

Factored Facade Acquisition using Symmetric Line Arrangements

Duygu Ceylan

EPFL



Computer Graphics & Geometry Laboratory
ÉCOLE POLYTECHNIQUE FÉDÉRALE DE LAUSANNE

Niloy J. Mitra

UCL



Virtual Environments & Computer Graphics
UNIVERSITY COLLEGE LONDON

Hao Li

Columbia
University

Thibaut Weise

EPFL

Mark Pauly

EPFL

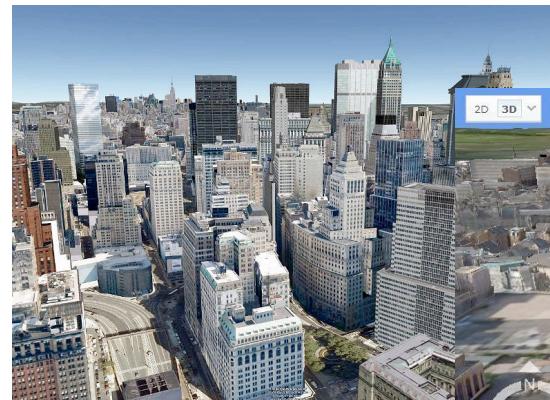


Columbia Computer Graphics Group
COLUMBIA UNIVERSITY

3D Reconstruction of Urban Scenes



urban design

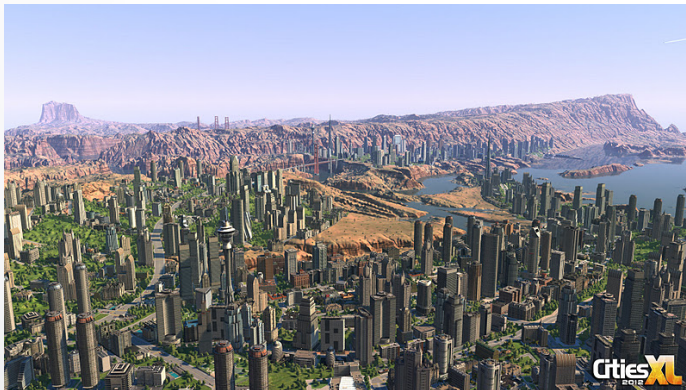


Google Earth



Microsoft Visual Earth

mapping and navigation



content creation



virtual tours

State of the Art

State of the Art

Multi-View Stereo

State of the Art

Multi-View Stereo



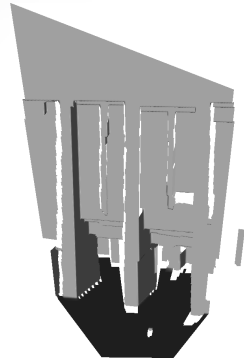
Furukawa et al.
CVPR'07

State of the Art

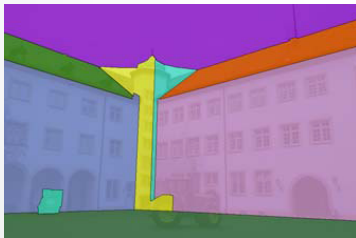
Multi-View Stereo



