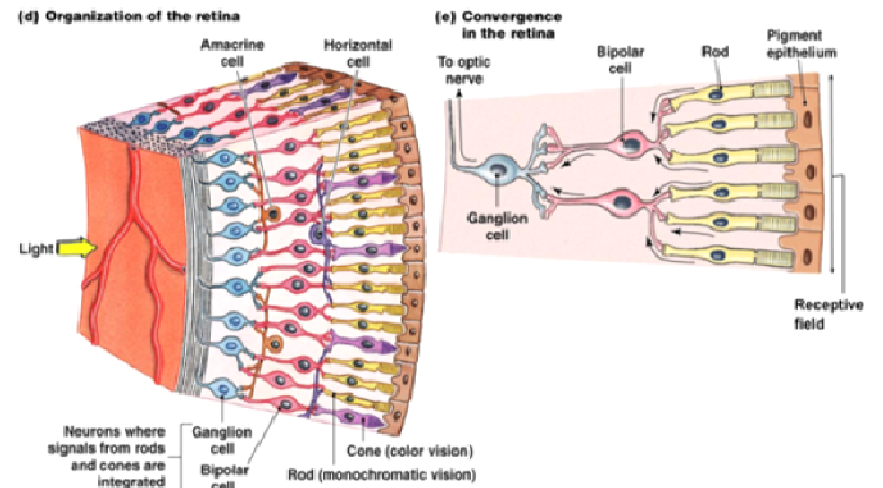
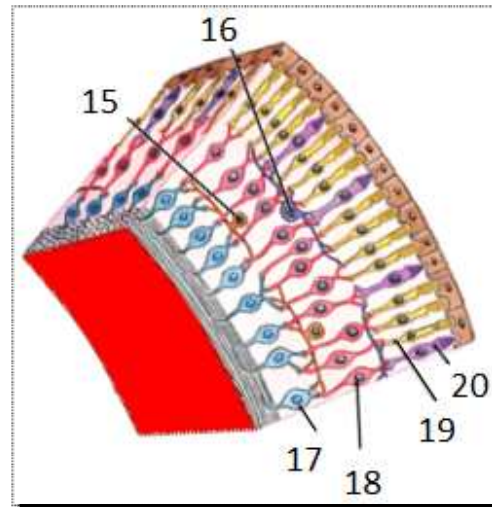
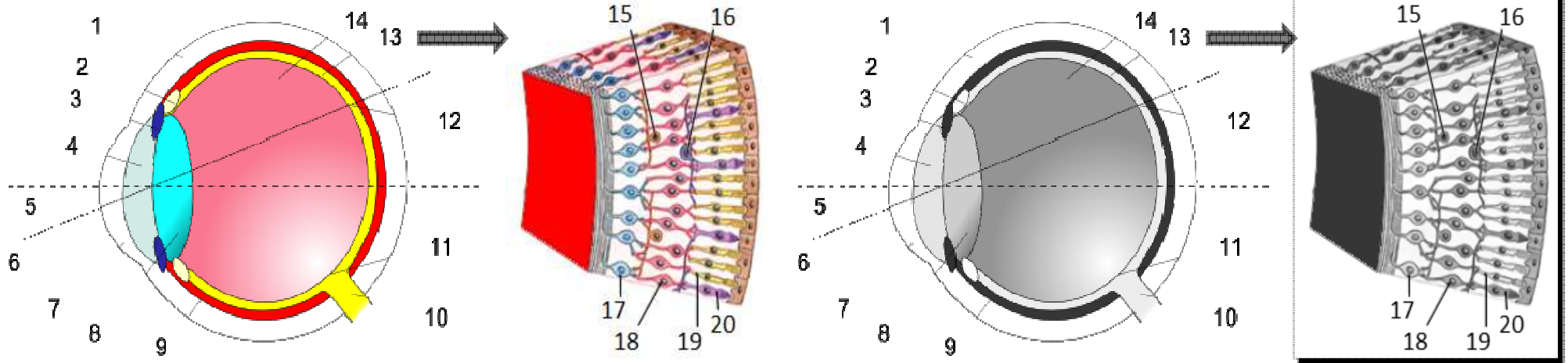
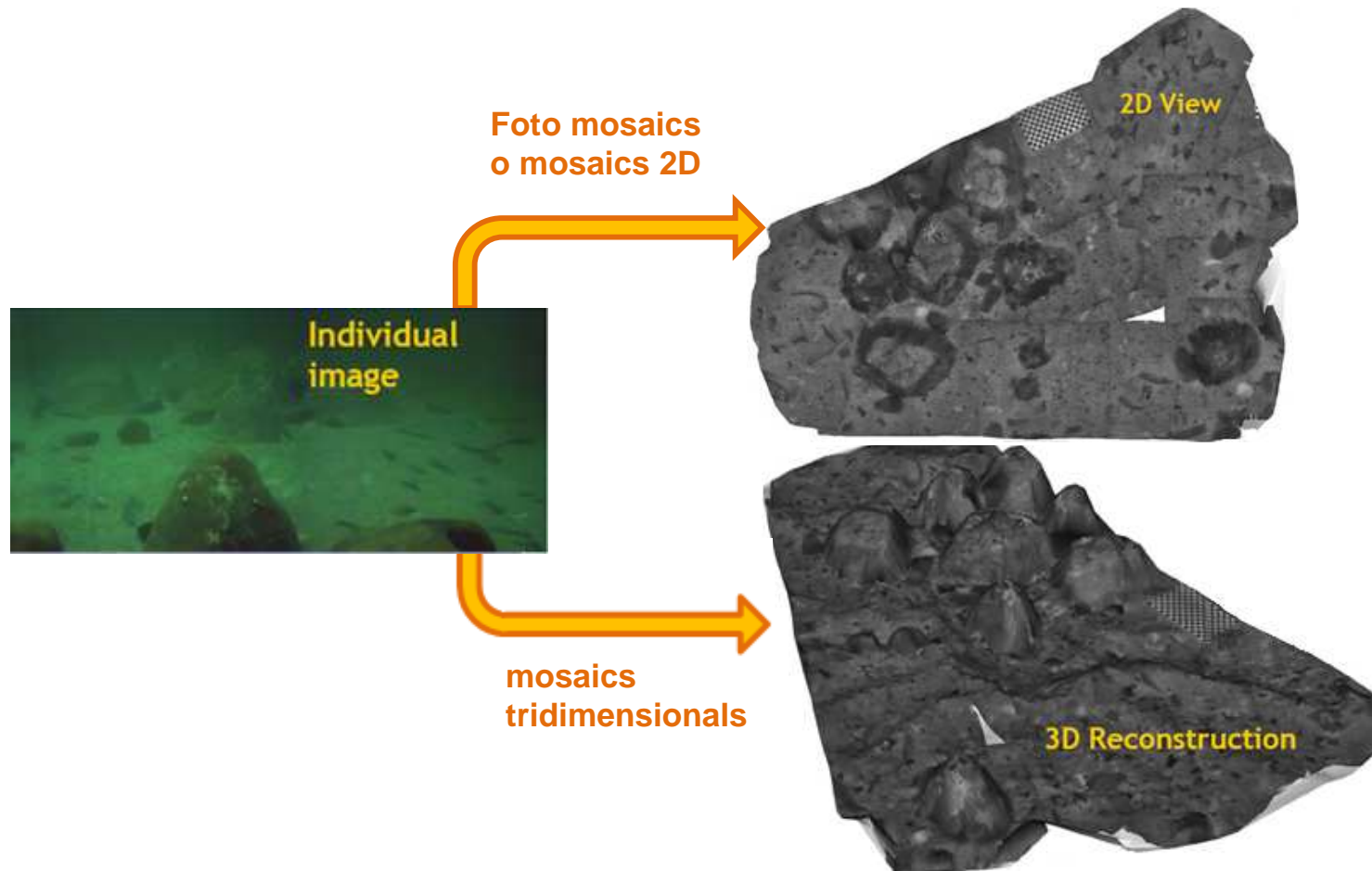


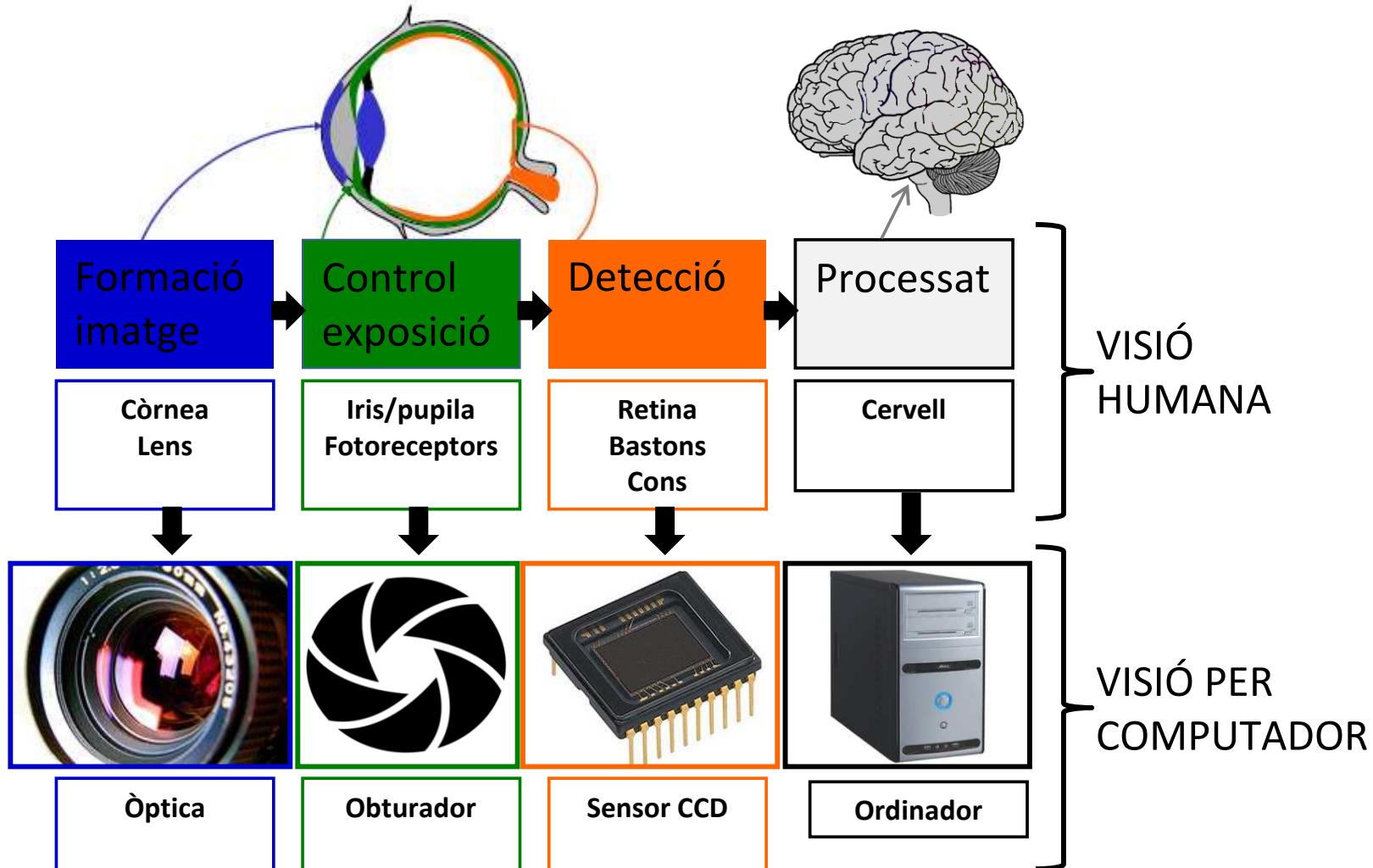
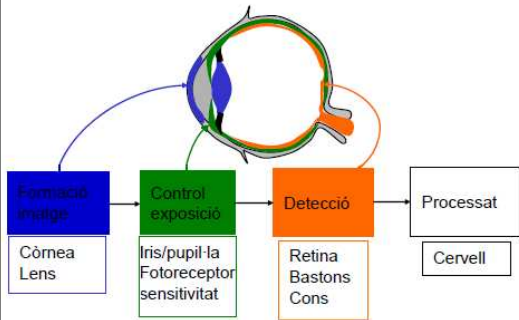
IMATGE ULL



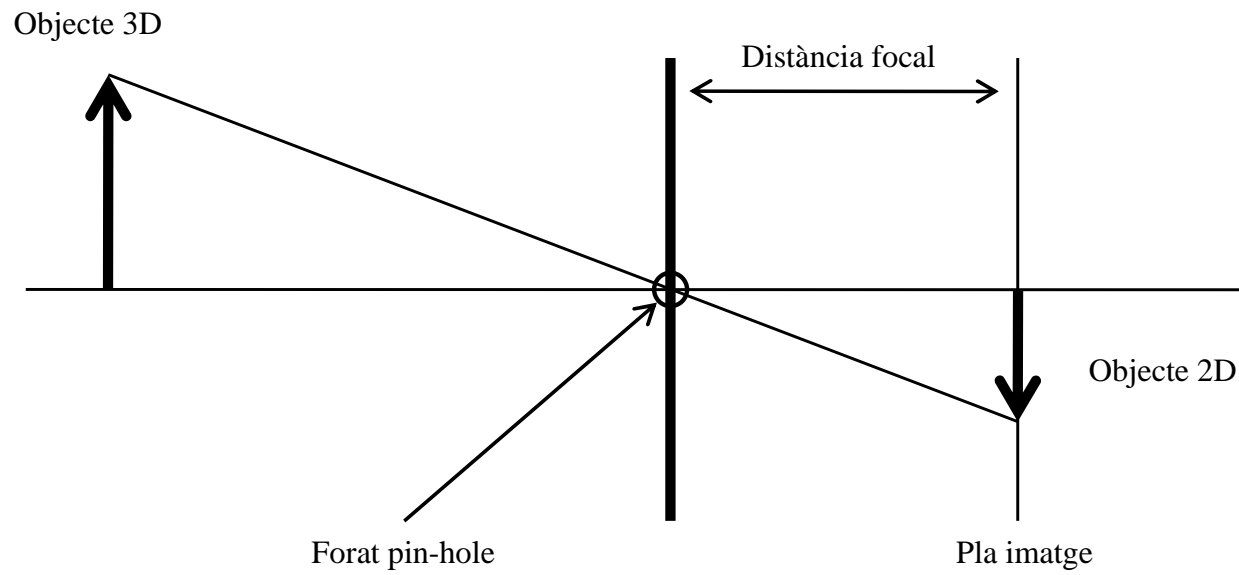
IMATGES TEMA 1 VPC



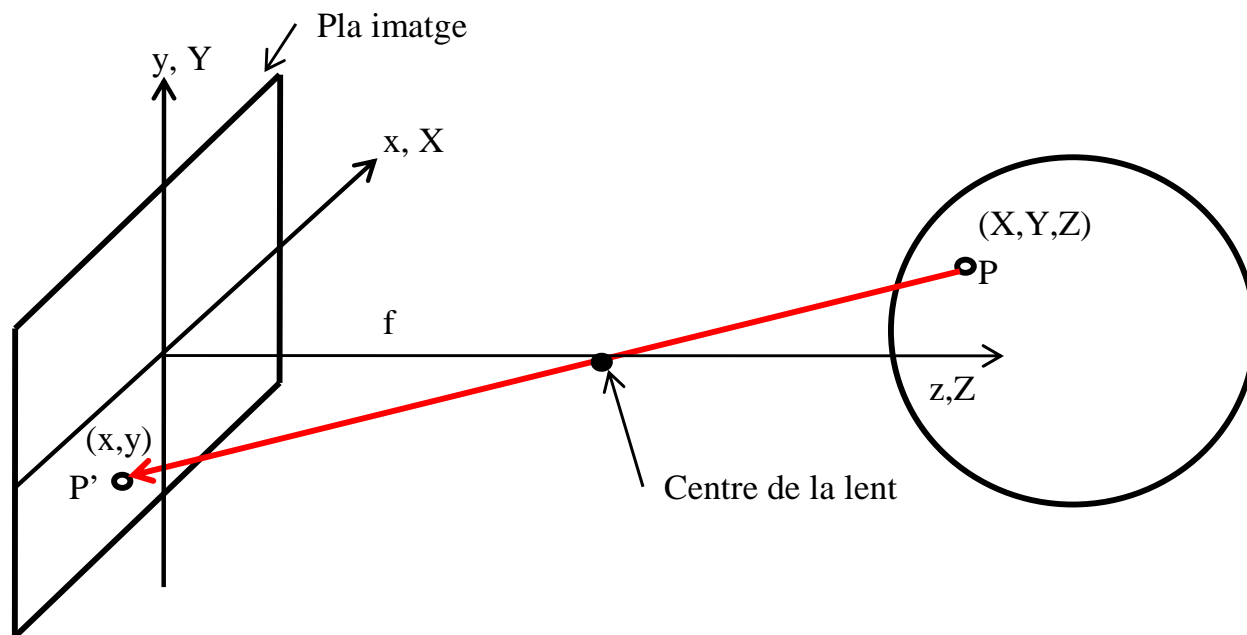
DELS APUNTS TEMA 6 VPC (MODIFICADA)



