Multimedia

- Text
- Graphics
- Audio
- Images
- Video

Imaging Configurations

- Stationary camera stationary objects
- Stationary camera moving objects
- Moving camera stationary objects
- Moving camera moving objects

Video

- sequence of images
- clip
- mosaic
- key frames

Sequence of Images

Clip

Mosaic

Key Frames

Steps in Video Computing

- Acquire (CCD arrays/synthesize (graphics))
- Process (image processing)
- Analyze (computer vision)
- Transmit (compression/networking)
- Store (compression/databases)
- Retrieve (computer vision/databases)
- Browse (computer vision/databases)
- Visualize (graphics)

Computer Vision

- Measurement of Motion
  - 2-D Motion
    - optical flow
    - point correspondences
  - 3-D Motion
    - structure from motion (sfm)
    - compute 3D translation, 3D rotation
    - shape from motion (depth)

Computer Vision (contd.)

- Scene Change Detection
  - consecutive frame differencing
  - background differencing
    - median filter
    - pfinder
    - W4
    - Mixture of Gaussians

Computer Vision (contd.)

- Tracking
  - people
  - vehicles
  - animals

Computer Vision (contd.)

- Video Recognition
  - activity recognition
  - gesture recognition
  - facial expression recognition
  - lipreading
- Video Segmentation
  - shots
  - scenes
  - stories
  - key frames

Image Processing

- Filtering
- Compression
  - MPEG-1
  - MPEG-2
  - MPEG-4
  - MPEG-7 (Multimedia Content Description Interface)

Databases

- Storage
- Retrieval
- Video on demand
- Browsing
  - skim
  - abstract
  - key frames
  - mosaics

Networking

- Transmission
- ATM

Computer Graphics

- Visualization
- Image-based Rendering and Modeling
- Augmented Reality

Video Computing

- Computer Vision
- Image Processing
- Computer Graphics
- Databases
- Networks

PART I

Measurement of Motion

Contents

- Image Motion Models
- Optical Flow Methods
  - Horn & Schunck
  - Lucas and Kanade
  - Anandan et al
  - Szeliski
  - Mann & Picard
- Video Mosaics

3-D Rigid Motion

$$\begin{bmatrix} X' \\ Y' \\ Z' \end{bmatrix} = R \begin{bmatrix} X \\ Y \\ Z \end{bmatrix} + T = \begin{bmatrix} r_{11} & r_{12} & r_{13} \\ r_{21} & r_{22} & r_{23} \\ r_{31} & r_{32} & r_{33} \end{bmatrix} \begin{bmatrix} X \\ Y \\ Z \end{bmatrix} + \begin{bmatrix} T_X \\ T_Y \\ T_Z \end{bmatrix}$$

Rotation matrix (9 unknowns)

Translation (3 unknowns)

Rotation

$$X = R\cos f$$

$$Y = R\sin f$$

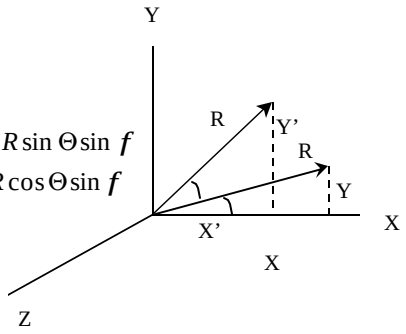
$$X' = R\cos(\Theta + f) = R\cos\Theta\cos f - R\sin\Theta\sin f$$

$$Y' = R\sin(\Theta + f) = R\sin\Theta\cos f + R\cos\Theta\sin f$$

$$X' = X\cos\Theta - Y\sin\Theta$$

$$Y' = X\sin\Theta + Y\cos\Theta$$

$$\begin{bmatrix} X' \\ Y' \\ Z' \end{bmatrix} = \begin{bmatrix} \cos\Theta & -\sin\Theta & 0 \\ \sin\Theta & \cos\Theta & 0 \\ 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} X \\ Y \\ Z \end{bmatrix}$$

