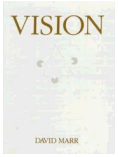
Binocular Stereo Vision

Marr-Poggio-Grimson (MPG)
multi-resolution stereo algorithm



CS332 Visual Processing
Department of Computer Science
Wellesley College

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Key points about human stereo vision

- **Image features used for matching:**
  ~simple, precise locations, similar between left/right images
- **At a single fixation, match features over a limited range of horizontal & vertical disparity**
- Eye movements used to match features over larger range of horizontal & vertical disparity
- ***Stereo matching is performed at multiple scales***
  - **stereo information at different scales is processed independently**
  - **information at coarser scales can be "fused" over a larger range of stereo disparity**
  - information at coarser scales can trigger vergence eye movements that narrow the range of stereo disparity in the region of view

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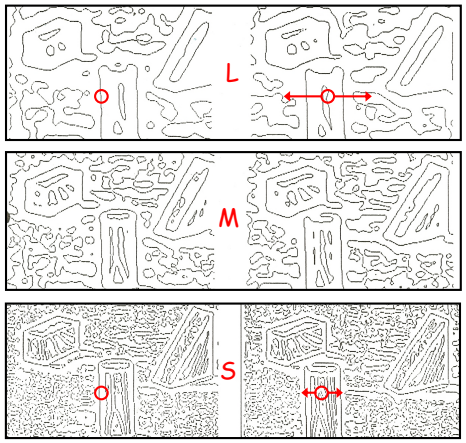
Matching features for the MPG stereo algorithm



zero-crossings of image convolutions with $\nabla^2 G$ operators of different size

rough disparities over large range

accurate disparities over small range

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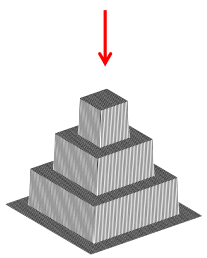
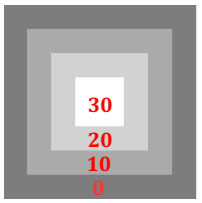
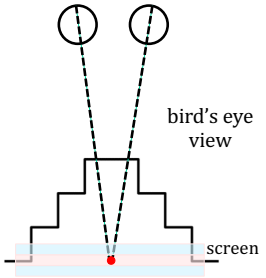
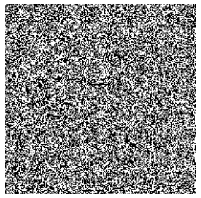


