Mathematical Principles in Visual Computing

Prof. Friedrich Fraundorfer

SS 2022

About me

- Assoc. Prof. Dr. Friedrich Fraundorfer
- Email: fraundorfer@icg.tugraz.at
- Institute of Computer Graphics and Vision
- Inffeldgasse 16/II
- +43 (316) 873 - **5020**
- Send email to schedule an appointment

Additional lecturer

- Assoc. Prof. Dr. Markus Steinberger
- Email: steinberger@icg.tugraz.at
- Institute of Computer Graphics and Vision
- Inffeldgasse 16/II

Lecture schedule

- 02.03.2022 Fraundorfer
- 09.03.2022 Fraundorfer
- 16.03.2022 Fraundorfer
- 23.03.2022 Fraundorfer
- 30.03.2022 Fraundorfer
- 06.04.2022 Fraundorfer
- 27.04.2022 Fraundorfer
- 04.05.2022 Fraundorfer
- 11.05.2022 Fraundorfer
- 18.05.2022 Fraundorfer
- 25.05.2022 Fraundorfer
- 01.06.2022 Steinberger
- 08.06.2022 Steinberger
- 15.06.2022 Steinberger
- 22.06.2022 Steinberger
- 29.06.2022 Exam

Tutor

- Christian Sormann
- Email: christian.sormann@icg.tugraz.at
- Responsible for questions about classroom assignments
- Q&A slots with tutor
- Q&A in TC forum or e-mail

Course grading

- 3 class room assignments (50% of grade)
  - Math problems
  - Small programming assignments
- Final written exam (50% of grade)

- Written exam at last lecture slot (29 June 2022)
- Submitting the first assignment counts as attempt. A grade will be issued in this case.

- *"§ 22 para. 4: In order to assist students in completing their degrees in a timely manner, all courses with continual assessment must allow students to submit, supplement or repeat in any case at least one partial course requirement to be determined by the course director, by no later than four weeks after the course has ended."*
- This one course requirement is the examination.

Assignments

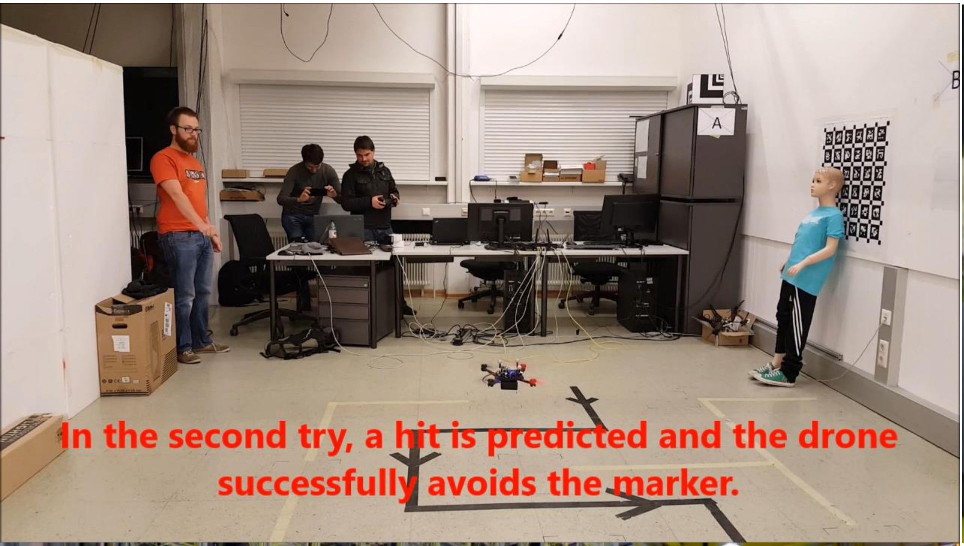
- Individual work, no group work
- Electronic submission using the TeachCenter (Hand-writing and scanning is ok)

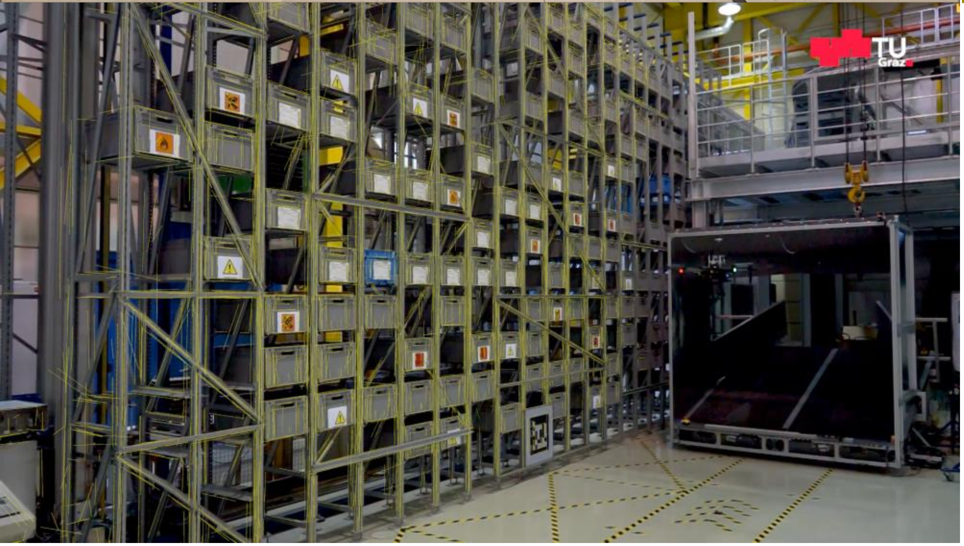
- Schedule:
  - Assignment 1
    - Handout: 16.3.2022
    - Deadline: 3.5.2022
  - Assignment 2
    - Handout: 4.5.2022
    - Deadline: 31.5.2022
  - Assignment 3
    - Handout: 1.6.2022
    - Deadline: 28.6.2022

Lecture material

- Slides are the main material
- Links to relevant publications and book sections will be given
- Lecture recordings from last year are available in the Teach Center