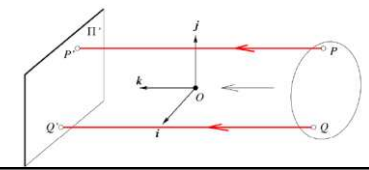
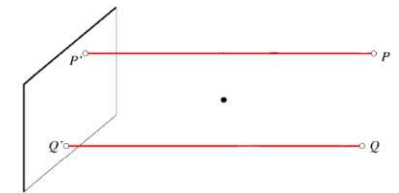
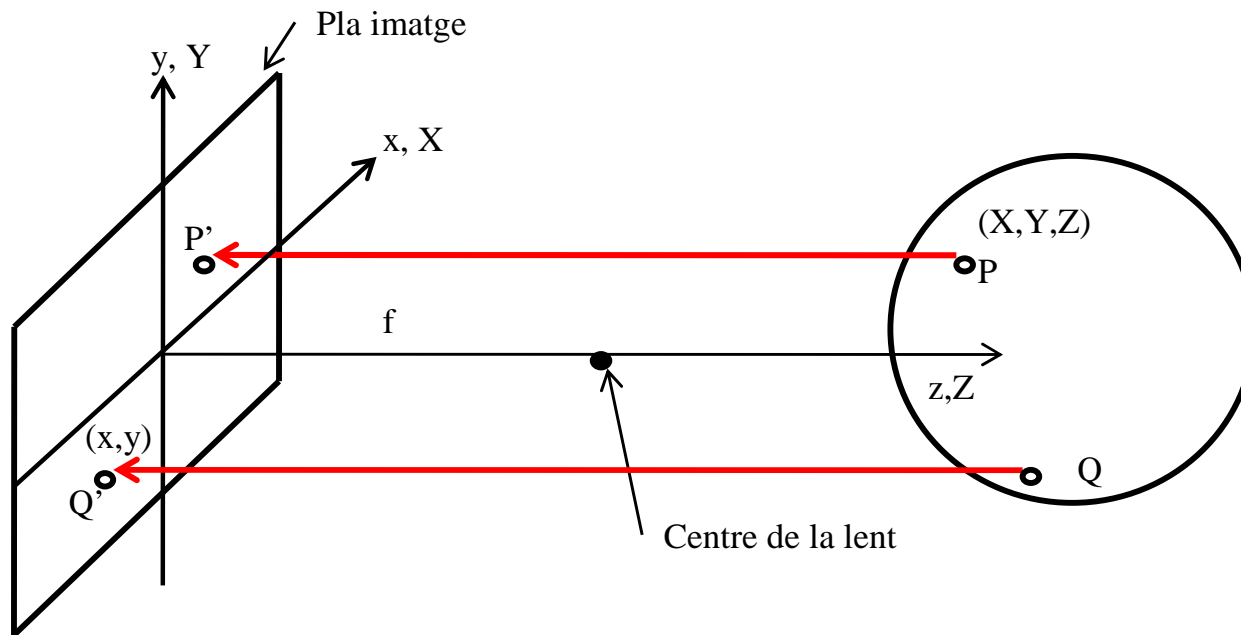
Pin-hole



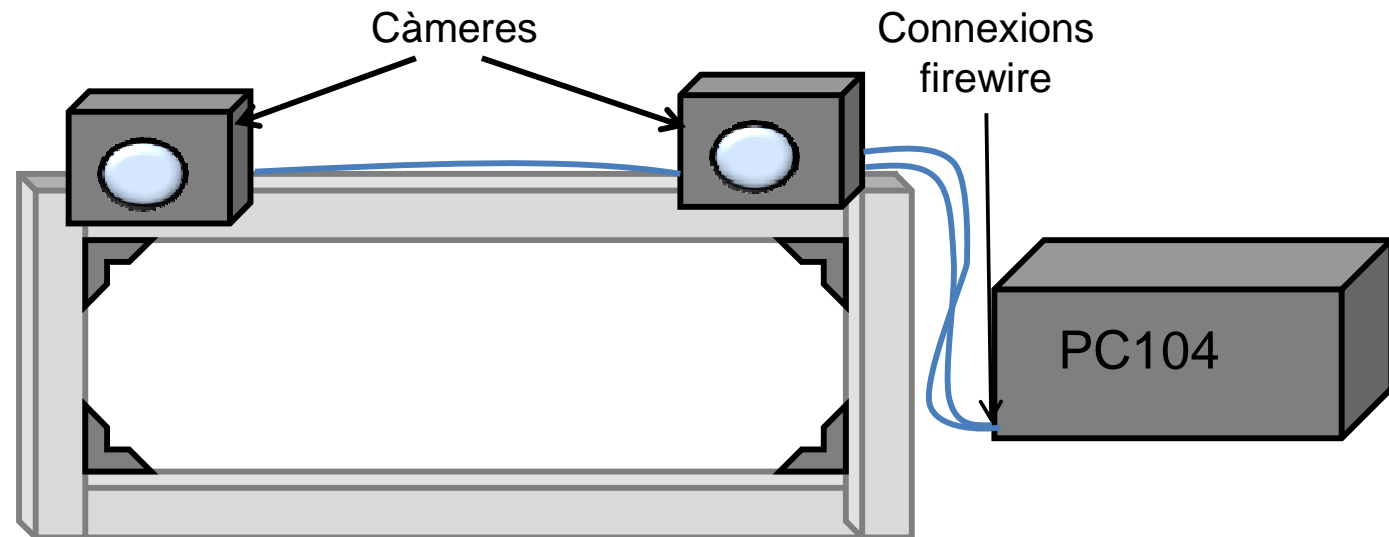
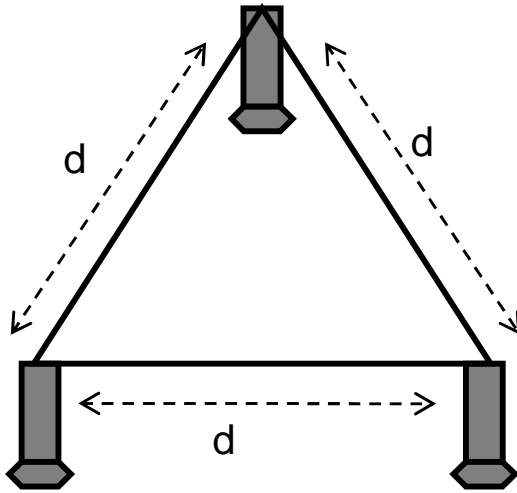
Projecció perspectiva



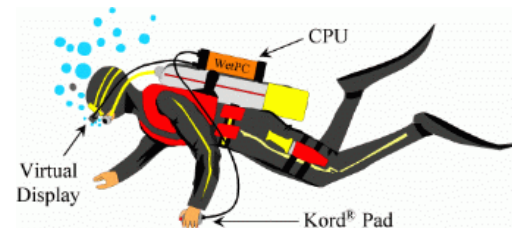
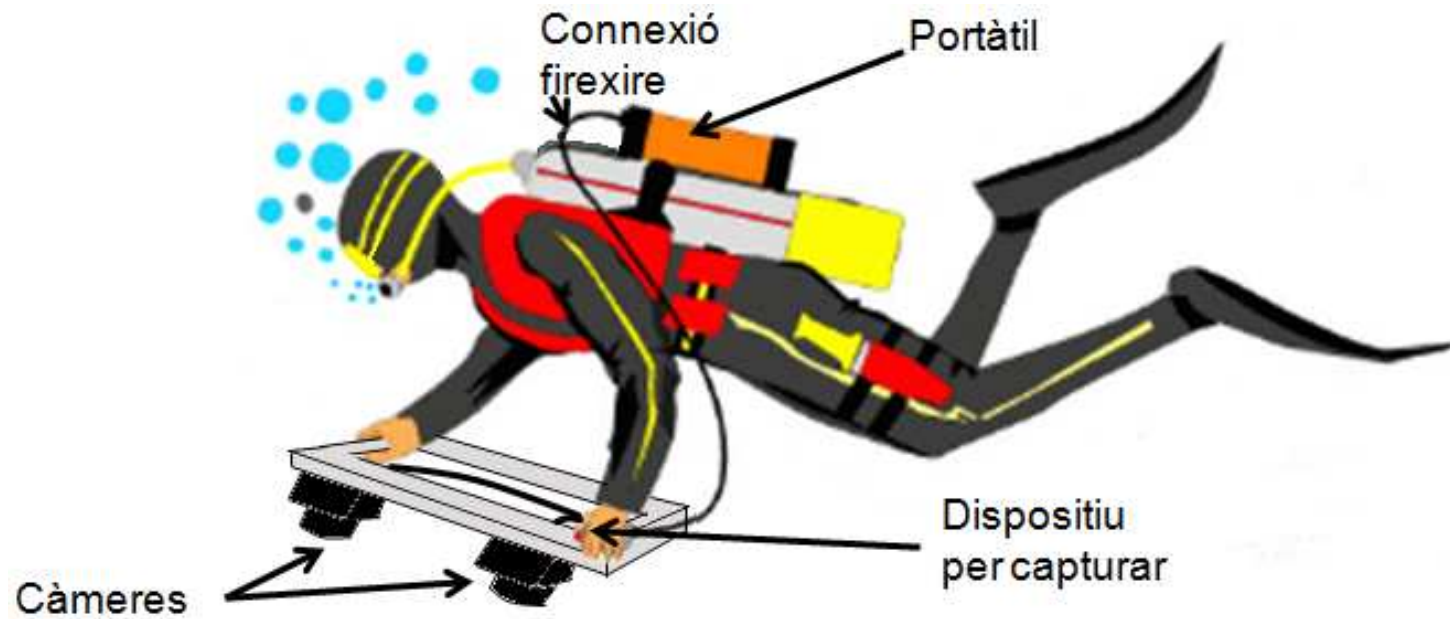
Projeccio ortografica



