

Chapter 10: Variational Multiview Reconstruction

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1 Shape Representation and Optimization

1.1 Shape optimization

Shape optimization is a field of mathematics that is focused on formulating the estimation of geometric structures by means of optimization methods.

Among the major challenges in this context is the question how to mathematically represent **shape**. The choice of representation entails a number of consequences, in particular regarding the question of how efficiently one can store geometric structures and how efficiently one can compute optimal geometry.

There exist numerous representations of shape which can loosely be grouped into two classes:

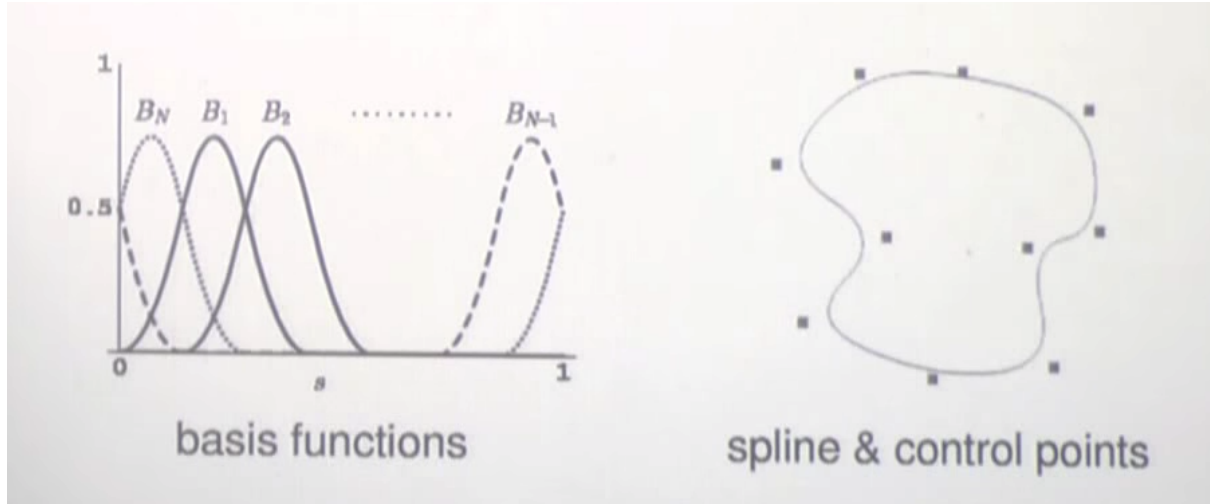
- **Explicit representations:** The points of a surface are represented explicitly (directly), either as a set of points, a polyhedron or a parameterized surface.
- **Implicit representations:** The surface is represented implicitly by specifying the parts of ambient space that are inside and outside a given surface.

1.2 Explicit Shape Representations

An explicit representation of a closed curve $C \subset \mathbb{R}^d$ is a mapping $C : S^1 \rightarrow \mathbb{R}^d$ from the circle S^1 to \mathbb{R}^d . Examples are polygons or - more generally - spline curves:

$$C(s) = \sum_{i=1}^N (C_i B_i(s)) \quad (1)$$

where $C_1, \dots, C_N \in \mathbb{R}^d$ denote control points and $B_1, \dots, B_N : S^1 \rightarrow \mathbb{R}$ denote a set of spline basis functions:

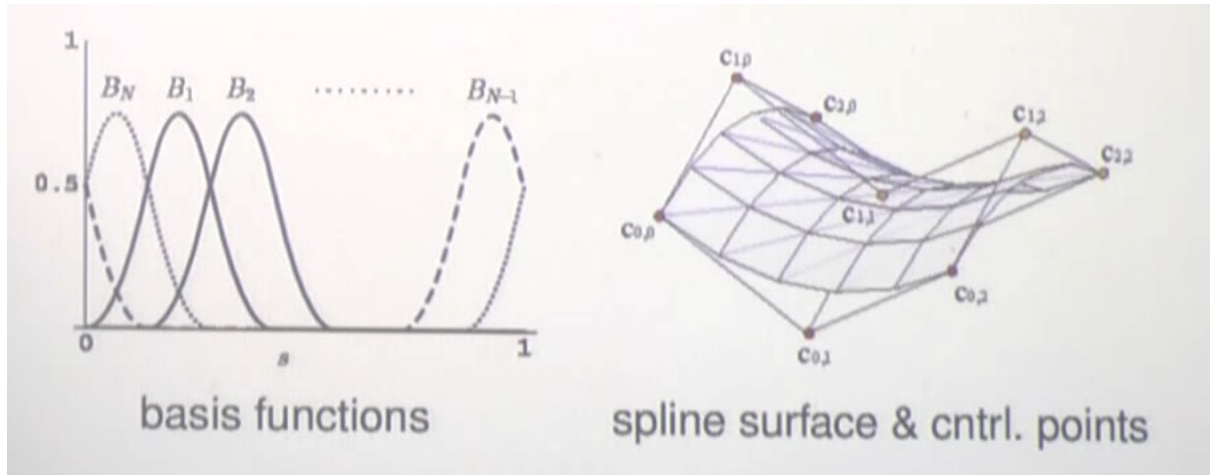


1.3 Explicit Shape Representations

Splines can be extended from curves to surfaces or higher dimensional structures. A spline surface $S \in \mathbb{R}^d$ can be defined as:

$$S(s, t) = \sum_{i,j} C_{i,j} B_i(s) B_j(t) \quad (2)$$

where $C_{i,j} \in \mathbb{R}^d$ denote control points and $B_1, \dots, B_N : [0, 1] \rightarrow \mathbb{R}$ denote a set of spline basis functions. Depending on whether the surface is closed or open these basis functions will have a cyclic nature (as below) or not:



1.4 Implicit Shape Representations

One example of an implicit representation is the **indicator function** of the surface S , which is a function $u : V \rightarrow [0, 1]$ defined on the surrounding volume $V \in \mathbb{R}^3$ that takes on the values 1 inside the surface and 0 outside the surface:

$$u(x) = \begin{cases} 1, & \text{if } x \in \text{int}(S) \\ 0, & \text{if } x \in \text{ext}(S) \end{cases} \quad (3)$$

Another example is the **signed distance function** $\phi : V \rightarrow \mathbb{R}$ which assigns all points in the surrounding volume the (signed) distance from the surface S :

$$\phi(x) = \begin{cases} +d(x, S), & \text{if } x \in \text{int}(S) \\ -d(x, S), & \text{if } x \in \text{ext}(S) \end{cases} \quad (4)$$

Depending on the application it may be useful to know for every voxel how far it is from the surface. Signed distance functions can be computed in polynomial time. **BatLab: bwdist.**

1.5 Explicit Versus Implicit Representations

In general, compared to explicit representations the **implicit representations** have the following strengths and weaknesses:

- - Implicit representations **typical require more memory** in order to represent a geometric structure at a specific resolution. Rather than storing a few points along the value or surface, one needs to store an occupancy value for each volume element.
- - Moving or updating an implicit representation is **typically slower**: rather than moving a few control points, one needs to update the occupancy of all volume elements.
- + Methods based on implicit representation **do not depend on a choice of parameterization**.
- + Implicit representations allow to represent objects of **arbitrary topology** (i.e. the number of holes is arbitrary).
- + With respect to an implicit representation many shape optimization challenges can be formulated as **convex optimization problems** and **can then be optimized globally**.

2 Variational Multiview Reconstruction

2.1 Multiview Reconstruction as Shape Optimization

How can we cast **multiple view reconstruction** as a shape optimization problem? To this end, we will assume that the camera orientations are given. Rather than estimating the correspondence between all pairs of pixels in either image we will simply ask:

How likely is a given voxel x on the object surface S ?

If the voxel $x \in V$ of the given volume $V \subset \mathbb{R}^3$ was on the surface then (up to visibility issues) the projection on that voxel into each image should give rise to the same color (or local texture). Thus we can assign to each voxel $x \in V$ a so-called **photoconsistency function**

$$\rho : V \rightarrow [0, 1] \quad (5)$$

which takes on low values (near 0) if the projected voxels give rise to the same color (or local texture) and high values (near 1) otherwise.