Furukawa et al.
CVPR'07



Furukawa et al.
CVPR'09



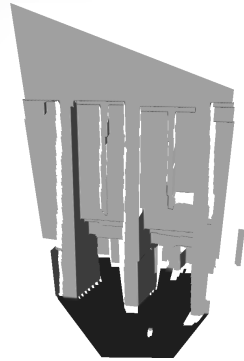
Sinha et al.
ICCV'09

State of the Art

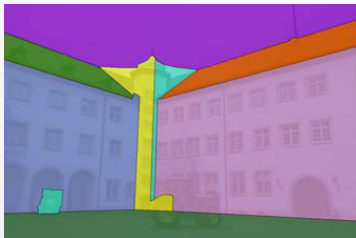
Multi-View Stereo



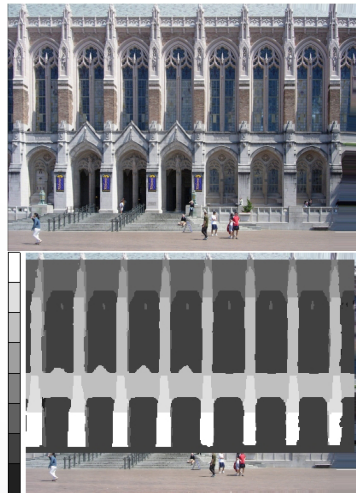
Furukawa et al.
CVPR'07



Furukawa et al.
CVPR'09



Sinha et al.
ICCV'09



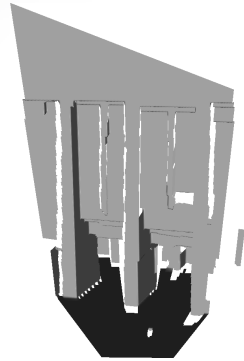
Wu et al.
CVPR'11

State of the Art

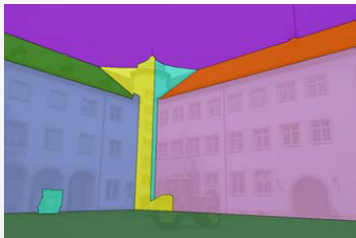
Multi-View Stereo



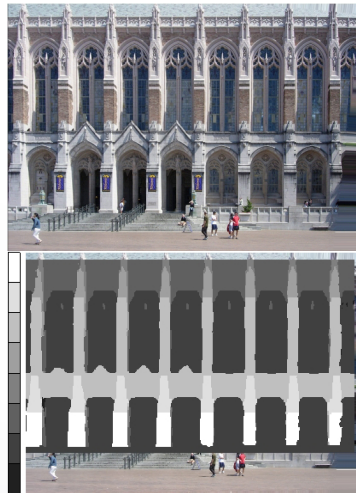
Furukawa et al.
CVPR'07



Furukawa et al.
CVPR'09

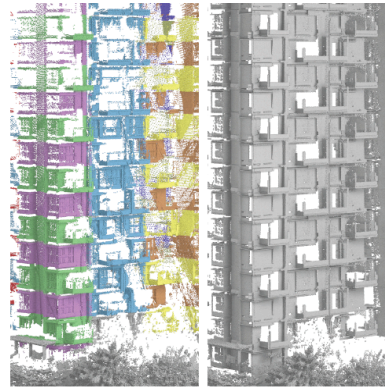


Sinha et al.
ICCV'09



Wu et al.
CVPR'11

Other Data Sources



Zheng et al.
Siggraph'10



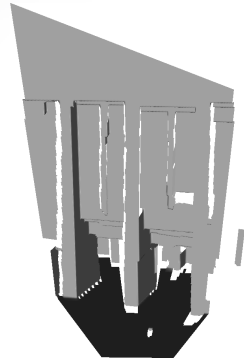
Li et al.
ICCV'11

State of the Art

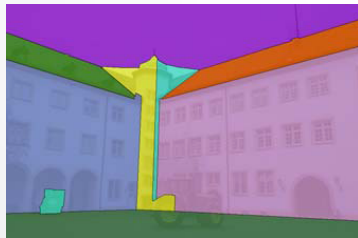
Multi-View Stereo



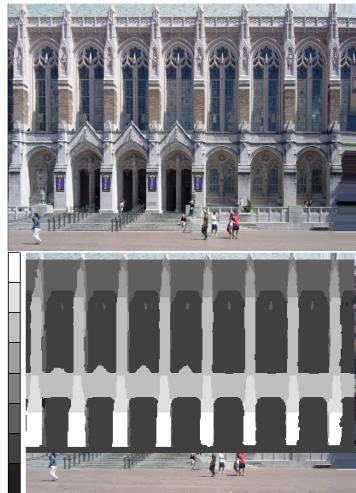