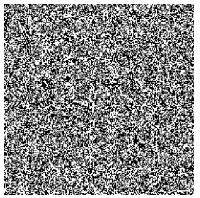
disparity map



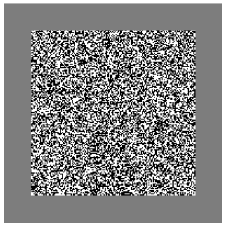




left

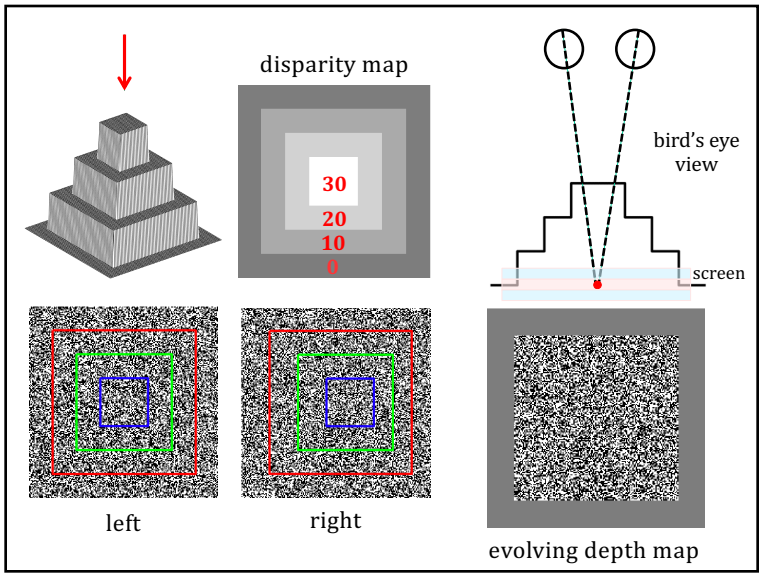


right

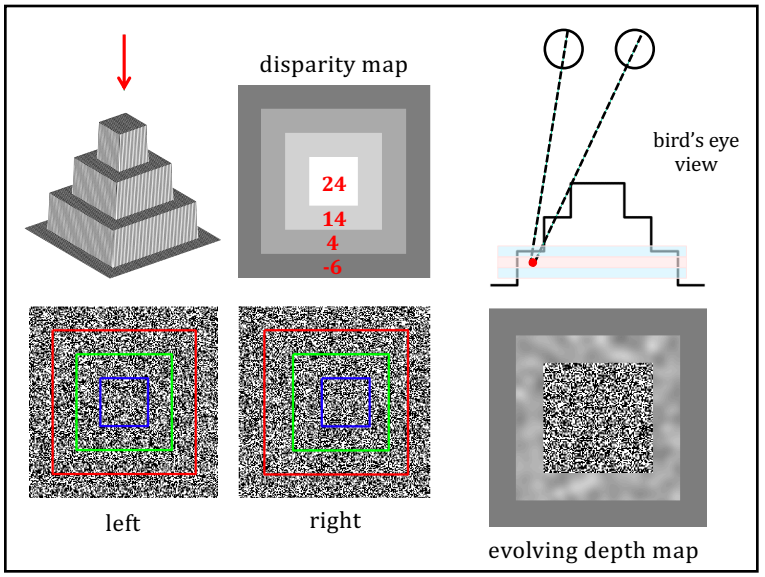


evolving depth map

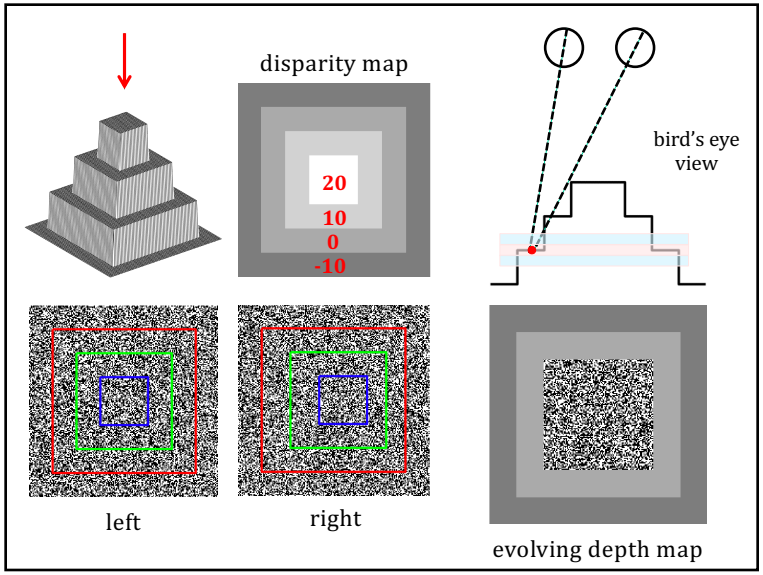
4


disparity map
30
20
10
0
bird's eye view
screen
left
right
evolving depth map

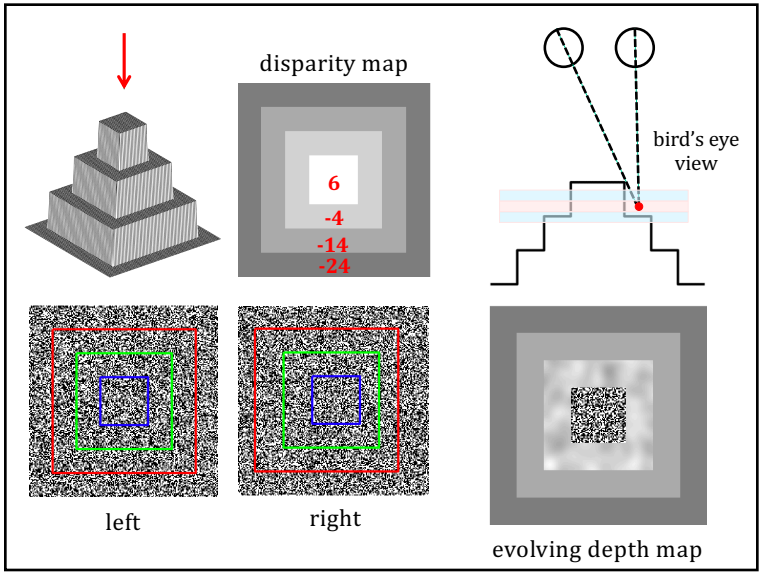
5


disparity map
24
14
4
-6
bird's eye view
left
right
evolving depth map

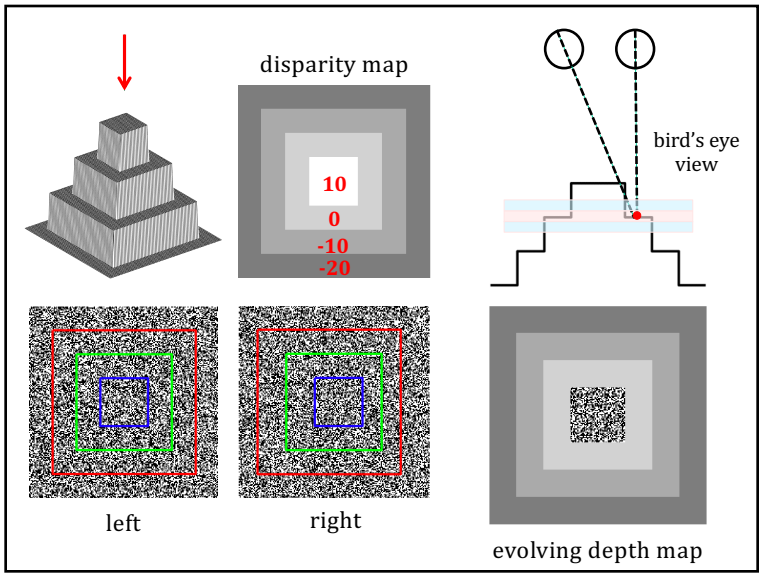
6


disparity map
20
10
0
-10
bird's eye view
left
right
evolving depth map

7


disparity map
