Report goal: Provide report describing method, implementation, “proof” of correctness, and performance of the method

# Introduction

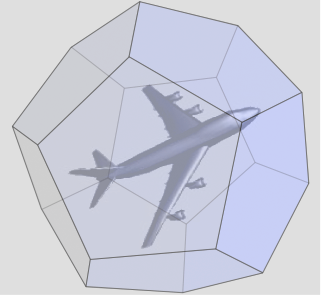
Most 3d similarity methods focus on similarity of geometric distributions of models rather than searching on visual similarity. In this paper we use an approach that uses the visual similarity of models to compare and compute the distance between these models. This method focuses more on the visual perception of 3d models by humans.

# Method overview

The main idea of comparing models based on visual similarity is explained by the following quote: “If two 3D models are similar, they also look similar from all viewing angles”. So essentially, the similarity of two 3D models can be defined by summing up the similarity of all viewing angles. However, sometimes 3D models are translated, rotated or scaled. In order to compare 3D models that are transformed using visual similarity, we use lightfield descriptors.

## Lightfield descriptors

A lightfield descriptors is in short: a 4D representation of a 3D model using 2D images. Basically, these 2D images are rendered from an array of camera’s which are distributed uniformly around the 3D model. With this render, all lights are turned off so that only silhouettes remain . The 3D model is now represented by a list of 2D image silhouettes. Due to performance limitations, the number of 2D images that represent the 3D model cannot be too high. Therefore we distribute the camera’s on vertices of a regular dodecahedron, which has exactly 20 vertices. From these 20 vertices, there will be 10 unique rendered images. This is because in a dodecahedron all vertices will have another point lying exactly on the other side of the model. This will result in the same silhouette of the 3D model, only rotated. Therefore these images are not used, which leaves 10 images per lightfield.

  
  
Sets of lightfields

A 3D model is not described by one lightfield, but by a set of lightfields in order to improve robustness against rotations of 3D models. Some models might be rotated around the axis, which will result in different silhouettes if only one lightfield is used. Therefore we use multiple lightfields which have a slightly rotated dodecahedron. All these lightfields have 10 images which contain the visual information of the model. Comparing two models based on sets of lightfields is now a problem of comparing sets of lightfields of each model against each other. The minimum distance between two models is the smallest distance between any lightfield of one model against each other.

## Image processing

In order to compare two lightfields, 2D images have to be compared. The comparison has to be robust against rotation, transformation and image distortion. To best achieve this we extract feature vectors from the image which are transformation invariant. These feature vectors can be classified into region-based and boundary-based descriptors. Region based feature vectors can be computed by a Zernike transform. The result is a vector that describes the region features of a 2D image but neglects shape information. Boundary based descriptors can be computed by doing a Fourier Transform on the boundary of the shape. This results in a vector that describes the shape of a 2D image but ignores region information. It is shown(link) that if both vectors are combined, the comparison function performs better then situations where the vectors are used individually. Therefore we use a combination of both Zernike and Fourier feature vectors to represent the image. Now the distance between two images can be defined simply as computing the Euclidian distance between the combined feature vectors of both images.

### Zernike transform

Zernike complex moments are constructed using a set of Zernike polynomials. Zernike polynomials are a sequence of orthogonal polynomials on the unit disk and they can be expressed as (Weizhuo Wanga, 2008)

where , *n* is the order of the radial polynomial and *m* a positive and negative integers subject to constrains even, , representing the repetition of the azimuthal angle. From *x* and *y* we obtain and by simple conversion to polar coordinates. The radial polynomial is defined as

From the definition itself we can see that . We will use this property later in the implementation. As we are concerned only with calculating the Zernike moments for a digital image we will skip directly to the formulation of the moments in adequate form

With rotation by an angle we get and by simply substituting that into the equation we get

and

Which indicates that the modulo of the rotated image is the same as the original, thus using the modulo as a feature descriptor will yield rotation invariance and make the method more robust. As suggested by the original paper we use 36 unique coefficients from the Zernike moments up to order 10.

### Fourier transform

The Fourier transform uses boundary information to compute the feature vector. First the boundary of the silhouette has to be found. Then, we can compute the center of mass of the boundary points. We simply take the average of all x and y coordinates and define the result as the x and y center of mass. Then, the boundary can be traced and the distance from the boundary point to the center of mass can be computed. The resulting list is a 1 dimensional function that describes the boundary of the object. This list is rotation invariant because we only took the distance to the boundary in account, not the actual coordinates.