Furukawa et al.
CVPR'07



Furukawa et al.
CVPR'09

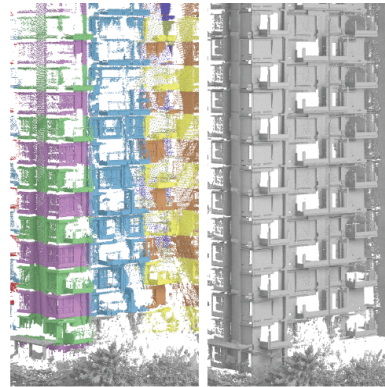


Sinha et al.
ICCV'09



Wu et al.
CVPR'11

Other Data Sources



Zheng et al.
Siggraph'10

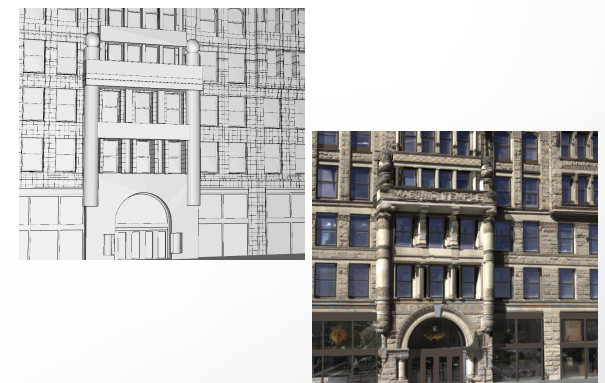


Li et al.
ICCV'11

Procedural Modeling



Muller et al.
Siggraph'08



Xiao et al.
Siggraph'08

Challenges

Challenges



tall buildings

Challenges



tall buildings



textureless regions

Challenges



tall buildings



textureless regions



strong variation in illumination

Challenges



tall buildings



textureless regions



strong variation in illumination



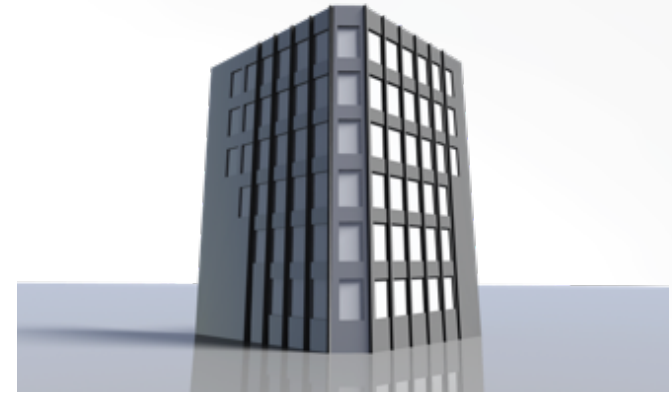
reflective surfaces

Our Algorithm

Our Algorithm



input images

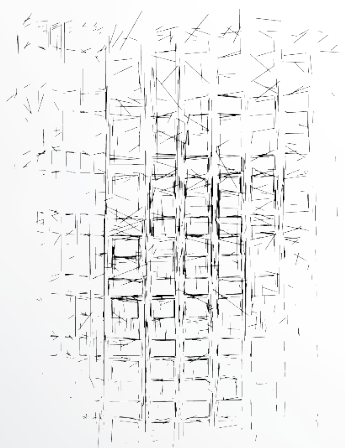


output reconstruction

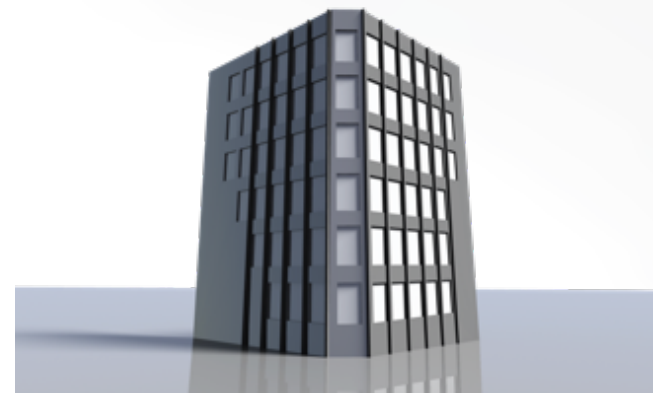
Our Algorithm



input images



3D lines

