n}}}$$

The **least squares solution** is given by (albedo ρ and normal \mathbf{n} as before):

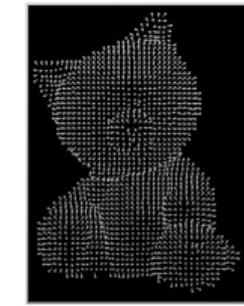
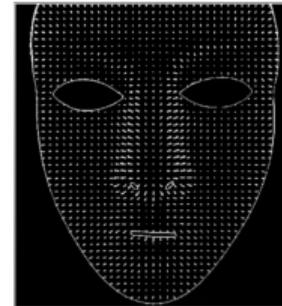
$$\mathbf{S}^\top \mathbf{I} = \mathbf{S}^\top \mathbf{S} \tilde{\mathbf{n}}$$
$$\tilde{\mathbf{n}} = \underbrace{(\mathbf{S}^\top \mathbf{S})^{-1} \mathbf{S}^\top}_{\text{Pseudoinverse}} \mathbf{I}$$

Photometric Stereo Algorithm



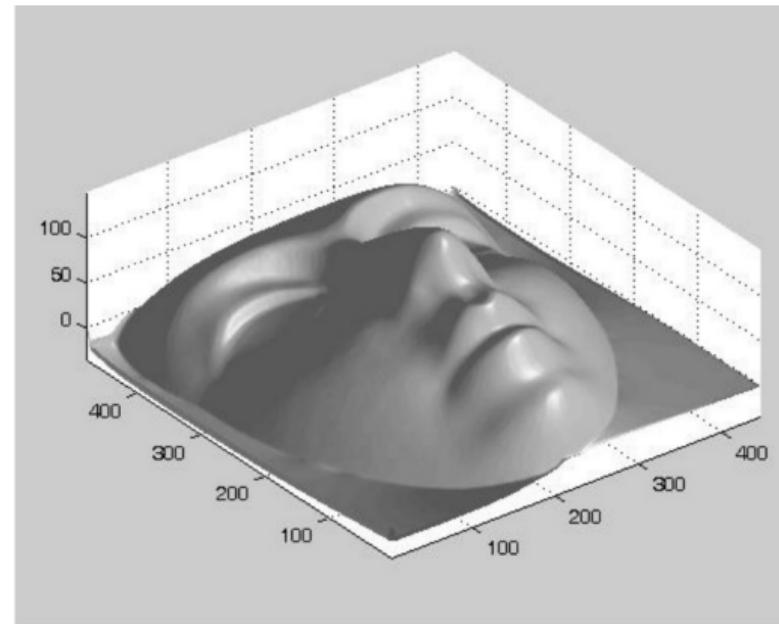
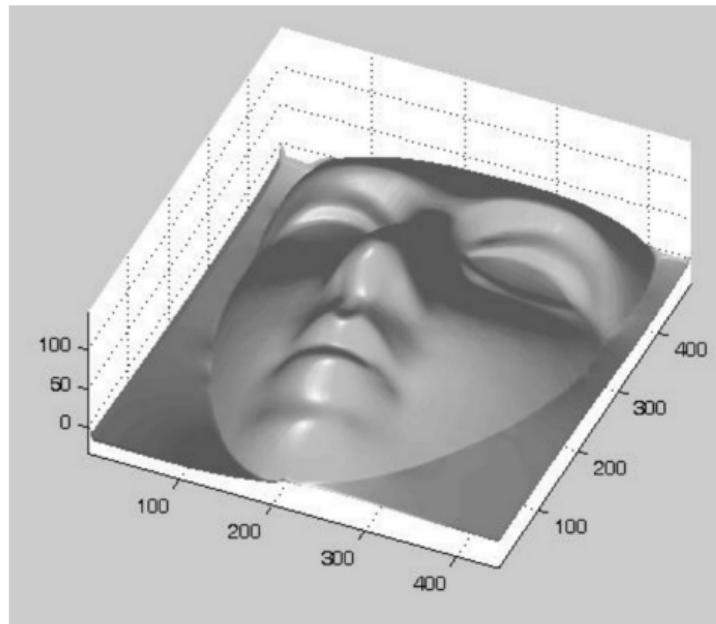
1. Compute **surface normals and albedo** values (per pixel)
2. **Integrate depth** from surface normals
3. **Relight** the object (here: with uniform albedo)

Photometric Stereo Algorithm



- ▶ For color images, apply PS to each channel separately to obtain color albedo
- ▶ Deviations from Lambertian assumption and global illumination cause errors

Photometric Stereo Algorithm



- ▶ For color images, apply PS to each channel separately to obtain color albedo
- ▶ Deviations from Lambertian assumption and global illumination cause errors

Photometric Stereo for Outdoor Webcams



Figure 1. The geographic context of the scene with camera (red marker) and target object (green marker) on the left, and an example image from the camera with sky mask (red region) and object mask (green region) on the right. Sat image © by Google Inc.



Figure 6. One input image, detected shadow regions, selected points for intensity estimation and the recovered object albedo.

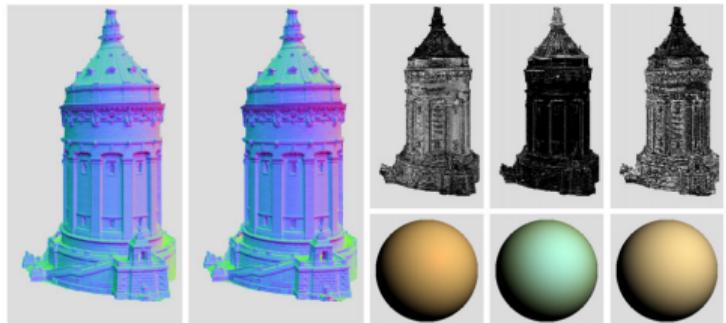


Figure 7. The initial normal map, the final normal map, and the four recovered BRDFs with corresponding material map.

Deep Uncalibrated Photometric Stereo

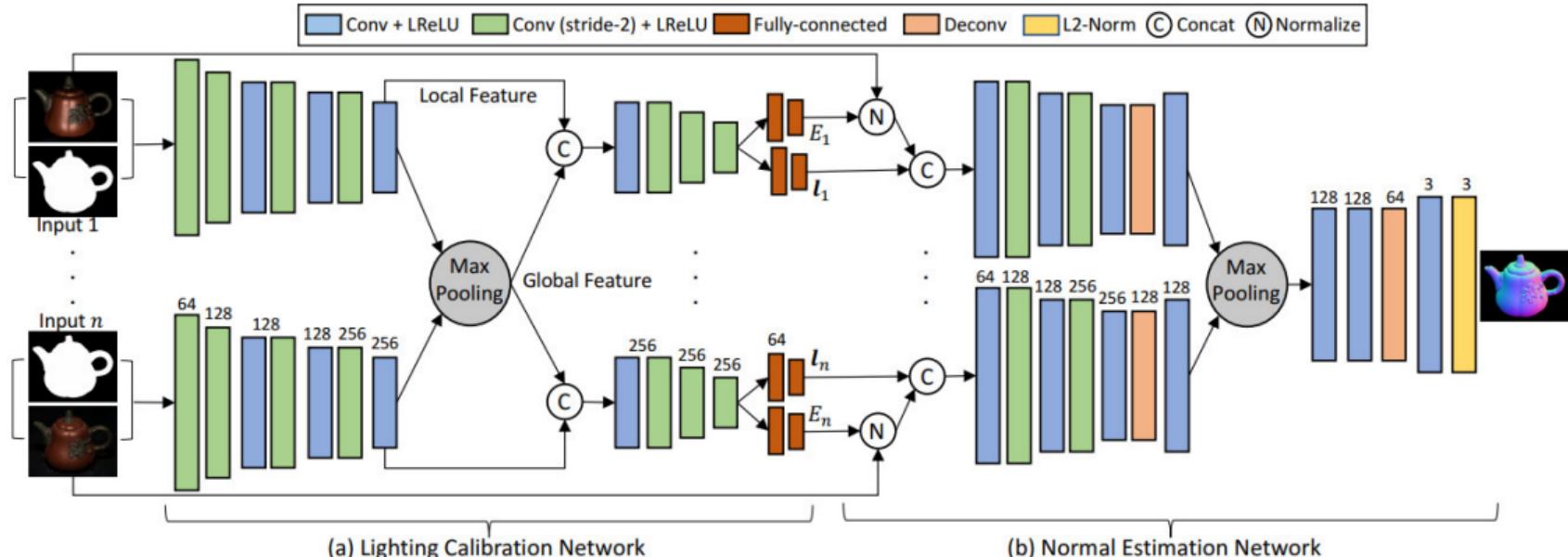
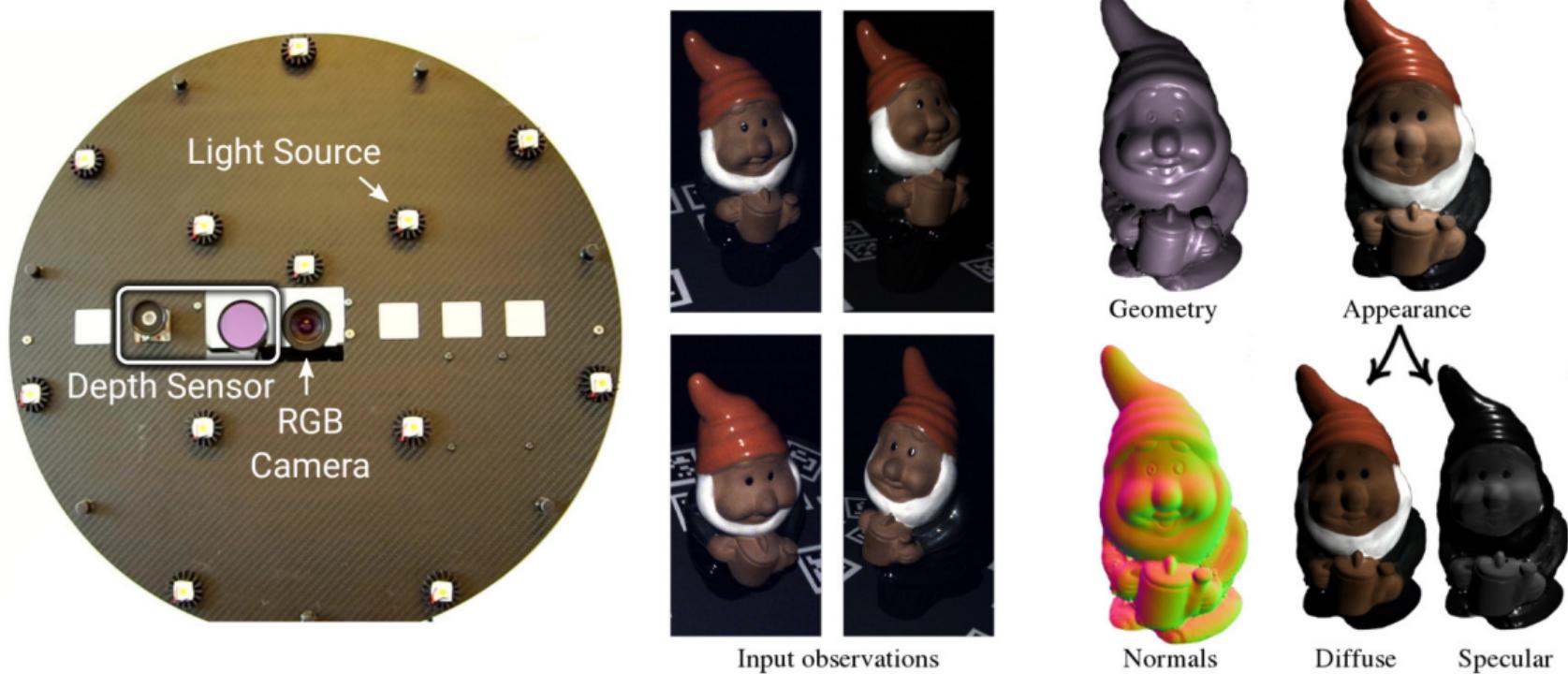


