UNIVERSITÀ
DEGLI STUDI DI MILANO-BICOCCA

SYLLABUS DEL CORSO

Computer and Robot Vision (blended)

2425-2-F1801Q149

Aims

The course aims to provide theoretical and practical skills related to the processing of data generated by cameras and range sensors, to analyze the observed scene by extracting information about its geometry.

Contents

The course presents an introduction to the perception of the observed scene and recostruction of its geometry (image formation, stereoscopy, analysis of image sequences, bayesian filtering, and perception for mobile autonomous robotics).

Detailed program

1. Image formation

- image formation - geometry: geometric models of projection, model-based vision (hint), the need for optics, thin lenses, blur circles and depth of view, external and intrinsic projection parameters, FOV (Field Of View), calibration of the projection parameters
- image formation - technological issues and considerations.

2. Stereoscopy

- terminology, pixel-level and feature-based approaches
- example of pixel level stereo-matching algorithm: correlation-based stereo-matching, and usage of multi-resolution

- feature-based stereo-matching algorithms, hints about feature detection and description
- epipolar geometry

3. Analysis of image sequences

- the different problems, according to the scene and the observer motion
- image and scene motion field
- brightness constancy equation and the aperture problem
- differential methods and estimation of the optical flow with an LSE approach
- feature-based approaches
- data association and missing information problems: effects of outliers, breakdown level, Least Median of Squares, RANSAC

4. Bayesian filtering

- dynamical systems and Bayesian filtering
- Kalman filter (KF), extended Kalman filter (EKF), and usage of mixtures of gaussians
- unscented Kalman Filter (UKF)
- non-parametric filters: hints on histogram filter, particle filter (PF)

5. Perception for mobile autonomous robotics

- Review of kinematics of different mobile bases, Velocity Motion Model and Odometry Motion Model
- short review of sensors for range sensing and measurement model of laser scanners
- the point clouds registration and its usage in a variety of robot vision problems
- localization problem, EFK-based and PF-based approaches
- SLAM PF-based (FASTSLAM) and EKF-based
- Visual SLAM with inverse depth

Prerequisites

- Basic knowledge of geometry, linear algebra, and programming.

Teaching form

Teaching is expected to take place in italian. Nevertheless, the course will be given in english should one of the following conditions become true:

- at least one foreign student prefers to use english;
- students ask to have classes and practicals given in english.

The scheduled activities are: 40 hours of lessons in dispensing mode and/or in interactive mode, 12 hours of laboratory in interactive mode.

The teaching activities will include:

- classes: pre-recorded classes;
- periodic interactive meetings about the topics covered via the pre-recorded classes;
- laboratory events (practice, no programming);

- interactive meetings about laboratory programming activities;
- activities with preparation of talks by students on some parts of the course that will be discussed in the classroom and commented by the professors.

Textbook and teaching resource

Textbooks

- A. Fusiello, "Visione Computazionale: tecniche di ricostruzione tridimensionale", Franco Angeli, 2013
- E. Trucco, A. Verri, "Introductory techniques for 3D Computer Vision", Prentice Hall, 1998
- S. Thrun, W. Burgard, D. Fox, "Probabilistic Robotics", Mit press, 2005

Other learning material

- Short videos (audio and tablet screen used as blackboard, taken from the videos of classes from previous years) for each subtopic
- Extra material, available on the elearning platform
- Videos, reports and other documents publicly available and produced by experts of the field.

Semester

II° Year, I° Semester

Assessment method

Afeter the end of the course, an in person meeting with each student will take place, during which all assignments will be evaluated, and the final score will be determined.
The final mark will be the weighted average of:

- marks obtained in the 2 written exams about theory (first: image formation and stereoscopy, second image sequences and robot vision), weight 0.2 each;
- marks on the laboratory activity about Bayesian filtering: documents on the the system equations (state and measurement, weigh 0.1 each), short matlab programs on KF and PF, weight 0.2 each.
- A maximum of 3 bonus points will be awarded to reasonably good implementations of one of the physical laboratory activities.

Office hours

Send email to arrange an appointment

Sustainable Development Goals

INDUSTRY, INNOVATION AND INFRASTRUCTURE | SUSTAINABLE CITIES AND COMMUNITIES