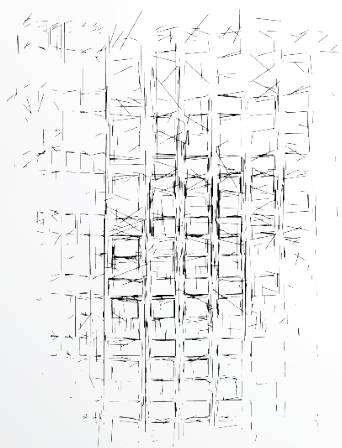


output reconstruction

Our Algorithm



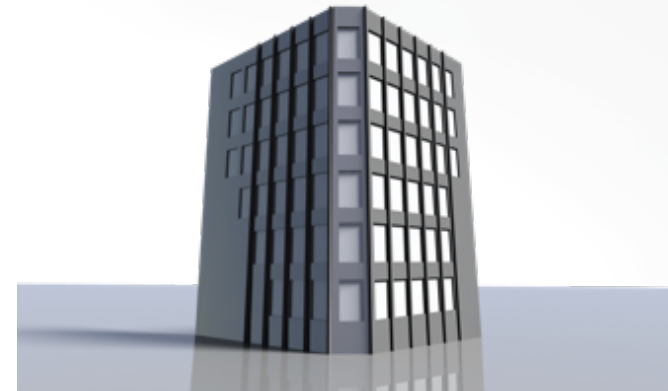
input images



3D lines



plane fitting

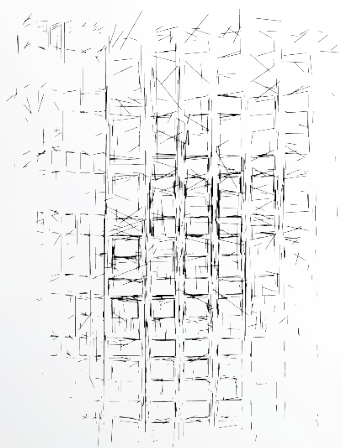


output reconstruction

Our Algorithm



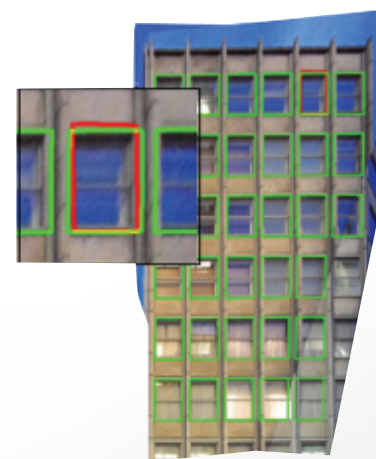
input images



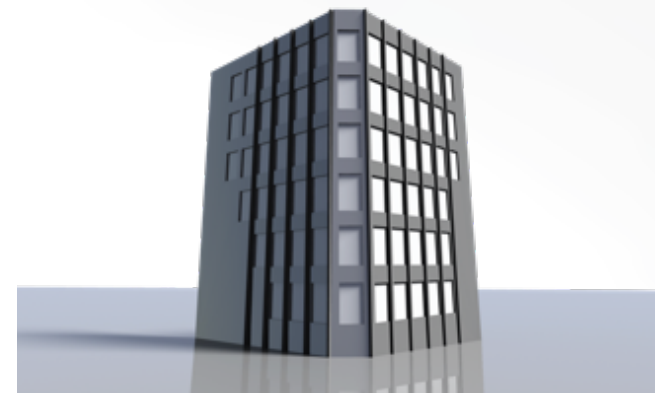
3D lines



plane fitting



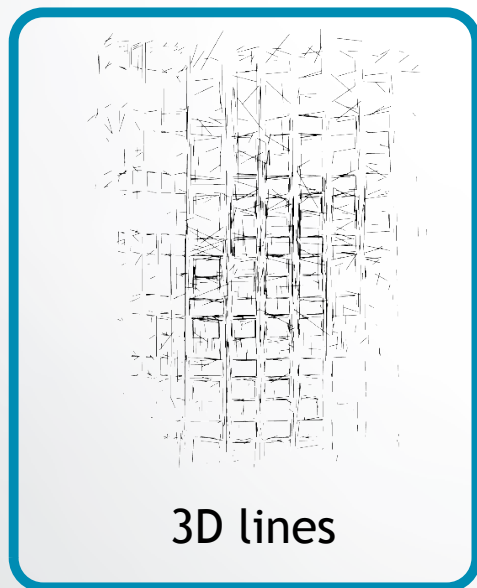
structure detection



output reconstruction



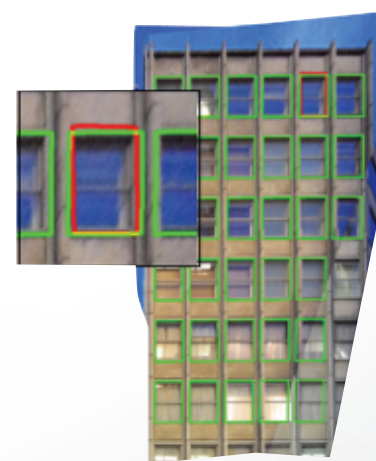
input images



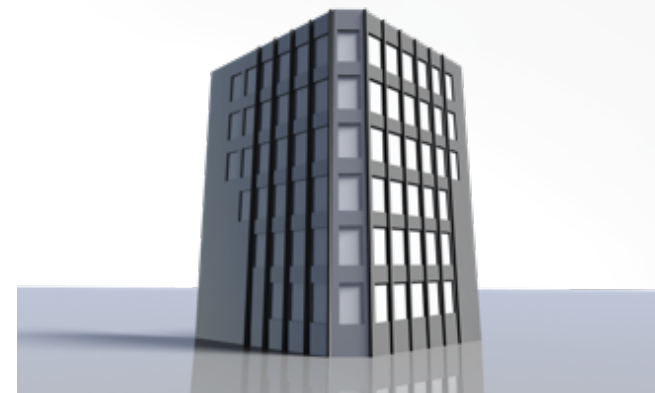
3D lines



plane fitting



structure detection

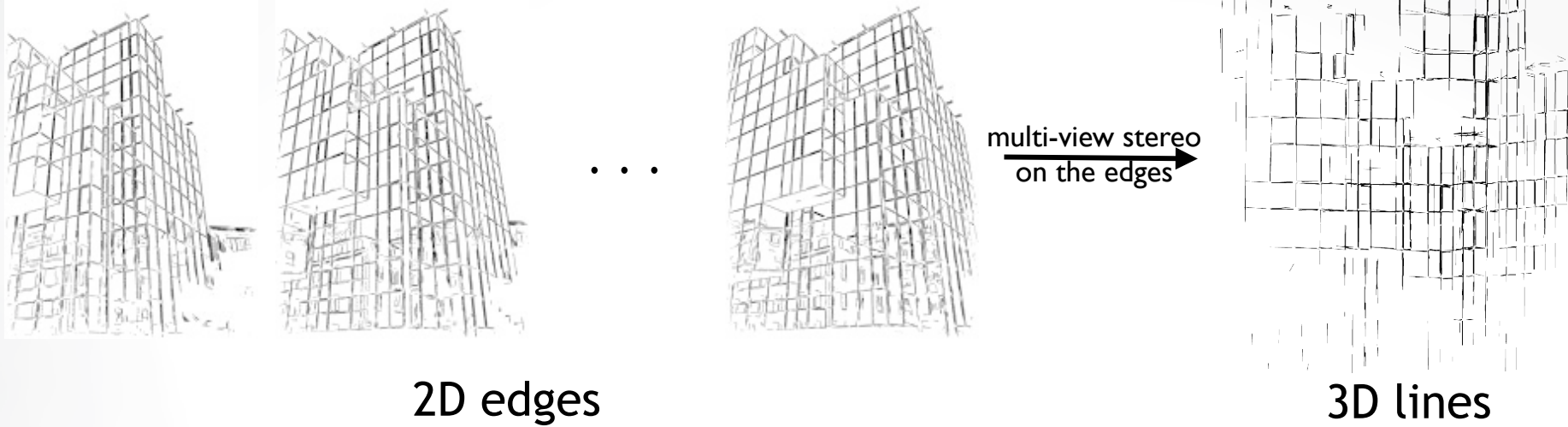


output reconstruction

3D Line Reconstruction

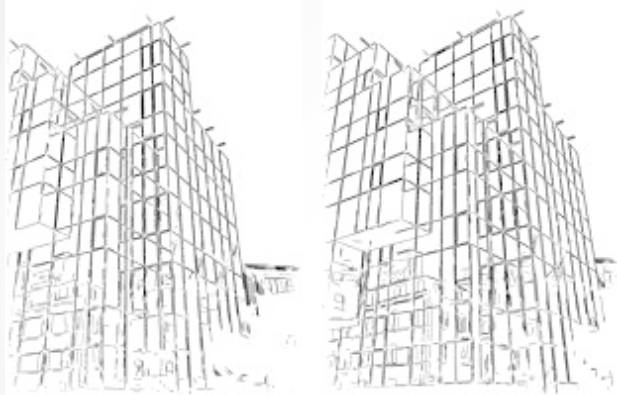


3D Line Reconstruction



input image

3D Line Reconstruction

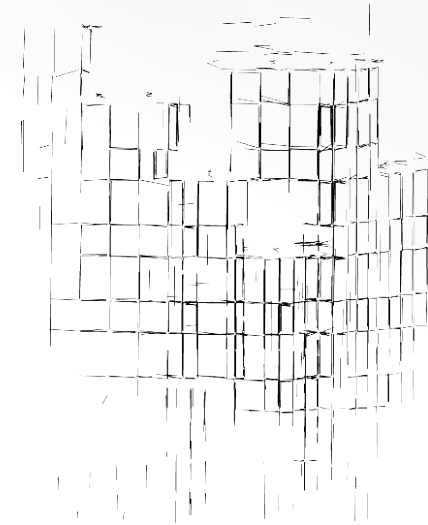


2D edges

...



