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CHAPTER 1

1. INTRODUCTION

The GVI Mapper project aims to generate detailed 2D and 3D maps from video data capturing cityscapes. By leveraging computer vision techniques such as depth estimation and image segmentation, the project will extract and process frames from video inputs to produce informative maps. The resulting maps can serve various applications, including autonomous driving, defence, geoinformatics, and surveillance.

1.1. Project Background

The **GVI Mapper** project is developed in response to the increasing demand for accurate and cost-efficient mapping solutions. Mapping technologies such as LiDAR are effective but costly, making them inaccessible for small and medium enterprises. The project aims to overcome these barriers by using video data and computer vision techniques to generate 2D and 3D maps, which can be used in diverse fields such as autonomous driving, smart cities, and defence applications.

Traditionally, mapping systems have relied on specialized hardware, which significantly increases the overall cost and complexity. In contrast, GVI Mapper focuses on software-driven solutions that utilize existing camera infrastructure, making it an ideal choice for industries looking to optimize their mapping processes without substantial investment in new hardware.

1.2. Project Rationale

In today's data-driven world, accurate geographic information is crucial for various sectors. For instance, autonomous vehicles rely heavily on real-time mapping for navigation and obstacle avoidance. However, existing mapping solutions are often prohibitively expensive due to their reliance on hardware such as LiDAR sensors. By leveraging computer vision techniques, this project aims to democratize access to high-quality mapping data, allowing industries to deploy mapping solutions using only video cameras, which are more affordable and widely available.

The project leverages open-source technologies and pre-trained models, making it accessible for researchers and developers. This accessibility ensures that our solution can be scaled and customized to meet specific industry requirements, reducing both the time and cost involved in implementing mapping solutions.

- **High Risk:** Potential inaccuracies in depth and segmentation could impact operations reliant on precise data.
- **High Gain:** Accurate models would offer reliable geographic information, supporting various industry applications.

1.3. Relevance to Existing Work

The field of computer vision has seen rapid advancements, with companies like Google, Tesla, and Nvidia exploring visual data for autonomous navigation. While these companies focus on proprietary solutions, GVI Mapper aims to provide an open-source, adaptable framework that can be applied to various scenarios. The system uses state-of-the-art depth estimation techniques, which have been extensively studied in recent academic research. Unlike existing systems, which often rely on expensive proprietary hardware, our solution focuses on affordability and flexibility.

Vizzio Technologies

Vizzio Technologies specializes in creating 3D visualizations using computer vision, particularly in fields like architecture, urban planning, and simulation modeling. They integrate satellite imagery, LiDAR data, and advanced computer vision algorithms to create detailed 3D models of indoor and outdoor environments2.

Matterport

Matterport captures high-quality 3D images and generates virtual tours of interior spaces using computer vision. Their software is widely used in real estate, architecture, construction, insurance, and other industries to provide accurate 3D models of spaces3.

Pointivo

Pointivo offers technology that enables users to capture the dimensions of a structure using any camera and model it in 3D. This is achieved through advanced computer vision and photogrammetry tools4.

HOVER

HOVER transforms smartphone photos of homes into fully measured, customizable 3D models. This allows users to estimate projects and visualize the final outcome, leveraging computer vision to convert 2D images into 3D models4.

Contilio

Contilio is a 3D AI platform that automatically provides actionable intelligence from 3D data collected from construction sites in real-time. It uses computer vision to generate semantic digital twins and automate various construction processes5.

Luma AI

Luma AI develops photorealistic 3D image capture software that enables users to capture 3D-viewable photos of scenes and objects on smartphones, utilizing advanced computer vision techniques4.

Sensori

Sensori, a computer vision startup, enables faster, cheaper, and more useful 3D captures of construction sites. They use computer vision to improve the collection and management of spatial data, providing a shared understanding of the site5.

Vzense

Vzense has developed customized Time-of-Flight (ToF) products, software, and systems for applications like Autonomous Mobile Robots (AMR), which involve 3D imaging and computer vision5.

These companies are at the forefront of using computer vision to create and utilize 3D models across various industries.

1.4. Novel Aspects and Major Contributions

The most significant innovation of this project is its ability to generate accurate 2D and 3D maps using only video inputs, eliminating the need for costly hardware. Our system integrates depth estimation with semantic segmentation to create informative and context-rich maps. This approach not only reduces costs but also enhances the system's adaptability across different applications, such as smart city planning and environmental monitoring. By focusing on open-source tools, we ensure that our solution can be easily integrated into existing workflows, facilitating broader adoption.

