

Two View Image Processing

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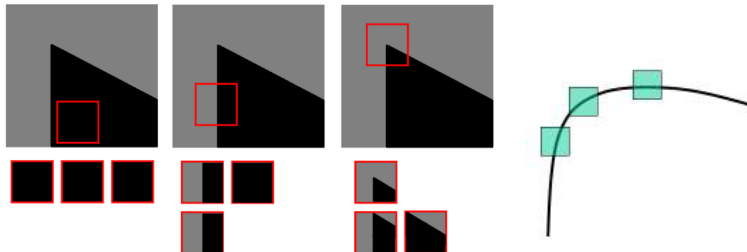
Steps of my Program

- Keypoint location and matching
- 8-point algorithm \rightarrow fundamental matrix
- Depth map

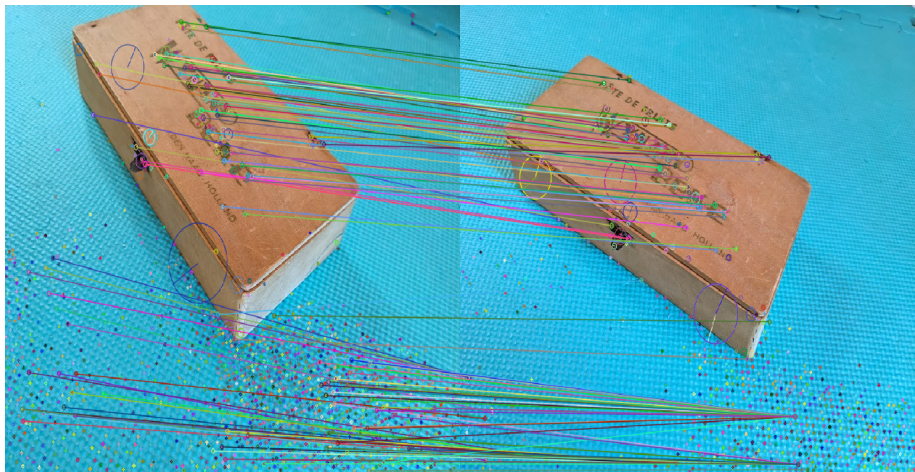


Finding and Matching Points

- Harris corner detector
- the three main detectors: SIFT, ORB, SURF



SIFT error



Depth Map

- Matching points \rightarrow fundamental matrix \rightarrow camera positions
- Triangulation gives depth from two matching points
- StereoMatcher does this in one go