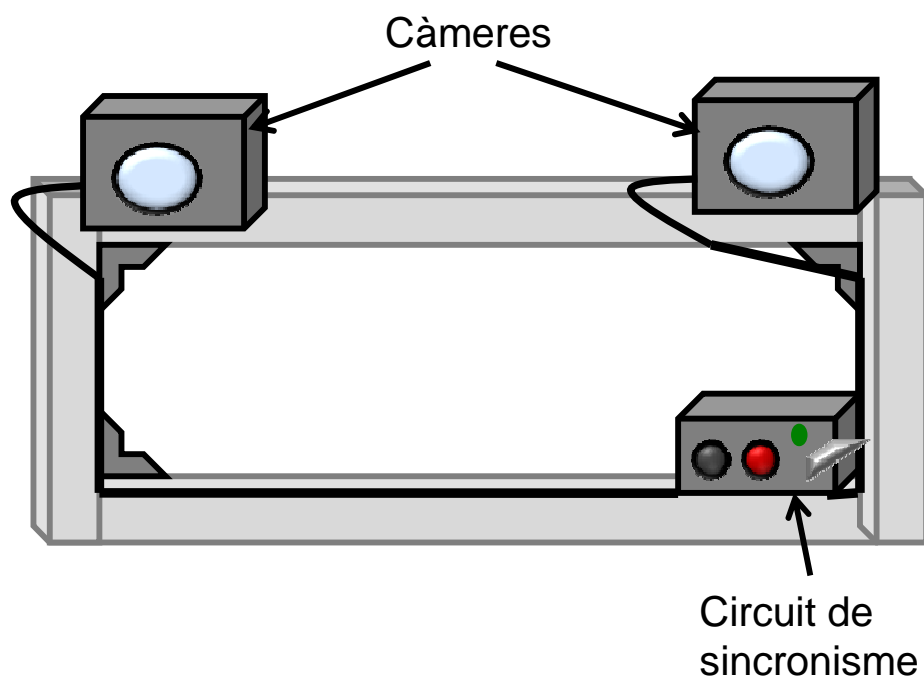
Estratègia Pc104



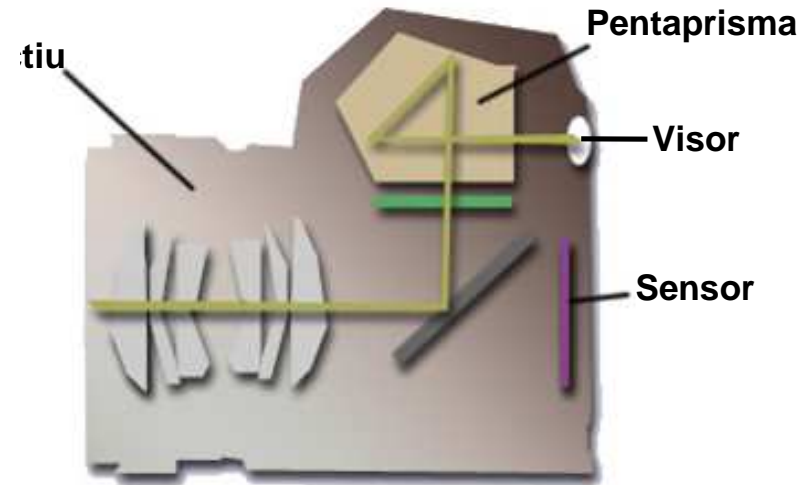
Estrategia laptop : Wet pc



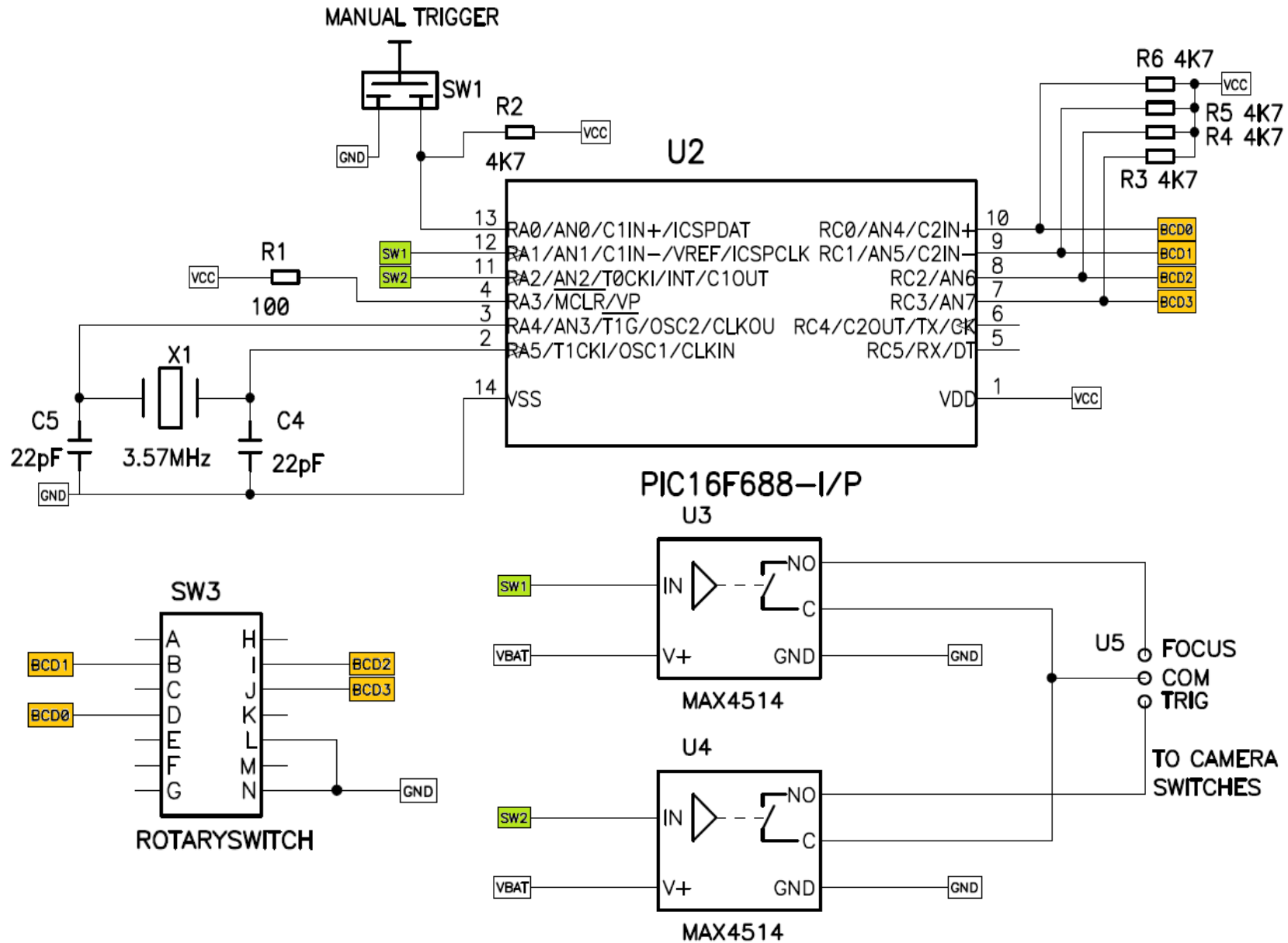
Estratègia Cameres amb targetes



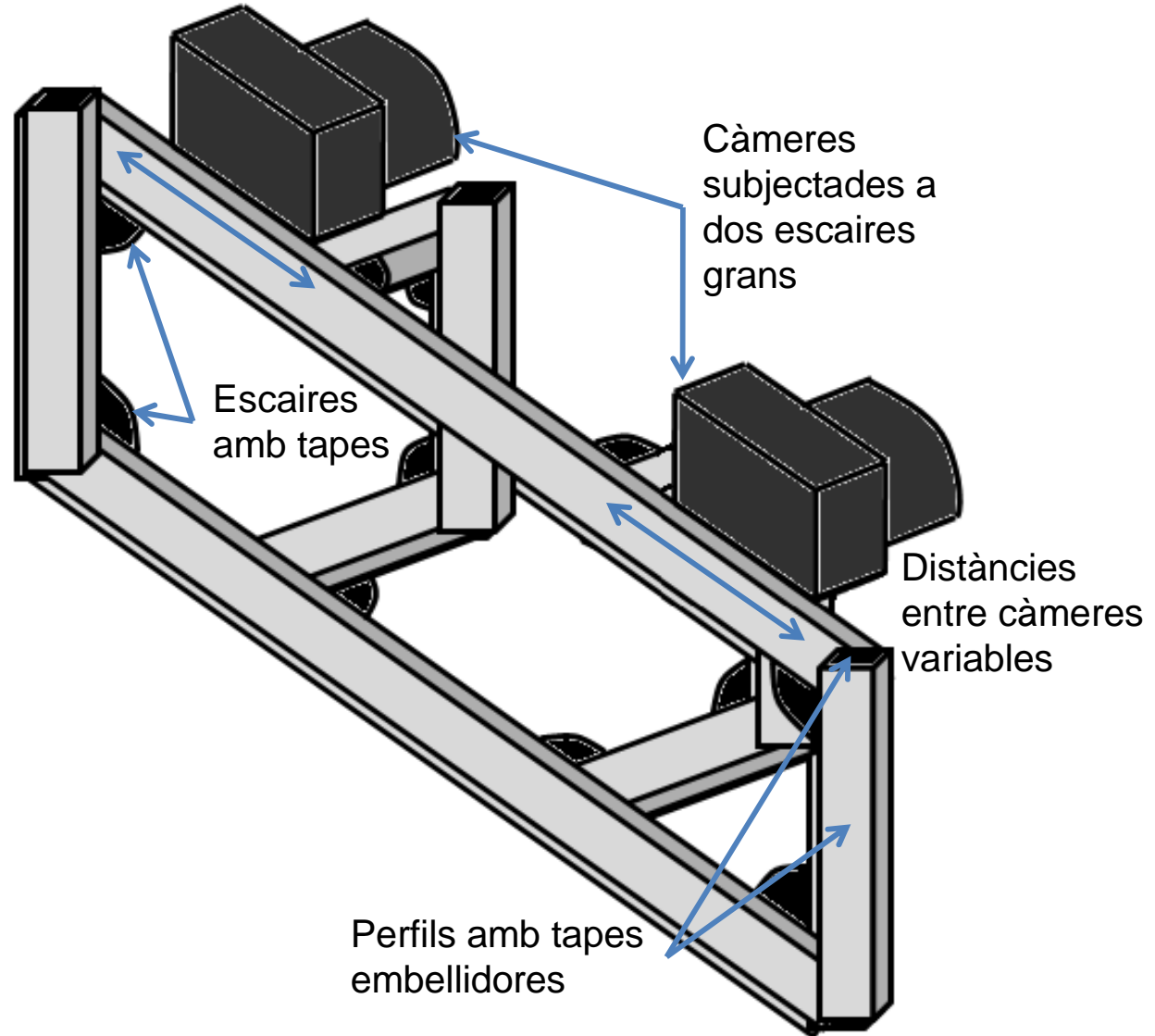
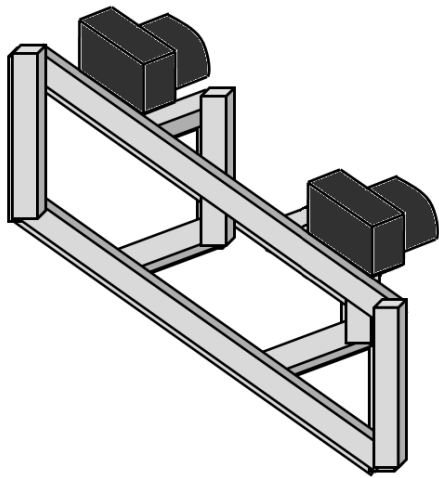
CAMERES REFLEX



CIRCUIT SINCRONISME



Estructura de suport



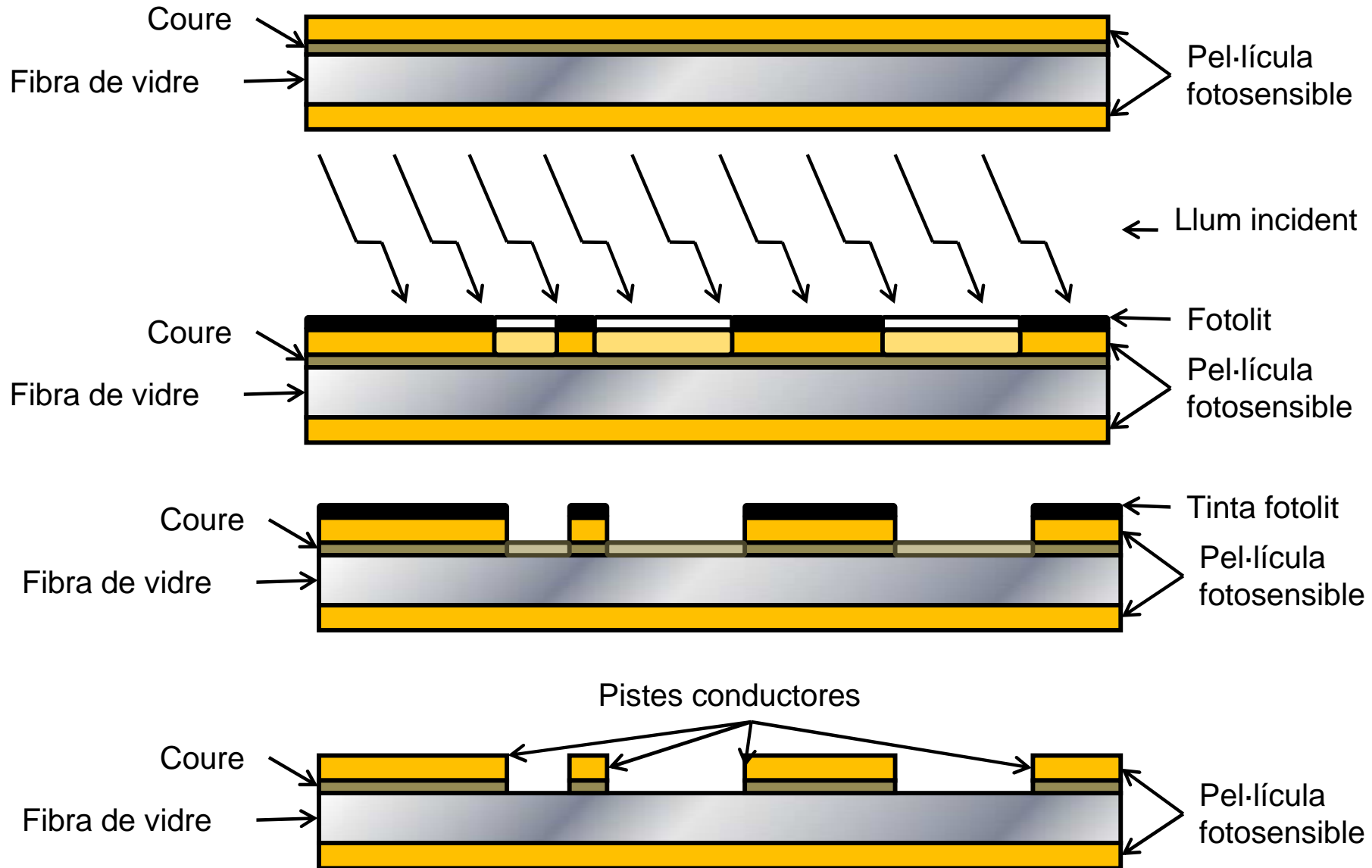
Càmeres
subjectades a
dos escaires
grans

Escaires
amb tapes

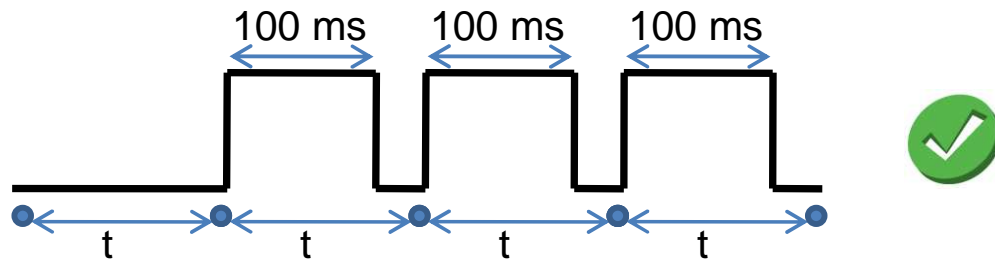
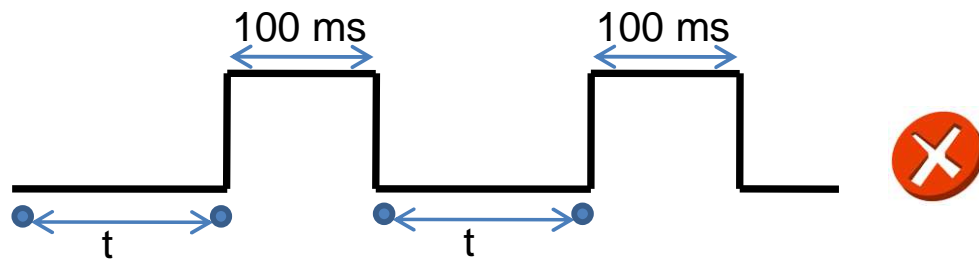
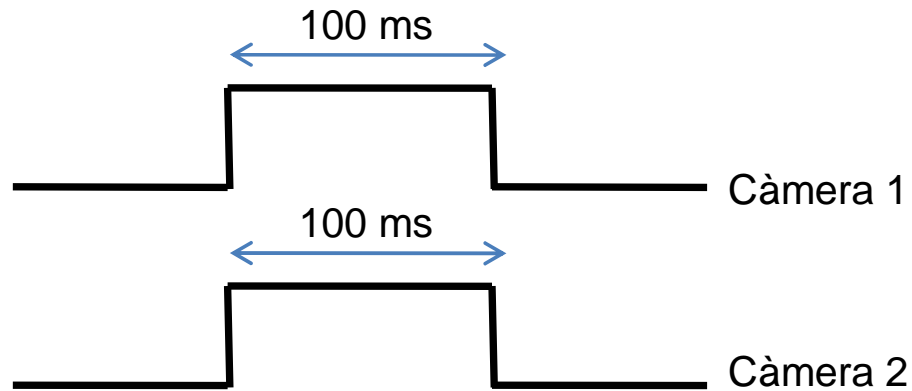
Distàncies
entre càmeres
variables

Perfils amb tapes
embellidores

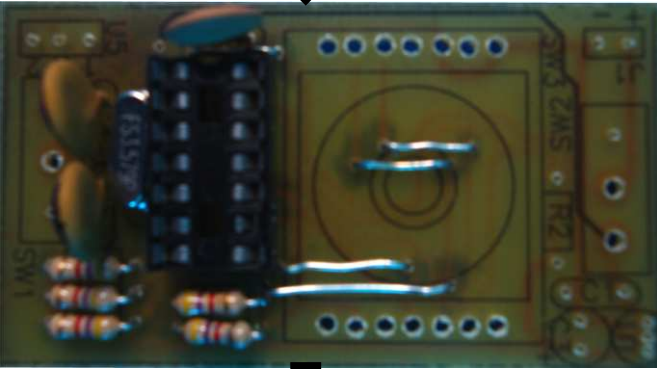
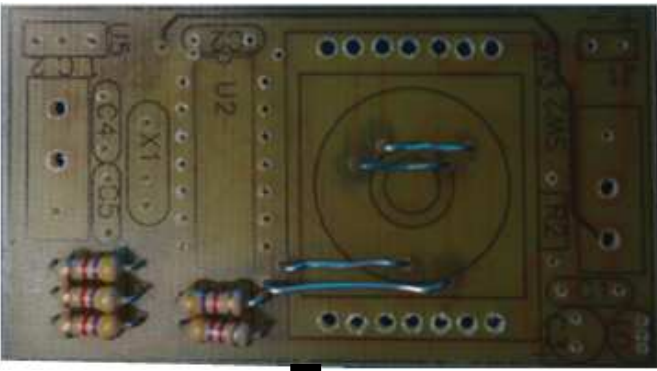
placa