multi-view stereo
on the edges →



3D lines

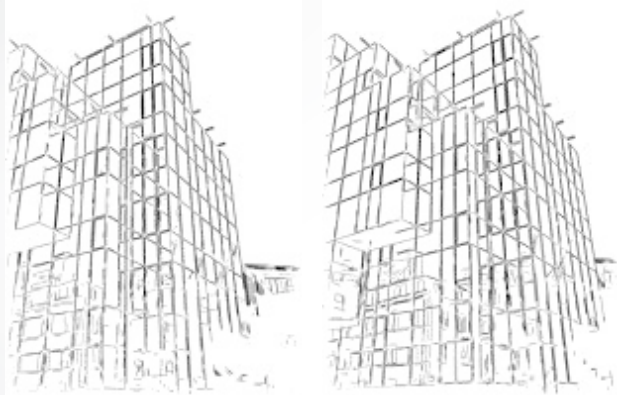


input image



2D edges

3D Line Reconstruction

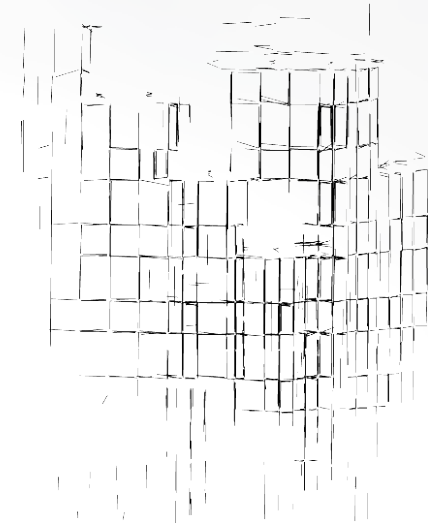


2D edges

...



multi-view stereo
on the edges →



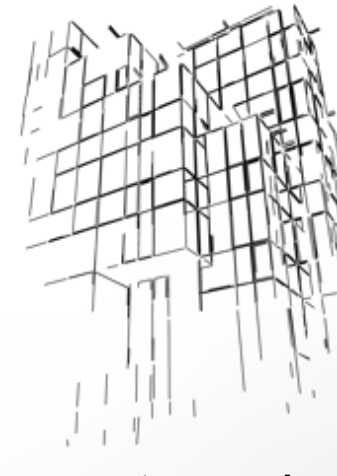
3D lines



input image

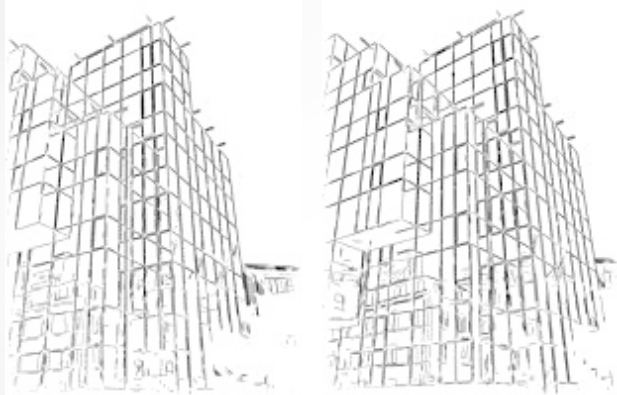


2D edges



projected
3D lines

3D Line Reconstruction

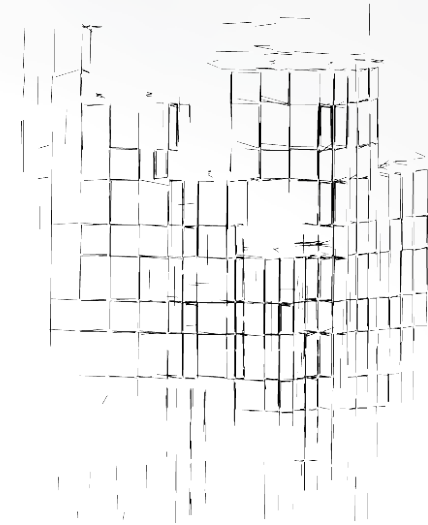


2D edges

...