Figure 1. The network architecture of SDPS-Net is composed of (a) Lighting Calibration Network and (b) Normal Estimation Network. Kernel sizes for all convolutional layers are 3×3 , and values above the layers indicate the number of feature channels.

Pose, Geometry and svBRDF from a Handheld Scanner



Volumetric Multi-View Photometric Stereo



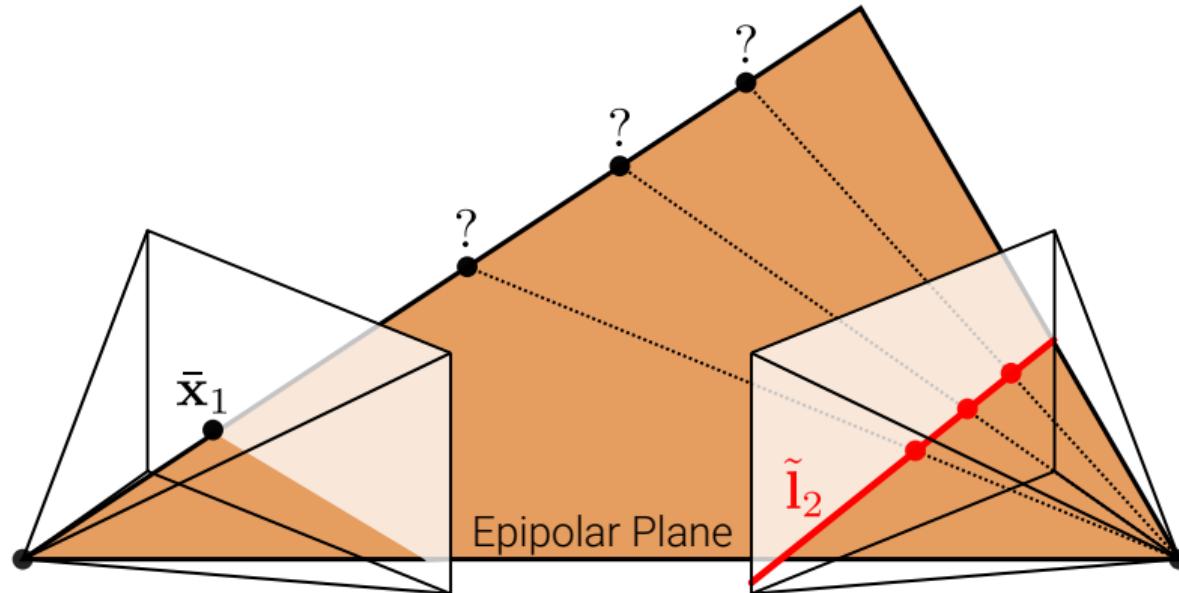
Current Research:

- ▶ Perspective PS, Uncalibrated PS, Deep PS, Volumetric PS, Mobile Setups
- ▶ Shadows, Estimation of non-lambertian materials (more parameters \Rightarrow larger K)

8.3

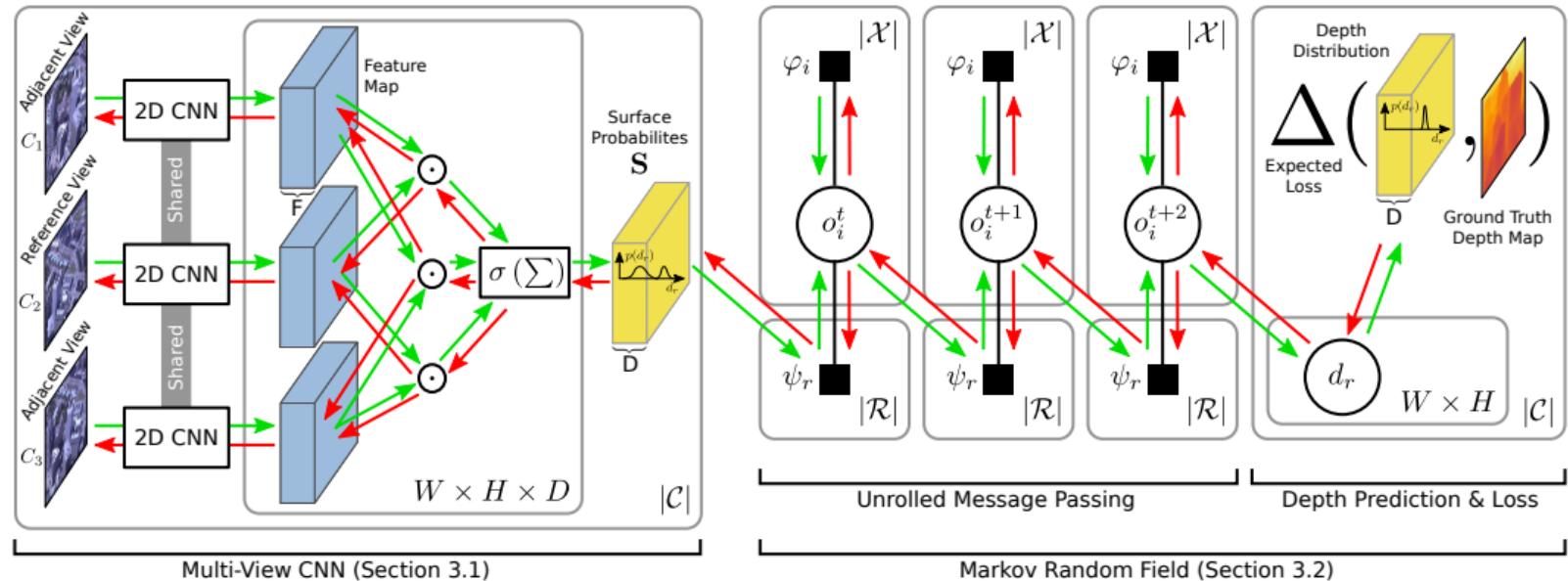
Shape-from-X

Binocular Stereo



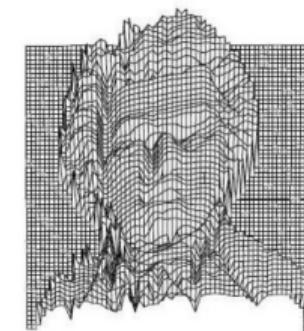
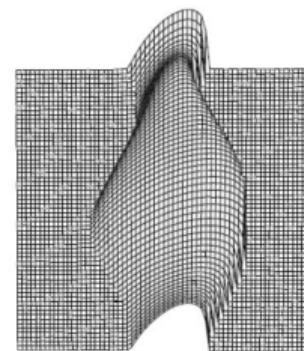
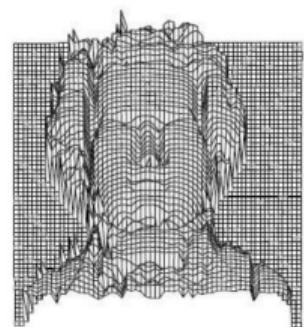
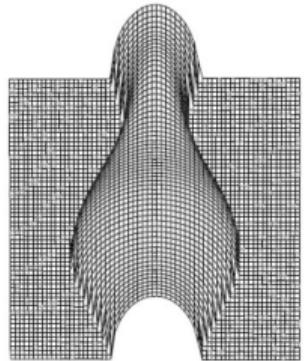
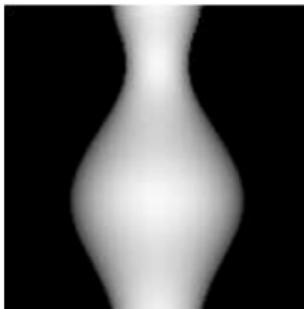
- ▶ Find correspondences between two images