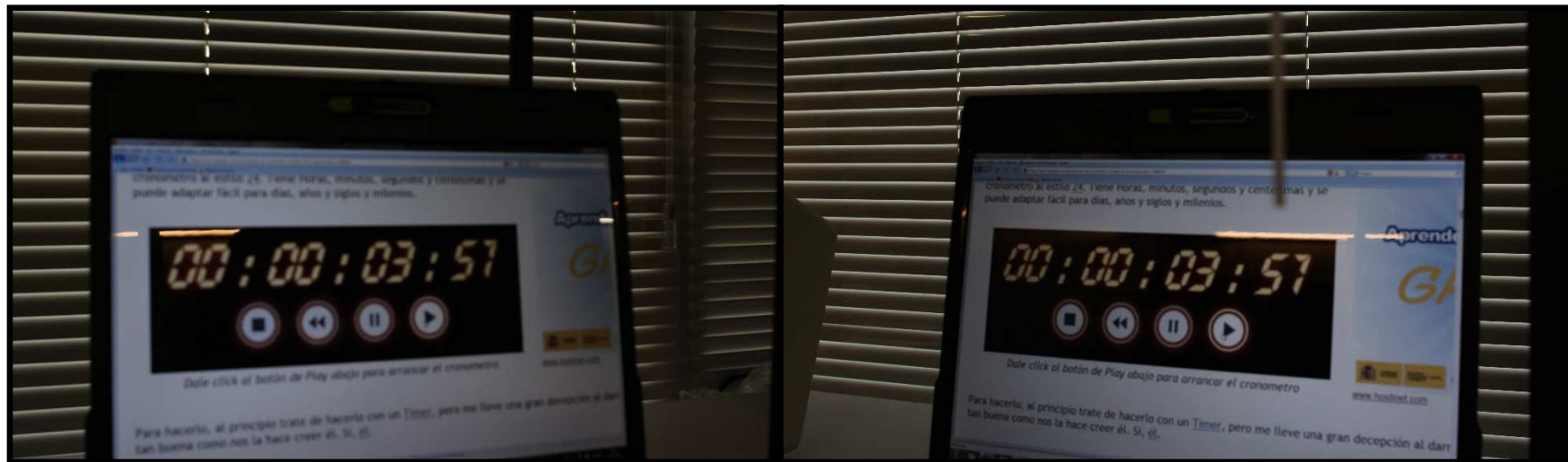
Temps cameraTrigger



CIRCUIT



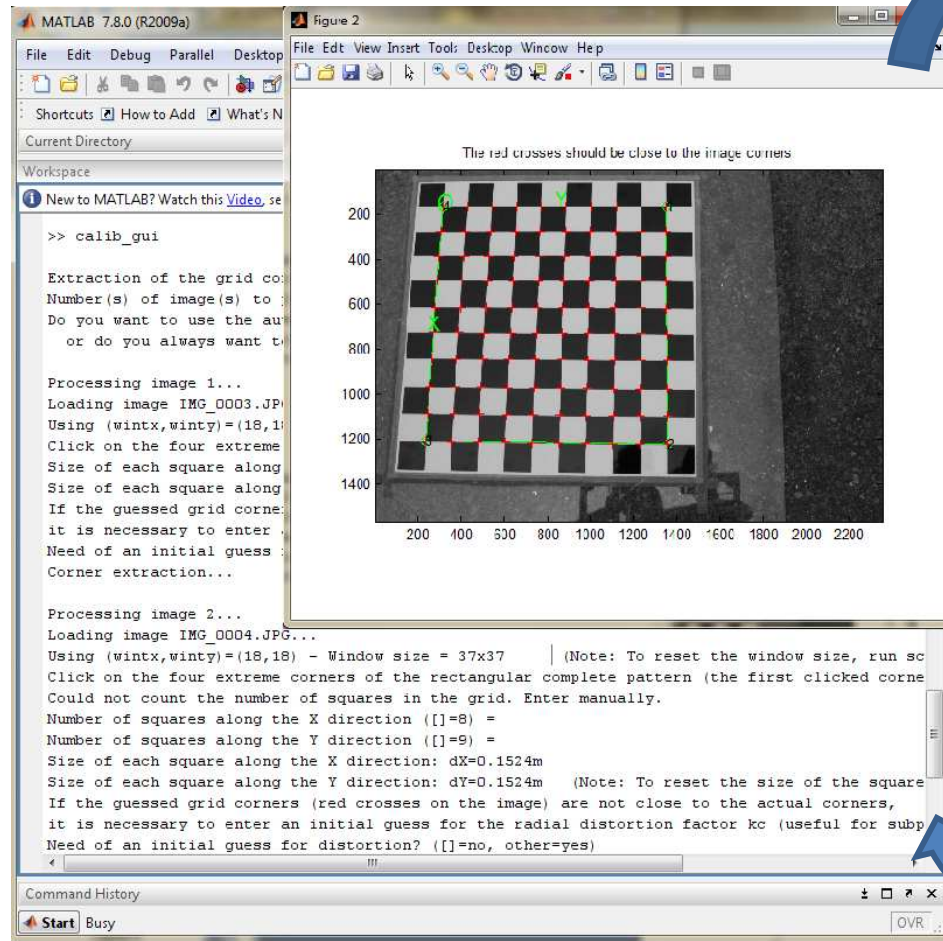
resultats



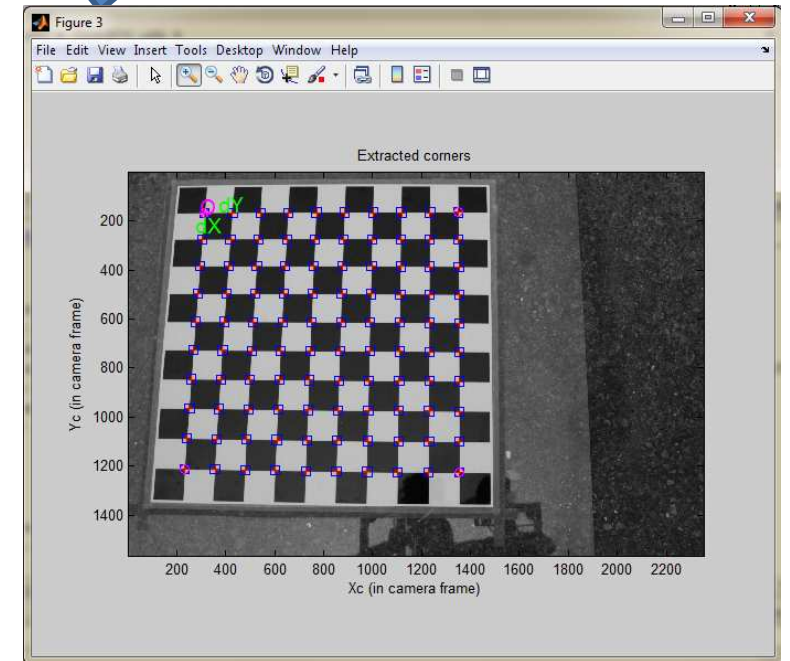
results2



calibració



Extreure els
corners



Per cada
imatge

calibració

Càmera esquerra:

Calibration results (with uncertainties):

Focal Length: $fc = [2641.46819 \quad 2641.46819] \pm [5.50659 \quad 5.50659]$
Principal point: $cc = [1171.16768 \quad 806.10335] \pm [1.56366 \quad 3.14623]$
Skew: $\alpha_c = [0.00000] \pm [0.00000] \Rightarrow$ angle of pixel axes = 90.00000 ± 0.00000 degrees
Distortion: $kc = [-0.08200 \quad 0.00000 \quad -0.00118 \quad -0.00000 \quad 0.00000] \pm [0.00114 \quad 0.00000 \quad 0.00028 \quad 0.00000 \quad 0.00000]$

Càmera dreta:

Calibration results (with uncertainties):

Focal Length: $fc = [2626.58373 \quad 2626.58373] \pm [5.14031 \quad 5.14031]$
Principal point: $cc = [1170.98111 \quad 773.16358] \pm [1.63917 \quad 3.31582]$
Skew: $\alpha_c = [0.00000] \pm [0.00000] \Rightarrow$ angle of pixel axes = 90.00000 ± 0.00000 degrees
Distortion: $kc = [-0.07521 \quad 0.00000 \quad -0.00309 \quad -0.00000 \quad 0.00000] \pm [0.00125 \quad 0.00000 \quad 0.00031 \quad 0.00000 \quad 0.00000]$

calibració

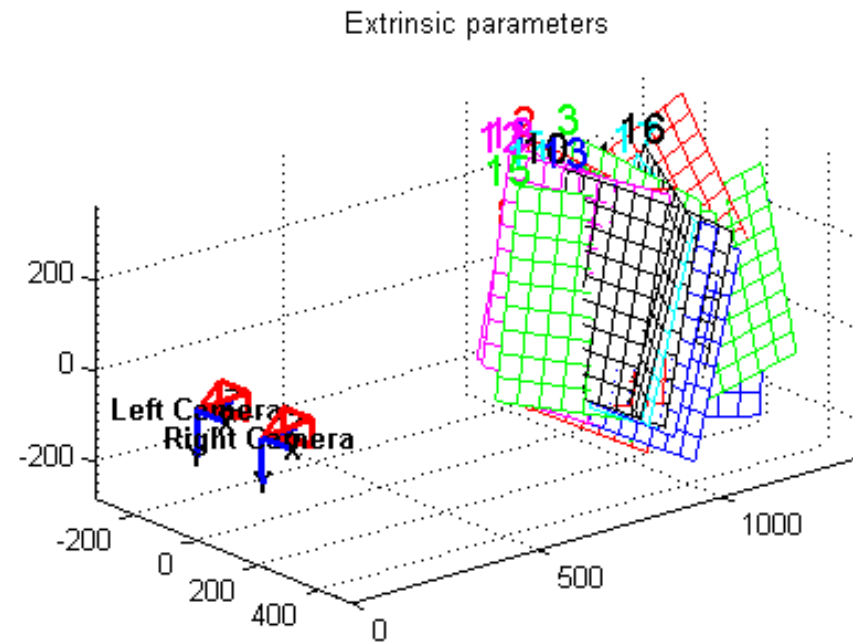
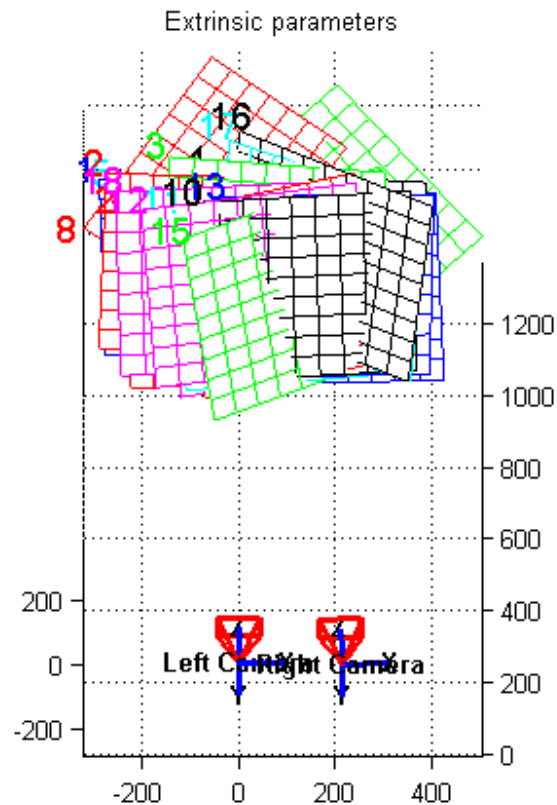
Extrinsic parameters (position of right camera wrt left camera):

Rotation vector:

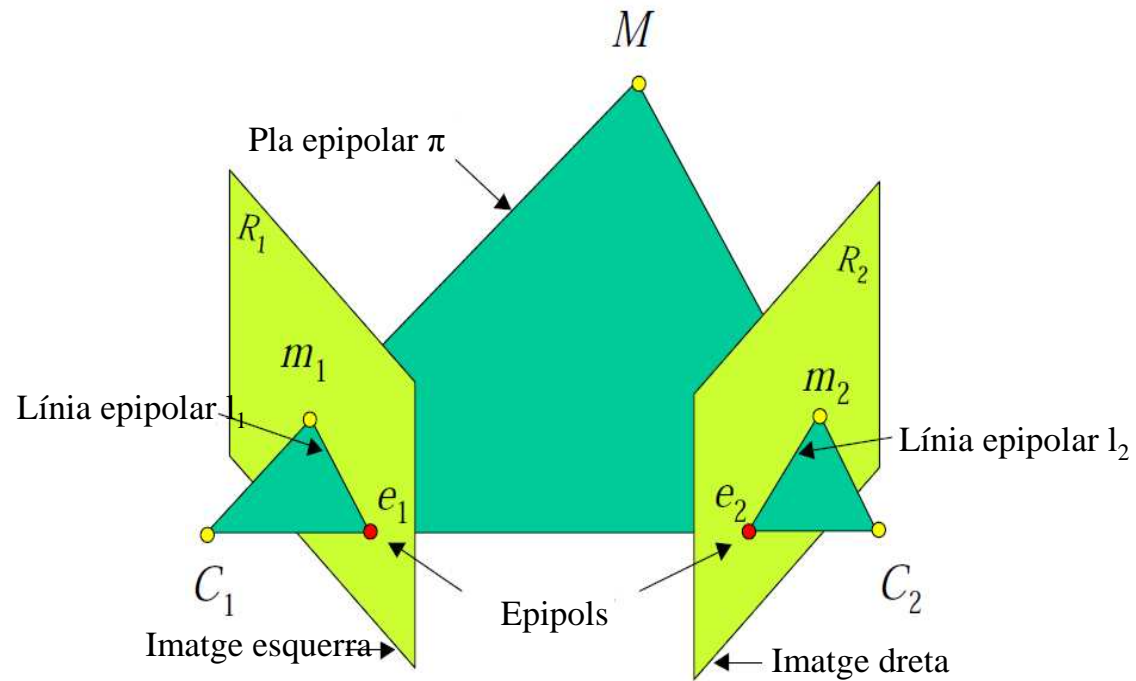
$\text{om} = [-0.00763 \quad 0.03809 \quad 0.00022]$

Translation vector:

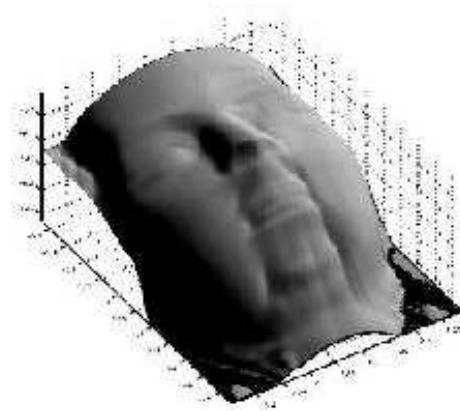
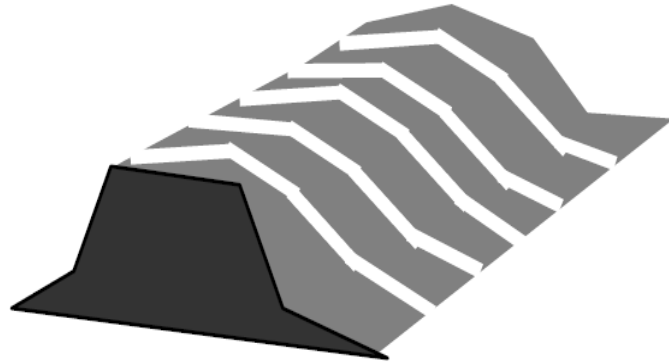
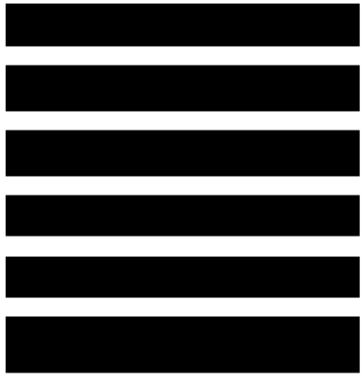
$T = [-215.13396 \quad 1.37844 \quad 13.36574]$



Geometria epipolar



Altres reconstruccions 3d



Sistema de visió estereoscòpica (dues càmeres)

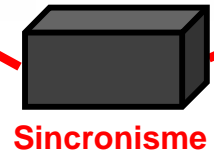
Anàlisi i estudi de les càmeres



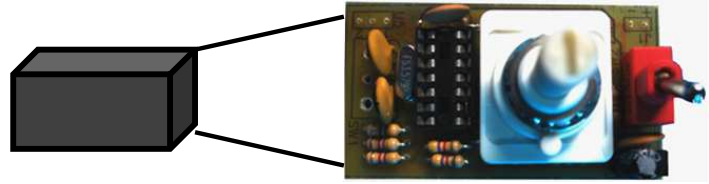
Sistema estèreo



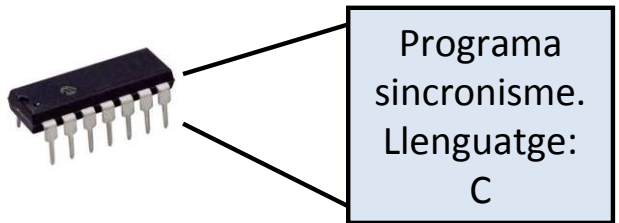
Problema sincronisme



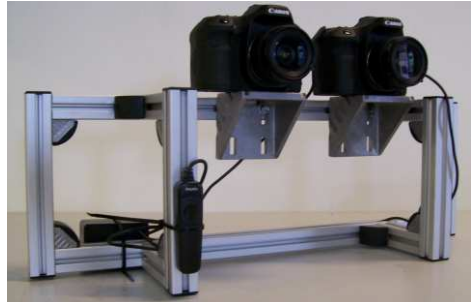
Hardware



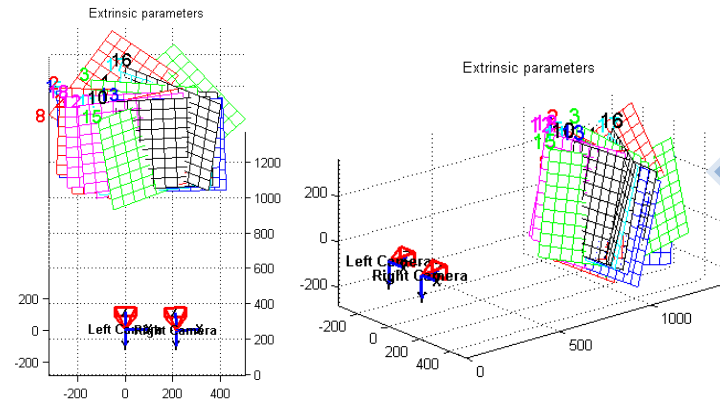
Software



Estructura de suport



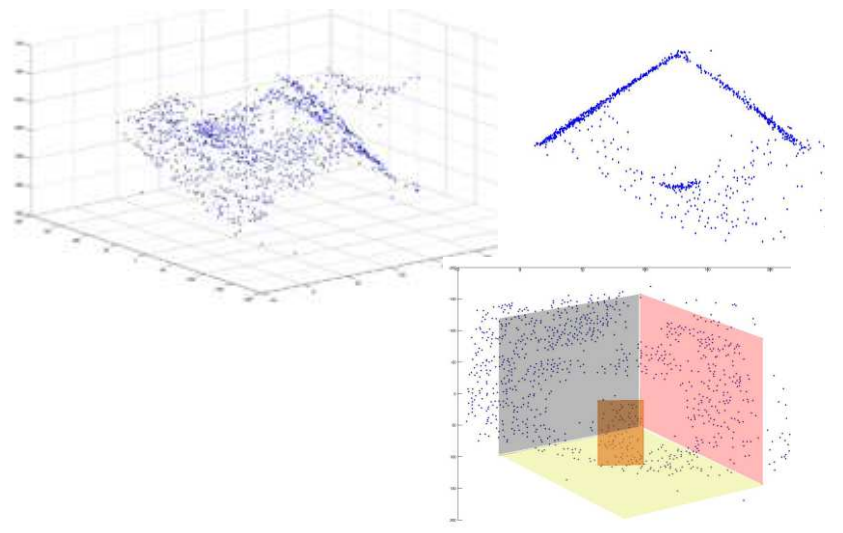
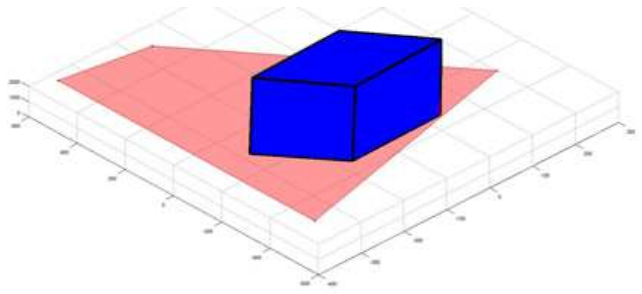
Calibració del sistema