multi-view stereo
on the edges →



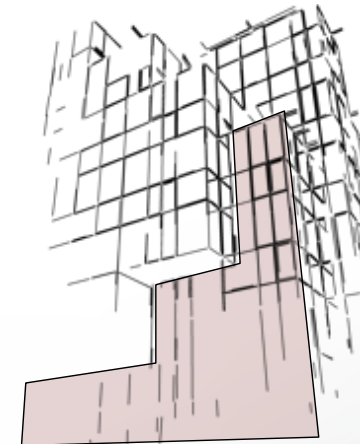
3D lines



input image



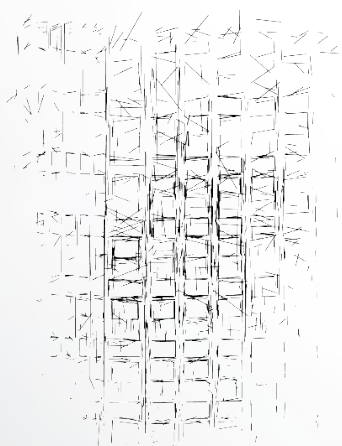
2D edges



projected
3D lines



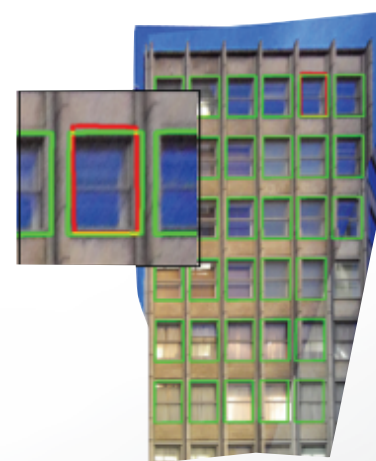
input images



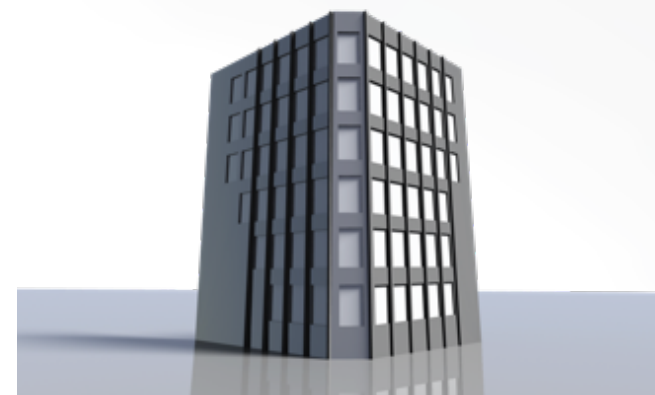
3D lines



plane fitting



structure detection



output reconstruction

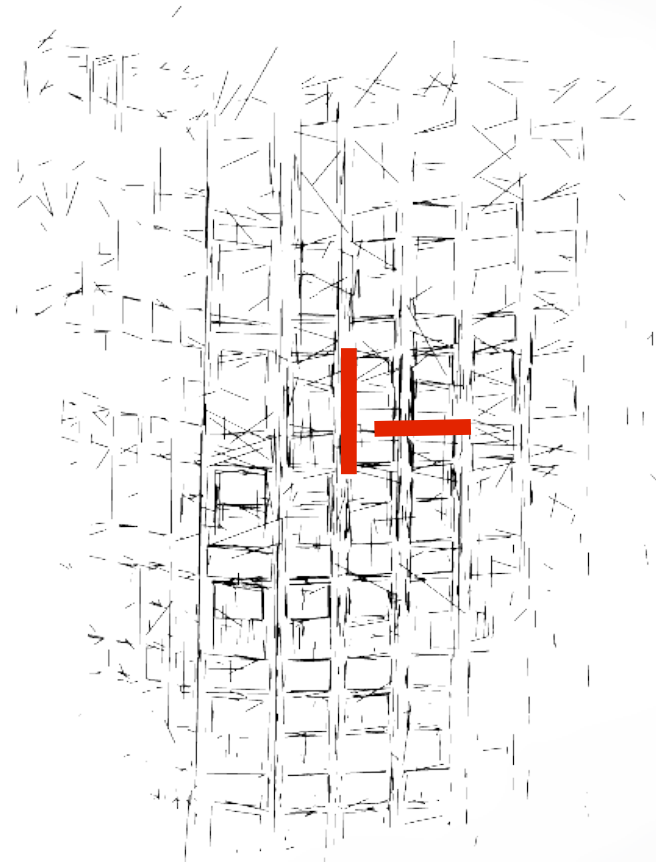
Candidate Plane Generation

Candidate Plane Generation

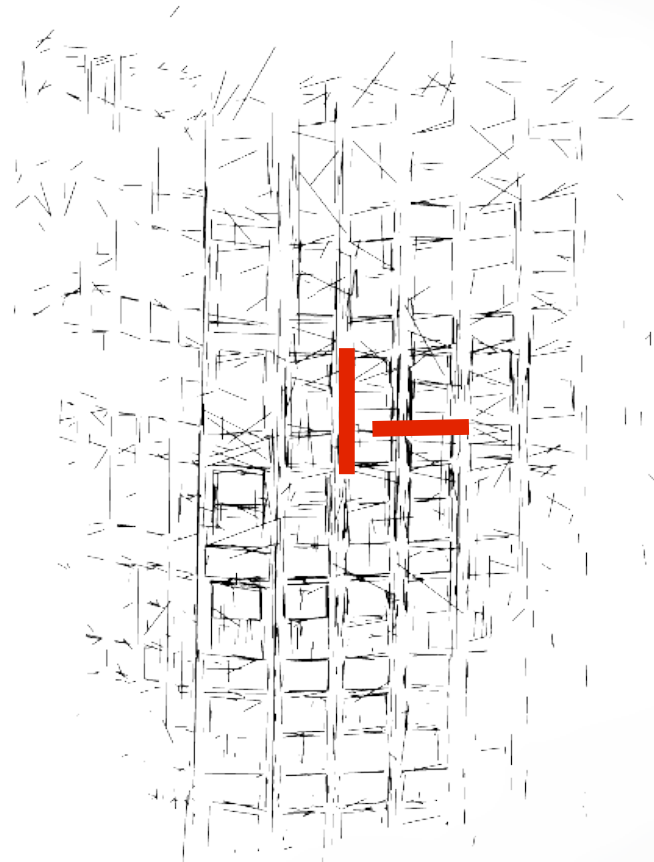
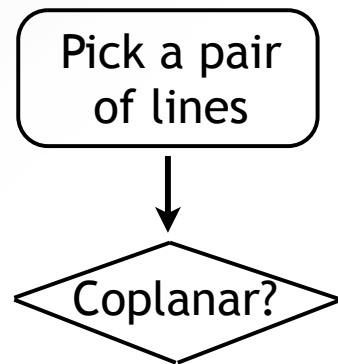
Pick a pair
of lines