Multi-View Stereo



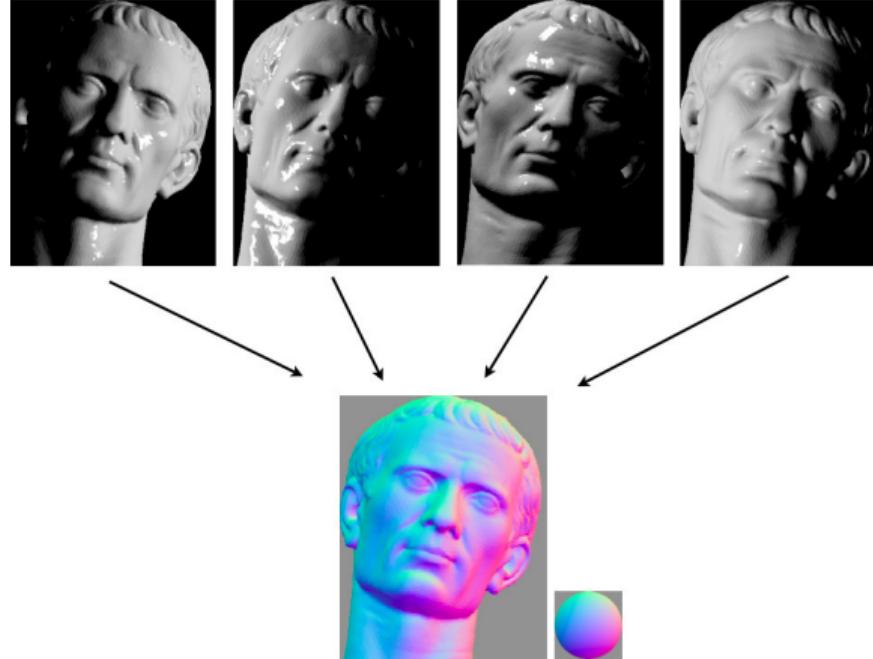
- Find correspondences between multiple images or estimate volumetric model

Shape-from-Shading



- ▶ Estimate shape from shading of a single image (smooth Lambertian scene)

Photometric Stereo



- ▶ Estimate shape (and albedo) from multiple images under varying illumination

Shape-from-Texture

maximum likelihood estimate). It seems most likely therefore that discrepancies result from a local “basis of attraction” for learning that does not lead to a local maximum of the likelihood. Impurities can be eliminated for the model with a correlation connection in either of two ways. One way is to reduce the learning of generative parameters (in the wake phase), while leaving the learning rate unchanged. As discussed in section 3.2, there is a reason to think that this method will lead to the maximum estimates, since the recognition model will then have time to learn the generative model perfectly. When the generative learning is induced by setting $\eta = 0.00005$ and $\alpha = 0.99975$, the maximum estimates are indeed found in eight of eight test runs. The second is to impose a constraint that prevents the generative model

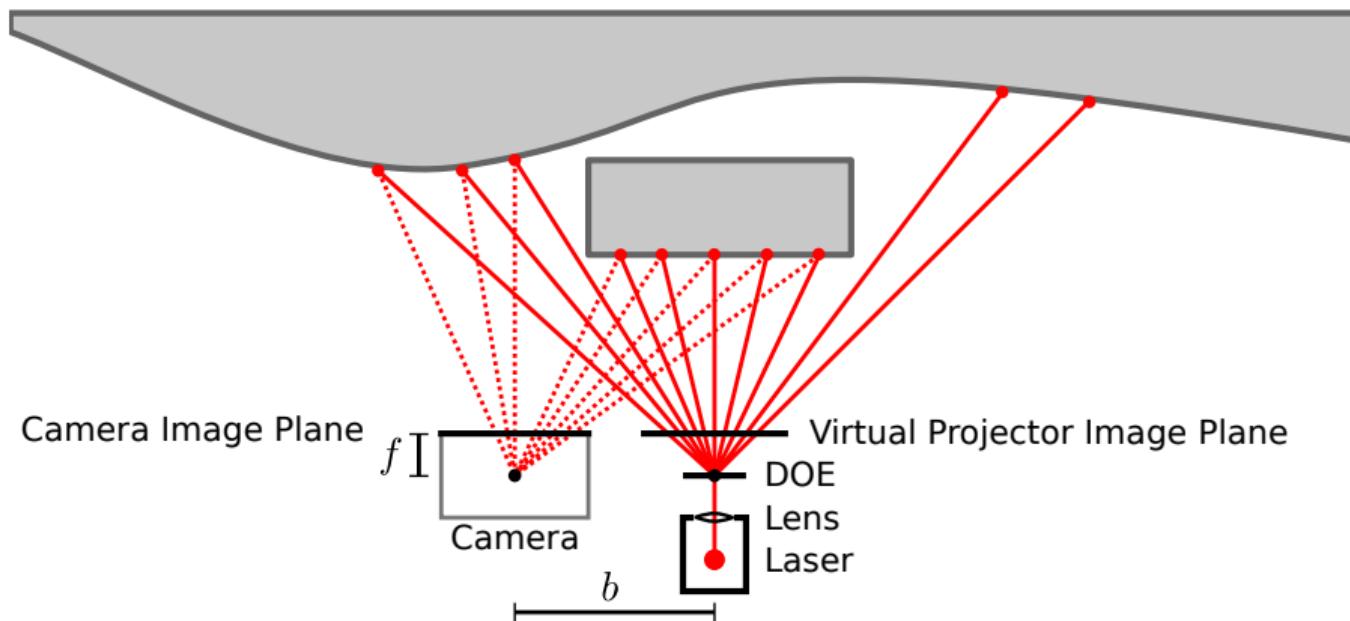


► Estimate shape by exploiting regularity of local textural elements
The first step in estimating shape from texture is to find the correspondence between the input image and the generated image. This is done by matching local textural features. The generated image is created by applying a learned generative model to the input image. The generative model takes the input image and generates a new image that is similar to the input but with some variations. These variations are used to estimate the shape of the object. The correspondence between the input and generated images is found by matching local textural features. This is done by comparing the local textural features of the input and generated images. The local textural features are extracted from the images using a learned feature extractor. The feature extractor takes the input image and generates a feature map. The feature map is then compared with the generated image to find the correspondence. The correspondence is used to estimate the shape of the object.



- ▶ Estimate shape by exploiting regularity of local textural elements

Structured Light



- ▶ Use a pattern projector to actively illuminate the scene
- ▶ If pattern is calibrated and known, one camera suffices

Structured Light



Kinect V1 (2010)
XBox 360, Windows 7



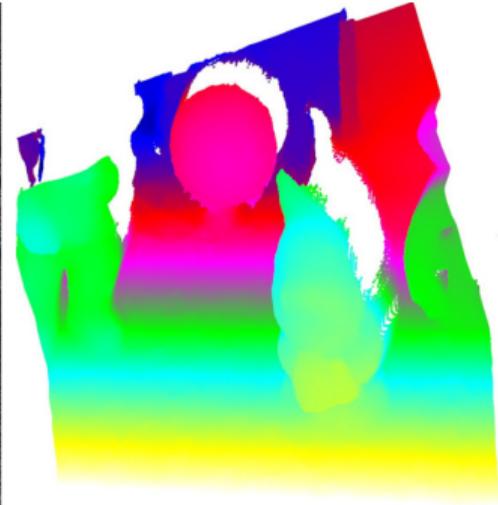
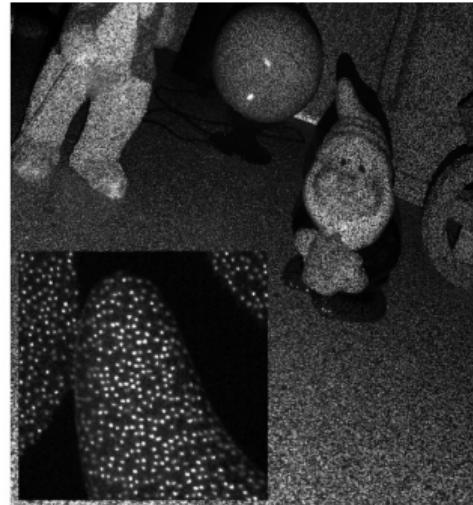
Kinect V2 (2013)
XBox One, Windows 10