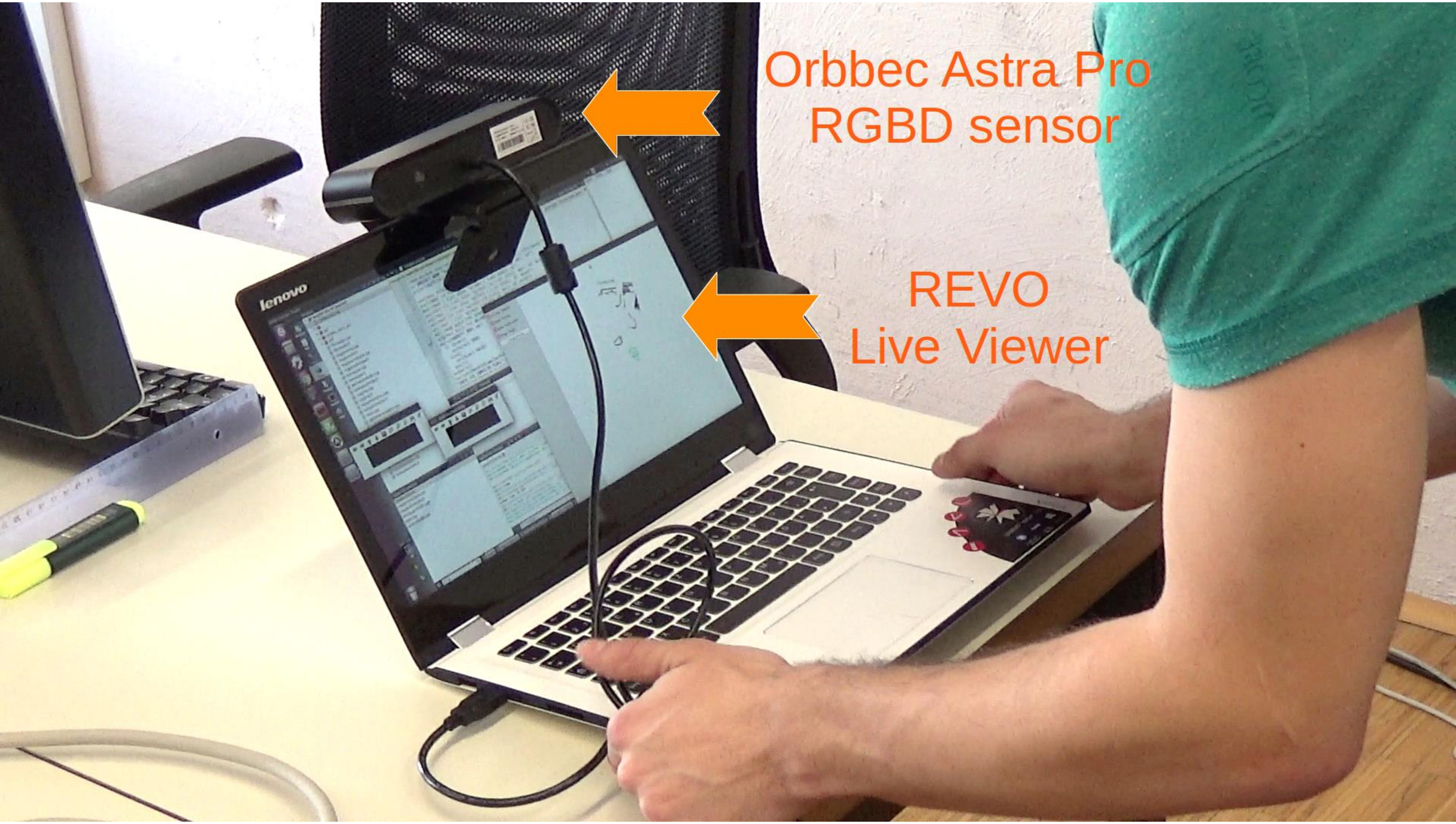
Research areas



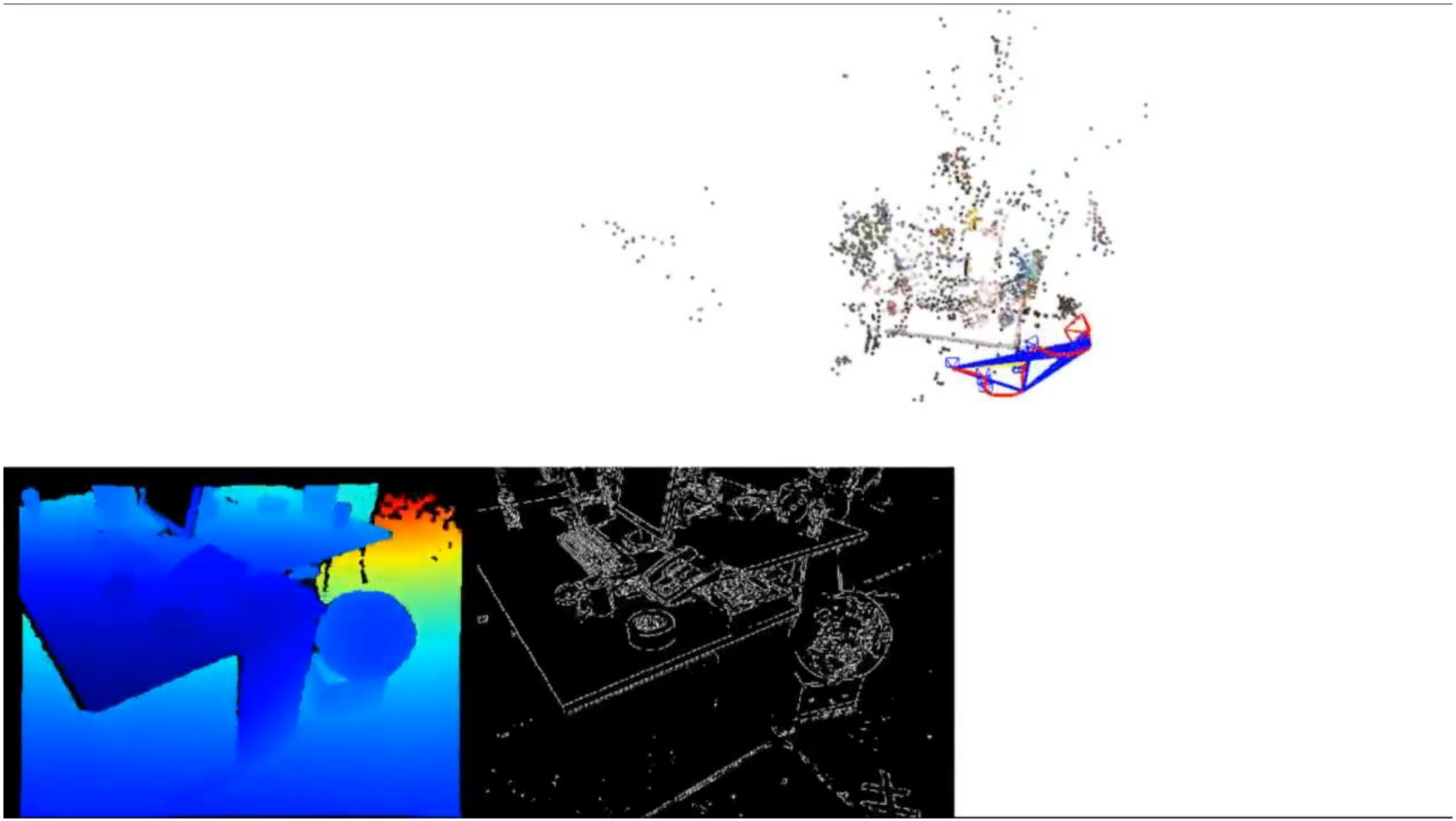


3D scanning - REVO

- RGBD recordings with Orbbec Astra Pro

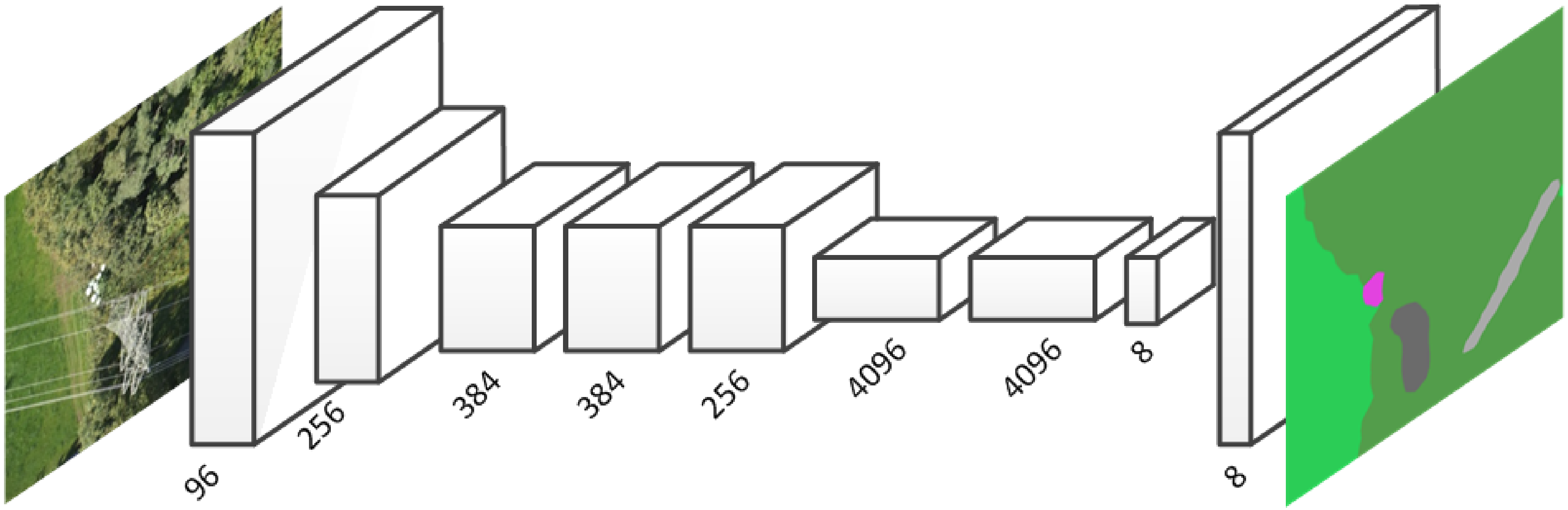


3D scanning - REVO

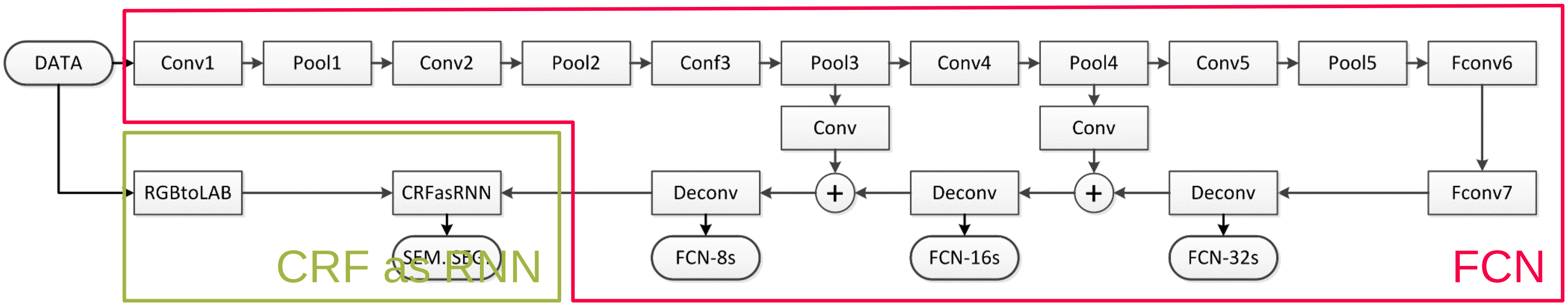


Semantic 3D