Candidate Plane Generation

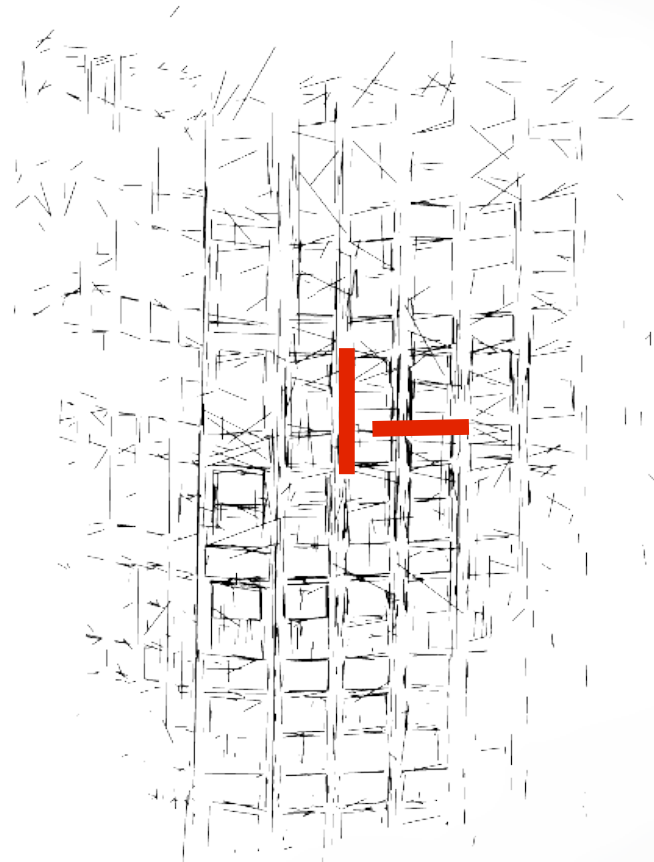
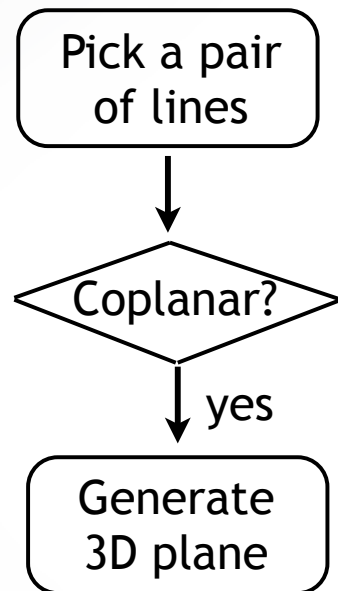
Pick a pair
of lines



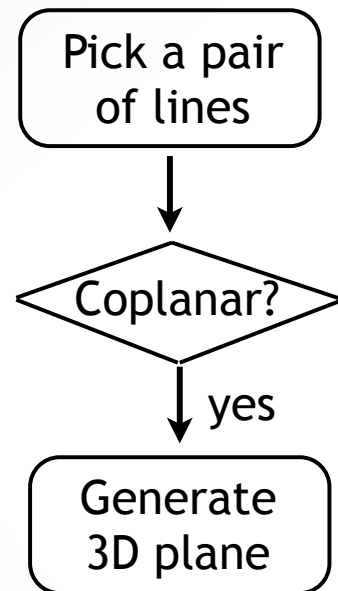
Candidate Plane Generation



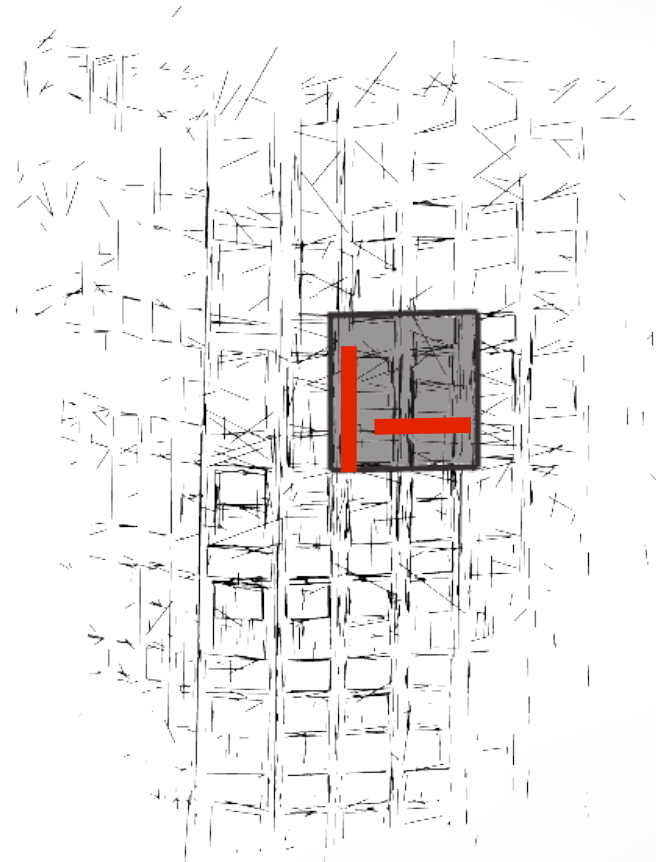
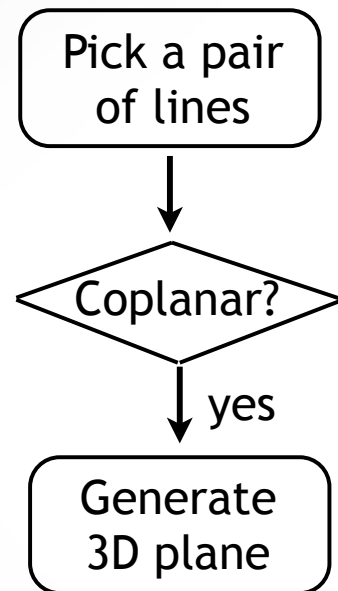
Candidate Plane Generation



