

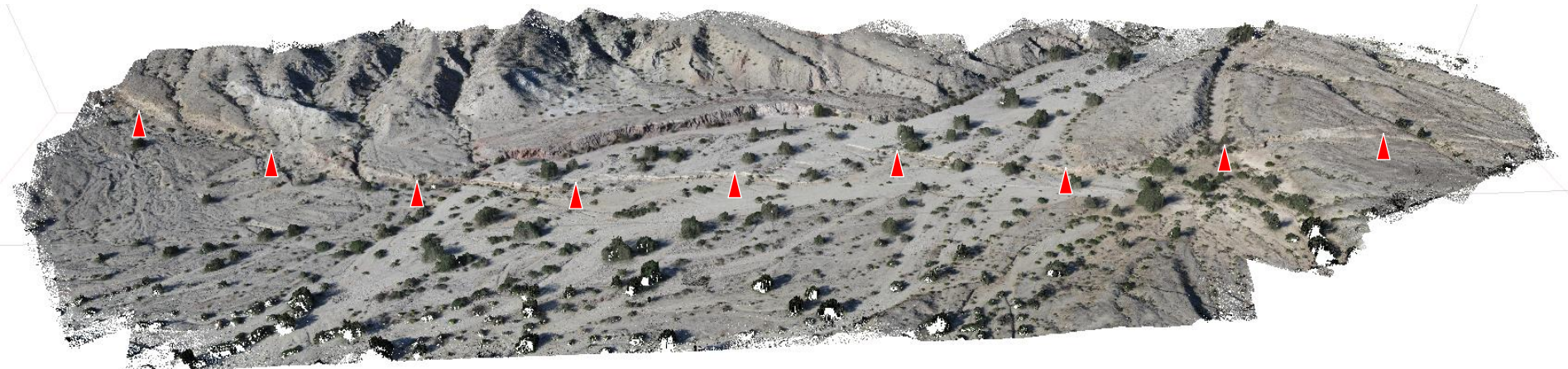
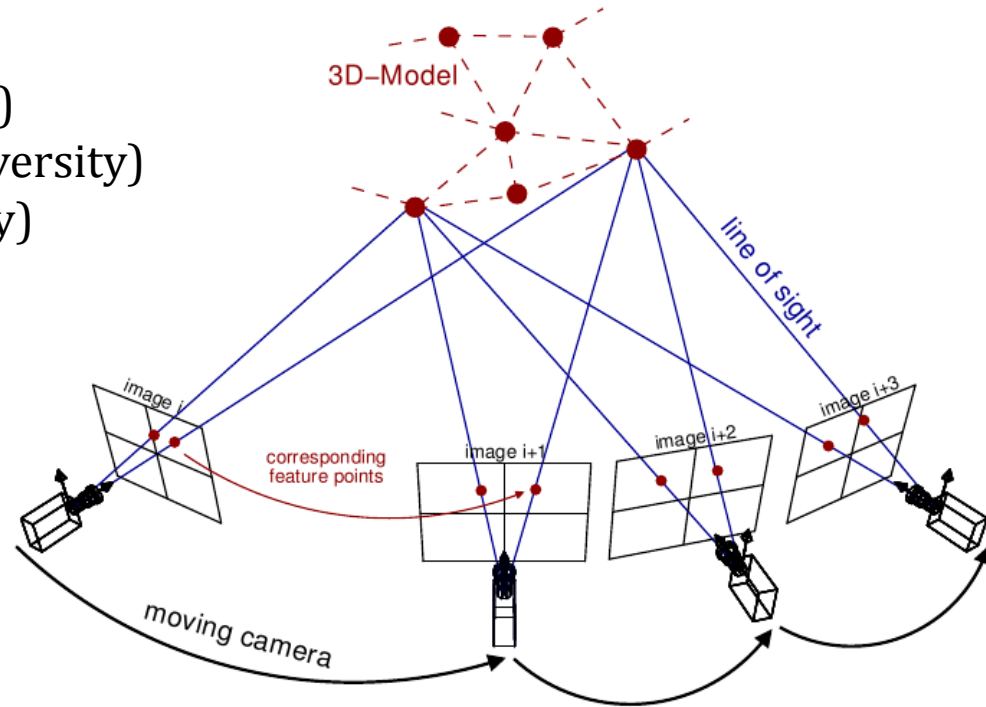
Introduction to Structure-from-Motion

Edwin Nissen (Colorado School of Mines)

J Ramon Arrowsmith (Arizona State University)

Chris Crosby (UNAVCO/OpenTopography)

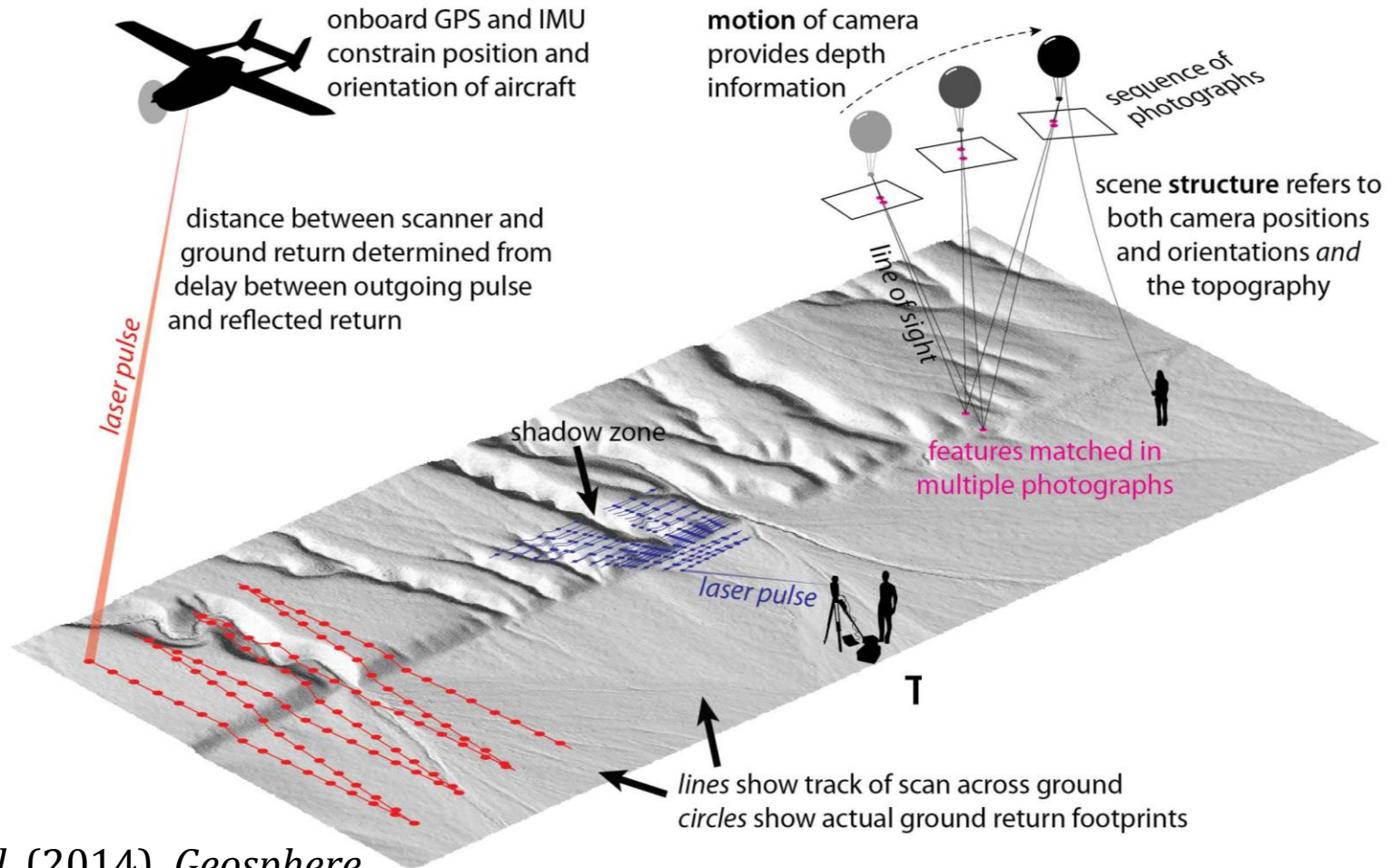
- **What is Structure-from-Motion?**
- **High resolution topography:
scientific motivations**



~500 points/m² coloured point cloud along a ~1 km section of the 2010 El Mayor-Cucapah earthquake rupture generated from ~500 photographs captured in 2 hours from a helium blimp

Lidar (ALS, TLS, MLS)

- Expensive laser equipment required
- Works in densely-vegetated landscapes
- Uses precise time-of-flight measurements but prone to artifacts from GPS and IMU



Structure-from-Motion

- Requires only a cheap camera
- Coloured points & orthophoto for texture mapping
- Back-solves for camera parameters; warping artifacts are a common problem but easily mitigated

Where it all started...