Semantic 3D

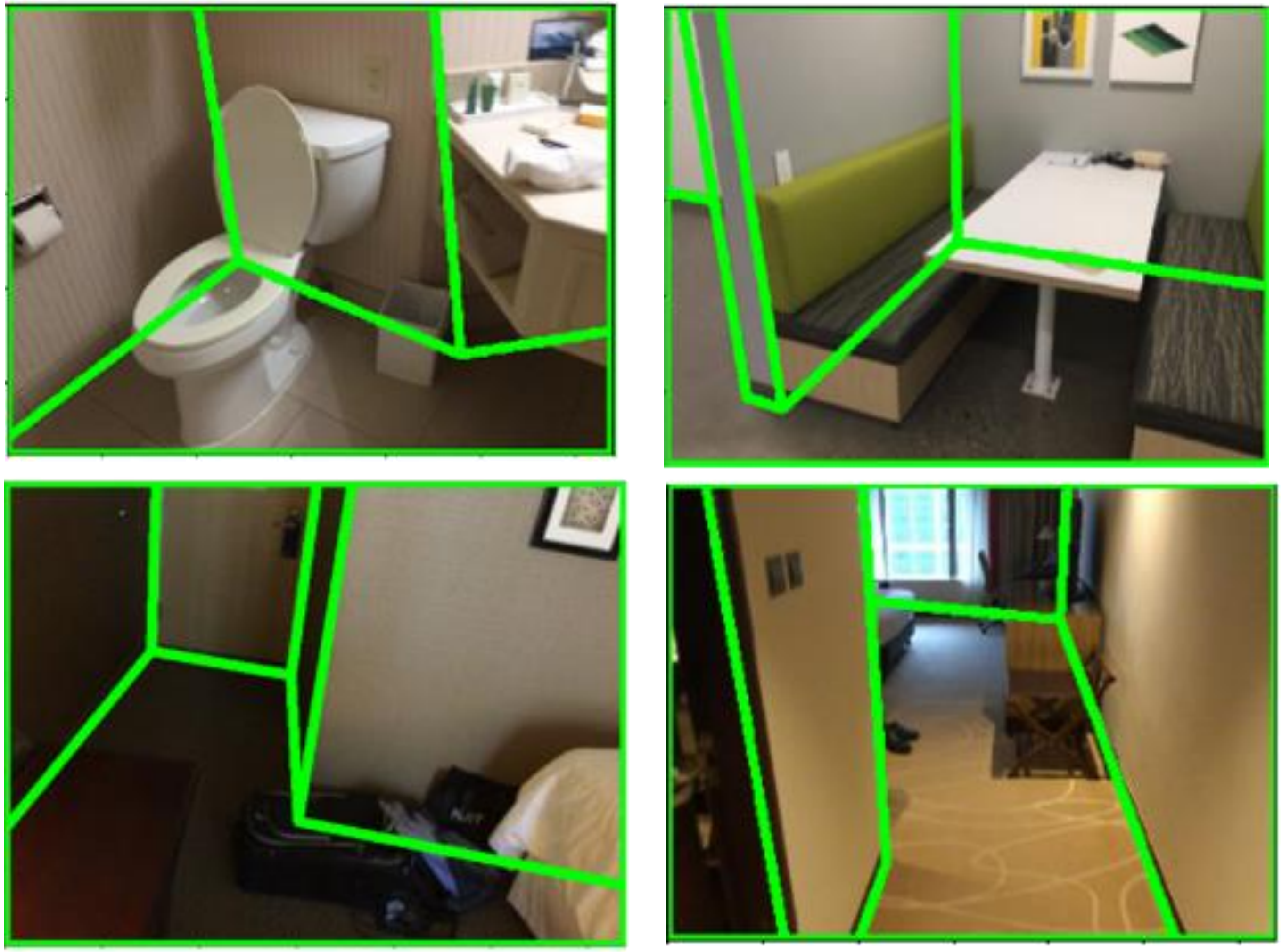


96
256
384
384
256
4096
4096
8
8



DATA
Conv1
Pool1
Conv2
Pool2
Conf3
Pool3
Conv4
Pool4
Conv5
Pool5
Fconv6
Conv
Conv
RGBtoLAB
CRFasRNN
Deconv
+
Deconv
+
Deconv
Fconv7
SEM. SEG
FCN-8s
FCN-16s
FCN-32s
CRF as RNN
FCN