6
-4
-14
-24
bird's eye view
left
right
evolving depth map

8



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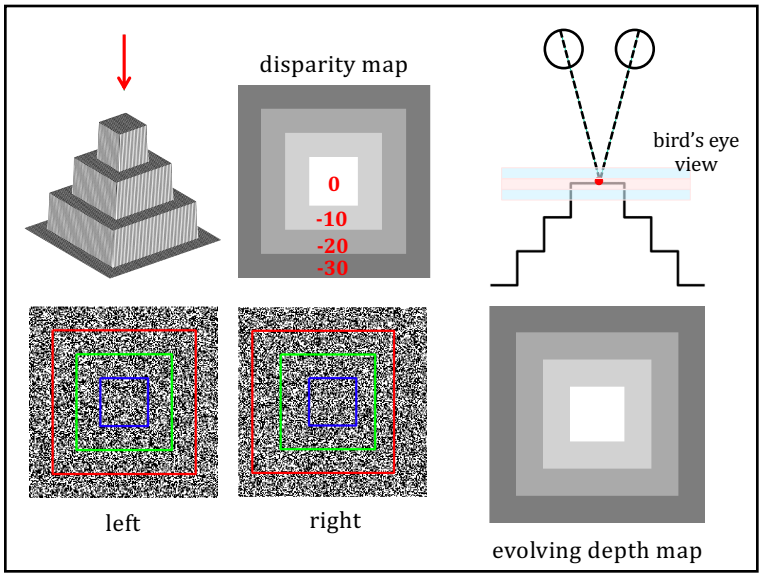

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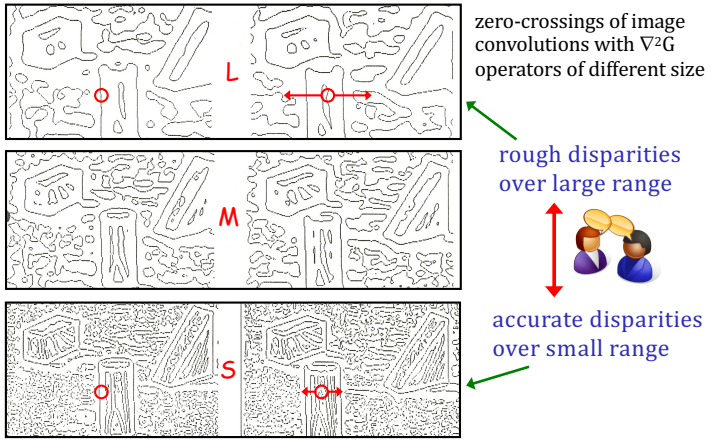
Matching features for the MPG stereo algorithm



zero-crossings of image convolutions with $\nabla^2 G$ operators of different size

rough disparities over large range

accurate disparities over small range

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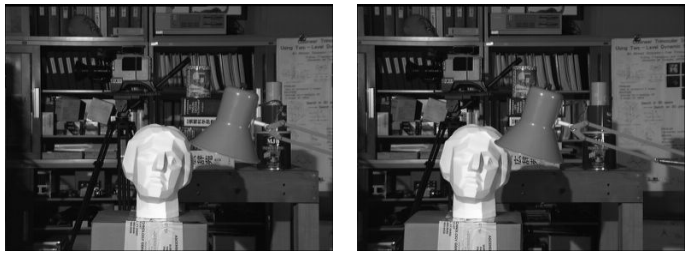
Stereo images (Tsukuba, CMU)