Captura de seqüències

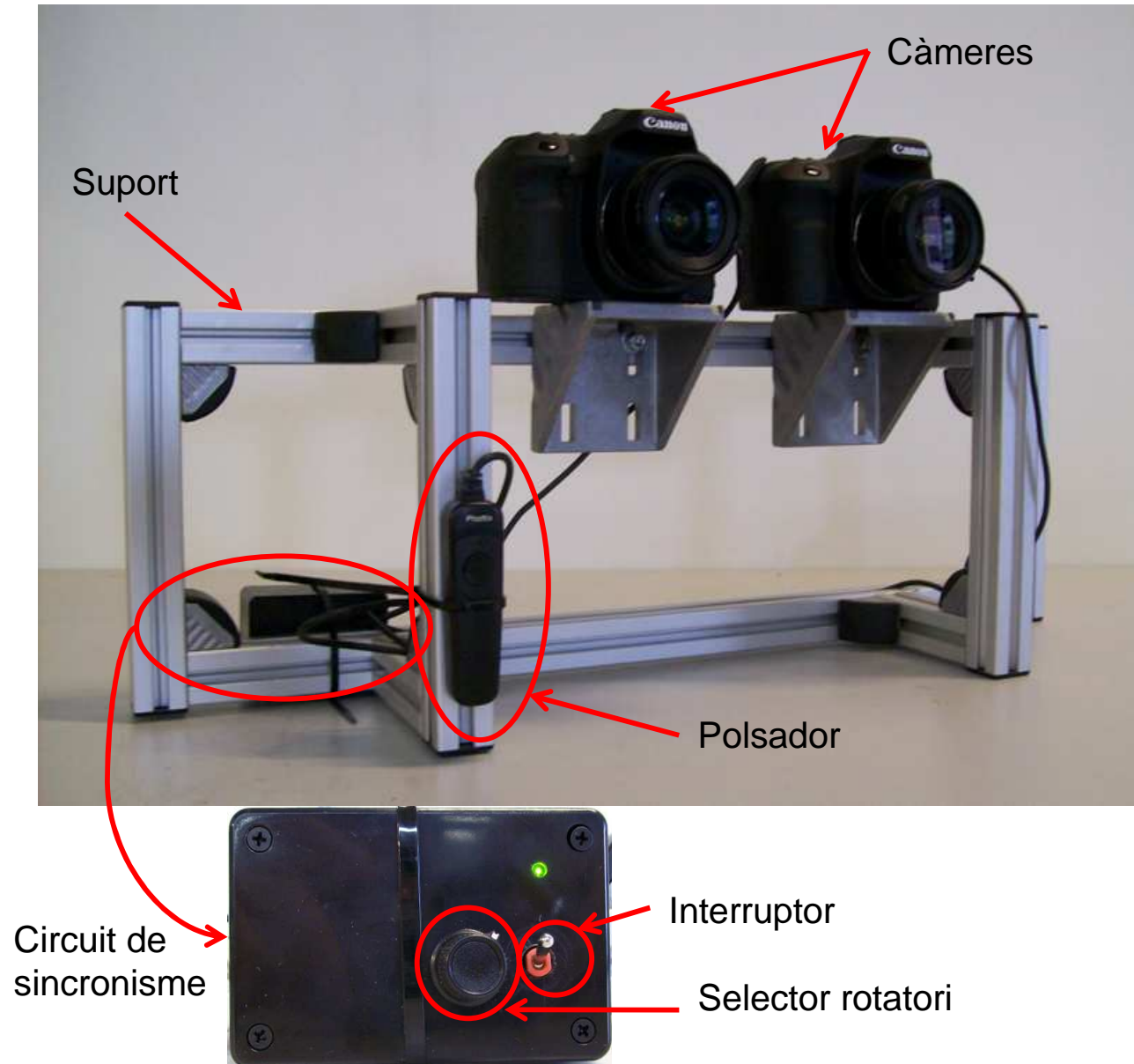


Reconstruccions 3D

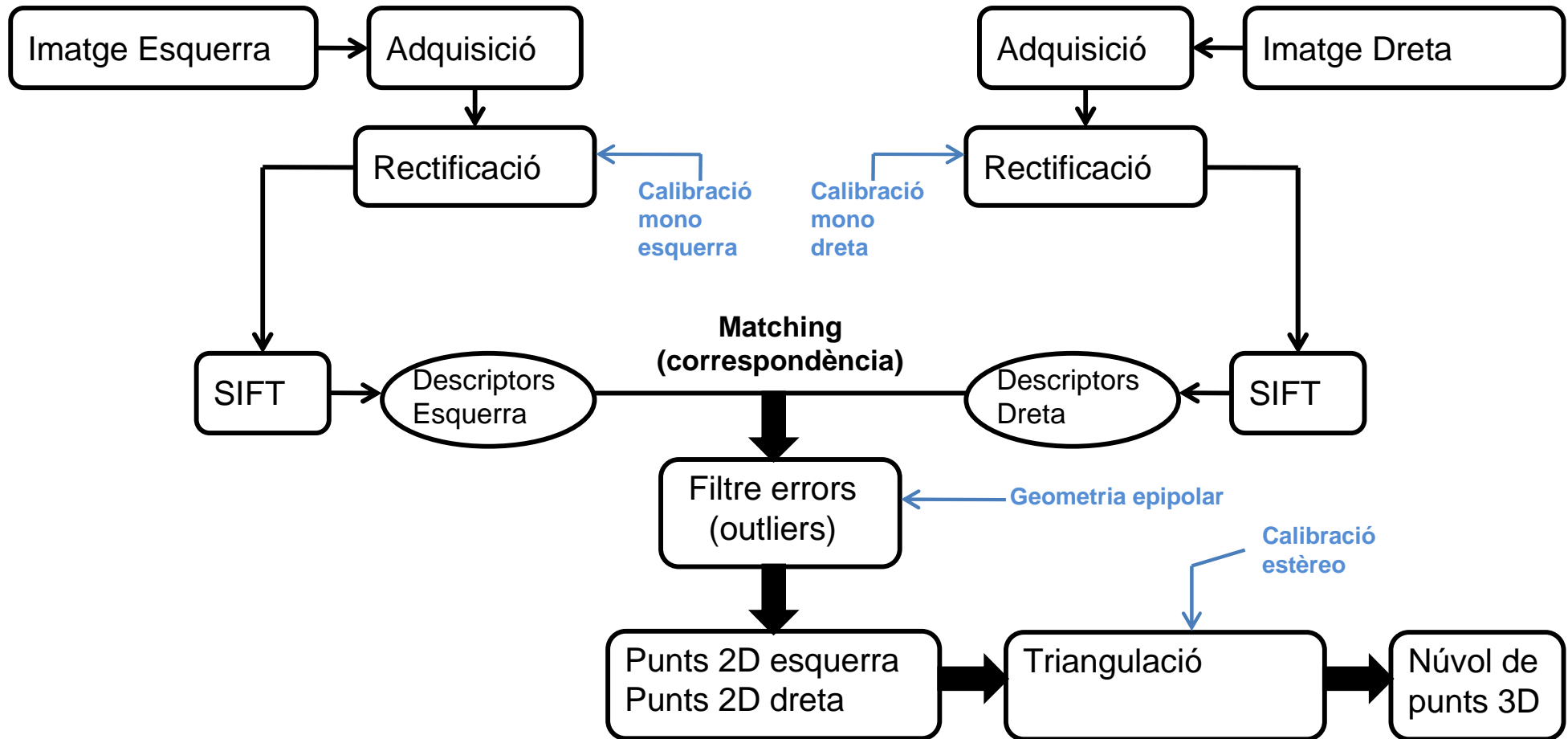


Validació del sistema

Esquema sistema



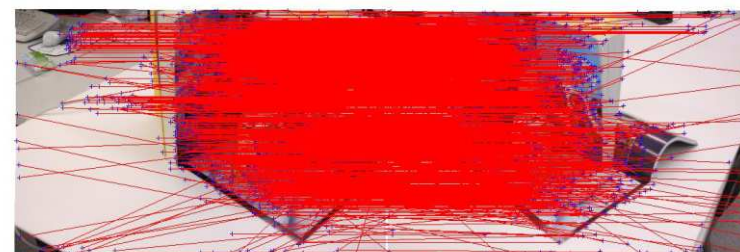
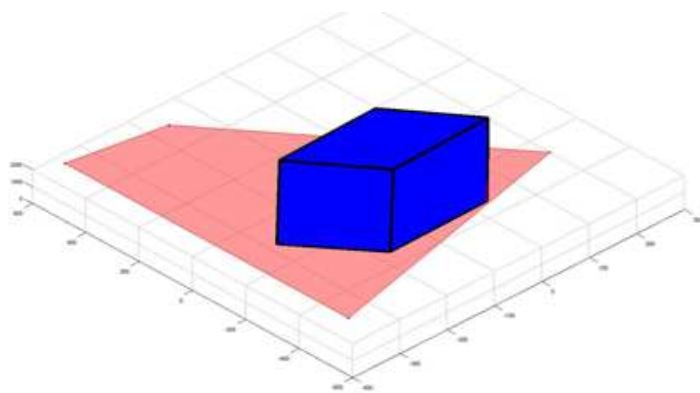
Esquema programa rec. 3D



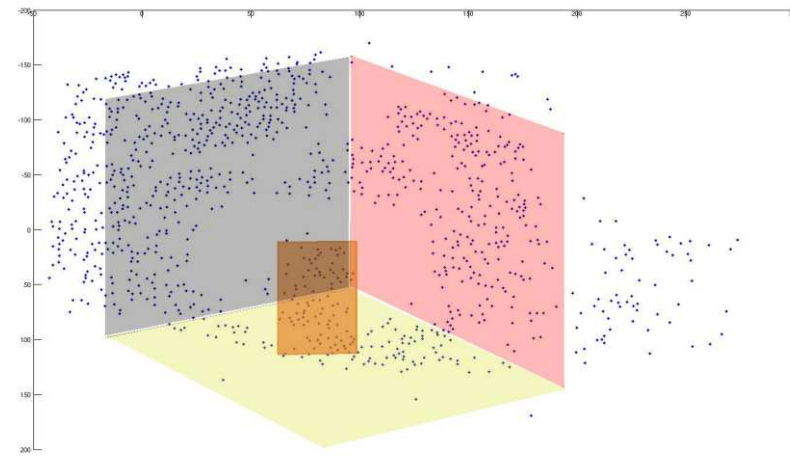
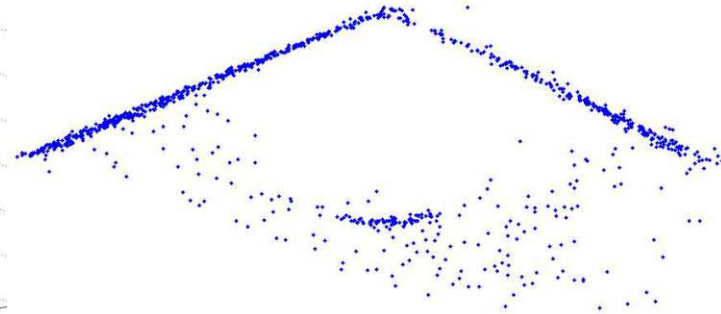
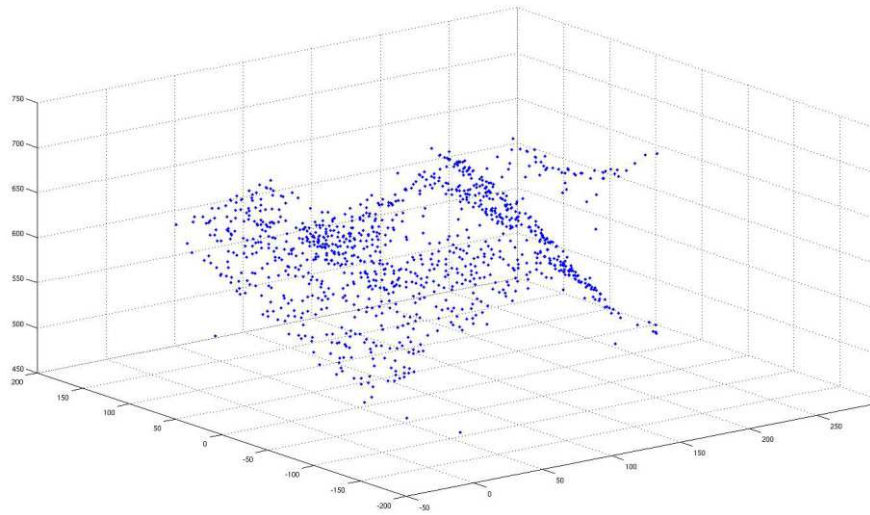
CAPTURES



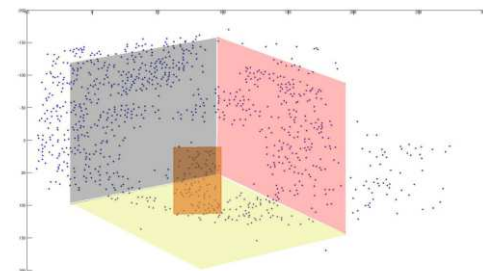
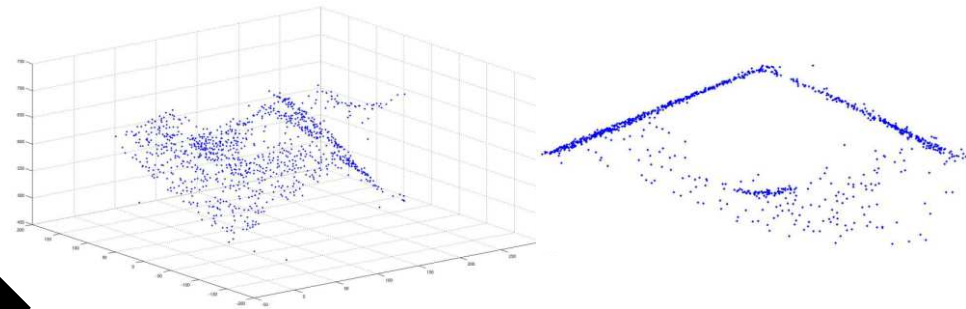
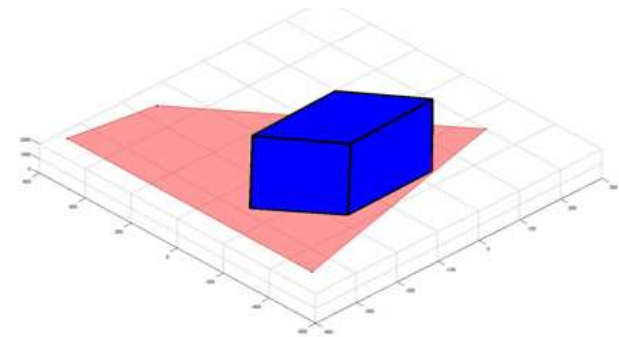
RECONSTRUCCIONES 3D