The original idea

Proc. R. Soc. Lond. B. **203**, 405–426 (1979)

Printed in Great Britain

The interpretation of structure from motion

BY S. ULLMAN

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(Communicated by S. Brenner, F.R.S. – Received 20 April 1978)

The interpretation of structure from motion is examined from a computational point of view. The question addressed is how the three dimensional structure and motion of objects can be inferred from the two dimensional transformations of their projected images when no three dimensional information is conveyed by the individual projections.

Where it all started...

The algorithm that powers SfM

*Proc. of the International Conference on
Computer Vision, Corfu (Sept. 1999)*

Object Recognition from Local Scale-Invariant Features

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Abstract

An object recognition system has been developed that uses a new class of local image features. The features are invariant to image scaling, translation, and rotation, and partially invariant to illumination changes and affine or 3D projection.

Where it all started...

- The **Scale Invariant Feature Transform (SIFT)** (Lowe, 1999) allows corresponding features to be matched even with large variations in scale and viewpoint and under conditions of partial occlusion and changing illumination



Where it all started...

First use of the SIFT algorithm to generate large point clouds

Snavely *et al.* (2006). Photo Tourism: Exploring Photo Collections in 3D, *ACM Transactions on Graphics*

Snavely *et al.* (2007). Modeling the World from Internet Photo Collections, *International Journal of Computer Vision*

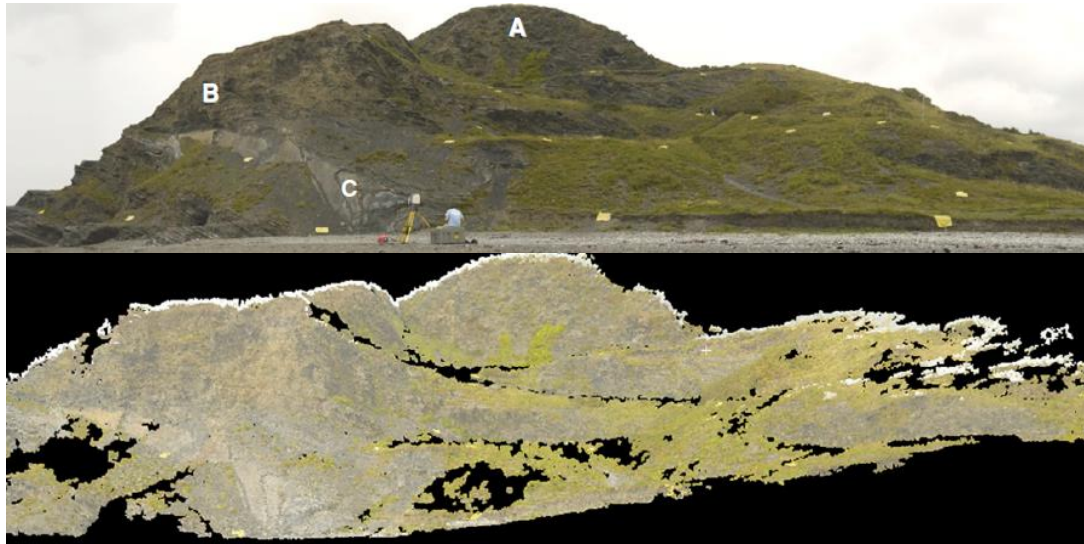


Using photographs from a
moving camera (or cameras)...

... reconstruct the scene **structure** (i.e. the geometry of the target *and* the positions, orientations & lens parameters of the cameras)

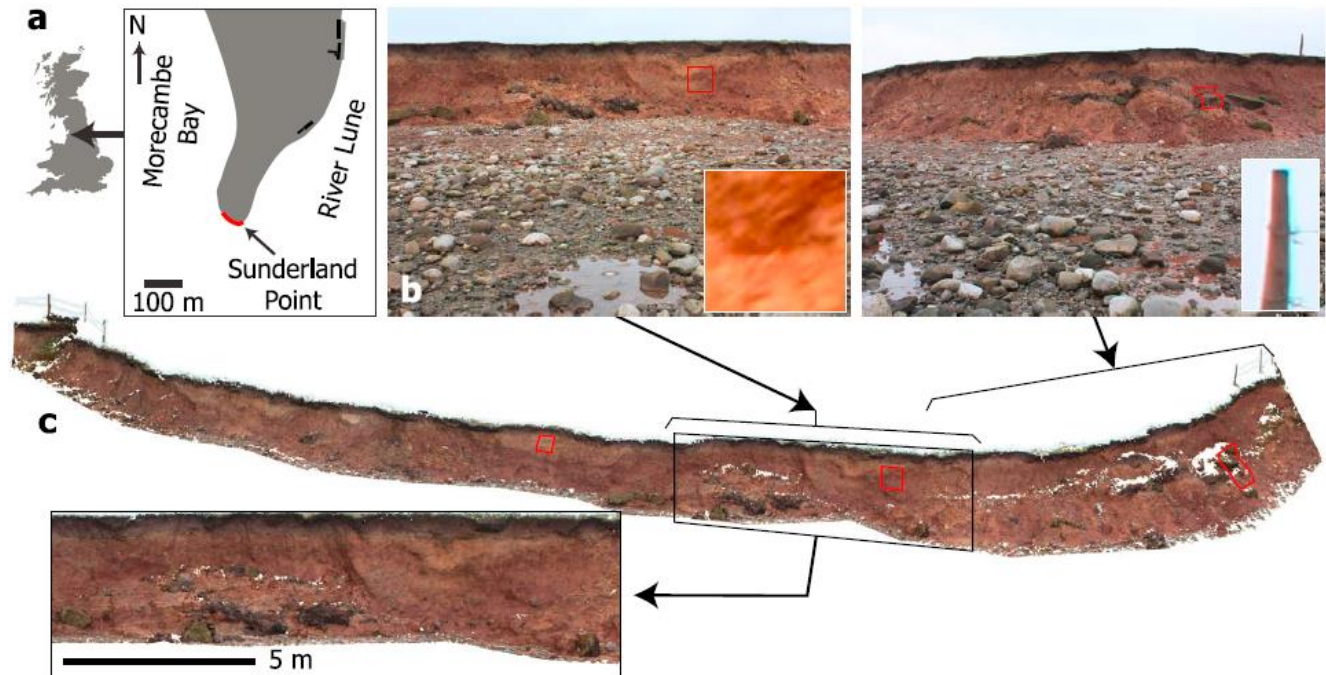
Where it all started...

