COMPUTER VISION AND ROBOTICS
[As per Choice Based Credit System (CBCS) scheme]
(Effective from the academic year 2016 -2017)
SEMESTER – VII

Subject Code	15CS752	IA Marks	20
Number of Lecture Hours/Week	3	Exam Marks	80
Total Number of Lecture Hours	40	Exam Hours	03

CREDITS – 03

Course objectives: This course will enable students to

- Review image processing techniques for computer vision
- Explain shape and region analysis
- Illustrate Hough Transform and its applications to detect lines, circles, ellipses
- Contrast three-dimensional image analysis techniques, motion analysis and applications of computer vision algorithms

Module – 1	**Teaching Hours**
CAMERAS: Pinhole Cameras**, Radiometry – Measuring Light:** Light in Space, Light Surfaces, Important Special Cases, **Sources, Shadows, And Shading:** Qualitative Radiometry, Sources and Their Effects, Local Shading Models, Application: Photometric Stereo, Interreflections: Global Shading Models, **Color:** The Physics of Color, Human Color Perception, Representing Color, A Model for Image Color, Surface Color from Image Color.	**8 Hours**
Module – 2	
Linear Filters: Linear Filters and Convolution, Shift Invariant Linear Systems, Spatial Frequency and Fourier Transforms, Sampling and Aliasing, Filters as Templates, **Edge Detection:** Noise, Estimating Derivatives, Detecting Edges, **Texture:** Representing Texture, Analysis (and Synthesis) Using Oriented Pyramids, Application: Synthesis by Sampling Local Models, Shape from Texture.	**8 Hours**
Module – 3	
The Geometry of Multiple Views: Two Views, **Stereopsis:** Reconstruction, Human Stereposis, Binocular Fusion, Using More Cameras, **Segmentation by Clustering:** What Is Segmentation?, Human Vision: Grouping and Getstalt, Applications: Shot Boundary Detection and Background Subtraction, Image Segmentation by Clustering Pixels, Segmentation by Graph-Theoretic Clustering,	**8 Hours**
Module – 4	
Segmentation by Fitting a Model: The Hough Transform, Fitting Lines, Fitting Curves, Fitting as a Probabilistic Inference Problem, Robustness, **Segmentation and Fitting Using Probabilistic Methods:** Missing Data Problems, Fitting, and Segmentation, The EM Algorithm in Practice, **Tracking With Linear Dynamic Models:** Tracking as an Abstract Inference Problem, Linear Dynamic Models, Kalman Filtering, Data Association, Applications and Examples**.**	**8 Hours**
Module – 5	
Geometric Camera Models: Elements of Analytical Euclidean Geometry, Camera Parameters and the Perspective Projection, Affine Cameras and Affine Projection Equations, **Geometric Camera Calibration:** Least-Squares Parameter Estimation, A Linear Approach to Camera Calibration, Taking Radial Distortion into Account, Analytical Photogrammetry, An Application: Mobile Robot Localization, **Model- Based Vision:** Initial Assumptions, Obtaining	**8 Hours**

Hypotheses by Pose Consistency, Obtaining Hypotheses by pose Clustering, Obtaining Hypotheses Using Invariants, Verification, Application: Registration In Medical Imaging Systems, Curved Surfaces and Alignment.	

Course outcomes: The students should be able to:

- Implement fundamental image processing techniques required for computer vision
- Perform shape analysis
- Implement boundary tracking techniques
- Apply chain codes and other region descriptors
- Apply Hough Transform for line, circle, and ellipse detections.
- Apply 3D vision techniques.
- Implement motion related techniques.
- Develop applications using computer vision techniques.

Question paper pattern:

The question paper will have ten questions.
There will be 2 questions from each module.
Each question will have questions covering all the topics under a module.
The students will have to answer 5 full questions, selecting one full question from each module.

Text Books:

1. David A. Forsyth and Jean Ponce: Computer Vision – A Modern Approach, PHI Learning (Indian Edition), 2009.

Reference Books:

2. E. R. Davies: Computer and Machine Vision – Theory, Algorithms and Practicalities, Elsevier (Academic Press), 4th edition, 2013.