Single image room layout estimation



General 3D Room Layout from a Single View by Render-and-Compare. Sinisa Stekovic, Shreyas Hampali, Mahdi Rad, Sayan Deb Sarkar, Friedrich Fraundorfer, Vincent Lepetit
https://github.com/vevenom/RoomLayout3D_RandC

Single image room layout estimation

Embedded AI – Dedicated processors allow integration of deep learning

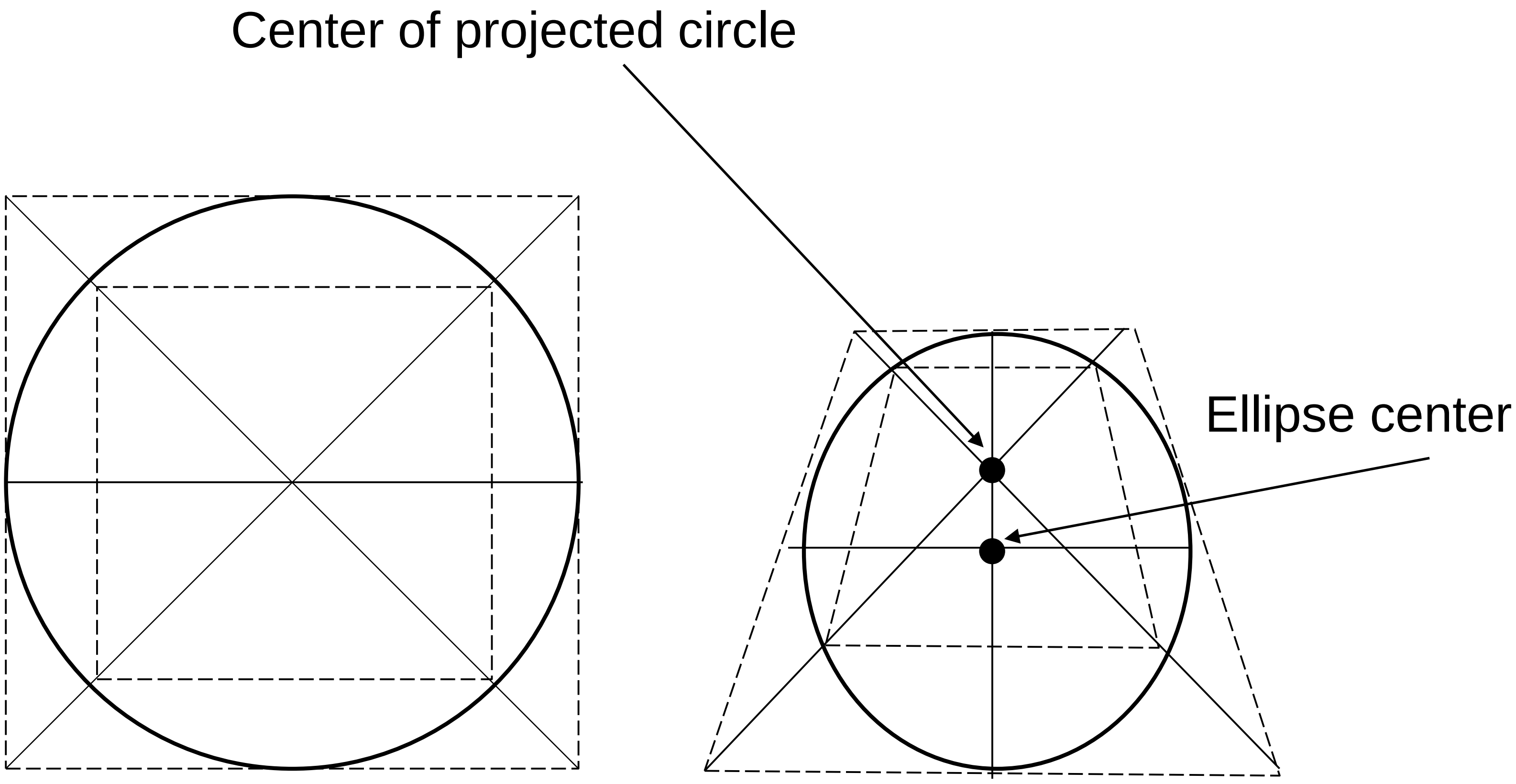
Embedded AI – Object detection

Topics

- Projective geometry
- Geometry of multi-view camera system
- Parameterization of rigid transformations
- Robust estimation (Ransac, Robust cost functions)
- Polynomial systems in computer vision
- Root-solving
- Projective geometric algebra (Steinberger)
- Mesh Matrix Basics (Steinberger)