First geoscience applications



Left. Westoby *et al.* (2012). Structure-from-Motion photogrammetry: A low-cost, effective tool for geoscience applications. *Geomorphology*

Right. James & Robson (2012). Straightforward reconstruction of 3D surfaces and topography with a camera: Accuracy and geoscience application. *Journal of Geophysical Research*



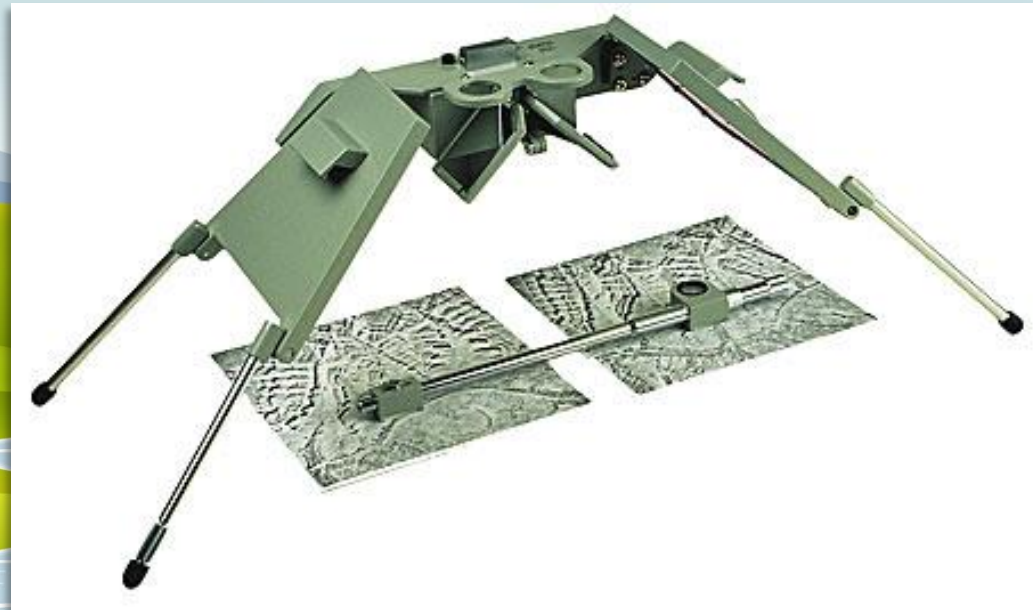
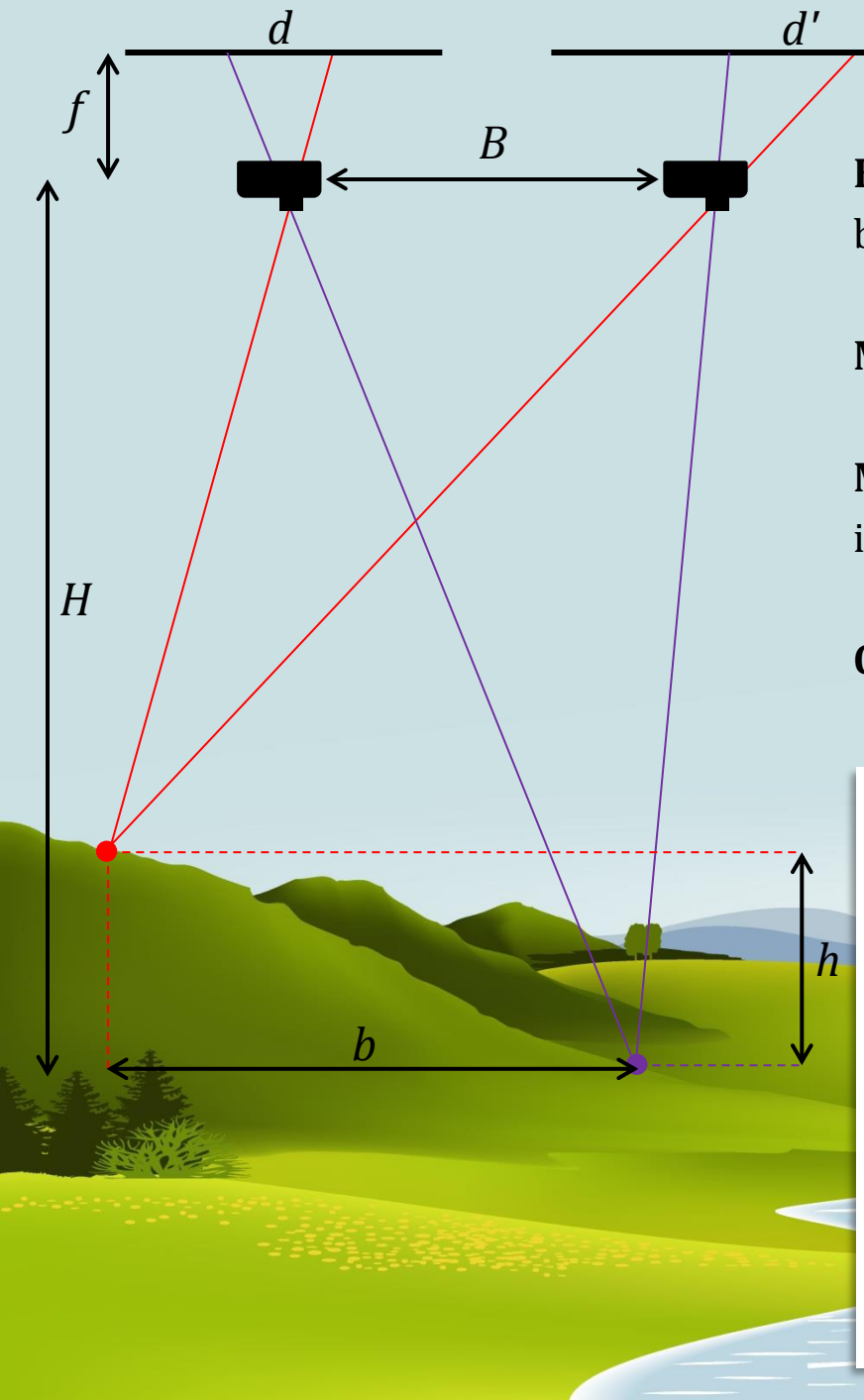
Traditional stereo-photogrammetry

Known camera height H and focal length f , and the baseline B between images

Match corresponding features

Measure distances between features on the camera image plane d, d'