Kinect V3 (2015)
HoloLens V1

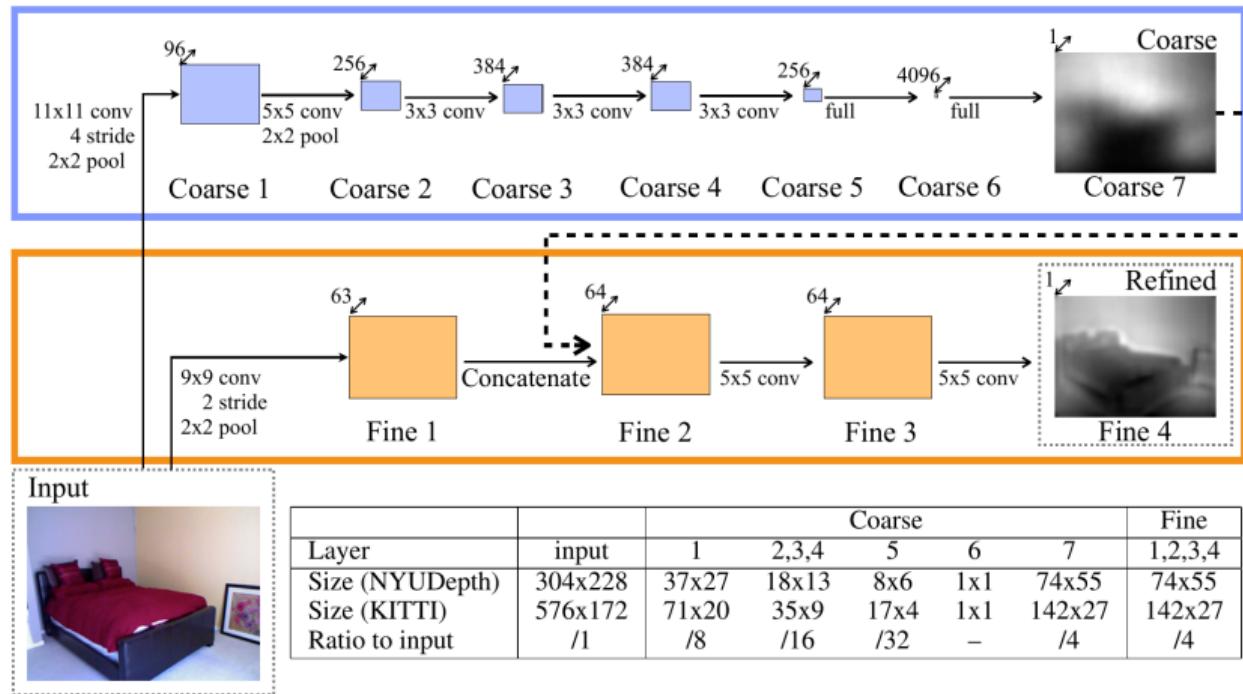


Kinect V4 (2019)
HoloLens V2, Windows 10



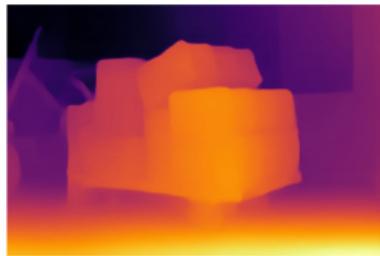
- ▶ Use a pattern projector to actively illuminate the scene
- ▶ If pattern is calibrated and known, one camera suffices

Monocular Depth Estimation

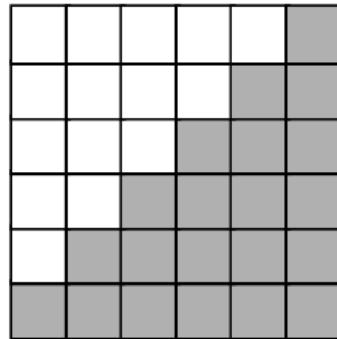


- ▶ Learn to predict depth from single RGB image using large annotated datasets

Monocular Depth Estimation

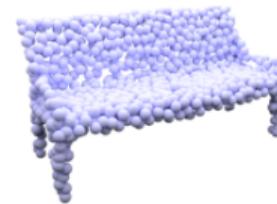
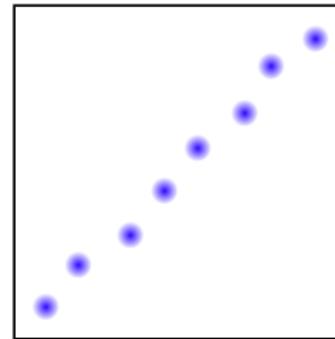


Monocular Shape Estimation and Completion



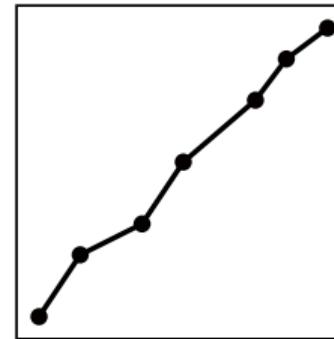
Voxels

[Maturana et al., IROS 2015]



Points

[Fan et al., CVPR 2017]



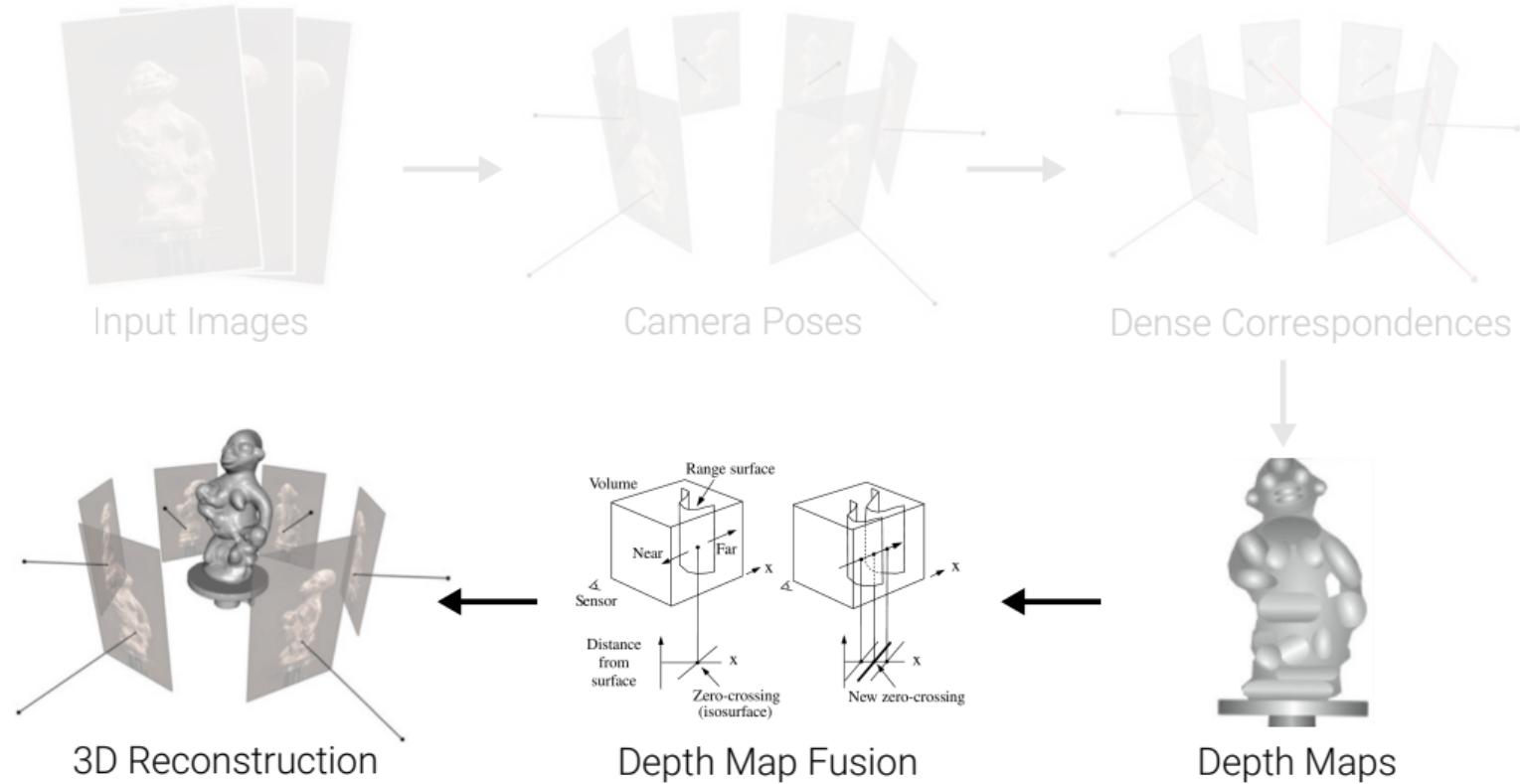
Meshes

[Groueix et al., CVPR 2018]