Assumptions:

- Visibility
- Lambertian
- Textured

2.2 A Weighted minimal Surface Approach

The reconstruction from multiple view can now be formulated as finding the maximally photoconsistency surface, i.e. a surface S_{opt} with an overall minimal photoconsistency score:

$$S_{opt} = \arg \min_S \int_S \rho(s) ds. \quad (6)$$

This seminal formulation was proposed among others by **Faugeras and Keriven (1998)**. Many good reconstructions were computed by starting from an initial guess of S and locally minimizing this energy using gradient descent. But can we compute the global minimum?

The global minimizer of (6) is the empty set.

It has zero cost while all surfaces have a non-negative energy. This short-coming of minimal surface formulations is often called the **shrinking bias**. How can we prevent the empty set?

2.3 Imposing Silhouette Consistency

Assume that we additionally have the silhouette S_i of the observed 3D object outlined in every image $i = 1, \dots, n$. Then we can formulate the reconstruction problem as a **constrained optimization problem** (**Cremer, Koley, Pami 2011**):

$$\min_S \int_S \rho(s) ds \text{ such that } \pi_i(S) = S_i, \forall i = 1, \dots, n \quad (7)$$

Written in the indicator function $u : V \rightarrow \{0, 1\}$ of the surface S this reads:

$$\min_{u: V \rightarrow \{0, 1\}} \int_V \rho(x) |\nabla u(x)| dx \quad (8)$$

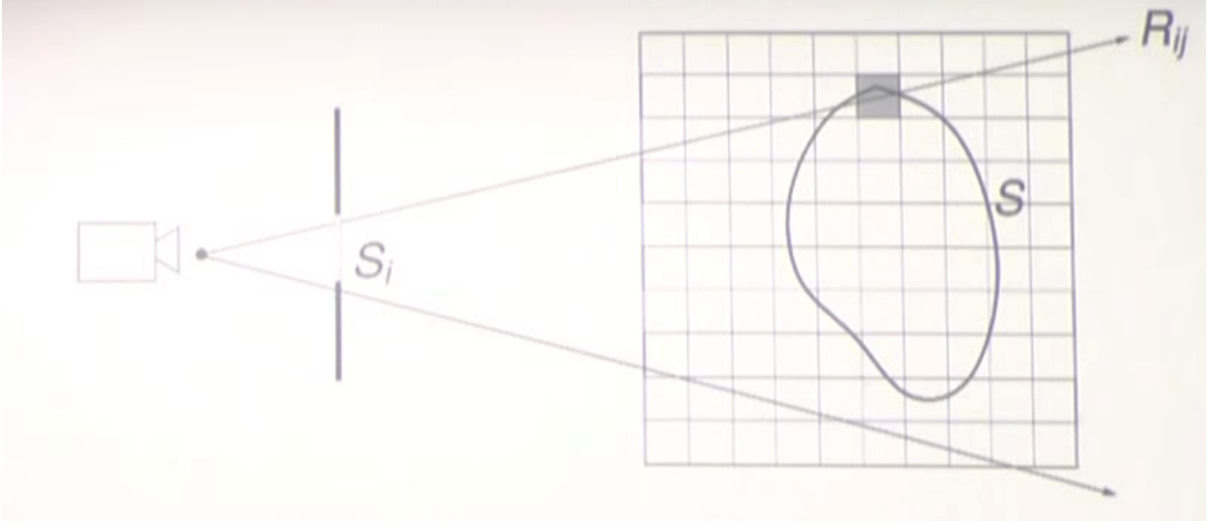
$$\text{s.t. } \int_{R_{ij}} u(x) dR_{ij} \geq 1, \text{ if } j \in S_i \quad (9)$$

$$\int_{R_{ij}} u(x) dR_{ij} = 0, \text{ if } j \notin S_i \quad (10)$$

where R_{ij} denotes the visual ray through pixel j of image i .

Weighted total variation: integral of gradient \rightarrow total variation

2.4 Imposing Silhouette Consistency



Any ray passing through the silhouette must intersect the object in at least one voxel.