Calculate relative positions of features b, h

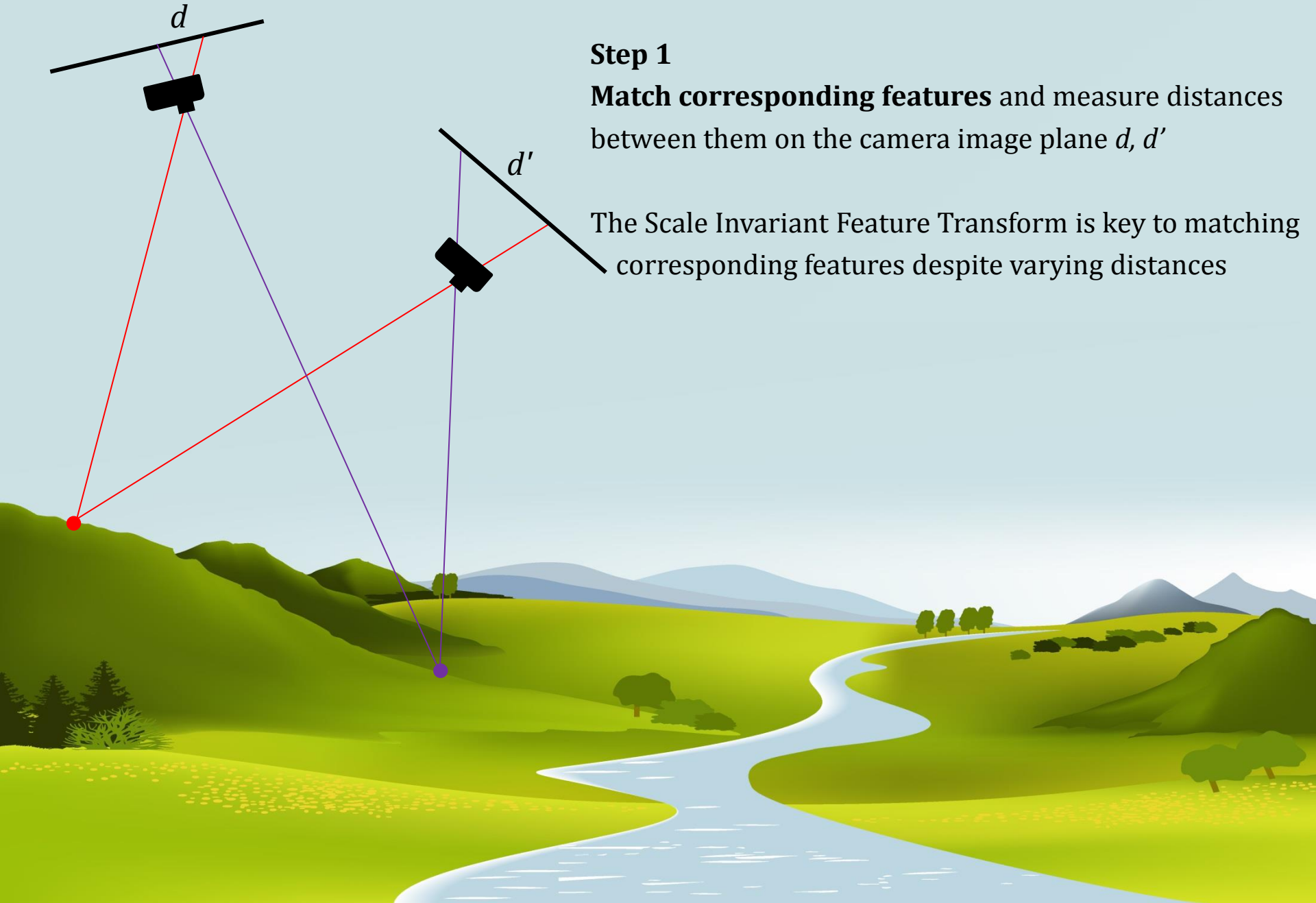


Structure-from-Motion

Step 1

Match corresponding features and measure distances between them on the camera image plane d, d'

The Scale Invariant Feature Transform is key to matching corresponding features despite varying distances



- The **Scale Invariant Feature Transform (SIFT)** (Lowe, 1999) allows corresponding features to be matched even with large variations in scale and viewpoint and under conditions of partial occlusion and changing illumination



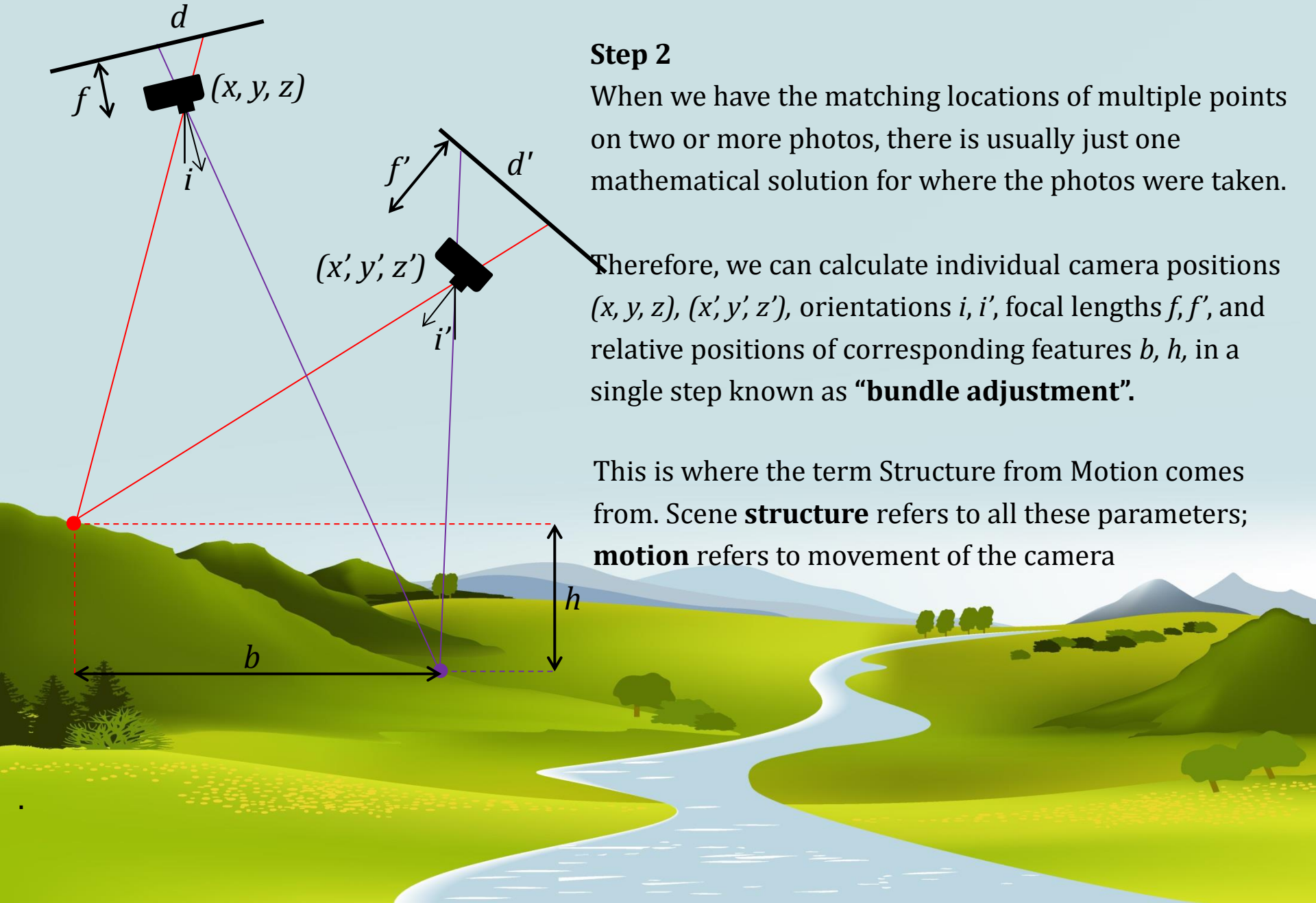
Structure-from-Motion

Step 2

When we have the matching locations of multiple points on two or more photos, there is usually just one mathematical solution for where the photos were taken.

Therefore, we can calculate individual camera positions (x, y, z) , (x', y', z') , orientations i, i' , focal lengths f, f' , and relative positions of corresponding features b, h , in a single step known as “**bundle adjustment**”.

This is where the term Structure from Motion comes from. Scene **structure** refers to all these parameters; **motion** refers to movement of the camera