8.4

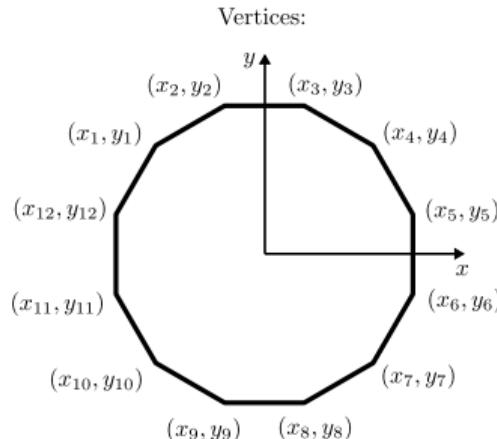
Volumetric Fusion

Traditional 3D Reconstruction Pipeline



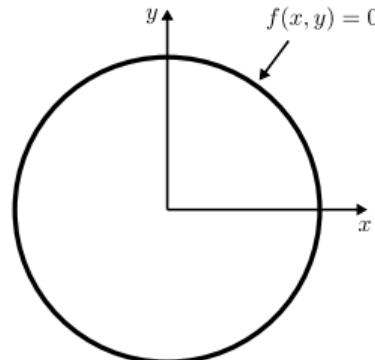
Representations

Mesh

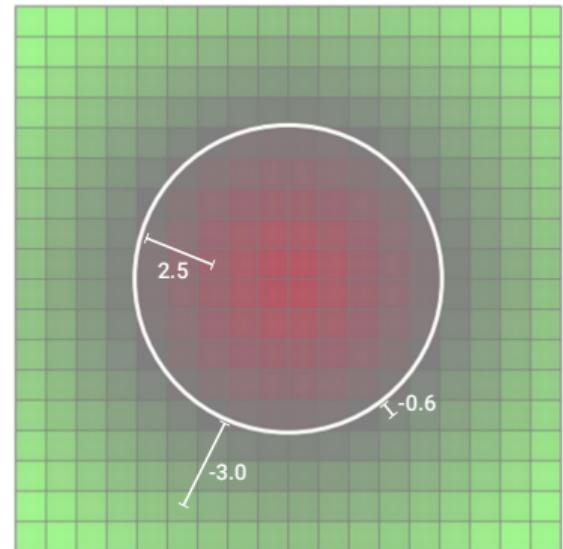


Implicit (Continuous)

$$f(x, y) = x^2 + y^2 - r^2$$

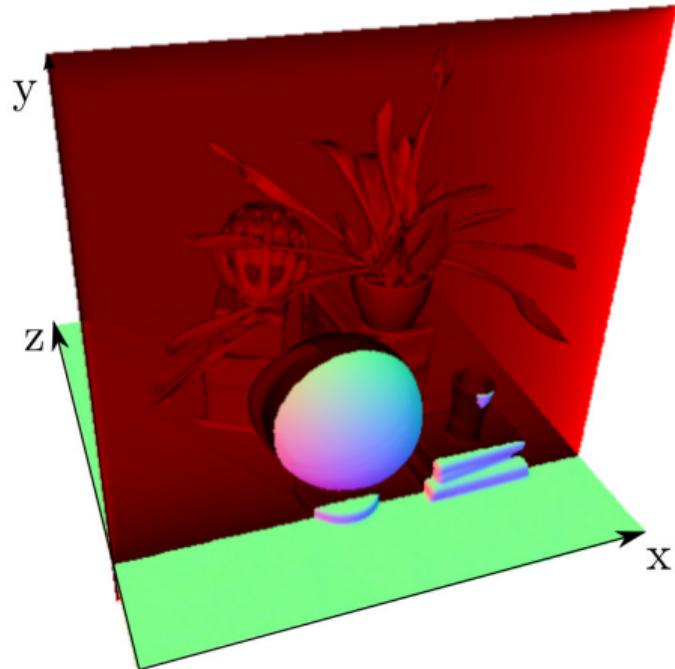
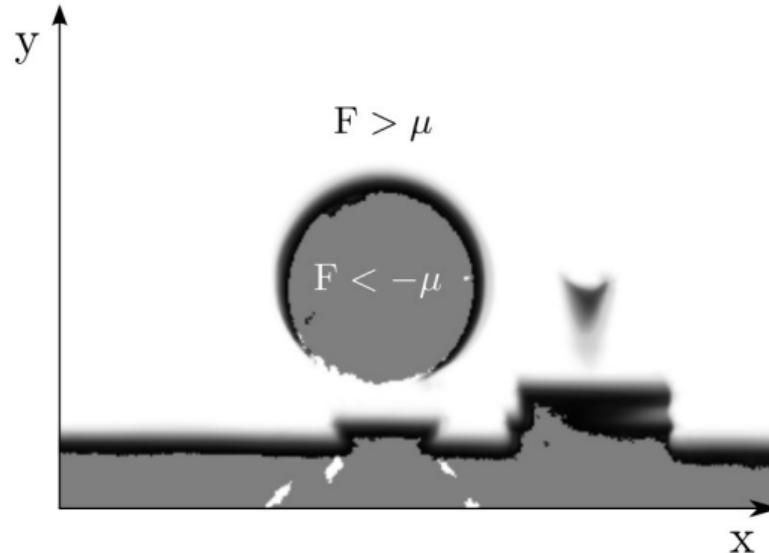


Implicit (Discrete SDF)



- SDF models store the **signed distance to the closest surface** at each voxel
- The **surface** is hence represented implicitly as the **zero level set**

Implicit Representations



- Crucial advantage: Implicit models allow for representing **arbitrary topology**

Implicit Representations



- Crucial advantage: Implicit models allow for representing **arbitrary topology**

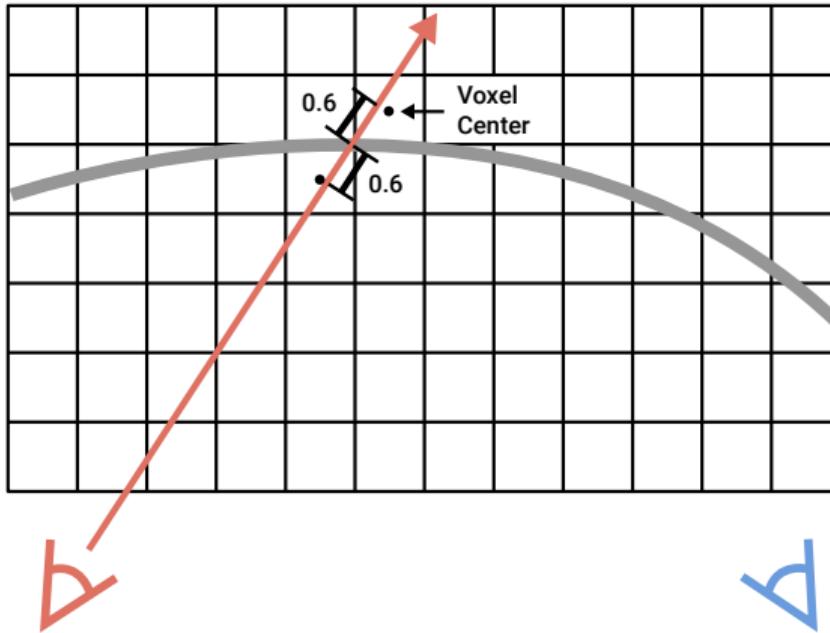
Volumetric Fusion

3 Steps:

- ▶ Depth-to-SDF Conversion
- ▶ Volumetric Fusion
- ▶ Mesh Extraction

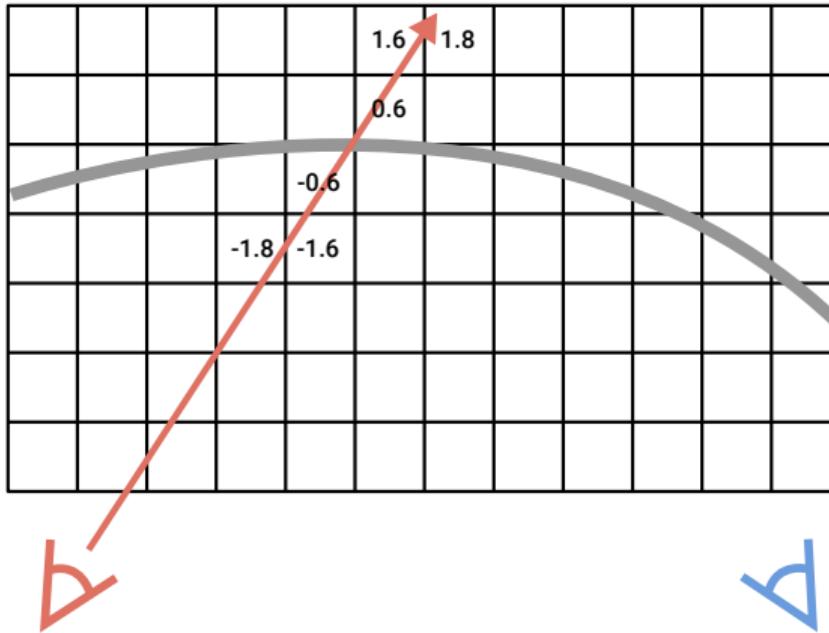
Depth-to-SDF Conversion

Depth-to-SDF Conversion



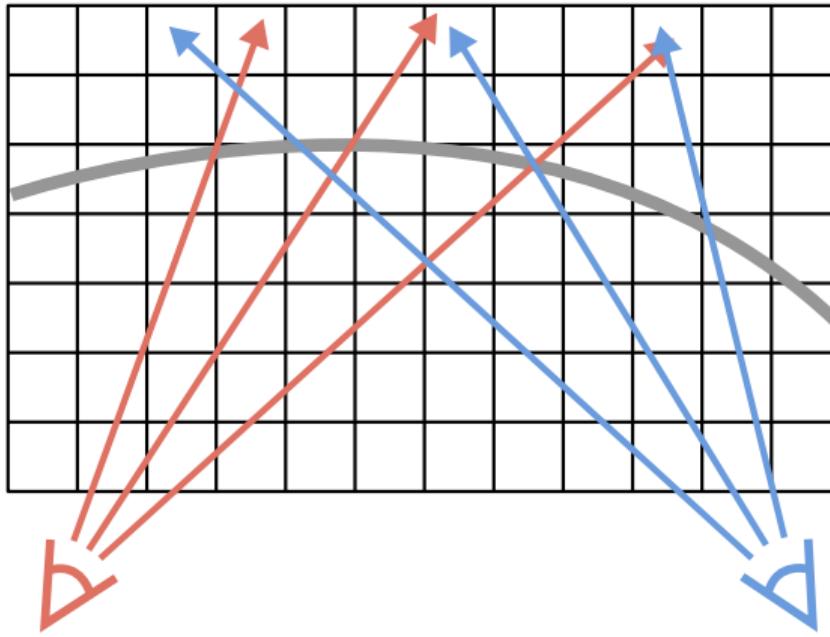
- ▶ As the distance to surface is unknown, approximate it with **distance along ray**
- ▶ This approximation is good only in the vicinity of the surface (often suffices)