Any ray passing outside the silhouette may not intersect the object in any pixel (Cremers, Koles, PAMI 2011)

2.5 Convex Relaxation and Thresholding

By relaxing the binarity constraint on u and allowing intermediate values between 0 and 1 for the function u , the optimization problem (*) becomes convex.

Proposition The set

$$\mathcal{D} := \{u, V \rightarrow [0, 1] \mid \begin{cases} \int_{R_{ij}} u(x) dR_{ij} \geq 1 & \text{if } j \in S_i \forall i, j \\ \int_{R_{ij}} u(x) dR_{ij} = 0 & \text{if } j \notin S_i \forall i, j \end{cases} \right. \quad (11)$$

of silhouette consistent functions is convex.

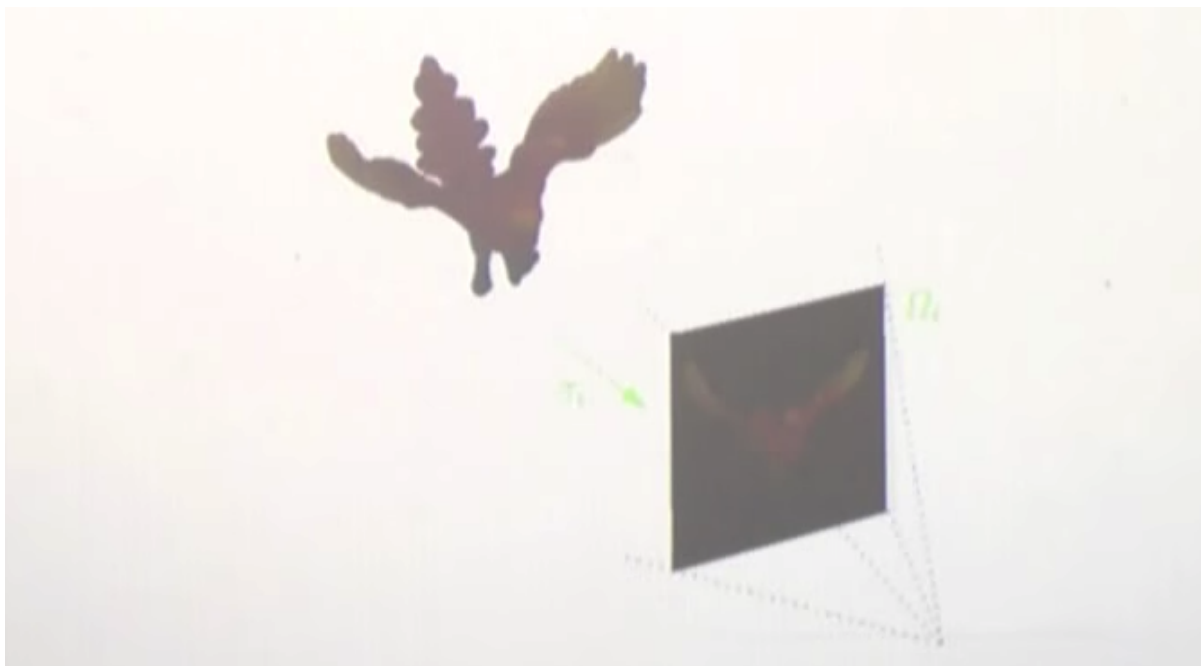
3 Super-resolution Texture Reconstruction

3.1 Multi-view Texture Reconstruction

In addition to the dense geometry S , we can also recover the **texture** $T : S \rightarrow \mathbb{R}^3$ of the object from the images $\mathcal{I}_i : \Omega_i \rightarrow \mathbb{R}^3$. Rather than simply back-projecting respective images onto the surface. **Goldlucke and Cremers ICCV 2009** suggest to solve a **variational super-resolution approach** of the form:

$$\min_{T: S \rightarrow \mathbb{R}^3} \sum_{i=1}^n \int_{\Omega_i} (b * (T \circ \pi_i^{-1}) - \mathcal{I}_i)^2 dx + \lambda \int_S \|\nabla_S T\| ds \quad (12)$$

where b is a linear operator representing **blurring and downsampling** and π_i denotes the projection onto image Ω_i :



What you can do with camera but not with laser scanner:

- Colour
- Illumination information

Laser scanner precision is better and no illumination noise.