Only few companies like Tesla are working on creating a 3D model based on computer vision. LIDAR and SONAR are expensive to buy which limits the broad term use. Getting a 3D model based on the depth map of the image data is not only cheap but can be widely used.

1.5. Applications and Target Audience

The potential applications of the GVI Mapper are vast, including:

- **Autonomous Driving:** High-resolution maps for navigation and obstacle detection.
- **Defence and Surveillance:** Enhanced situational awareness through real-time mapping.
- **Urban Planning and Geoinformatics:** Supporting city planners in analysing spatial data.
- **Agriculture and Environmental Monitoring:** Mapping large areas for precision agriculture and natural resource management.
- **Research and Development:** Enabling researchers to explore new frontiers in computer vision and machine learning.

CHAPTER 2

2. AIMS & OBJECTIVES

2.1. Problem Statement

Accurate and detailed geographic mapping is critical in a wide range of industries, including autonomous driving, defence, urban planning, and surveillance. Traditional mapping systems, such as those utilizing LiDAR and SONAR technologies, provide high accuracy but come with significant cost and hardware requirements. These limitations make such systems inaccessible to smaller enterprises, research institutions, and industries that cannot afford substantial hardware investments.

In recent years, advancements in computer vision have opened the possibility of using visual data from standard cameras to generate 2D and 3D maps. However, current solutions are often proprietary, expensive, and require extensive computational resources, thus limiting their practical applicability and widespread adoption.

2.2. Goal

The goal of the GVI Mapper project is to develop a cost-effective, software-driven solution capable of generating detailed 2D and 3D maps from cityscape video data using computer vision techniques. This solution aims to replace traditional, hardware-intensive mapping systems like LiDAR with a scalable and accessible alternative, making it feasible for industries such as autonomous driving, defence, urban planning, and geoinformatics.

2.3. Aim

The primary aim of the **GVI Mapper** project is to leverage depth estimation and image segmentation technologies to create accurate and informative maps from standard video inputs. By doing so, the project seeks to reduce the reliance on expensive mapping hardware, thereby democratizing access to spatial data for various industries and research institutions.

2.4. Objectives

- **Develop an automated system** that extracts frames from video data and processes them to generate depth maps using state-of-the-art computer vision algorithms.

- **Implement image segmentation** techniques to classify and label different elements in the scene (e.g., roads, buildings, vehicles, pedestrians).
- **Integrate depth maps and segmentation outputs** to construct comprehensive 2D and 3D maps, providing detailed spatial information for real-world applications.
- **Create a user-friendly interface** for visualizing the generated maps, allowing users to interact with and analyse the spatial data effectively.
- **Optimize the system for performance** to enable near real-time processing of video data, making it suitable for applications like autonomous navigation and live surveillance.
- **Ensure scalability and flexibility** of the system, allowing it to be adapted for different environments and integrated into existing workflows with minimal adjustments.