Depth-to-SDF Conversion



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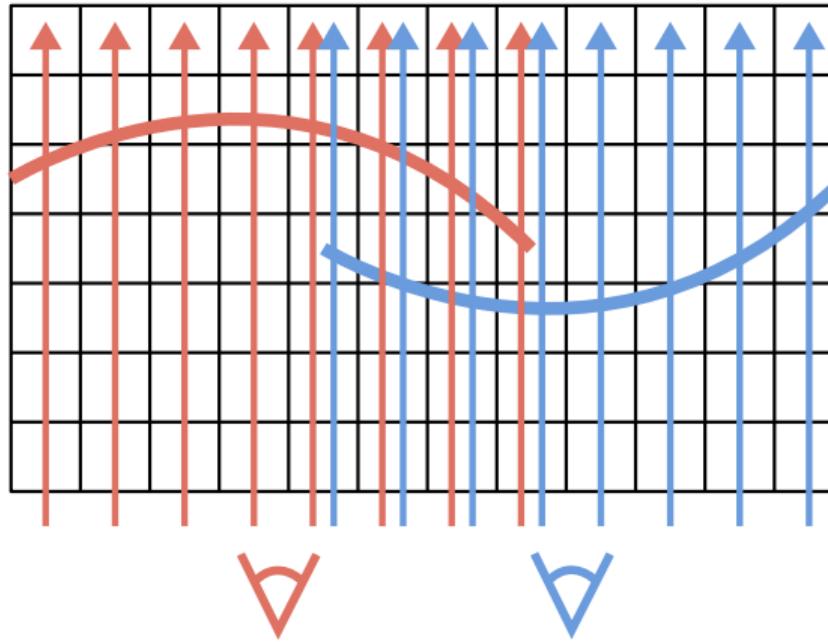
Depth-to-SDF Conversion



- As the distance to surface is unknown, approximate it with **distance along ray**
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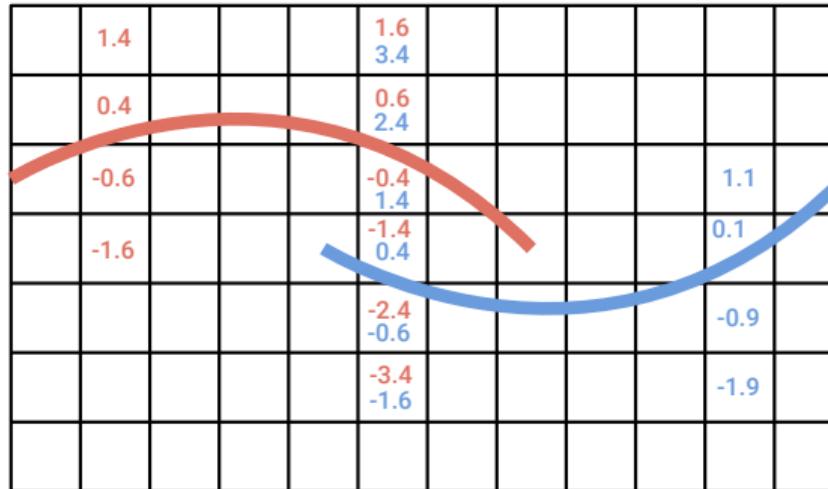
Volumetric Fusion

Volumetric Fusion (Orthographic Example)



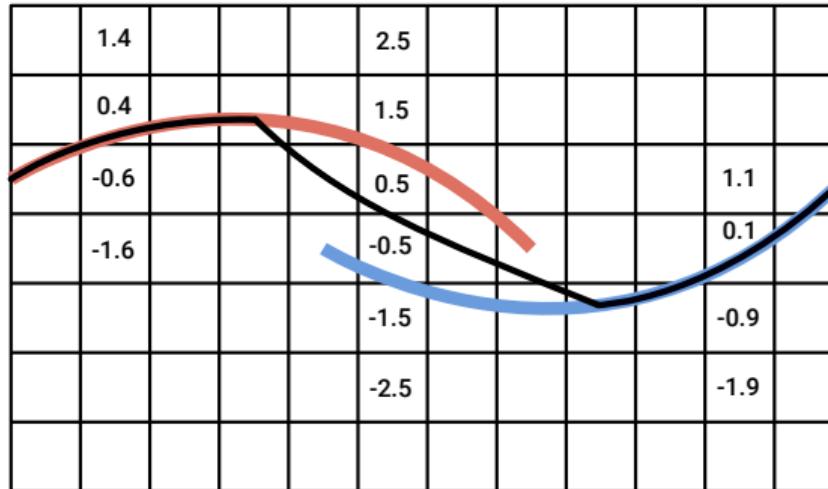
- ▶ After conversion, calculate average of the discrete SDF fields
- ▶ The implicit surface will be an average of the two original ones

Volumetric Fusion (Orthographic Example)



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Volumetric Fusion (Orthographic Example)



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Volumetric Fusion Formulation

SDF Fusion calculates the **weighted average** per voxel:

$$D(\mathbf{x}) = \frac{\sum_i w_i(\mathbf{x}) d_i(\mathbf{x})}{\sum_i w_i(\mathbf{x})}$$

$$W(\mathbf{x}) = \sum_i w_i(\mathbf{x})$$

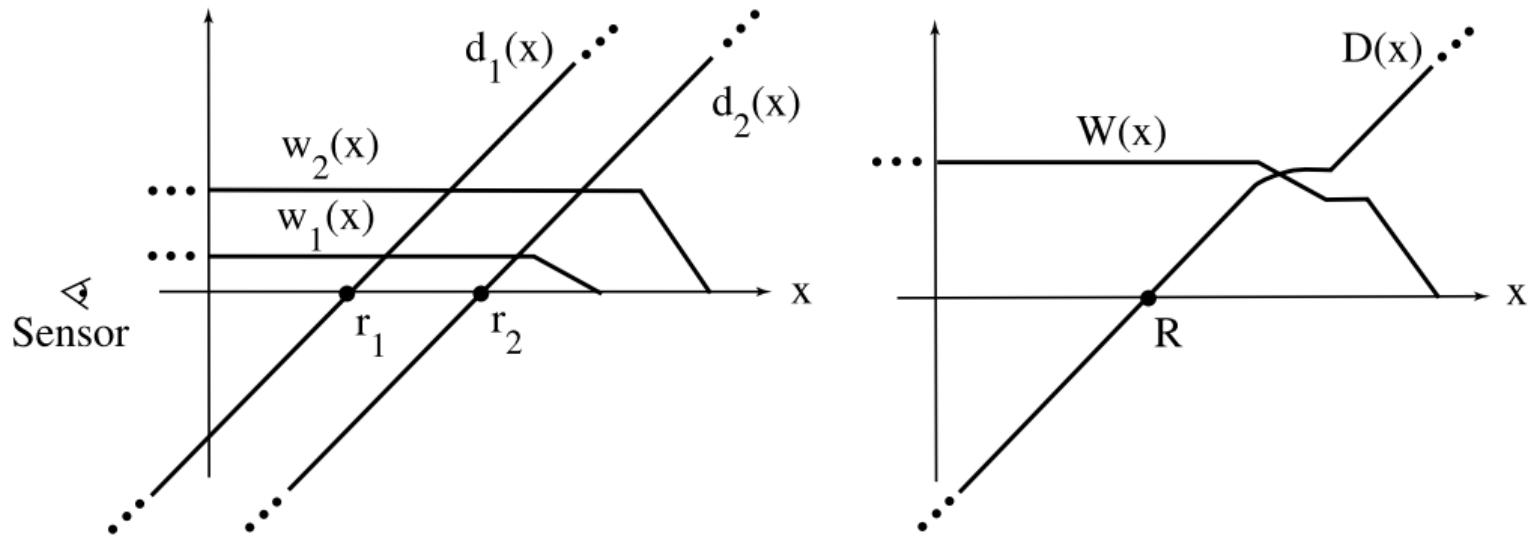
- ▶ $w_i(\mathbf{x}), d_i(\mathbf{x})$: weight and distance along ray at voxel \mathbf{x} for camera i
- ▶ $W(\mathbf{x}), D(\mathbf{x})$: sum of weights and fused distance at voxel \mathbf{x}

This can be conveniently expressed with an **incremental update rule**: (exercise)

$$D_{i+1}(\mathbf{x}) = \frac{W_i(\mathbf{x}) D_i(\mathbf{x}) + w_{i+1}(\mathbf{x}) d_{i+1}(\mathbf{x})}{W_i(\mathbf{x}) + w_{i+1}(\mathbf{x})}$$

$$W_{i+1}(\mathbf{x}) = W_i(\mathbf{x}) + w_{i+1}(\mathbf{x})$$

Volumetric Fusion Formulation



- ▶ Weights useful to downweight SDF values **behind the surface** (no observations)
- ▶ Also used to downweight **less certain** rays (distance, orientation, boundaries)