Projective geometry

Projective geometry

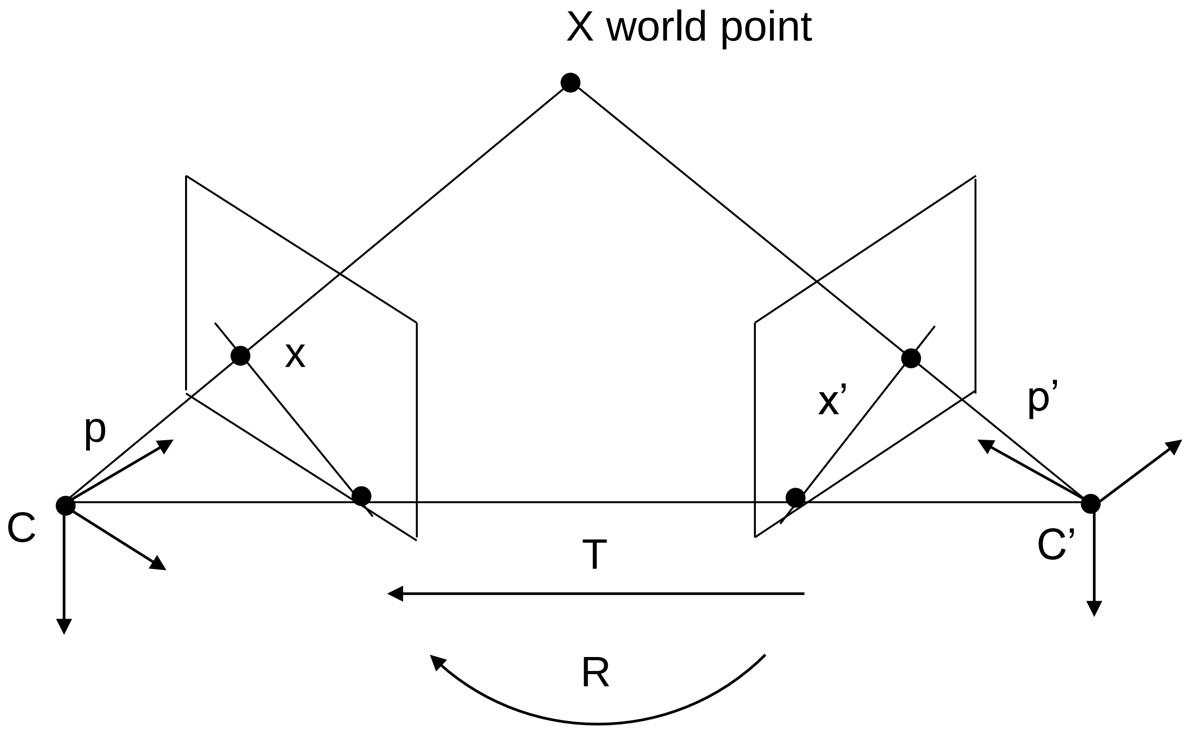


2D circle

Circle after projective transformation

Projective geometry

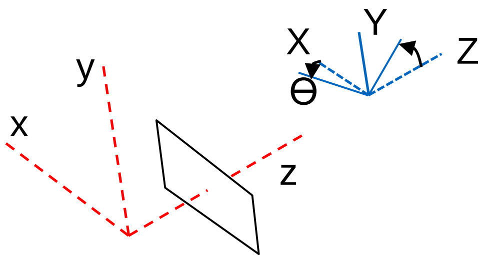
$$x'^T F x = 0 \quad \ldots \textit{Epipolar constraint}$$