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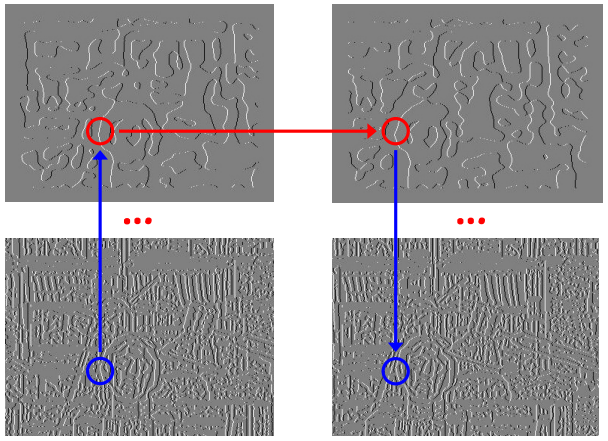
Zero-crossings for stereo matching



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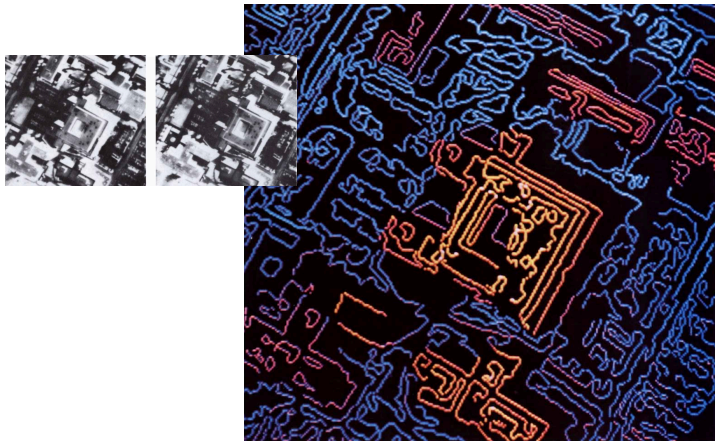
MPG stereo algorithm results



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Simplified MPG algorithm, Part 1

To determine initial correspondence:

(1) Find zero-crossings using a $\nabla^2 G$ operator with central positive width w

(2) For each horizontal slice:

(2.1) Find the nearest neighbors in the right image for each zero-crossing fragment in the left image

(2.2) Find the nearest neighbors in the left image for each zero-crossing fragment in the right image

(2.3) For each pair of zero-crossing fragments that are closest neighbors of one another, let the right fragment be separated by $\delta_{initial}$ from the left. Determine whether $\delta_{initial}$ is within the matching tolerance, m. If so, consider the zero-crossing fragments matched with disparity $\delta_{initial}$

$$m = w/2$$

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Simplified MPG algorithm, Part 2

To determine final correspondence:

(1) Find zero-crossings using a $\nabla^2 G$ operator with reduced width w/2

(2) For each horizontal slice:

(2.1) For each zero-crossing in the left image:

(2.1.1) Determine the nearest zero-crossing fragment in the left image that matched when the $\nabla^2 G$ operator width was w

(2.1.2) Offset the zero-crossing fragment by a distance $\delta_{initial}$, the disparity of the nearest matching zero-crossing fragment found at the lower resolution with operator width w

(2.2) Find the nearest neighbors in the right image for each zero-crossing fragment in the left image

(2.3) Find the nearest neighbors in the left image for each zero-crossing fragment in the right image

(2.4) For each pair of zero-crossing fragments that are closest neighbors of one another, let the right fragment be separated by δ_{new} from the left. Determine whether δ_{new} is within the reduced matching tolerance, m/2. If so, consider the zero-crossing fragments matched with disparity $\delta_{final} = \delta_{new} + \delta_{initial}$