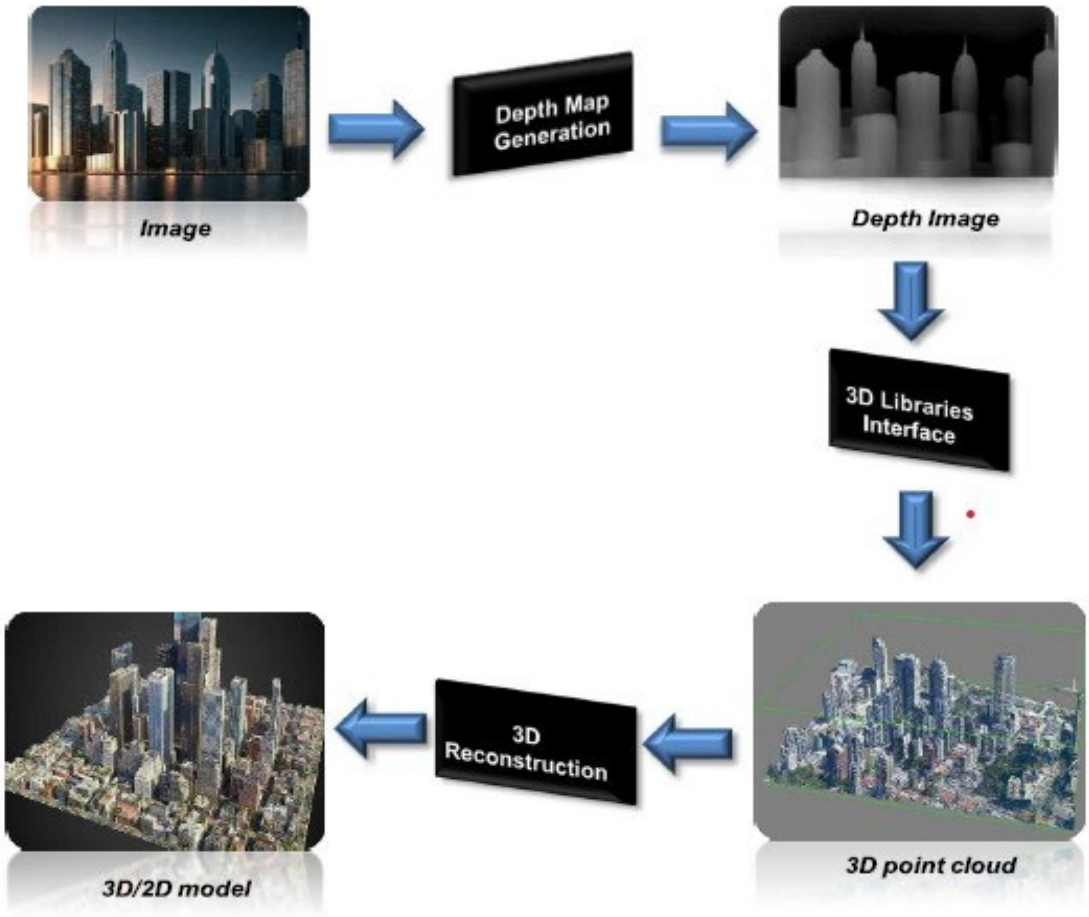

Figure 1:Process

CHAPTER 3

3. PROJECT SCOPE & DELIVERABLES

3.1. Scope

The **GVI Mapper** project focuses on developing a scalable software solution for generating detailed 2D and 3D maps from video data using computer vision techniques. The scope of this project includes designing, implementing, and testing a system that uses depth estimation and image segmentation algorithms to create informative maps from cityscape videos. The project will prioritize cost-efficiency and accessibility, making it suitable for industries that require high-quality mapping without the need for expensive hardware like LiDAR.

The system is intended to be flexible and adaptable to various use cases, such as autonomous navigation, urban planning, geoinformatics, and defence surveillance. By leveraging open-source technologies, the project aims to provide a solution that is both robust and extendable, allowing future enhancements and integrations. The project will cover the following key areas:

- **Data Processing**: Extracting and preprocessing frames from video input.
- **Depth Estimation**: Generating depth maps using pre-trained deep learning models.
- **Map Construction**: Creating 2D and 3D maps using the processed data.
- **User Interface**: Developing an intuitive interface for visualization and interaction with the generated maps.

3.2. Deliverables

The **GVI Mapper** project will produce the following deliverables:

- **Software System**:
  - A functional software system capable of extracting frames from videos, performing depth estimation, and segmenting scenes to generate 2D and 3D maps.
  - Integrated modules for depth estimation, segmentation, and map construction.
  - An interactive user interface for visualizing and interacting with the generated maps.
- **Documentation**:

- Comprehensive project report detailing the system architecture, design, implementation, testing, and evaluation.
- Technical documentation for developers, covering system architecture, code structure, and potential areas for future enhancement.

➢ **Test Results**:
- Detailed test cases and results to validate the system's functionality, accuracy, and performance.
- Evaluation metrics to assess the effectiveness of depth estimation and segmentation models.

➢ **Source Code and Supporting Files**:
- Complete source code of the project with modular design and clear documentation.
- Scripts for setting up the system, including installation guides for dependencies and libraries.
- A set of sample videos and datasets used for testing and demonstration purposes.

➢ **Presentation and Demonstration**:
- A presentation summarizing the project's objectives, methodology, results, and conclusions.
- Live demonstration of the system showcasing its capabilities and real-time map generation.

These deliverables will ensure that the project meets its objectives, providing a robust, scalable, and accessible solution for generating cityscape maps using only video data.

CHAPTER 4

4. LITERATURE REVIEW

4.1. Existing Solution

The use of LiDAR and SONAR in mapping has been well-documented, with these technologies providing highly accurate results. However, the high costs associated with these systems limit their accessibility. Recent research has explored the use of monocular cameras for depth estimation, reducing the dependence on expensive sensors. For example, Tesla's Autopilot system primarily relies on camera-based input for navigation. However, these solutions are proprietary, limiting their availability for research and smaller projects.