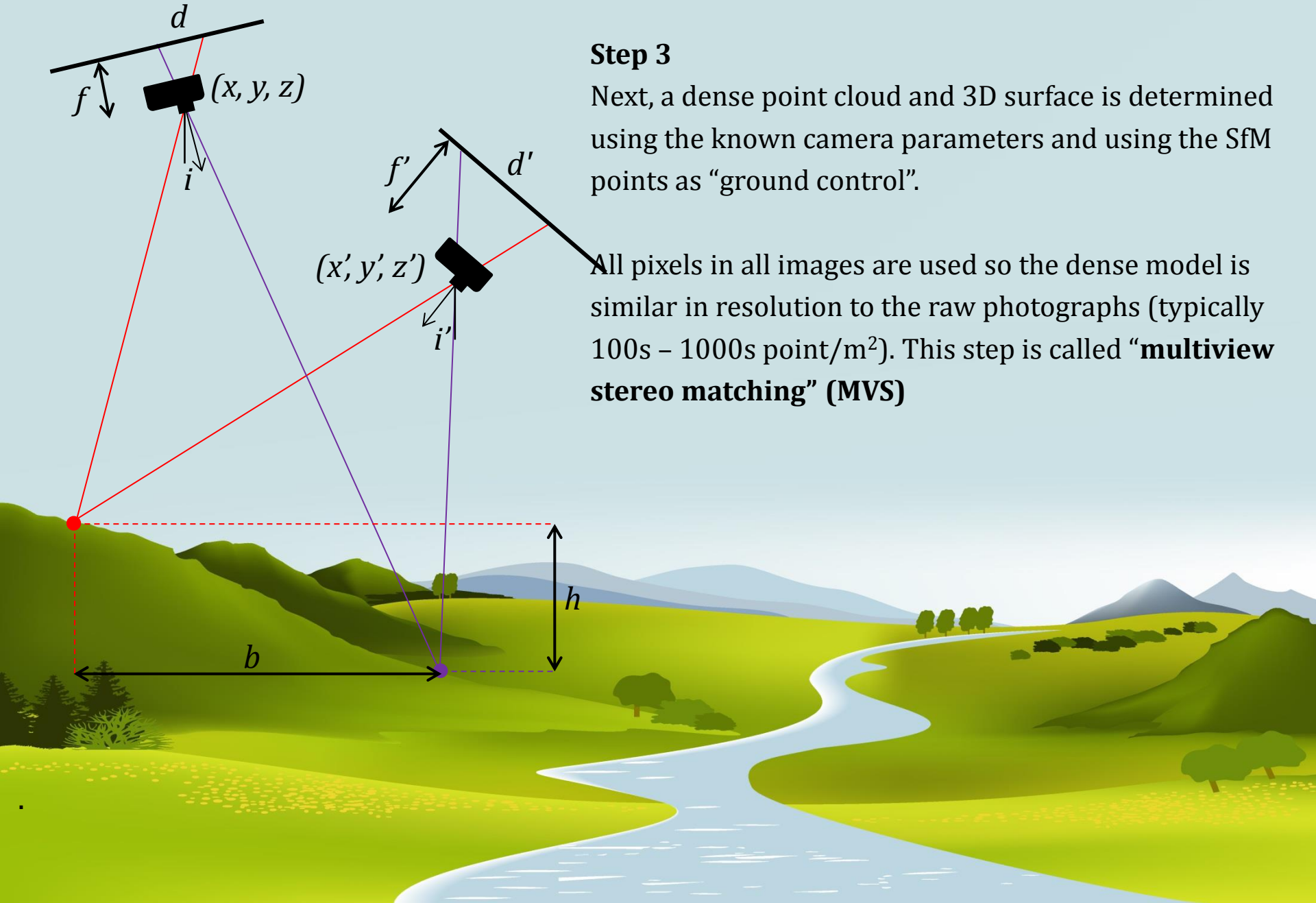


Structure-from-Motion

Step 3

Next, a dense point cloud and 3D surface is determined using the known camera parameters and using the SfM points as “ground control”.

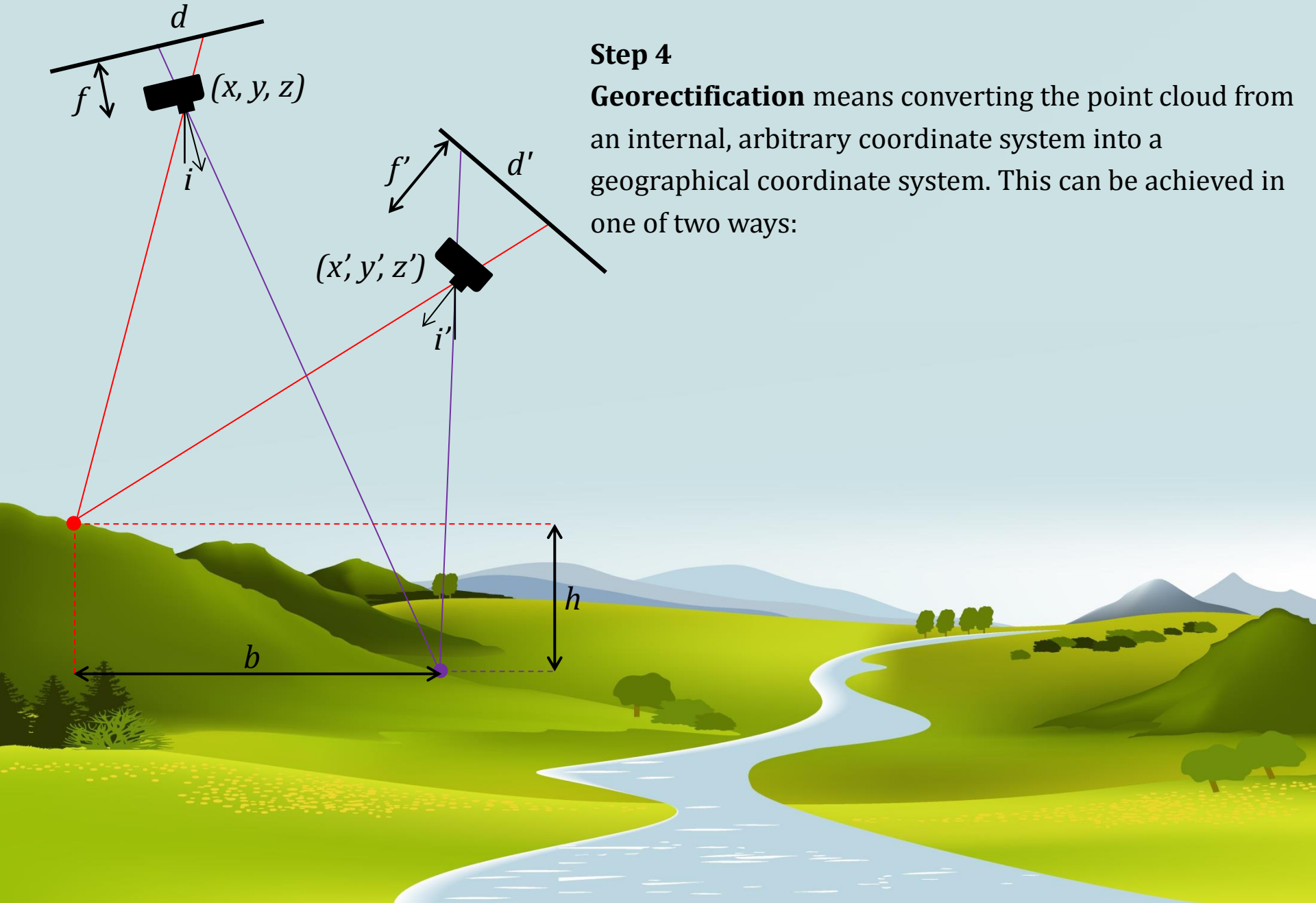
All pixels in all images are used so the dense model is similar in resolution to the raw photographs (typically 100s – 1000s point/m²). This step is called “**multiview stereo matching**” (MVS)



Structure-from-Motion

Step 4

Georectification means converting the point cloud from an internal, arbitrary coordinate system into a geographical coordinate system. This can be achieved in one of two ways:

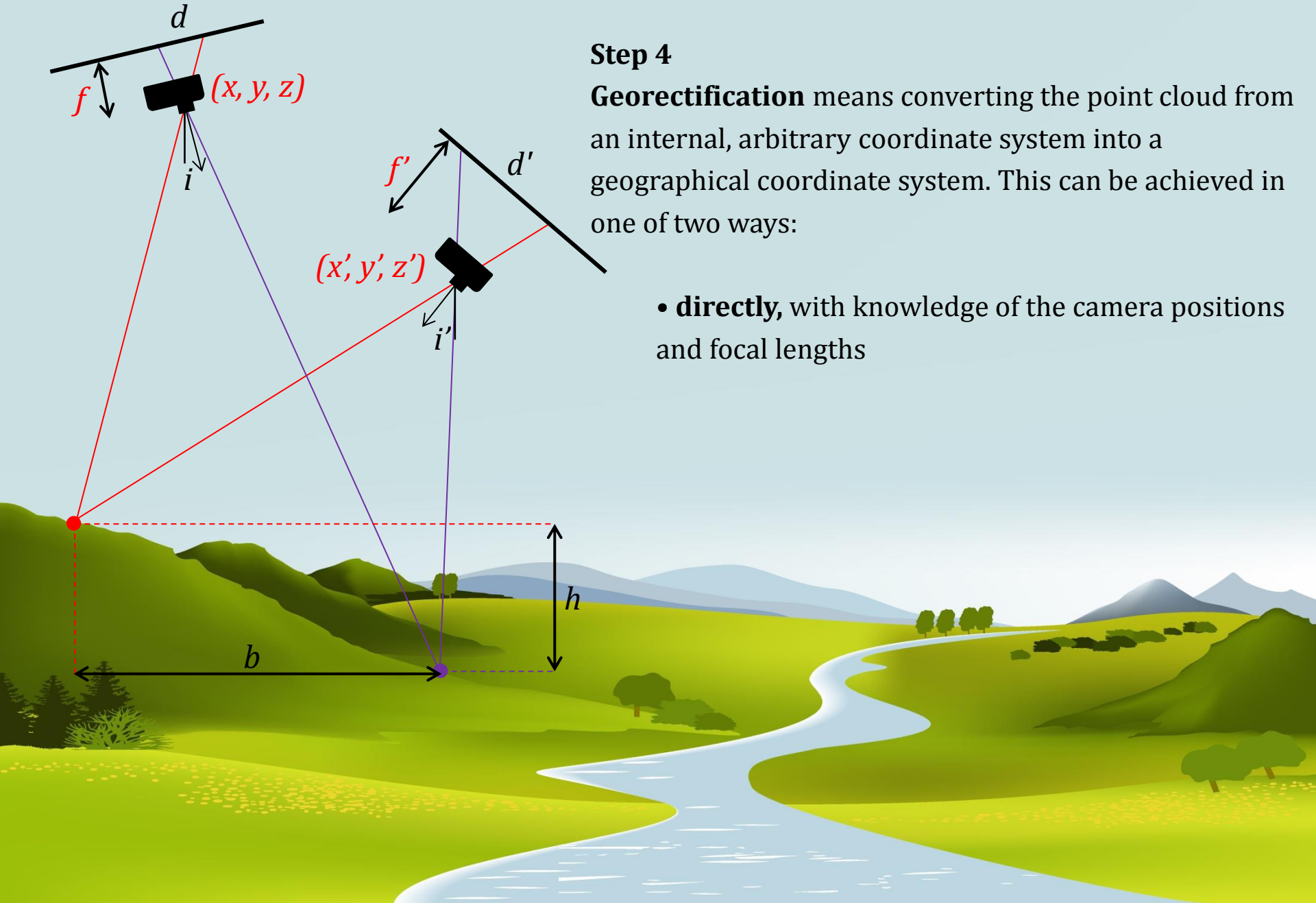


Structure-from-Motion

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- **directly**, with knowledge of the camera positions and focal lengths

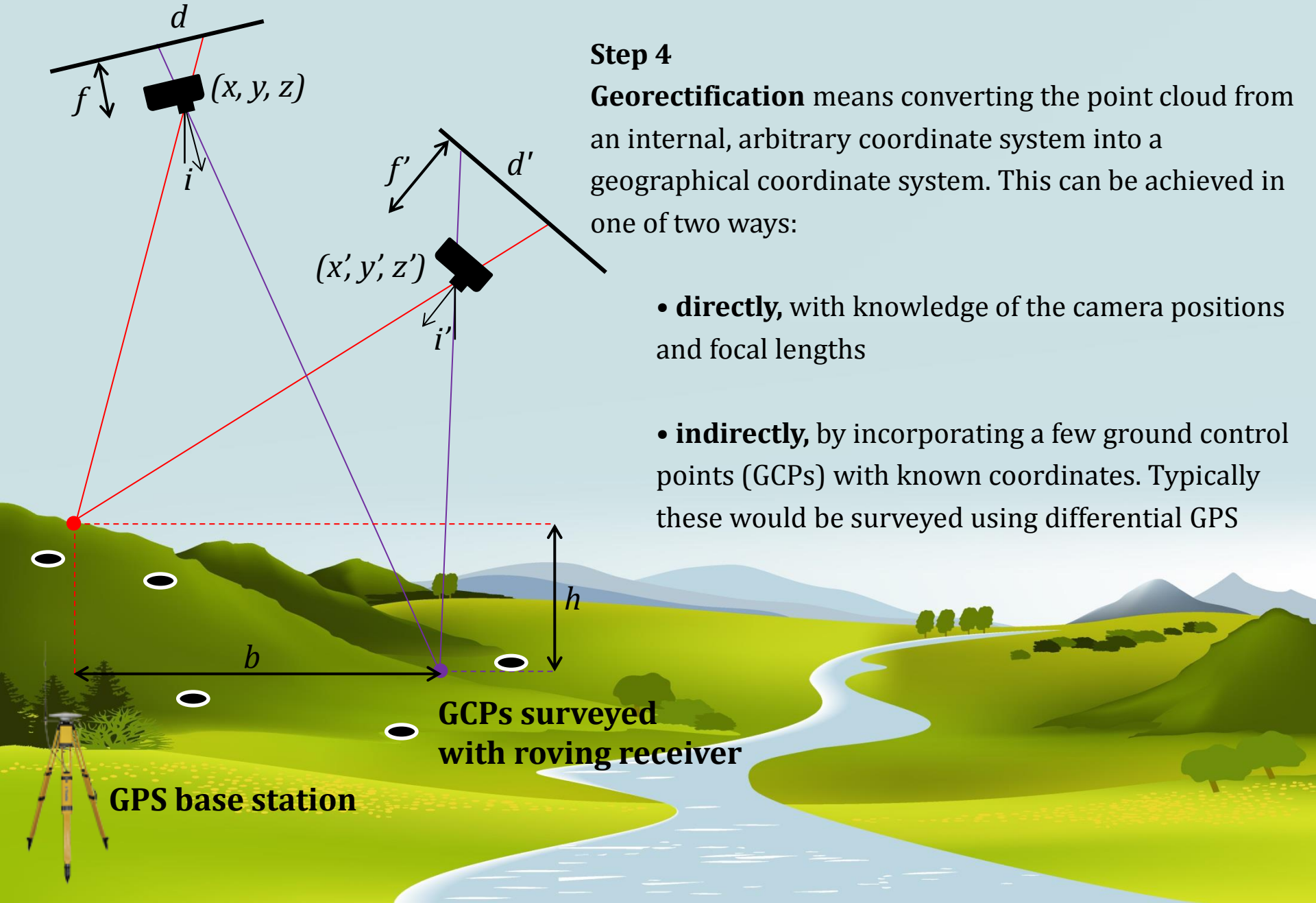


Structure-from-Motion

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Georectification means converting the point cloud from an internal, arbitrary coordinate system into a geographical coordinate system. This can be achieved in one of two ways:

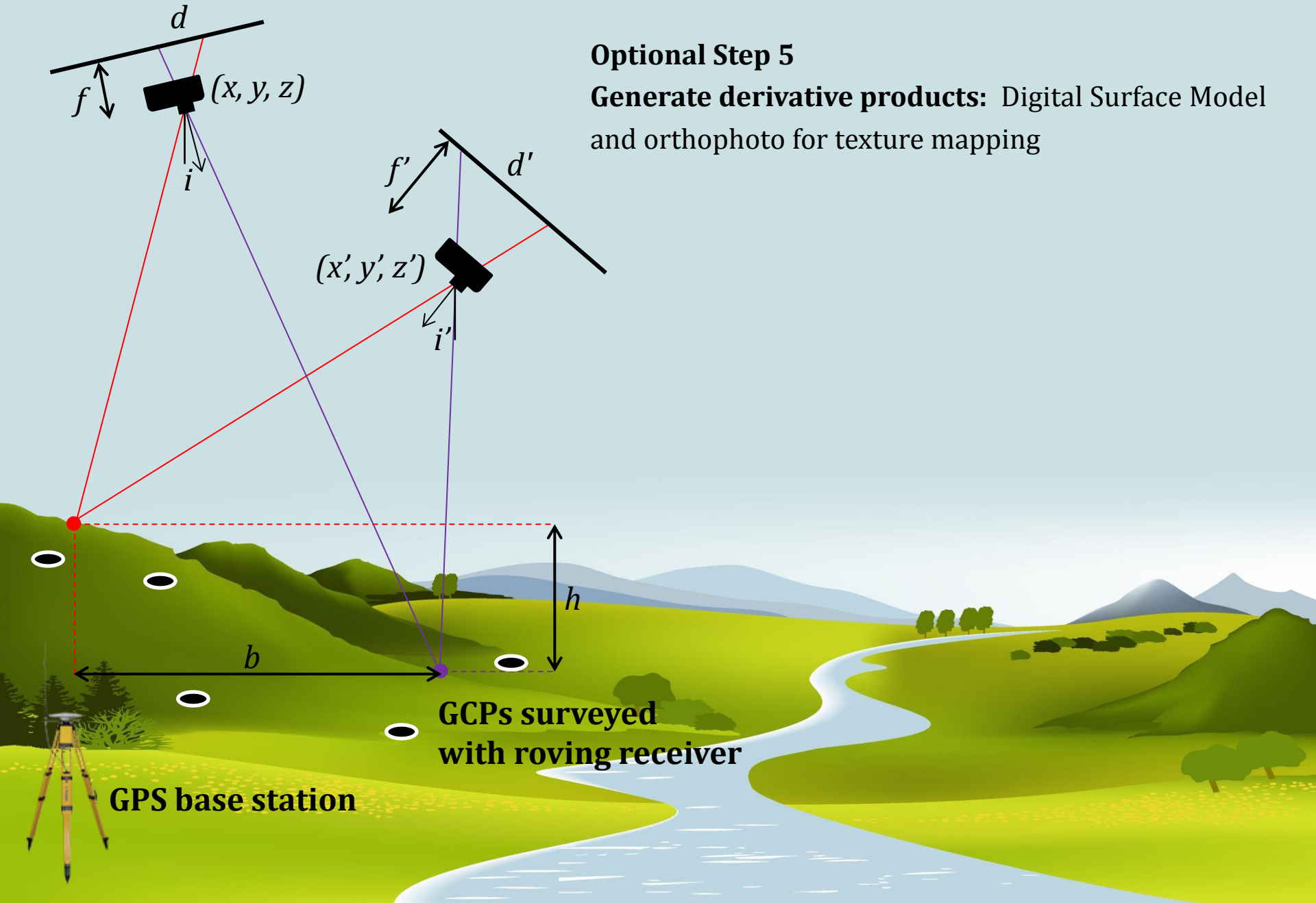
- **directly**, with knowledge of the camera positions and focal lengths
- **indirectly**, by incorporating a few ground control points (GCPs) with known coordinates. Typically these would be surveyed using differential GPS