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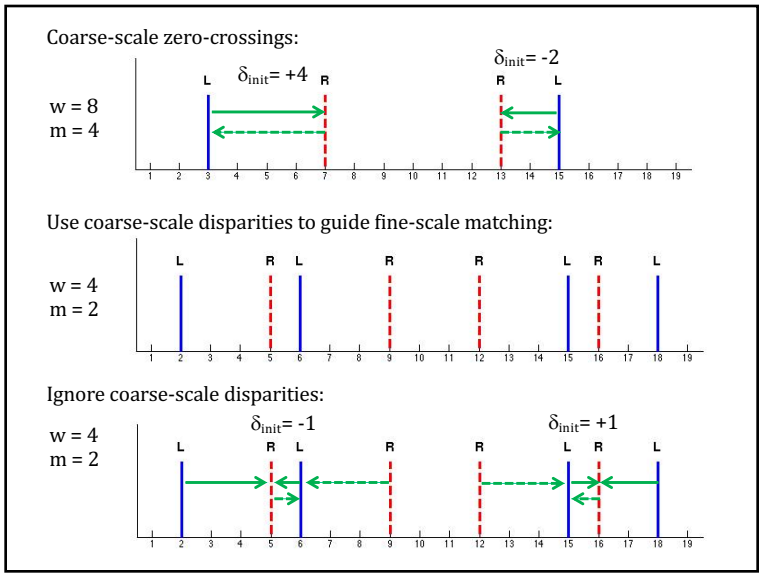

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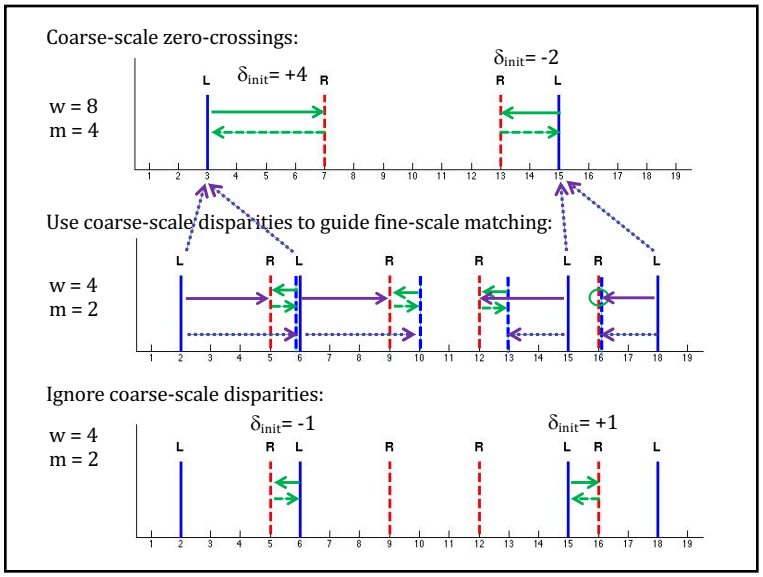

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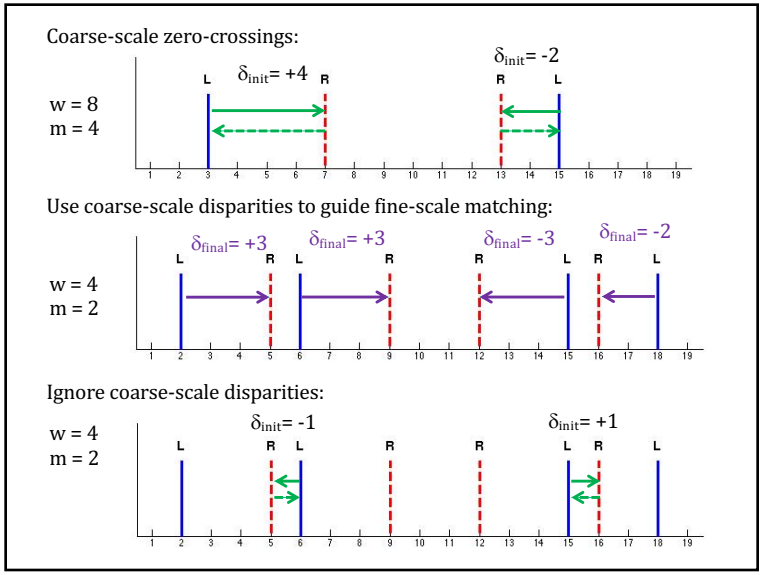

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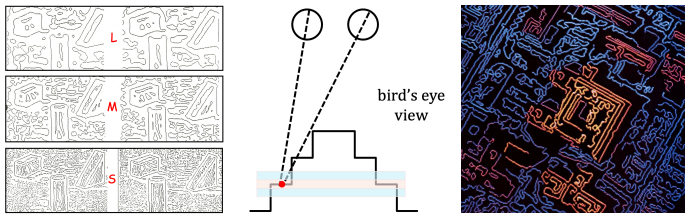
MPG stereo correspondence algorithm

- multi-resolution, feature-based stereo matching algorithm



- incorporates role of vergence eye movements and multi-scale processing observed in human stereo vision
- implemented in a computer vision system
- simplified version can be hand simulated to better understand interactions across scales

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