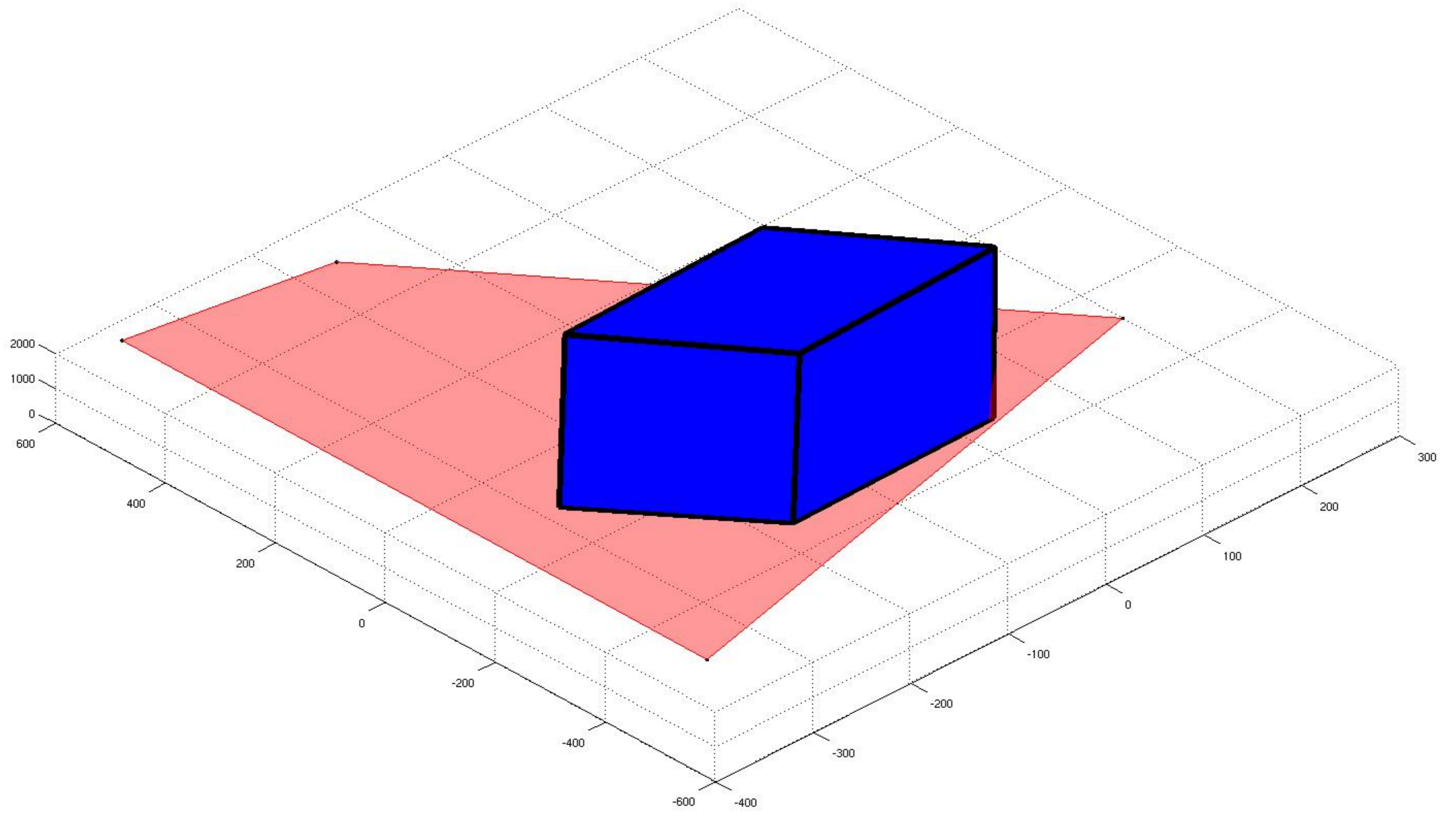


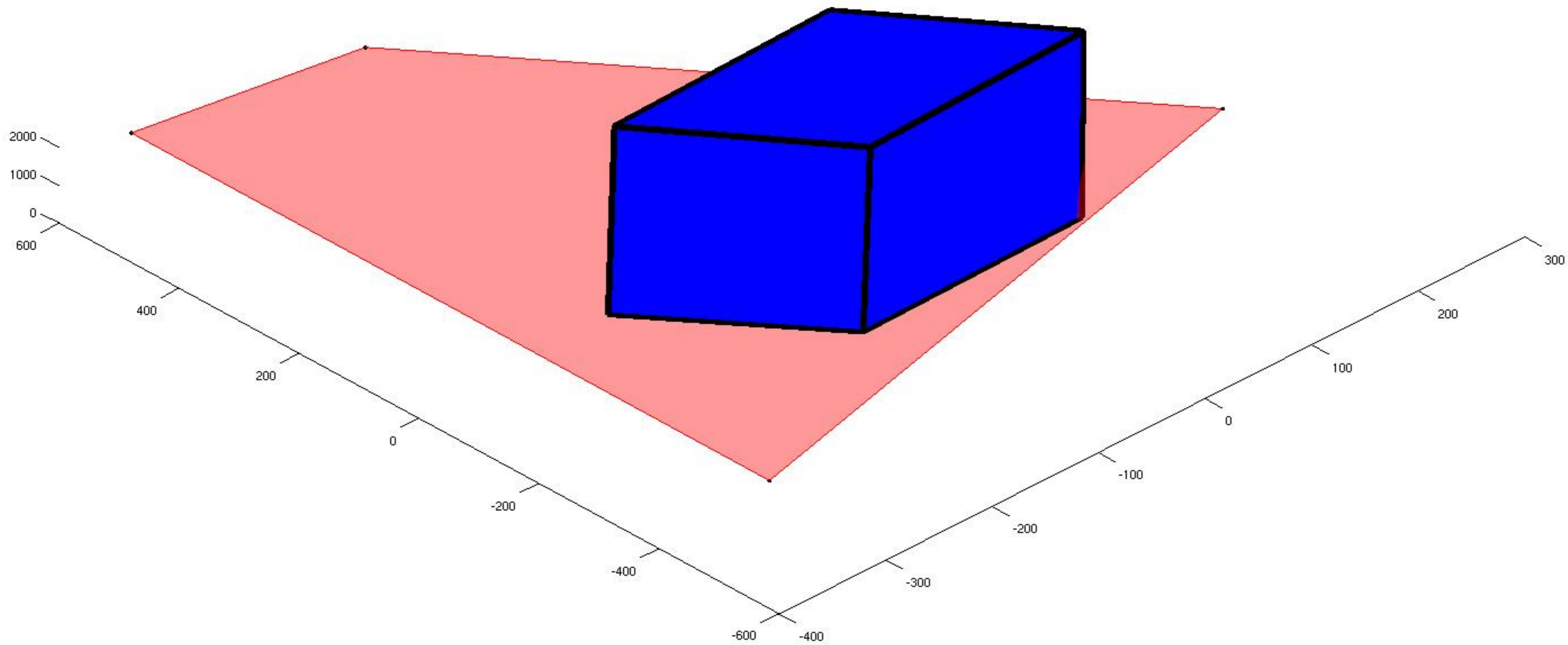
Reconstruccions 2

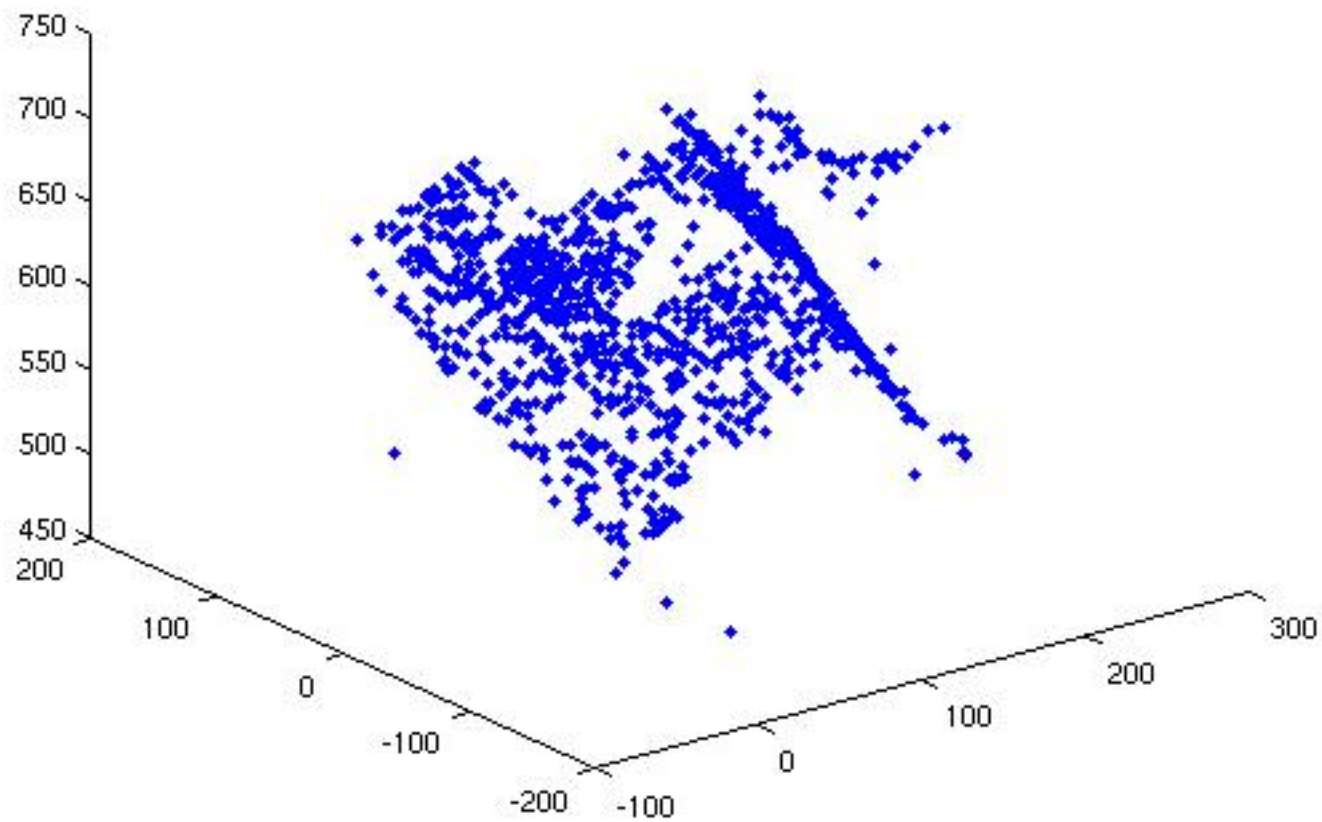


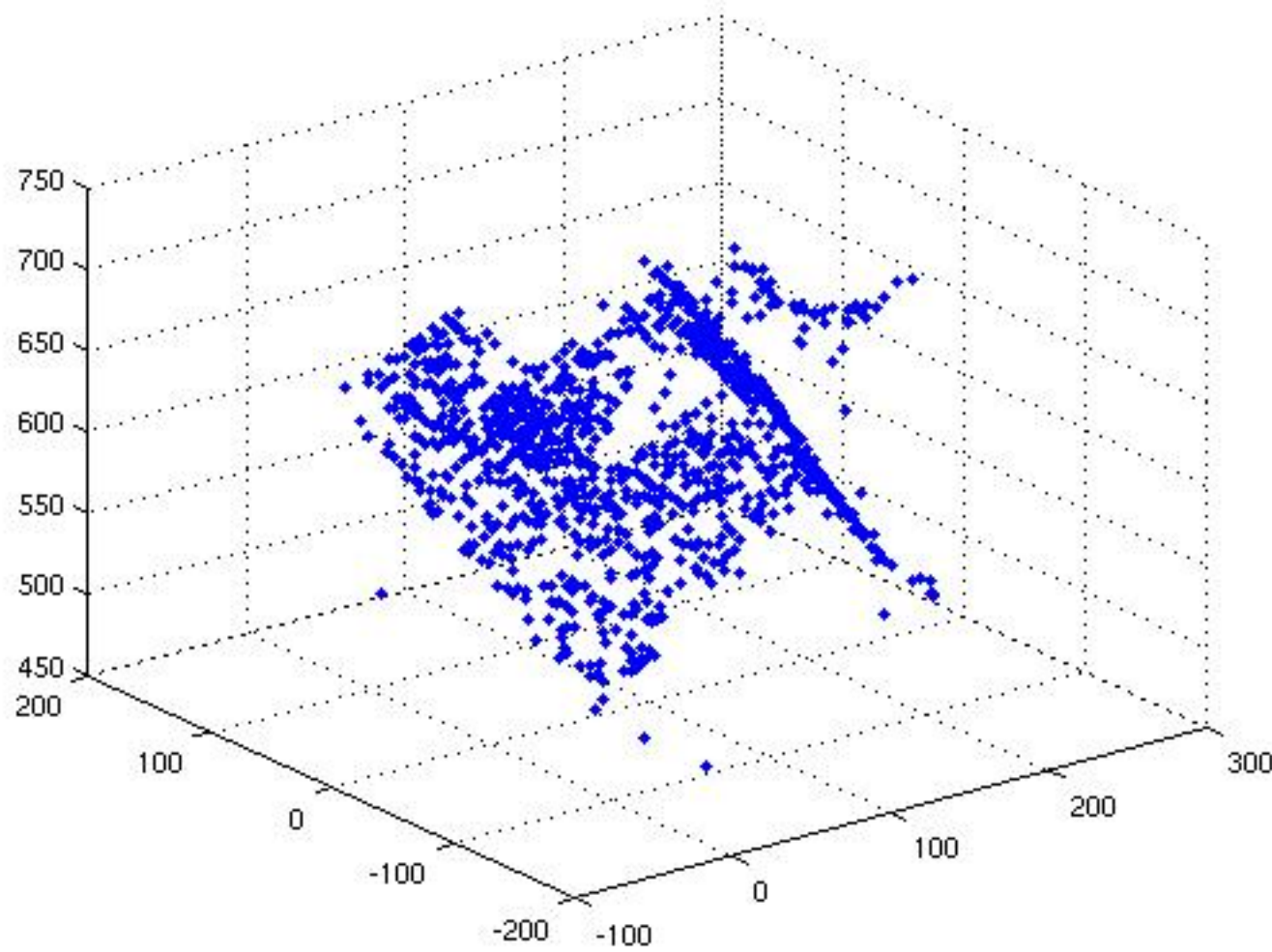
Results resum

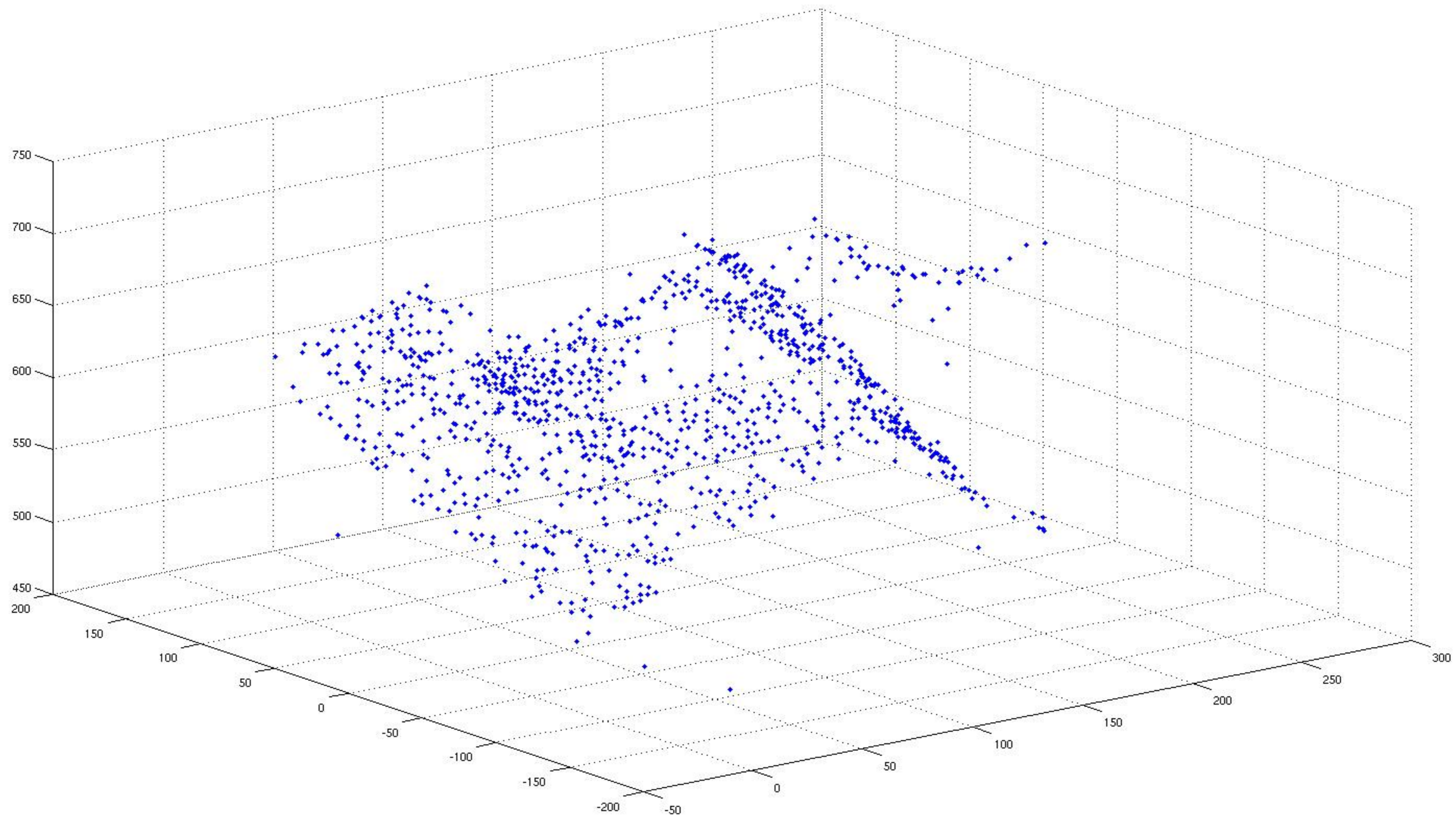