Structure-from-Motion

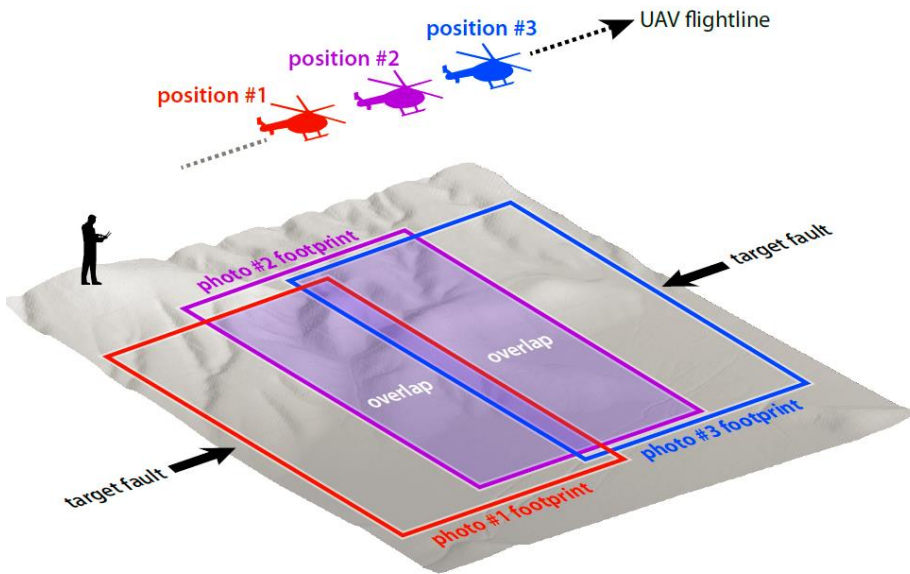
Optional Step 5

Generate derivative products: Digital Surface Model and orthophoto for texture mapping



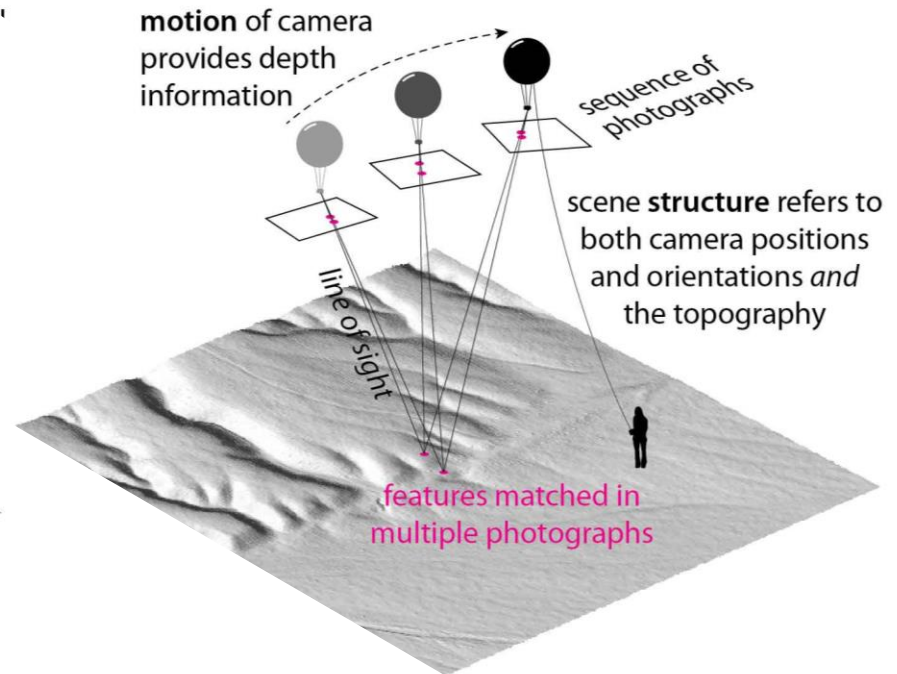
Traditional stereo-photogrammetry

- Requires a stable platform such as a satellite or aeroplane at a fixed elevation
- Photographs collected at known positions with fixed orientations and incidence angles