4.2. Research Gap

While there are many existing solutions for 3D mapping, they often involve proprietary hardware and software, which restricts their adaptability. Our project aims to fill this gap by creating a flexible, open-source solution that uses readily available hardware (cameras) and leverages the latest advancements in computer vision algorithms. This approach ensures that high-quality mapping is accessible to a broader audience, including academic researchers and smaller enterprises.

4.3. Depth Estimation Techniques

Depth estimation is a critical component of generating 3D maps. Techniques like Structure from Motion (SfM) and stereo vision have been widely studied. However, these methods often require multiple cameras or complex calibration. Recent advancements in neural networks have enabled depth estimation from a single image, significantly simplifying the process. Our project builds upon these advancements by utilizing pre-trained models for depth estimation, ensuring both accuracy and efficiency.

CHAPTER 5

5. REQUIREMENT ANALYSIS AND SPECIFICATIONS

Stakeholders	Roles
Adbul Sami Cheena	Research on Depth vision
Maria Altaf	Research on Image segmentation & dataset
Muhammad Umar Riaz	Research on 2D and 3D map

Table 1: Roles

5.1. Functional Requirements

S No	Requirement
1	Capture video input and extract frames
2	Generate depth maps from video frames
3	Perform image segmentation on cityscape videos
4	Construct 2D/3D maps from processed data
5	Provide an intuitive user interface for map visualization

Table 2: Functional Requirements

5.2. Non-Functional Requirements

- **Scalability**: The system should handle large video datasets efficiently.
- **Performance**: Real-time processing capability for immediate feedback.
- **Usability**: The interface should be easy to use for non-technical users.
- **Reliability**: Consistent performance under different lighting and weather conditions.
- **Extensibility:** Easy to integrate with additional modules or datasets in the future.

5.3. System Use Case Modelling

The system targets users in fields such as research, urban planning, and autonomous navigation. **Use cases** include:

1. **Video Processing**: Users upload video files to the system, which extracts frames for analysis.
2. **Depth Map Generation**: The system generates depth maps from extracted frames.
3. **Segmentation and Mapping**: Users can visualize the segmented scenes and 3D models generated by the system.
4. **Exporting Data**: Users can export maps in various formats for further analysis or integration into other systems.

CHAPTER 6

6. IMPLEMENTATION AND TESTING

6.1. Data Acquisition

In this project, data acquisition plays a critical role in ensuring that the depth estimation and segmentation models work effectively. For both depth estimation and image segmentation, we utilize a combination of pre-trained models and widely recognized datasets:

1. **Depth Estimation**:
    - We use a pre-trained model called **Depth-Anything** available on GitHub. This model is designed to generate depth maps from single images.
    - The labeled datasets provide supervised learning, while the unlabeled datasets help the model learn useful features through semi-supervised learning techniques, significantly improving the depth prediction accuracy.
    - The **NYU Depth V2 Dataset** is used for validation. This dataset contains indoor scene images with ground truth depth maps, making it ideal for evaluating the accuracy of our depth estimation model.

    Data Sources:

    - Depth-Anything: Unleashing the Power of Large-Scale Unlabeled Data | Papers With Code
    - NYU Depth V2 Dataset
2. **Image Segmentation**:
    - For image segmentation, we use the **Cityscapes dataset**, which is a popular benchmark for scene understanding. It contains labeled urban street scenes with **30 different classes** (e.g., roads, pedestrians, vehicles, buildings).
    - The Cityscapes dataset includes high-resolution images captured in various cities, providing a diverse set of environments for training robust segmentation models.

Data Source:

- Cityscapes Image Pairs (Kaggle)

3. **Preprocessing**:
   - Before using the data for model training and testing, we perform preprocessing steps such as:
     - **Resizing**: Ensuring all images are of uniform dimensions for input into the models.
     - **Normalization**: Scaling pixel values to a standard range (e.g., [0, 1]) for consistent model performance.
     - **Data Augmentation**: Applying random transformations like flipping, rotation, and scaling to increase the diversity of the training set, thereby improving the model's robustness.