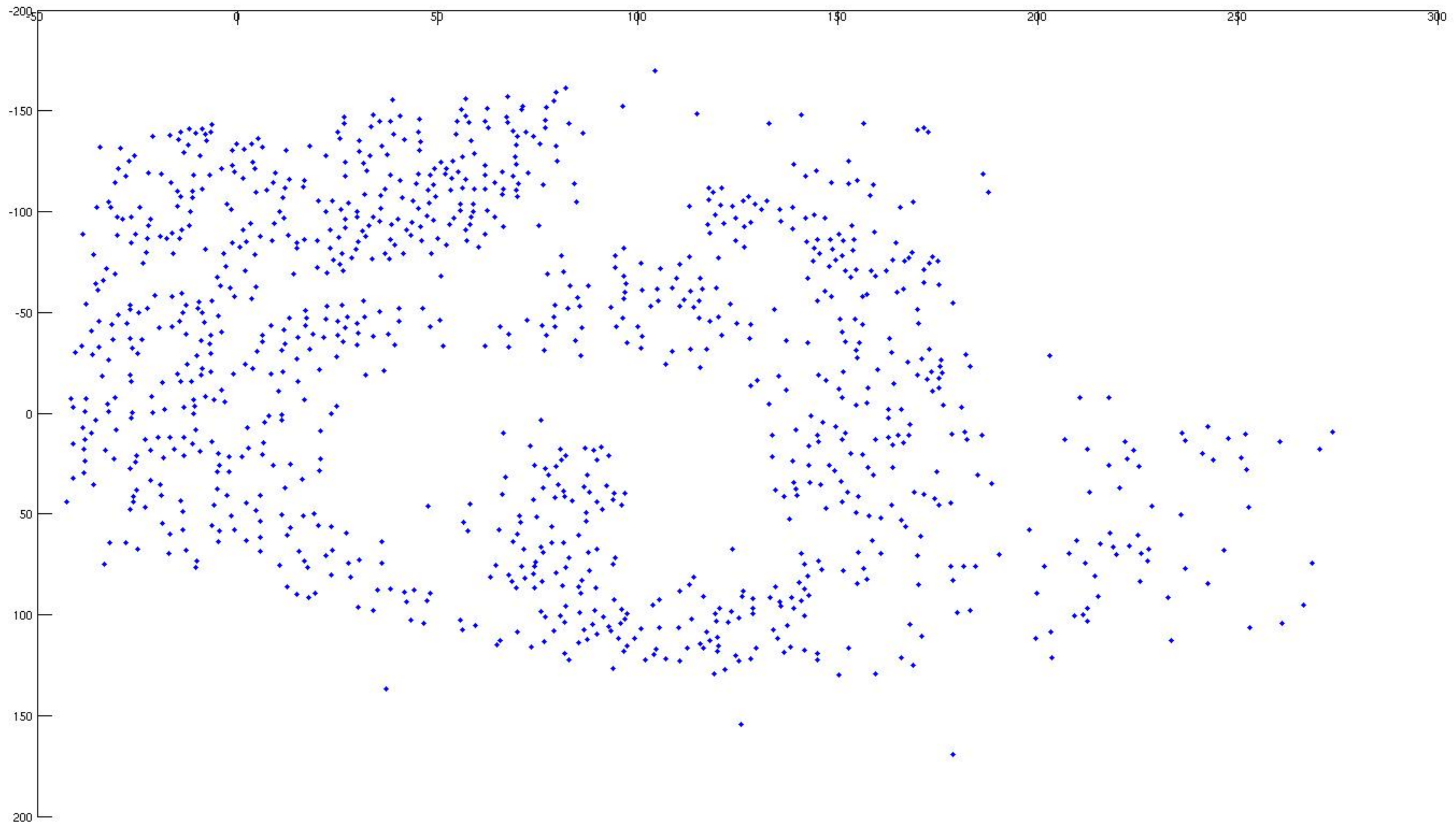


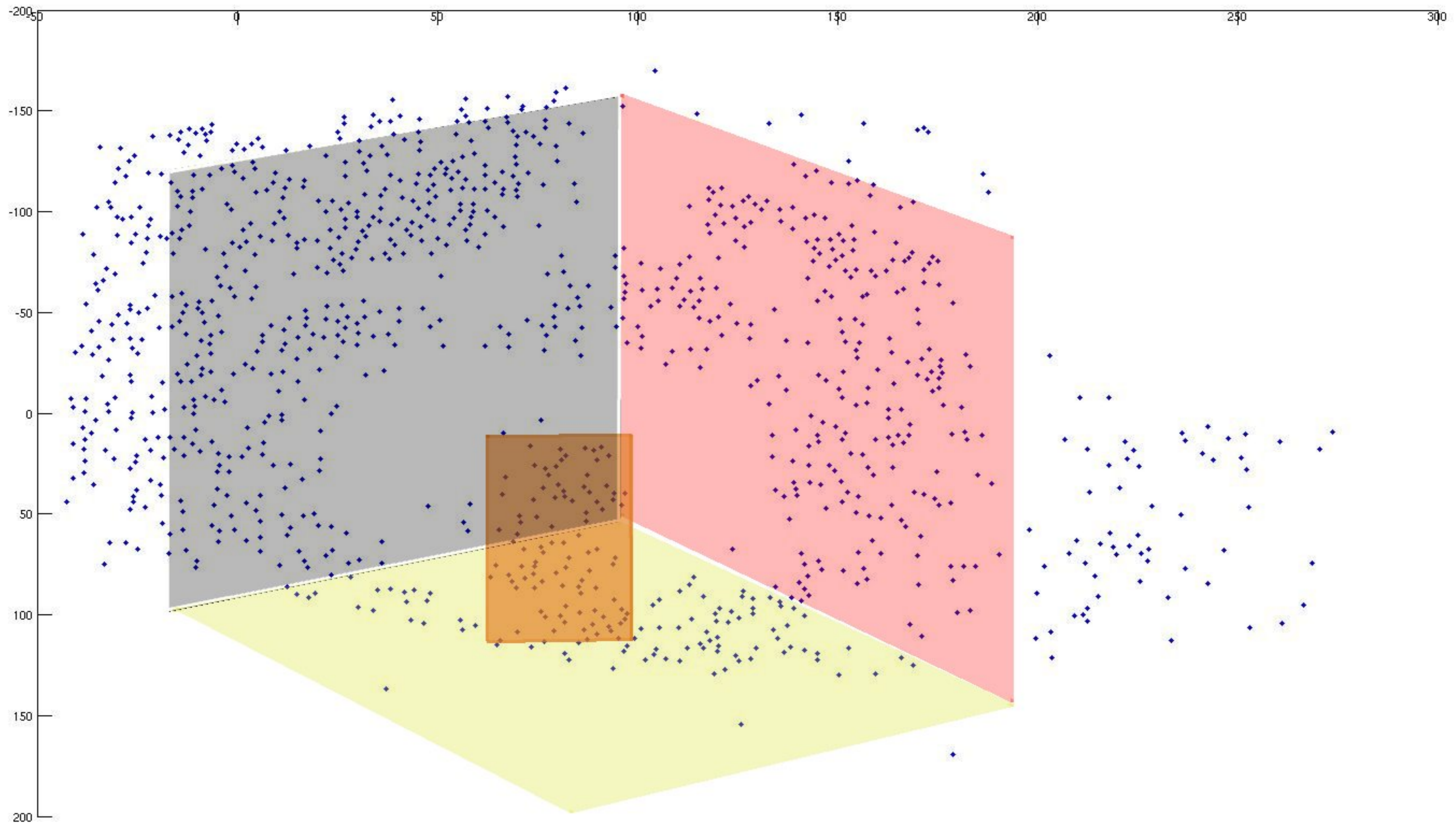


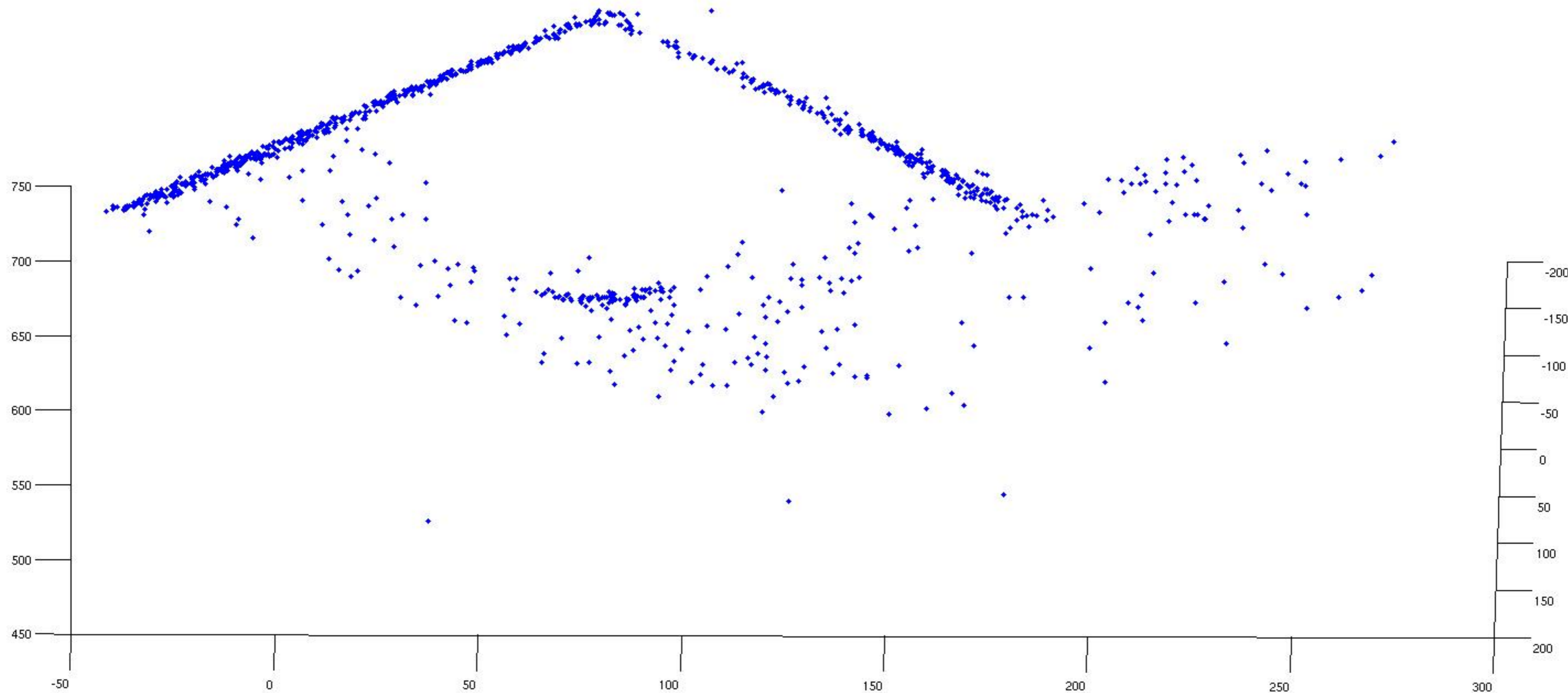






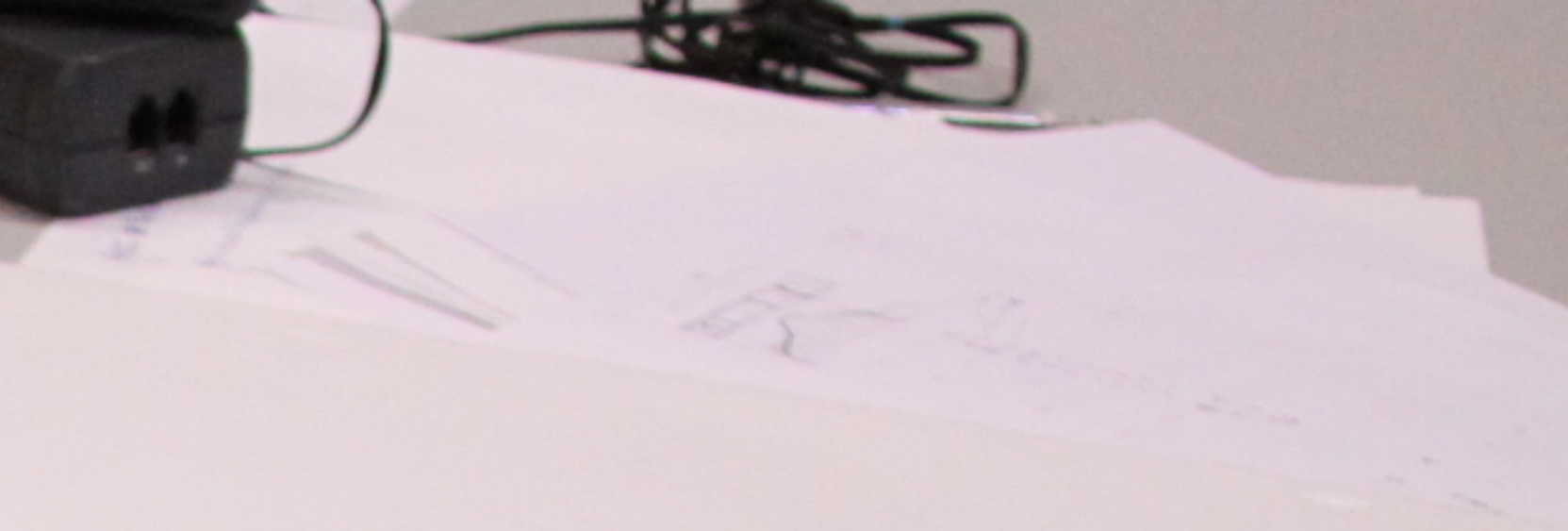
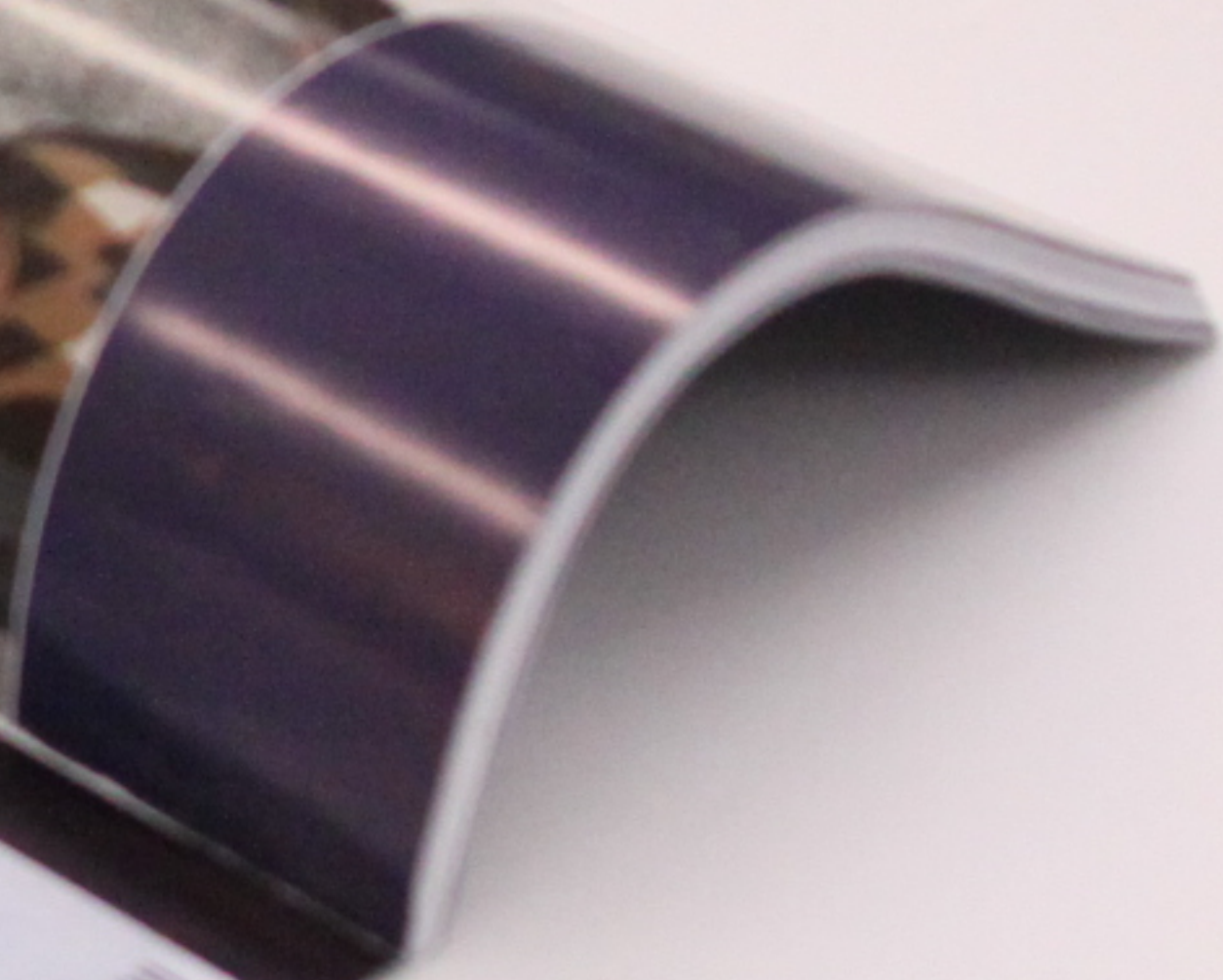
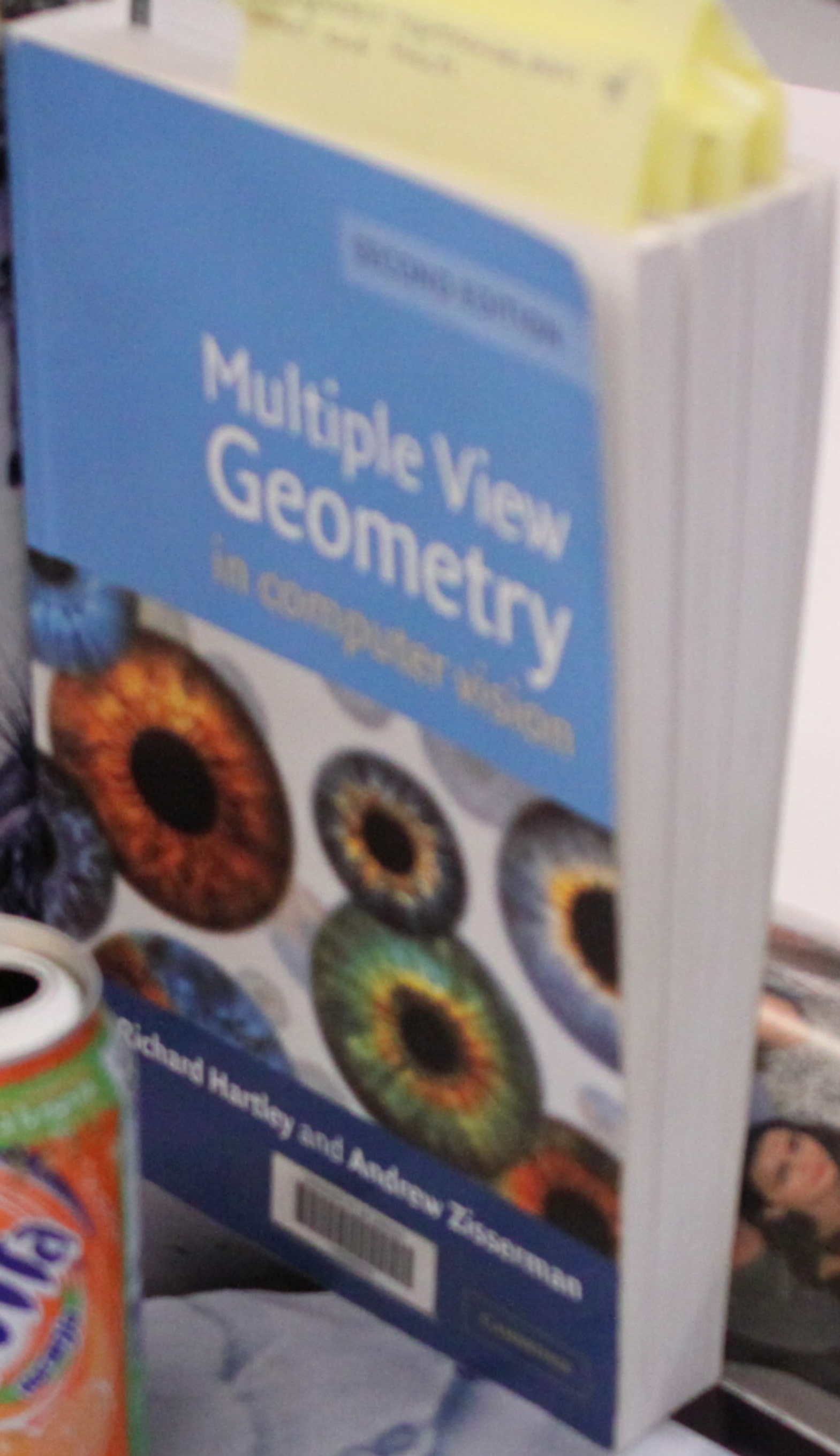