Volumetric Fusion Formulation

Why is weighted averaging a good idea?

$$D(\mathbf{x}) = \frac{\sum_i w_i(\mathbf{x}) d_i(\mathbf{x})}{\sum_i w_i(\mathbf{x})}$$

It is the solution to the following **weighted least squares problem:** (exercise)

$$D^* = \operatorname{argmin}_D \sum_i w_i (d_i - D)^2$$

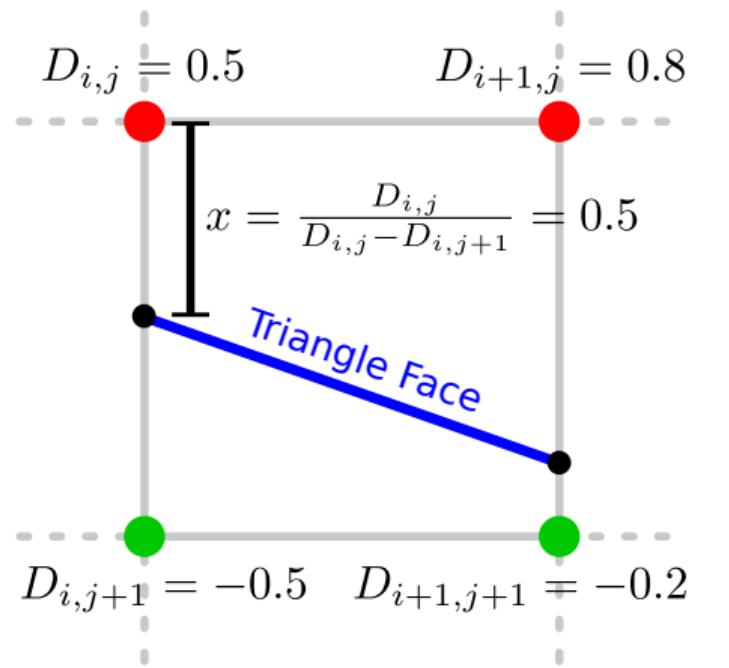
In other words, D is the optimal distance in least squares sense (at every location \mathbf{x}).

Mesh Extraction

Marching Cubes

How to extract a **mesh from the SDF?**

- ▶ Zero-level set \Rightarrow triangular mesh
- ▶ “March” through all grid cells and insert triangle faces whenever a sign change is detected. 2 Steps:
 1. Estimate **topology**
 2. Predict **vertex location**
- ▶ In 3D: $2^8 = 256$ possible topologies
- ▶ Vertices are zero crossing of linear interpolant $f(x) = D + x(D' - D)$
- ▶ $f(x) \stackrel{!}{=} 0 \Rightarrow x = D/(D - D')$

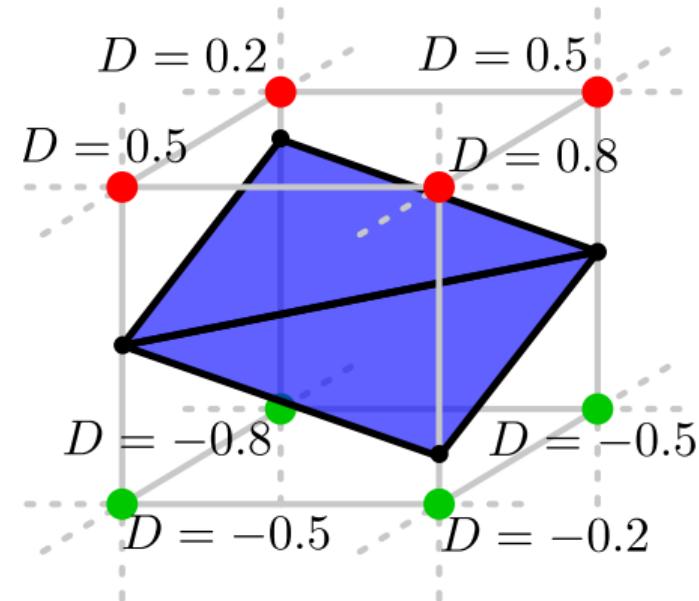


Red/green = **centers** of inside/outside cells

Marching Cubes

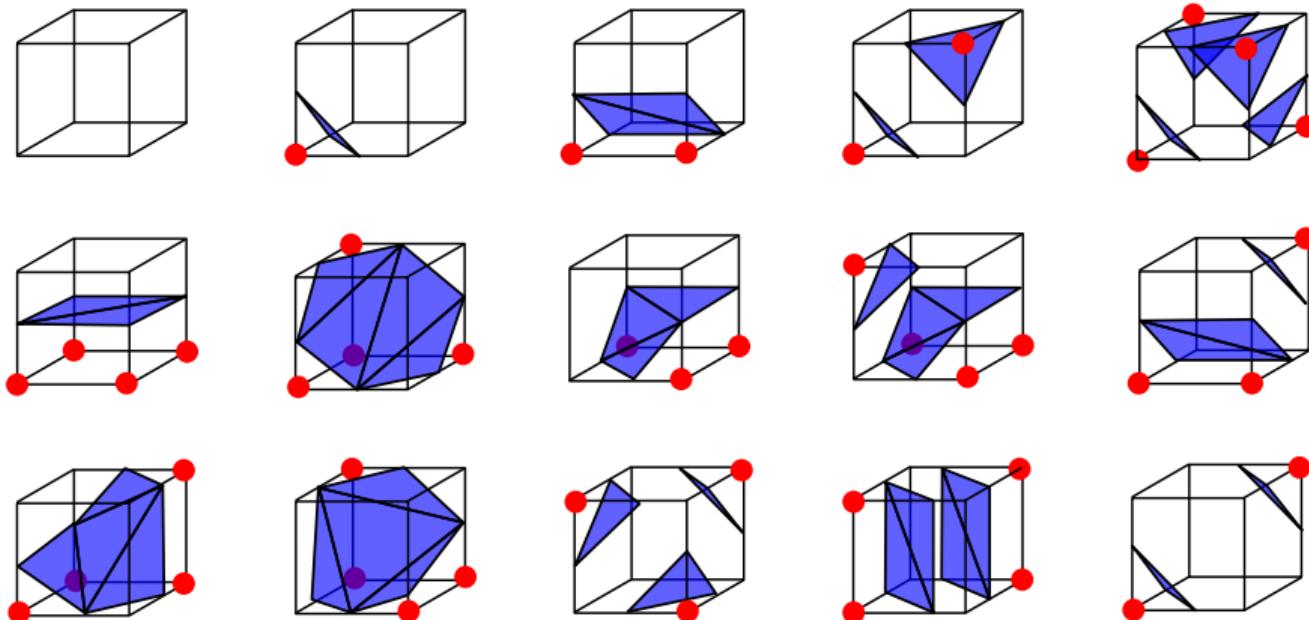
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Red/green = **centers** of inside/outside cells

Marching Cubes



- The $2^8 = 256$ topologies can be grouped into 15 classes (rotational symmetry)

Applications

KinectFusion

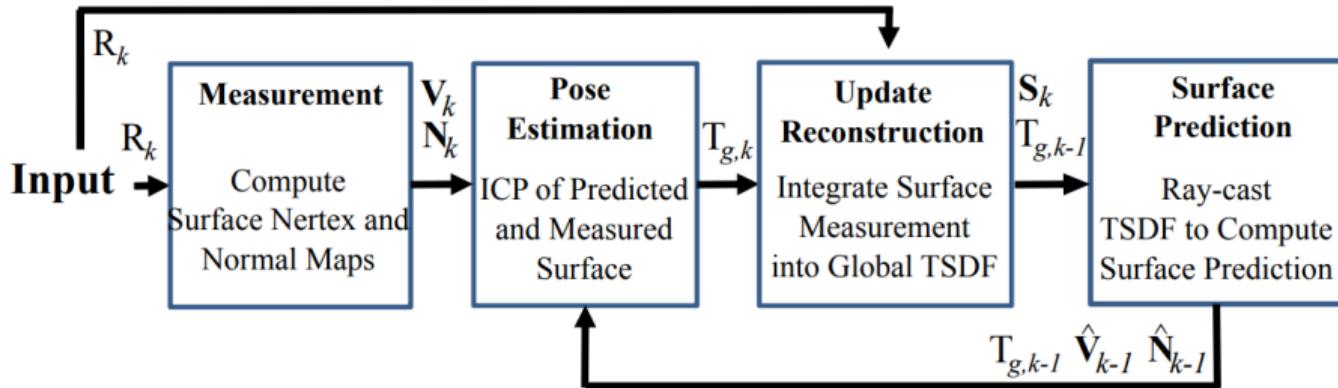
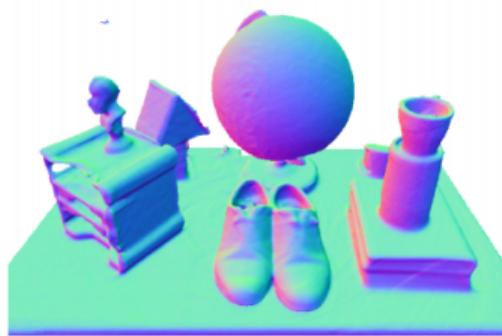
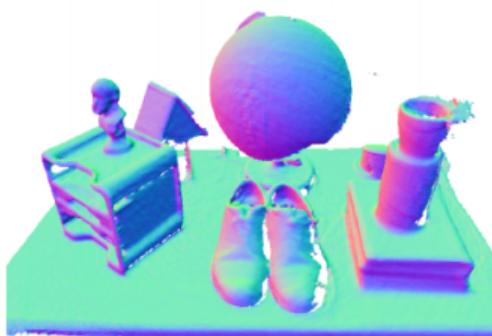
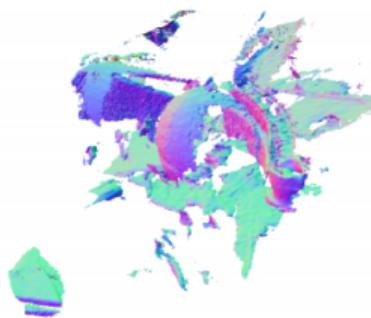
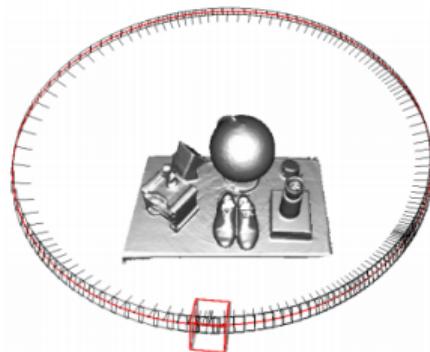
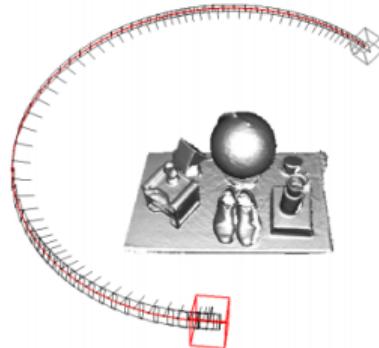