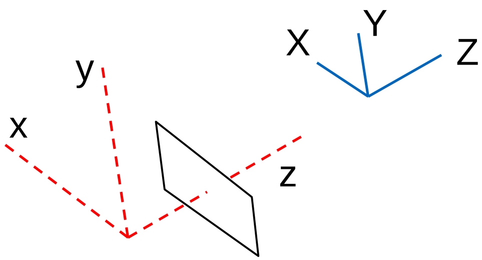


Projective geometry

before rectification

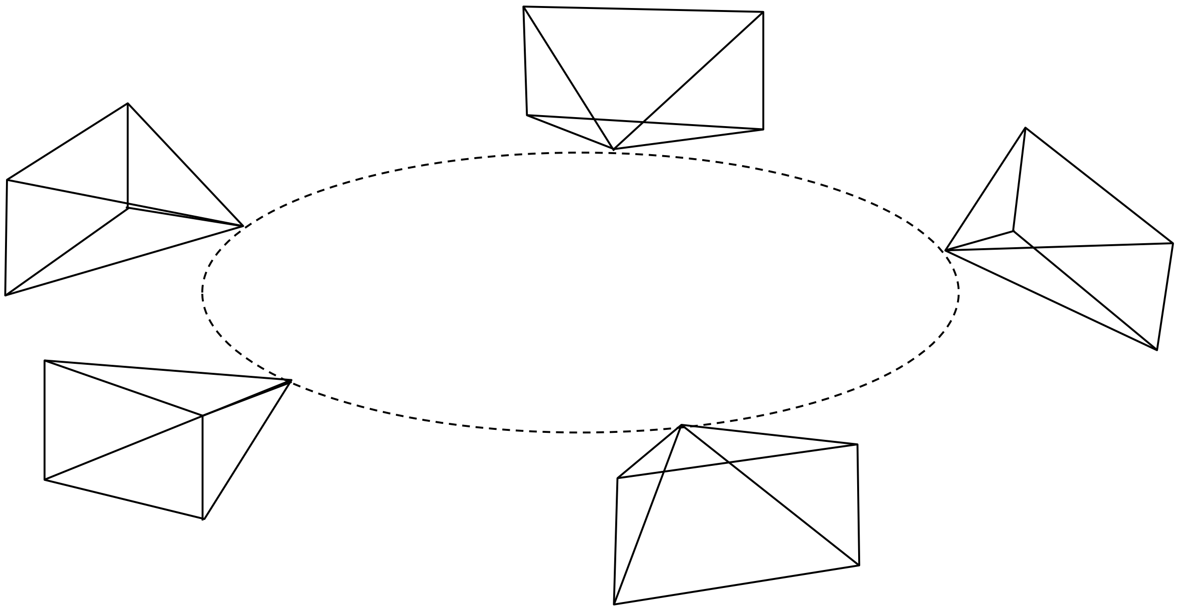
after rectification





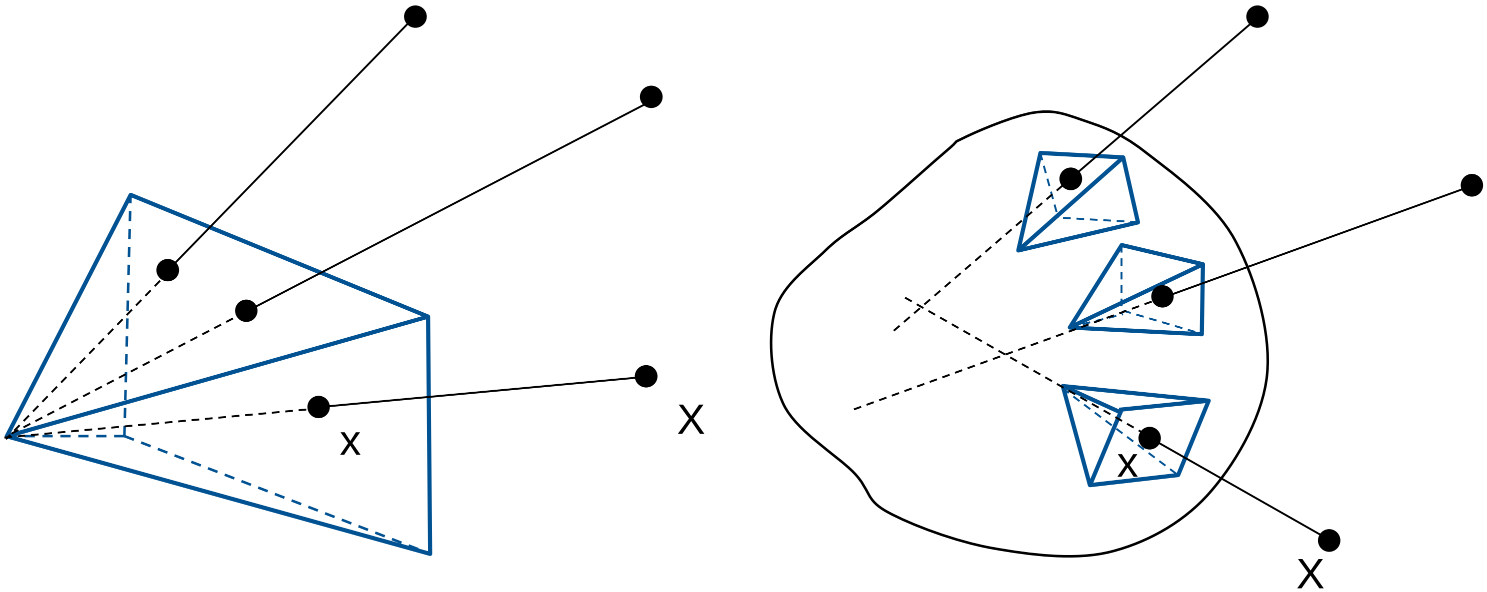
Geometry of multi-view camera system

$$l'^T E_G l = 0 \quad \textit{... generalized Epipolar constraint}$$



Geometry of multi-view camera system

Geometry of multi-view camera system



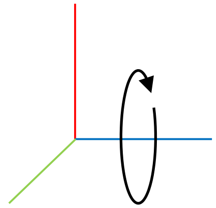
pinhole camera

generalized camera

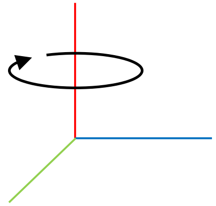
Hololens is a multi-camera system

Parameterization of rigid transformations

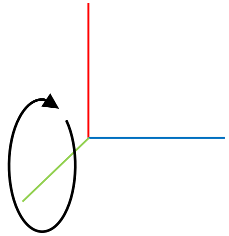
$$R_x(\alpha) = \begin{bmatrix} 1 & 0 & 0 \\ 0 & \cos\alpha & -\sin\alpha \\ 0 & \sin\alpha & \cos\alpha \end{bmatrix}$$



$$R_y(\beta) = \begin{bmatrix} \cos\beta & 0 & \sin\beta \\ 0 & 1 & 0 \\ -\sin\beta & 0 & \cos\beta \end{bmatrix}$$

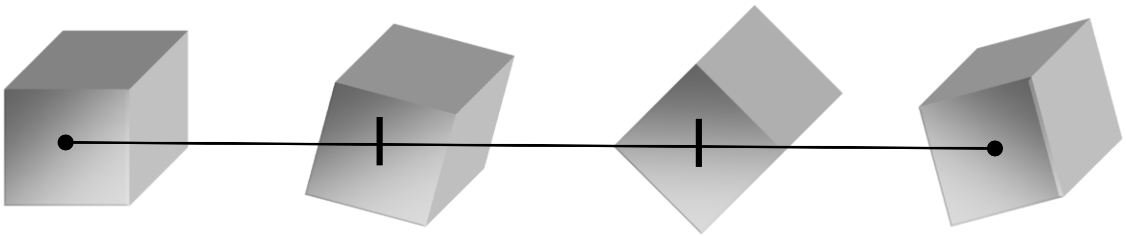


$$R_z(\gamma) = \begin{bmatrix} \cos\gamma & -\sin\gamma & 0 \\ \sin\gamma & \cos\gamma & 0 \\ 0 & 0 & 1 \end{bmatrix}$$



Problems with rotation matrices

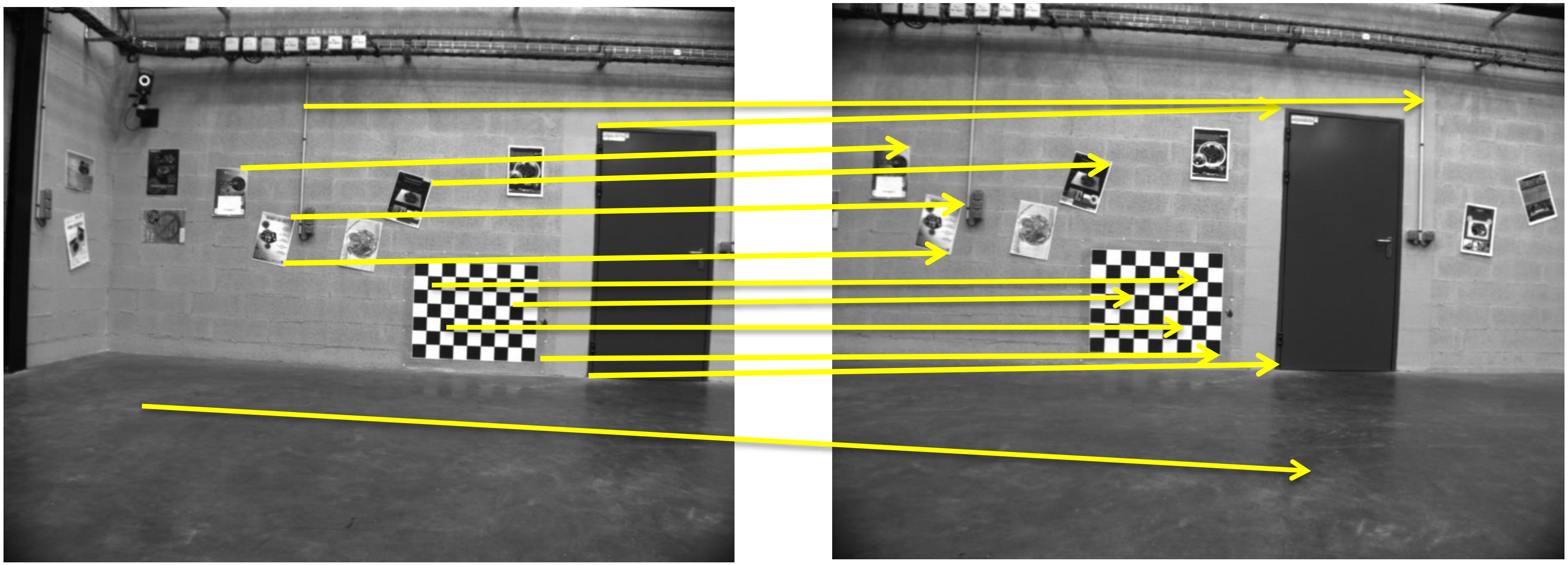
- Optimization of rotations (bundle adjustment)
  - Newton's method $x_{n+1} = x_n - \frac{f(x_n)}{f'(x_n)}$
- Linear interpolation



- Filtering and averaging
  - E.g. averaging rotation from IMU or camera pose tracker for AR/VR glasses