3.2 Multi-view Texture Reconstruction

The super-resolution texture estimation is a convex optimization problem which can be solved efficiently. It generates a textured model of the object which cannot be distinguished from the original:



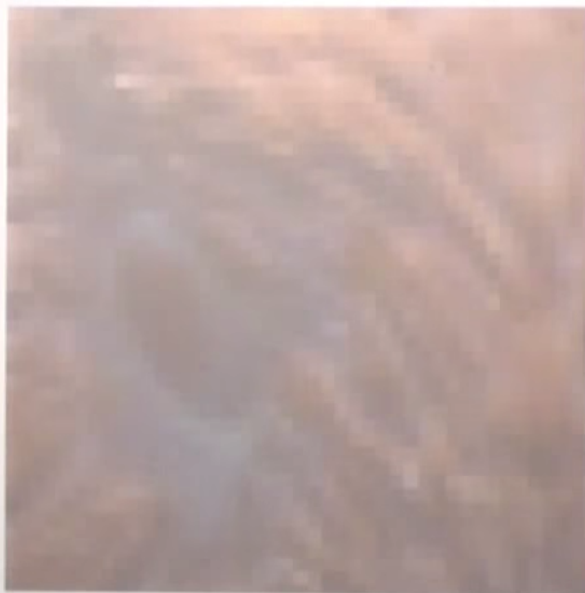
One of 36 input images



textured 3D model

3.3 Multi-view Texture Reconstruction

The super-resolution approach exploits the fact that every surface patch is observed in multiple images. It allows to invert the blurring and downsampling, providing a high-resolution texturing which is sharper than the individual input images:



input image close-up



super-resolution texture

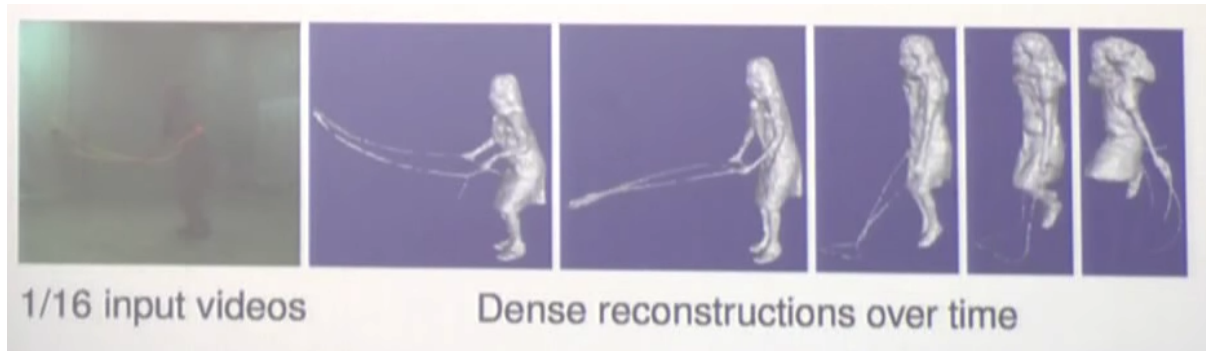
4 Space-Time Reconstruction from Multiview Video

4.1 Space-Time Reconstruction from Multi-view Video

Although laser-based reconstruction is often more accurate and more reliable (in the absence of texture), image-based reconstruction has two advantages:

- One can extract geometry and color of the objects.
- One can reconstruct actions over time filmed with multiple synchronized cameras.

Oswald & Cremers 4DMOD 2013 and Oswald, Stuhmer, Cremers, ECCV 2014, proposed convex variational approaches for dense space-time reconstruction from multi-view video.



4.2 Toward Free-Viewpoint Television

Space-time action reconstructions as done in **Oswald & Cremers 2013** entail many fascinating applications, including:

- For **video conferencing** one can transmit a full 3D model of a speaker which gives stronger sense of presence and immersion.
- For **sport analysis** one can analyze the precise motion of a gymnast.
- For **tree view television**, the spectator at home can interactively chose from which viewpoint to follow and action.