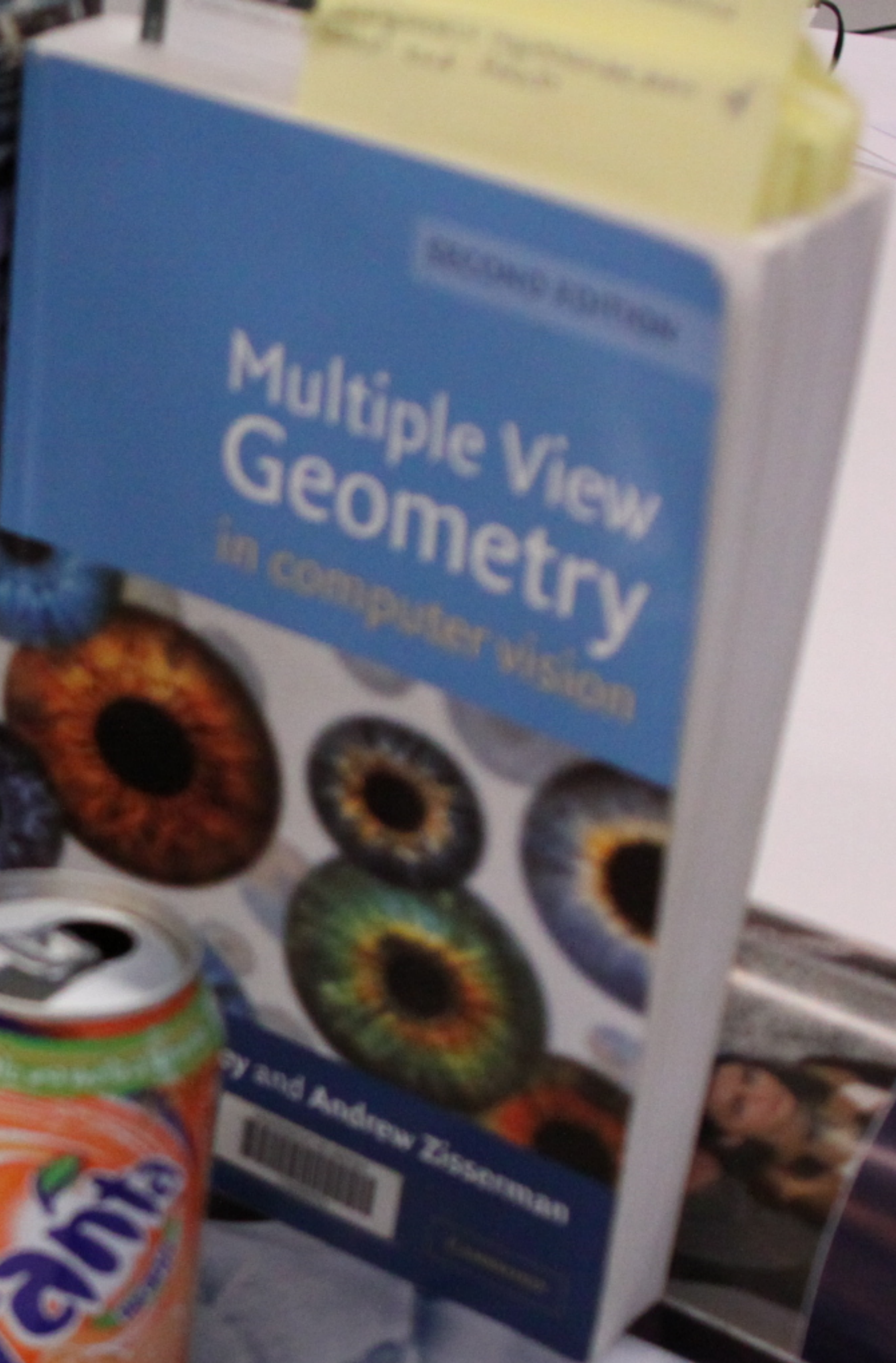
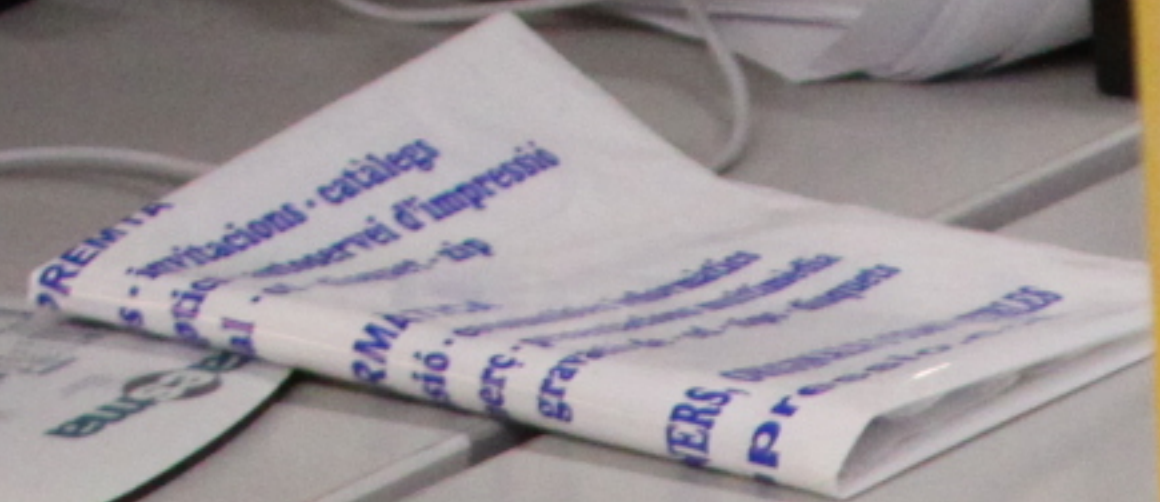


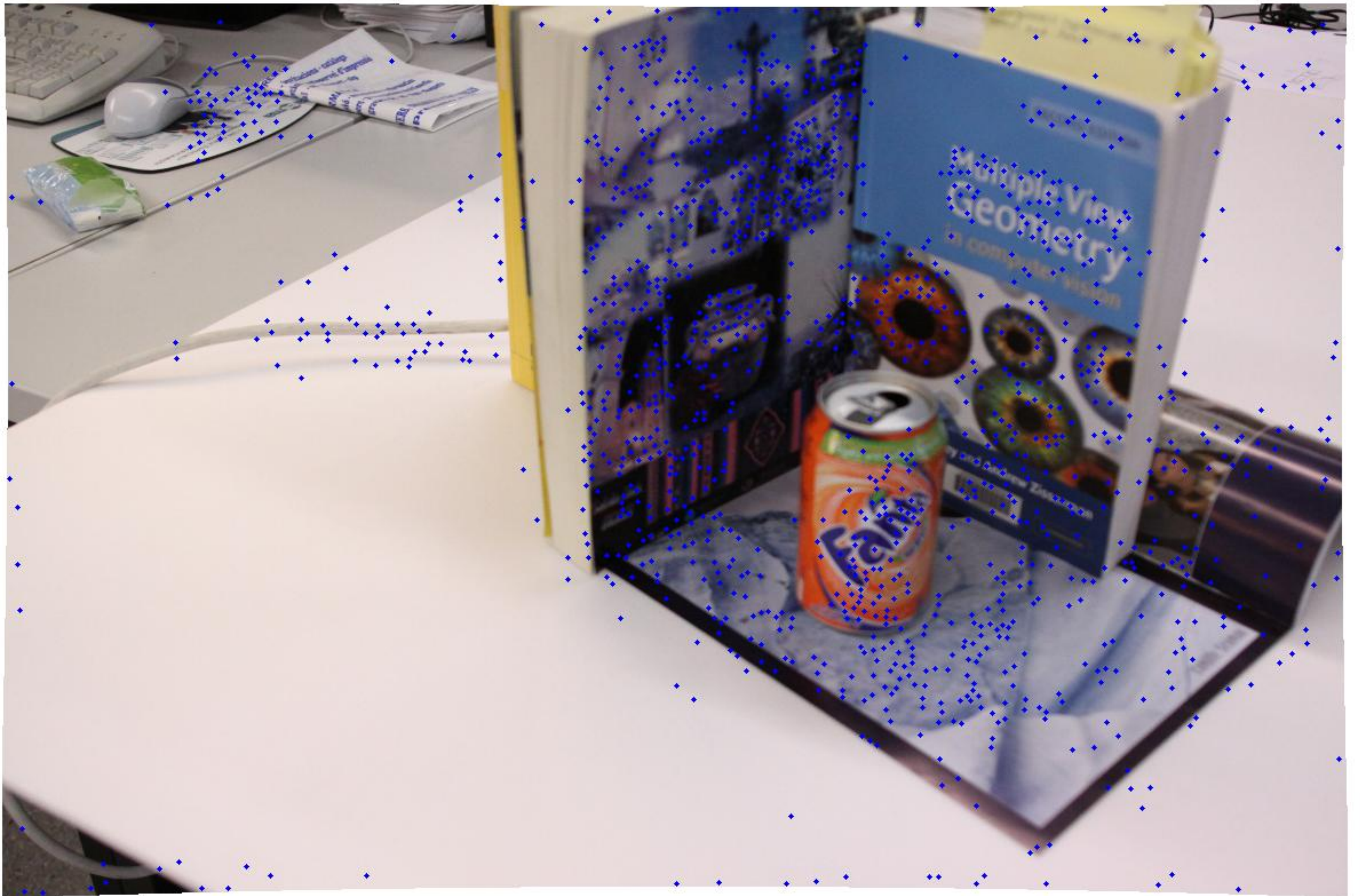


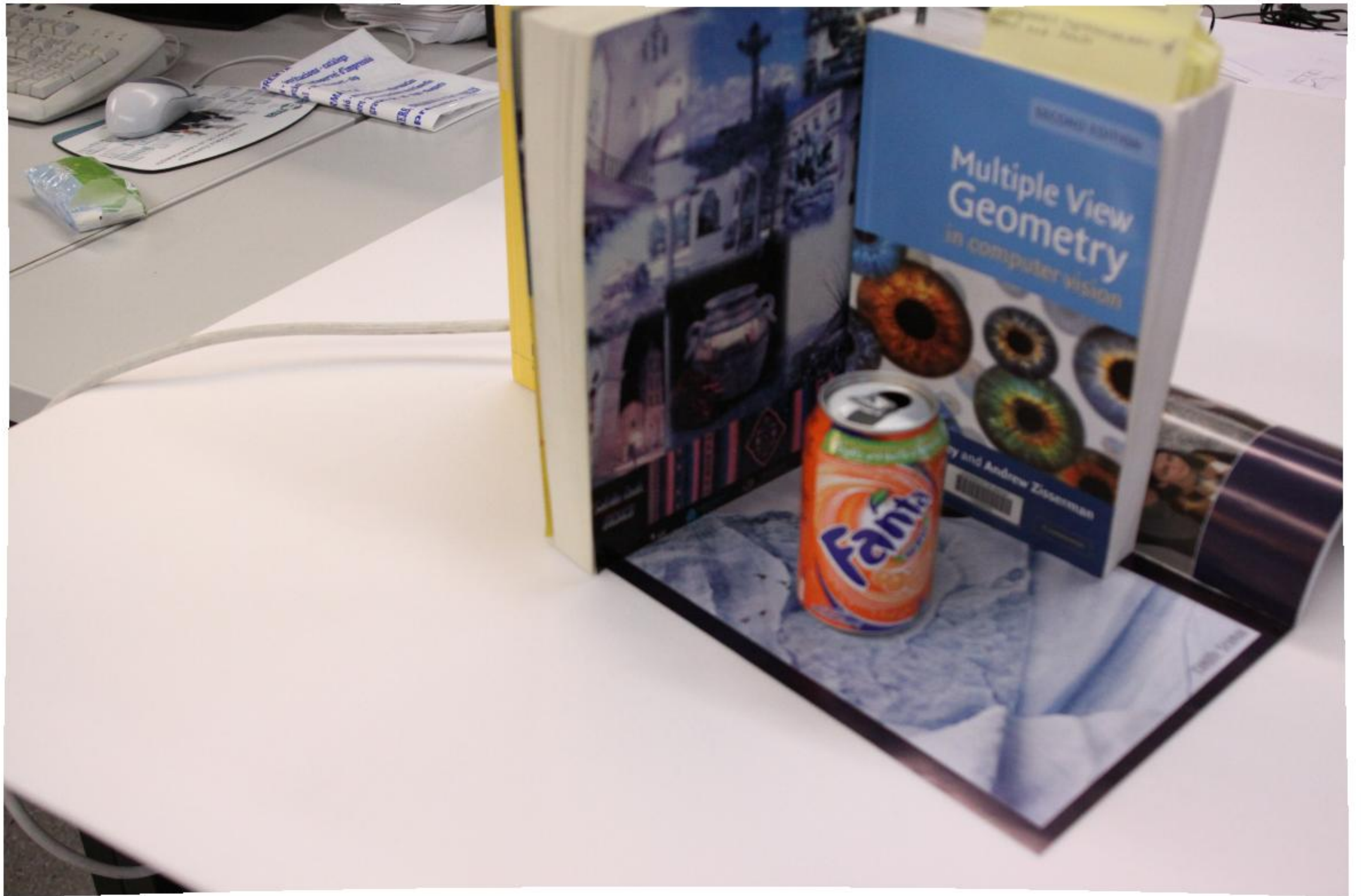










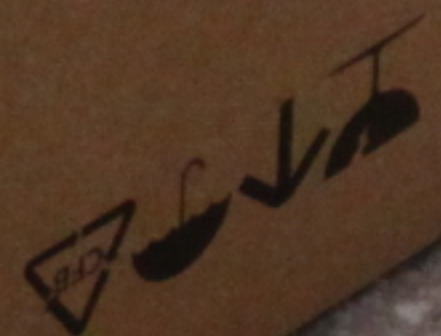




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