Now a Discrete Fourier Transform is computed with the 1D signal as input. The Fourier transform will result in a number of coefficients that describe the input signal as a combination of frequencies. When all frequencies are added together the 1D input signal will appear again. The lower coefficients describe overall features of the shape whilst the higher coefficients describe more precise features of the shape. We use only a set of lower coefficients to represent an image because we are only interested in comparing global features of a shape. Furthermore the coefficients are normalized to make the Fourier Transform scale invariant. To compare two sets of Fourier coefficients we can use the Euclidian distance.

### Comparing Two 3D models

As previously stated we use multiple lightfields to account for different orientations of the models. The measuring of the dissimilarity (distance) between two models is done by comparing all the lightfields from the first model with all the model of the second model and taking the orientations with minimal distance.

### Two lightfields

Each image is now described by a set of Fourier and Zernike descriptors which have been computed from the 2D images. These two sets of descriptors can be combined using the following function:

*fz={α·FD1, α·FD2, ... , α·FDm, β·z1, β·z2, ... ,β·zn }*

Alpha and beta are weighting factors for both descriptors. The resulting descriptor describes the 2D image. Comparing two descriptors is as simple as taking the Euclidian distance. Now a lightfield consists of 10 of those descriptors. While the image metric itself is rotation invariant in image space, we do have to take into account the different possible orientation of the model relative to the dodecahedron used for the lightfeild. For all lightfields the images have been rendered in the same order from the different vertices on the dodecahedron. The distance between two lightfields is defined as the best of the 60 possible, 20 vertices each with three neighboring vertices, orientations

Where are the corresponding images under the *i*-th rotation.

# Implementation

Our programs are written in C# (.NET) and we use a couple of shell scripts to execute these programs. There are 3 different programs.

The first program renders the lightfield descriptors using Direct X (XNA). This offloads the rendering to the GPU of the computer which speeds up the process. This program is called using a shell script which iterates through the model directories and computes 10 images for 10 lightfields.

The second program computes the Zernike and Fourier descriptors of each image and stores the result in the model directory. This program uses the basenames file to iterate through the model directory.

The third program computes the distance between all 3D models in the model s directory. It takes one model and then computes the distance to every other model in the models directory and stores this. Every model is iterated.

## Rendering

The rendering of the models is done in hardware using the XNA platform. The mesh is created as a pair of vertex buffer and index buffer on the GPU. We have already seen that the method does a lot of work to make the distance measure as rotation invariant as possible, so explicit normalization of the model is not necessary. Nevertheless the translation and scaling should be handled in some way. The centroid of the model is used as pivot for all the rotations, so carefully picking it is very important for the robustness of the whole system. The centroid of the model is calculated from its surface, taking the area of each triangle into account. This method gave much better results than using the average all the vertices, which can be biased towards areas modeled with higher detail. As previously stated we would like to use 10 images for the 20 points of view, for exactly this reason we use orthographic projection. The projection is simply constructed to fit the model into the disk in the center of the image, implicitly handling uniform scaling. While this doesn’t use the whole resolution of the image, it enables the whole shape to be used for the calculation of the Zernike moments.

The ten different orientations are calculated by creating a random vector, uniformly distributed over the unit sphere, and forming an orthonormal basis using the vector. As models are often modeled in a similar manner, we keep the first orientation to the original unrotated. In addition, for easier debugging we use pseudo random orientations, so that we get the same orientations for each model in consecutive runs.

Each time frame is used to render a single image in the back-buffer, with size 256x256 as suggested by the original paper, later resolved to a texture and saved to disk. This makes rendering extremely fast.

## Zernike Transform

### Implementation

Blablab

### Proof of correctness

Proof

### Performance

Perf

## Fourier Transform

### Implementation

Impl

### Proof of correctness

Proof

### Performance

Perf

## Comparison

### Implementation

Impl

### Proof of correctness

Proof

### Performance

Perf

# Conclusion

References

# Bibliography

Weizhuo Wanga, J. E. (2008). Mode-shape recognition and finite element model updating using the Zernike moment descriptor.