**Computer Vision – Exercise 2**

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**Part A - Hands on Projection and Epipolar Geometry:**

3. The distance is d = 179.7410

4. The COPs are: cop1 = [0,0,0], cop2 = [-178.2218,-18.8171,13.7744]

7. Only the left point (P) is 3D visible point on the object, because it seems that it indicates at the same semantic point.

**Part B – Triangulation:**

We used the points that were given in part A, but we took their [rejection of the image – so the points are:

pL=[203,348;305,314]

pR=[212,291;313,309];

The script that runs the functions is StereoTest.m. It also has an option to manually mark correspondence points (in comment – can be removed).

You can see the results in the attached images – “original points for triangulation” and “stereo results”.

**Part C – Correspondence:**

Since the running tome of this algorithms are long, we’ve added the resulting disparity maps and depth in the folder.

The script that runs the functions is HW2Q3.m.

The assumption of order gives us shorter running time, but causes the results to be more smeared over the x axis.

The results with the order assumption has more errors, because it is not necessarily true.