Robust estimation

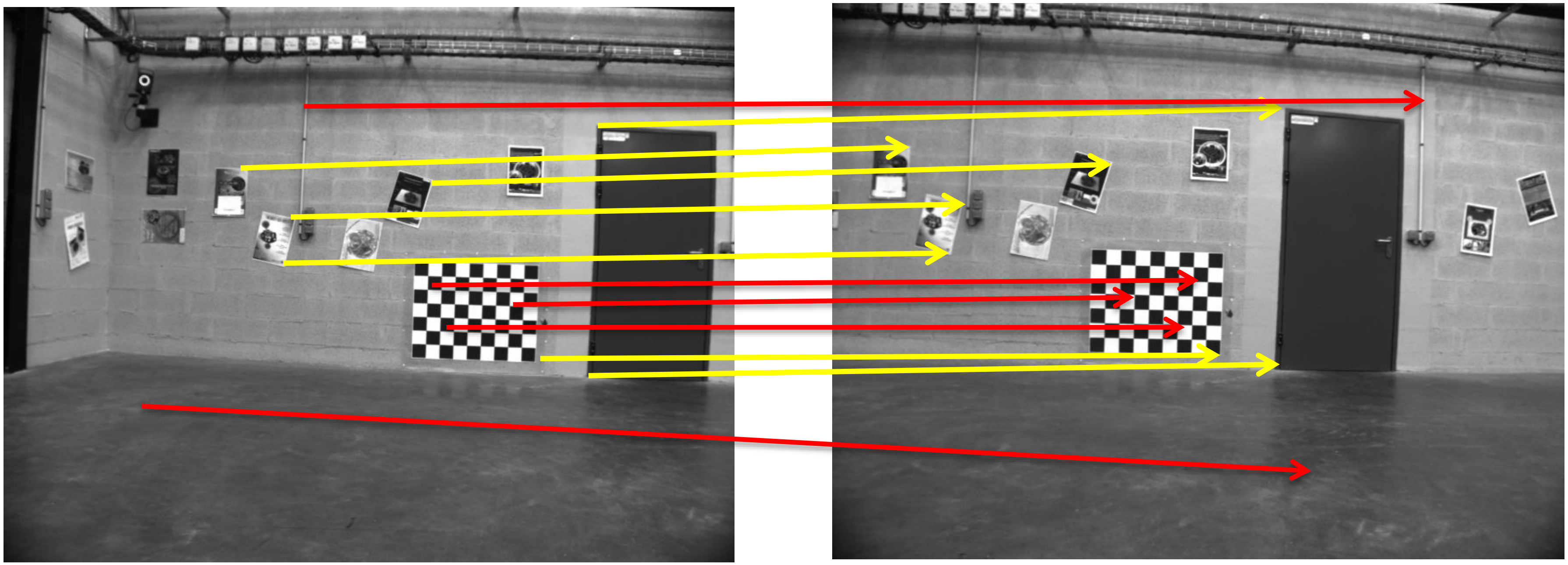
- Motion estimation needs to be robust against mismatches



Yellow: automatically generated image matches
(contain mis-matches)

Robust estimation

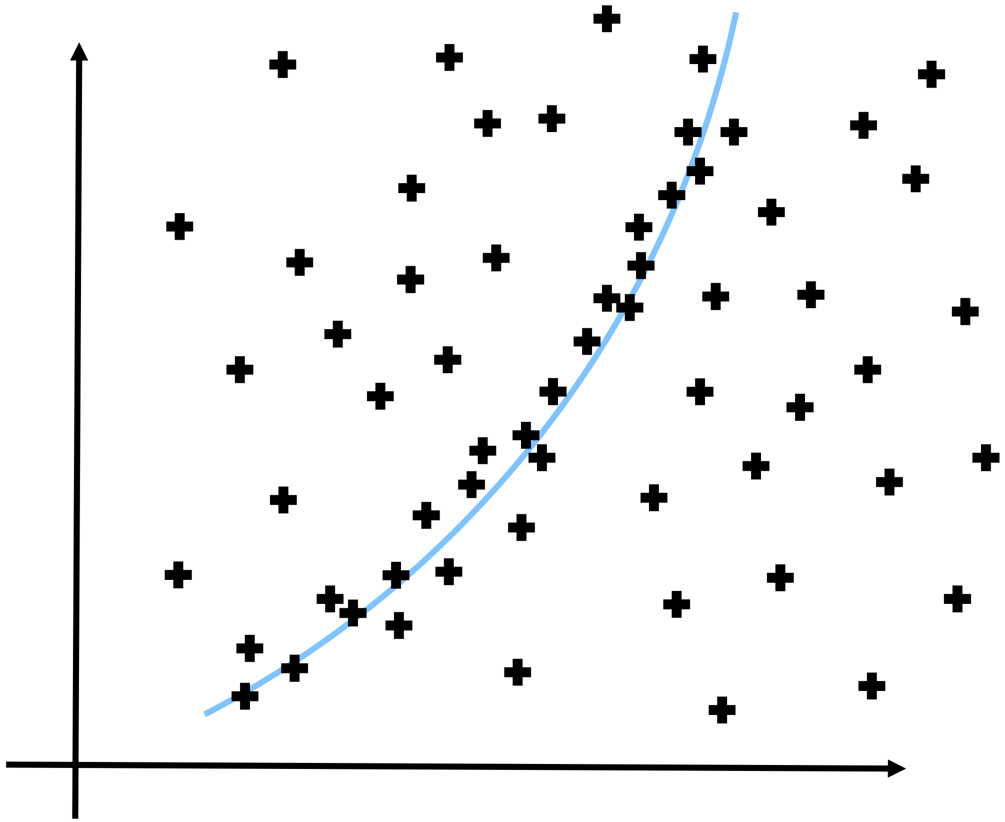
- All feature matches need to follow the same motion



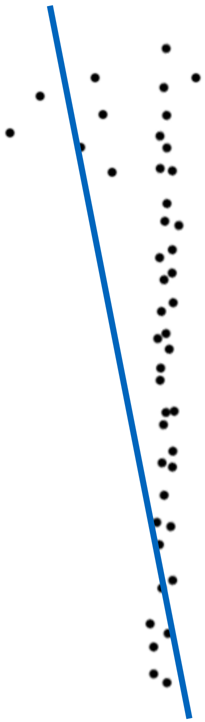
Yellow: correct matches
Red: incorrect matches.