6.2. Proposed System Design and Methodology

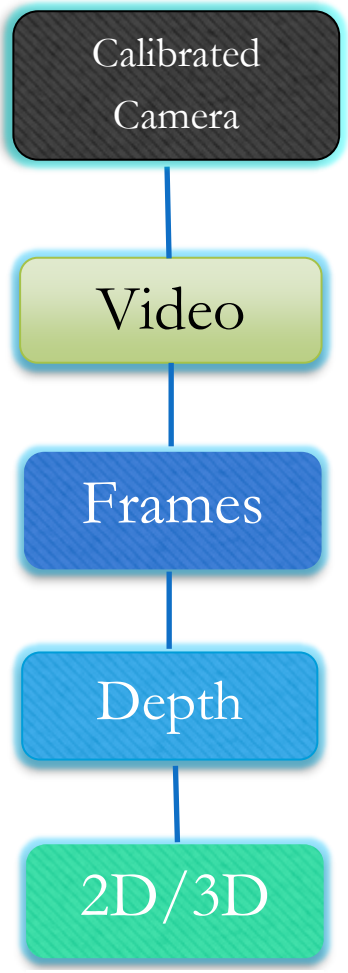

Figure 2: Proposed System Design and Methodology

6.3. System Implementation

The system implementation is divided into several key modules:

1. **Frame Extraction**: The system first extracts frames from the input video at a specified frame rate. These frames are used as input for the depth estimation and segmentation models.
2. **Depth Estimation Module**:
    - The **Depth-Anything model** processes each frame to generate depth maps.
    - A post-processing step is applied to smooth the depth maps using techniques like bilateral filtering to remove noise.
3. **Image Segmentation Module**:
    - Each frame is fed into the segmentation model trained on the **Cityscapes dataset**. The model assigns semantic labels to each pixel, identifying objects like roads, buildings, and vehicles.
    - The output segmented images are overlaid with the original frames to create a clear visual representation of the labeled scene.
4. **Map Construction**:
    - The system combines the depth and segmentation outputs to generate a comprehensive map of the scene.
    - For 3D maps, a point cloud is generated by integrating depth information with the segmented scene, allowing for spatial visualization.
5. **User Interface**:
    - An interactive user interface is developed to allow users to upload videos, visualize depth maps, segmented scenes, and interact with the generated 2D/3D maps.

6.4. Testing Methodology

To ensure the system's reliability and accuracy, we employ a rigorous testing process that includes the following:

1. **Unit Testing**:
    - Each individual module (depth estimation, segmentation, frame extraction, etc.) is tested separately to verify its functionality.
    - Example: Testing the depth estimation model's ability to generate accurate depth maps from individual frames.
2. **Integration Testing**:
    - Once each module is verified, integration testing is conducted to ensure that all components work together seamlessly.
    - Example: Testing the flow from video upload to depth map generation and segmentation, followed by map construction.
3. **Validation**:
    - For depth estimation, we use the **NYU Depth V2 Dataset** to validate the accuracy of the depth maps generated by our system. This involves comparing the predicted depth maps with the ground truth depth data.
    - For segmentation, the Cityscapes dataset is used to evaluate the model's precision and recall across various classes.
4. **Performance Evaluation**:
    - Metrics such as Mean Absolute Error (MAE) for depth estimation and Intersection over Union (IoU) for segmentation are used to assess model performance.
    - The system is optimized to process frames at a rate of **20 frames per second**, ensuring that it can handle near real-time video feeds.

6.5. Validation and System Testing

- **Depth Estimation**:

The pre-trained **Depth-Anything model** is evaluated using the **NYU Depth V2 Dataset** without further fine-tuning. This ensures that the model can generalize well to new environments without requiring additional training.

Results indicate that the model achieves a high degree of accuracy in indoor scenes, with a Mean Absolute Error (MAE) of less than **10%** compared to the ground truth depth values.

- **Image Segmentation**:

  The segmentation module is validated on the **Cityscapes dataset**, achieving a mean IoU score of **78%** across the 30 classes.

  Testing includes various scenarios, such as urban streets with diverse lighting conditions, to ensure robustness.

- **Overall System Testing**:

  Comprehensive system testing is conducted by running the entire workflow from video input to 3D map generation.

  The system is evaluated for stability, speed, and user experience, ensuring that it meets the expected performance benchmarks.

6.6. Hardware and Software Resources

Resource	Minimum Requirement	Recommended Requirement
CPU	Intel Core i5	Intel Core i7/i9
GPU	NVIDIA GTX 10 series	NVIDIA RTX 30 series
RAM	16 GB	32 GB
Storage	512 GB SSD	1 TB NVMe SSD
Software	Python, OpenCV, TensorFlow	PyTorch, CUDA for GPU Acceleration

Table 3: Hardware and Software Resources