Figure 3: Overall system workflow.

- Real-time pose estimation and volumetric fusion using Kinect depth data as input

KinectFusion

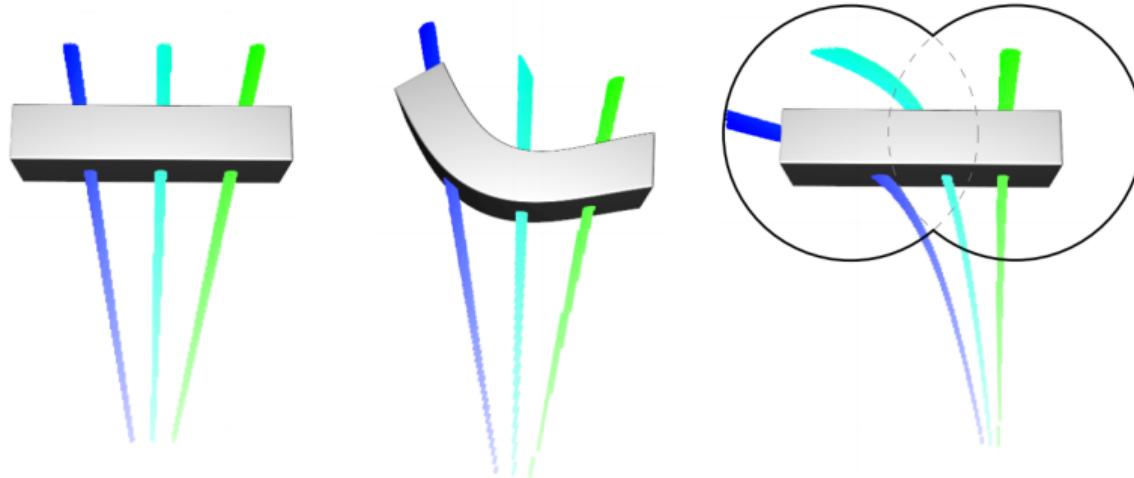


(a) Frame to frame tracking

(b) Partial loop

(c) Full loop

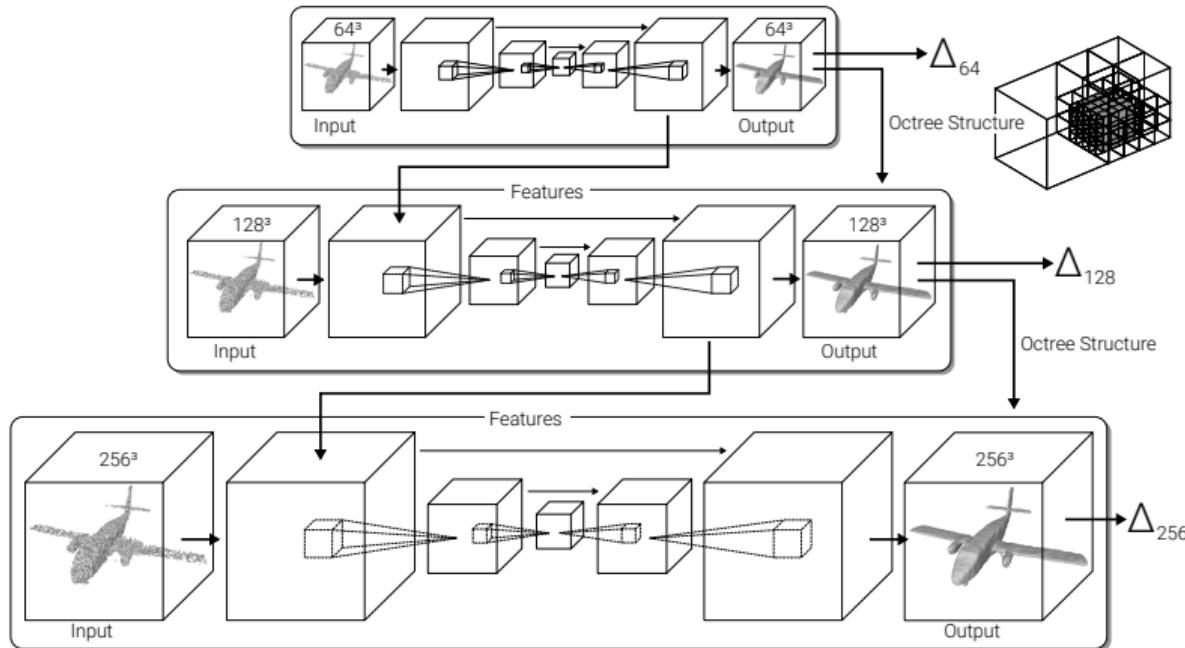
DynamicFusion



(a) Live frame $t = 0$ (b) Live Frame $t = 1$ (c) Canonical \mapsto Live

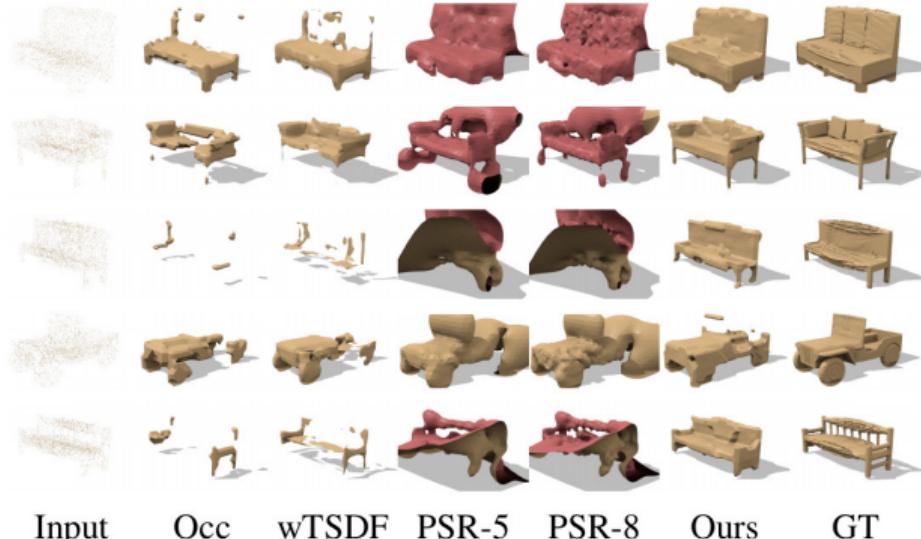
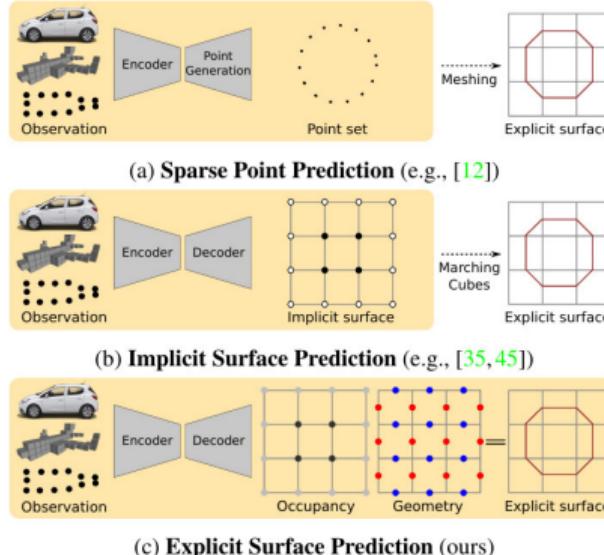
- Reconstruct non-rigid scenes by warping the estimated geometry into a live frame

OctNetFusion



- Use fused geometry as features in a learning framework to complete and denoise

Deep Marching Cubes



- Differentiable variants enable supervision directly via 3D point clouds