Robust estimation

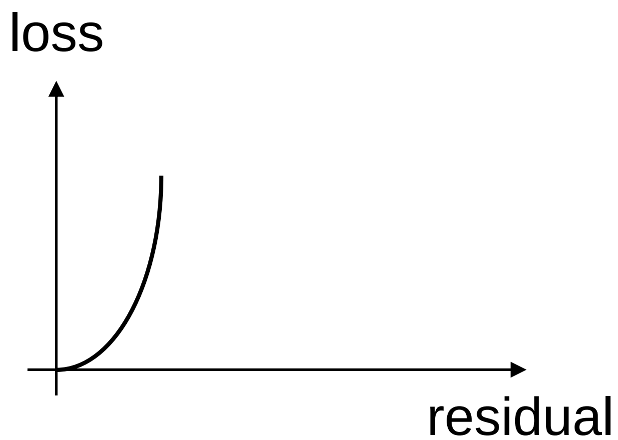
- Ransac – Random sample consensus



Robust estimation



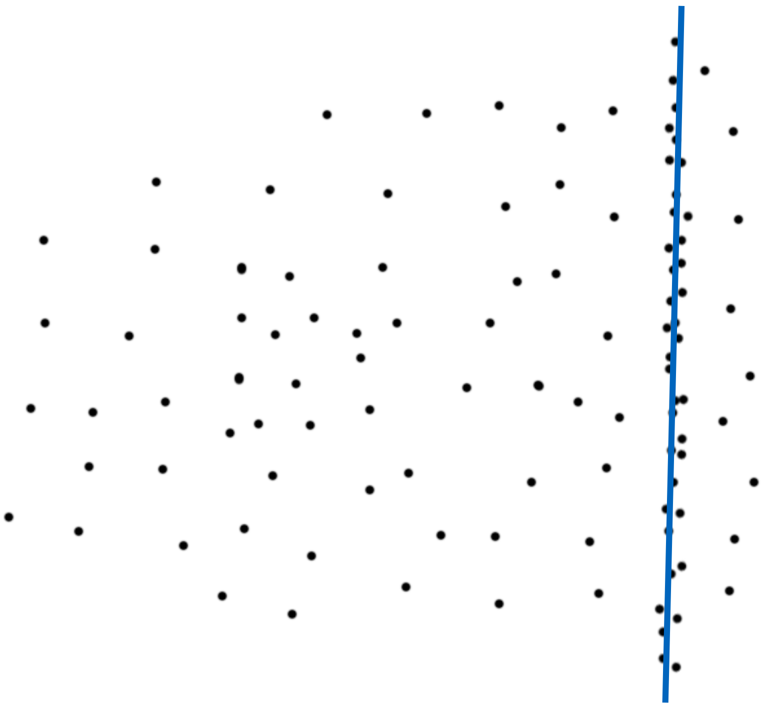
L2 solution

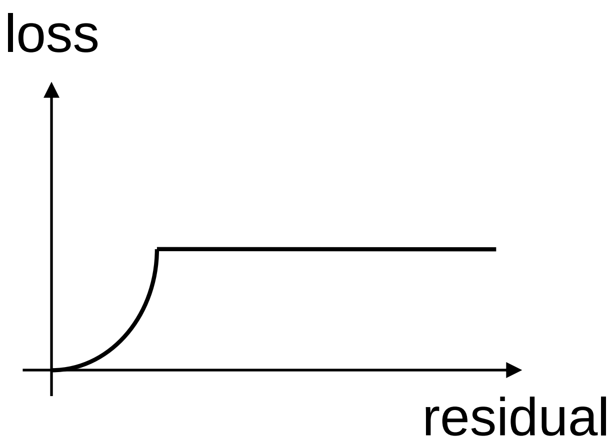


$$\min_x \sum_i r_i^2(x)$$

- Outliers lead to wrong estimate

Robust estimation

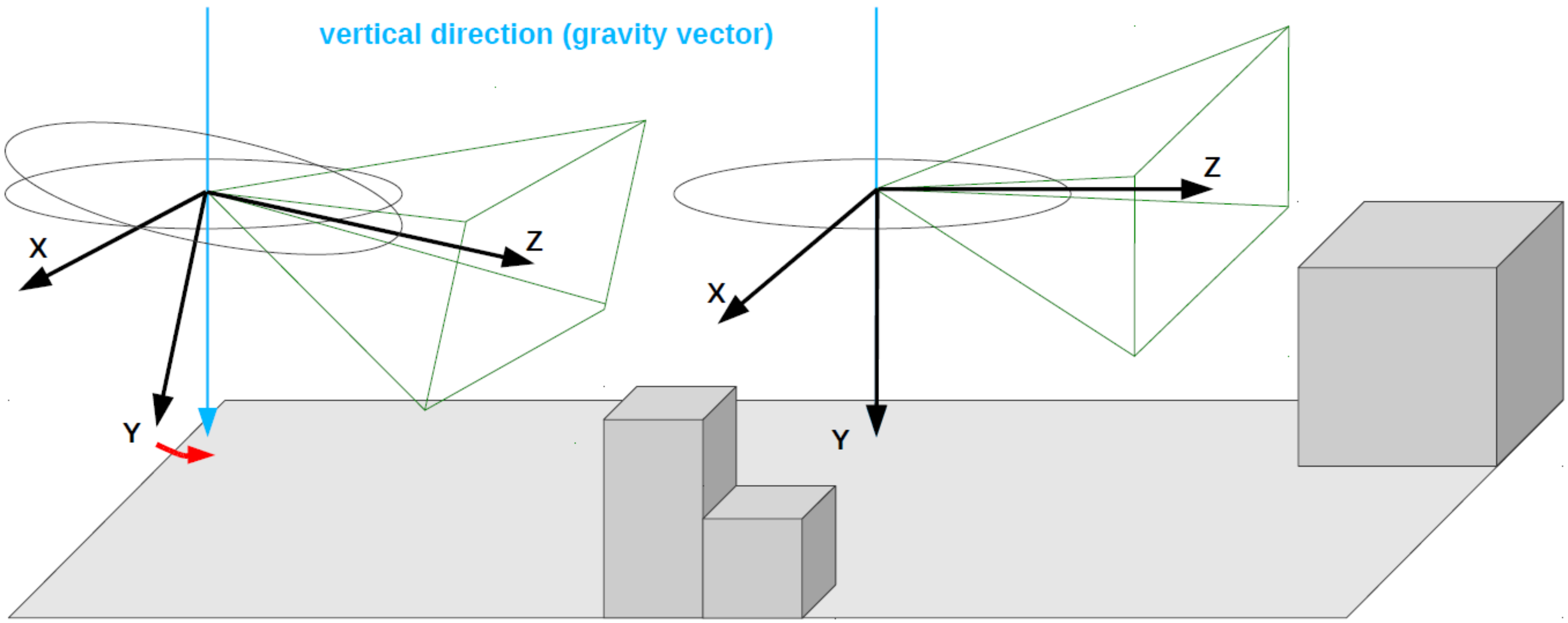




$$\min_x \sum_i \min(r_i^2(x), t^2)$$

Polynomial equation systems in computer vision

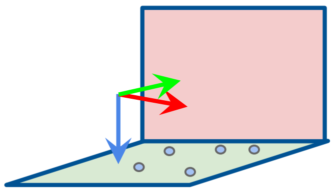
- Assumption: Ground plane normal to gravity vector, walls are vertical
  - IMU measurements can be used to align camera images/features to gravity vector
  - Motion can be computed from 2pt correspondences on the ground



Polynomial equation systems in computer vision
2pt relative pose

Homography Rotation (yaw) Rotation IMU Translation Plane normal

$$\boxed{\mathbf{H}} = \boxed{\mathbf{R}_y}\boxed{\mathbf{R}_x\mathbf{R}_z} + \boxed{\mathbf{t}^T}\boxed{\mathbf{n}}$$



$$\mathbf{H} = \mathbf{R}_y + \mathbf{t}^T\mathbf{n}$$ (for pre-rotated features)

$$\boxed{\mathbf{H}} = \boxed{\mathbf{R_y}} + \boxed{[t_x, t_y, t_z]^T}\boxed{[0, 1, 0]}$$ (H for ground plane)

Homography Rotation (yaw) Translation Plane normal

4 unknowns left, 2 point correspondences give 4 equations

Polynomial systems in computer vision

- P3P, PnP problem:

$$
\begin{array}{l}
L_1 \\ L_2 \\ L_3
\end{array}
\begin{cases}
2x^2 + y^2 - 2z + 3z^2 + 5 & = & 0 \\
x^2 + z + z^2 & = & 0 \\
x^2 y^2 + y^2 z^2 - 2 & = & 0
\end{cases}
$$

- Solution: Reduction to a single polynomial (several schemes)
- Automatic procedure – Gröbner Basis

Polynomial equation systems

Root solving

- 3pt+IMU, 8^{th} degree polynomial
- 6pt generalized camera, 64^{th} degree polynomial

- Fast method: Sturm bracketing