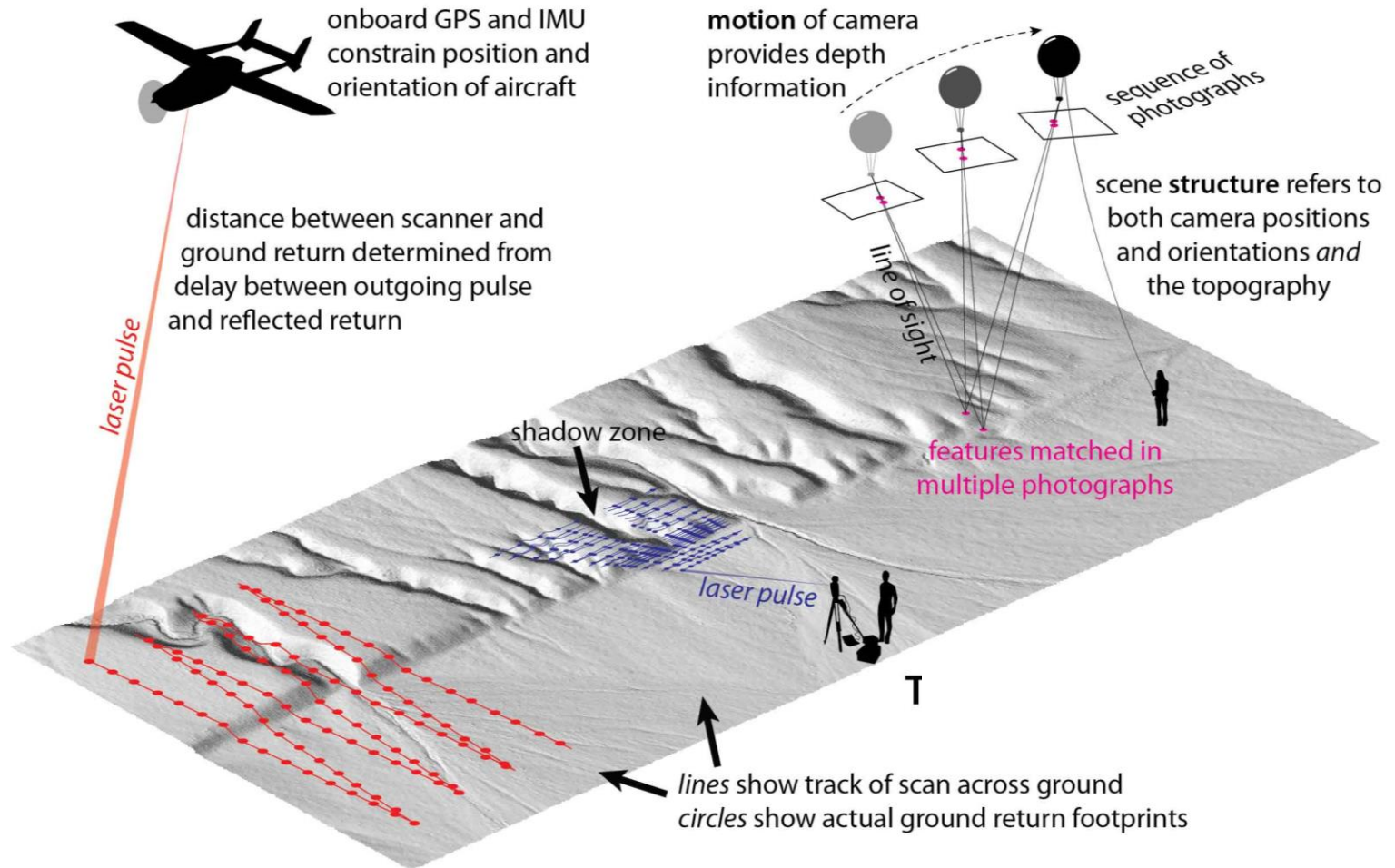
Structure-from-Motion

- Photos from many angles and distances can be used, with no *a priori* knowledge of locations or pose
- Enables “unstructured” image acquisition from the ground, legacy air-photosets, or unmanned platforms



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Structure-from-Motion

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SfM & MVS software

Table 1
Examples of open source and commercial software for photo-based 3d reconstruction.

Software	Url (valid on 17 May, 2014)	Notes
<i>Freely available</i>		
Bundler Photogrammetry Package ^{a,b}	http://blog.neonascent.net/archives/bundler-photogrammetry-package/	Used in James and Robson (2012) . Script-based, no graphical user interface (GUI). Windows OS only.
SFMTToolkit ^{a,b}	http://www.visual-experiments.com/demos/sfmtreekit/	Similar software to above.
Python Photogrammetry Toolbox (PPT) ^{a,b}	http://code.google.com/p/osm-bundler/	Formerly OSM-bundler. Python-driven GUI and scripts, with a Linux distribution.
VisualSFM ^b	http://www.cs.washington.edu/homes/ccwu/vsfm/	Advanced GUI with Windows, Linux and Mac. OSX versions. Georeferencing options, but camera model is more restricted than that used in Bundler.
3DF Samantha	http://www.3dflow.net/technology/samantha-structure-from-motion/	SfM only, but with more advanced camera models than all above (Farenzena et al., 2009). Provides output compatible with several dense matching algorithms.
<i>Web sites and services</i>		
Photosynth	http://photosynth.net/	Evolved from Bundler. SfM only, no dense reconstruction. Can incorporate a very wide variety of images, but does so at the cost of reconstruction accuracy.
Arc3D	http://www.arc3d.be/	Vergauwen and Van Gool [2006]
CMP SfM Web service ^a	http://ptak.felk.cvut.cz/sfm-service/	
Autodesk 123D Catch	http://www.123dapp.com/catch/	
Pix4D	http://pix4d.com/	
My3DScanner	http://www.my3dscanner.com/	Also available as standalone software.
<i>Commercial</i>		
PhotoScan	http://www.agisoft.ru/products/photoscan/	Full SfM-MVS-based commercial package.
Acute3D	http://www.acute3d.com/	Software, originally based on close-range photogrammetry, now also implements SfM.
PhotoModeler	http://www.photomodeler.com/	
3DF Zephyr Pro	http://www.3dflow.net/	Underlying SfM engine is 3DF Samantha

Note: Table modified from <http://www.lancaster.ac.uk/staff/jamesm/research/sfm.htm>.

SfM = Structure from Motion; MVS = Multi-View Stereo.

^a Uses Bundler (<http://phototour.cs.washington.edu/bundler/>) to compute structure from motion.

^b Uses PMVS2 (<http://grail.cs.washington.edu/software/pmvs/>) as a dense multi-view matcher.

Bemis *et al.* (2014). Ground-based and UAV-Based photogrammetry: A multi-scale, high resolution mapping tool for structural geology and paleoseismology. *Journal of Structural Geology*

SfM & MVS software

Agisoft

FEATURES

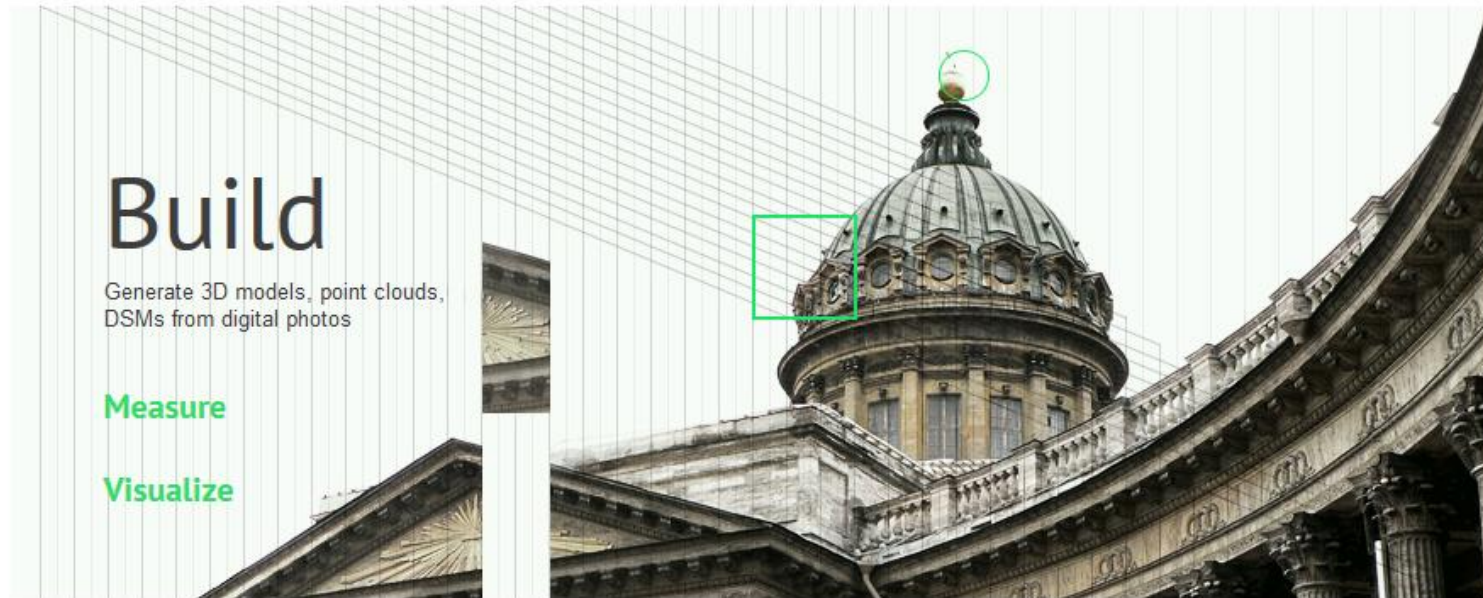
SUPPORT

COMMUNITY

DOWNLOADS

BUY

ABOUT



Agisoft Photoscan Pro: \$549 for an academic licence.

- Workflow includes *both* SfM *and* MVS, and builds DSM and orthophoto
- Intuitive graphical user interface (GUI)
- Data are georeferenced automatically if camera GPS stamps are available
- Camera calibration with Agisoft Lens
- Vertically-oriented orthophoto possible for trenching (see Reitman *et al.*, 2015, BSSA)