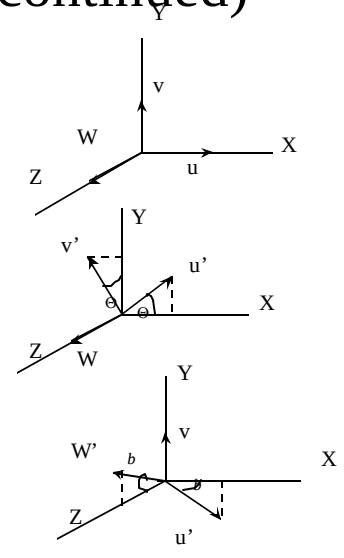


Rotation (continued)

$$R = \begin{bmatrix} 1 & 0 & 0 \\ 0 & 1 & 0 \\ 0 & 0 & 1 \end{bmatrix}$$

$$R = \begin{bmatrix} \cos\Theta & -\sin\Theta & 0 \\ \sin\Theta & \cos\Theta & 0 \\ 0 & 0 & 1 \end{bmatrix}$$

$$R = \begin{bmatrix} \cos\beta & 0 & -\sin\beta \\ 0 & 1 & 0 \\ \sin\beta & 0 & \cos\beta \end{bmatrix}$$



Euler Angles

$$R = R_Z^{\alpha} R_Y^{\beta} R_X^{\gamma} = \begin{bmatrix} \cos\alpha\cos\beta & \cos\alpha\sin\beta\sin\gamma - \sin\alpha\cos\gamma & \cos\alpha\sin\beta\cos\gamma + \sin\alpha\sin\gamma \\ \sin\alpha\cos\beta & \sin\alpha\sin\beta\sin\gamma + \cos\alpha\cos\gamma & \sin\alpha\sin\beta\cos\gamma - \cos\alpha\sin\gamma \\ -\sin\beta & \cos\beta\sin\gamma & \cos\beta\cos\gamma \end{bmatrix}$$

if angles are small($\cos\Theta \approx 1$) $\sin\Theta \approx \Theta$

$$R = \begin{bmatrix} 1 & -\alpha & \beta \\ \alpha & 1 & -\gamma \\ \beta & \gamma & 1 \end{bmatrix}$$

Displacement Model

Orthographic Projection

$$\begin{bmatrix} X' \\ Y' \\ Z' \end{bmatrix} = R\begin{bmatrix} X \\ Y \\ Z \end{bmatrix} + T = \begin{bmatrix} r_{11} & r_{12} & r_{13} \\ r_{21} & r_{22} & r_{23} \\ r_{31} & r_{32} & r_{33} \end{bmatrix}\begin{bmatrix} X \\ Y \\ Z \end{bmatrix} + \begin{bmatrix} T_X \\ T_Y \\ T_Z \end{bmatrix}$$

(x,y)=image coordinates,
(X,Y,Z)=world coordinates

$$x' = r_{11}x + r_{12}y + (r_{13}Z + T_X)$$
$$y' = r_{21}x + r_{22}y + (r_{23}Z + T_Y)$$
$$x' = a_1 x + a_2 y + b_1$$
$$y' = a_3 x + a_4 y + b_2$$

$$\mathbf{x}' = \mathbf{A}\mathbf{x} + \mathbf{b}$$

Affine Transformation

Orthographic Projection (contd.)

$$\begin{bmatrix} X' \\ Y \\ Z' \end{bmatrix} = R\begin{bmatrix} X \\ Y \\ Z \end{bmatrix} + T = \begin{bmatrix} 1 & -a & b \\ a & 1 & g \\ -b & g & 1 \end{bmatrix}\begin{bmatrix} X \\ Y \\ Z \end{bmatrix} + \begin{bmatrix} T_X \\ T_Y \\ T_Z \end{bmatrix}$$

$$x' = x - ay + bZ + T_X$$
$$y' = ax + y - gZ + T_Y$$

Perspective Projection

$$\begin{bmatrix} X' \\ Y' \\ Z' \end{bmatrix} = R\begin{bmatrix} X \\ Y \\ Z \end{bmatrix} + T = \begin{bmatrix} r_{11} & r_{12} & r_{13} \\ r_{21} & r_{22} & r_{23} \\ r_{31} & r_{32} & r_{33} \end{bmatrix}\begin{bmatrix} X \\ Y \\ Z \end{bmatrix} + \begin{bmatrix} T_X \\ T_Y \\ T_Z \end{bmatrix}$$

$$x' = \frac{X'}{Z'} \quad y' = \frac{Y'}{Z'}$$

focal length = -1

$$x' = \frac{r_{11}x + r_{12}y + r_{13} + \frac{T_X}{Z}}{r_{31}x + r_{32}y + r_{33} + \frac{T_Z}{Z}}$$

← scale ambiguity

$$y' = \frac{r_{21}x + r_{22}y + r_{23} + \frac{T_Y}{Z}}{r_{31}x + r_{32}y + r_{33} + \frac{T_Z}{Z}}$$