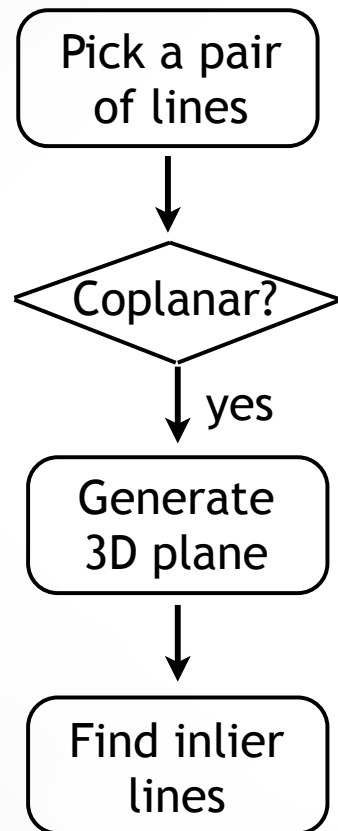
Candidate Plane Generation



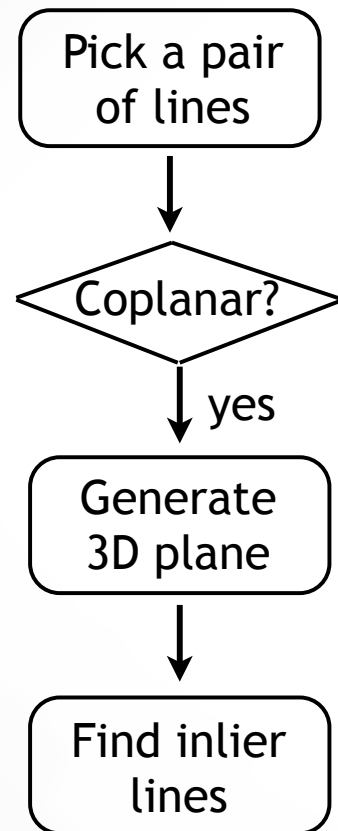
Candidate Plane Generation



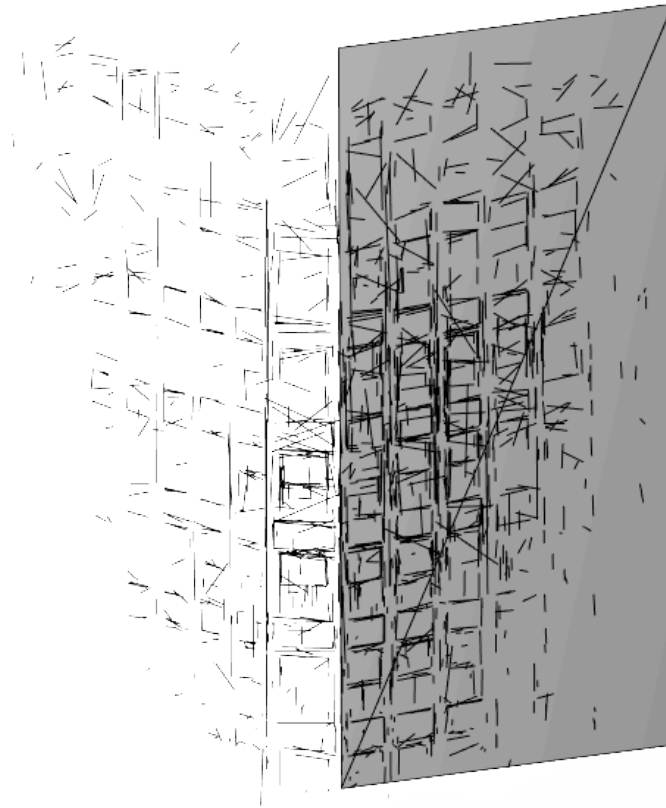
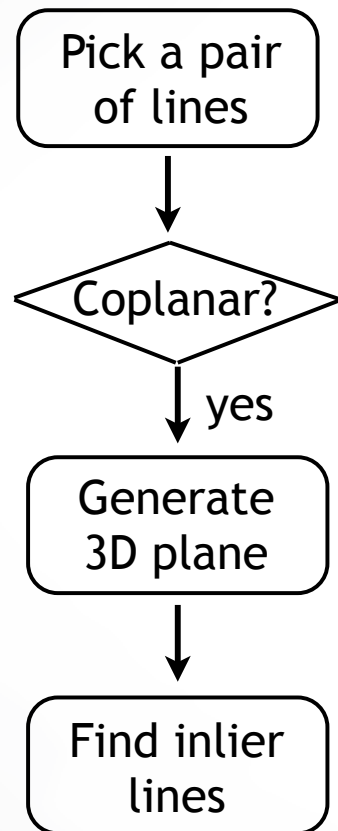
Candidate Plane Generation



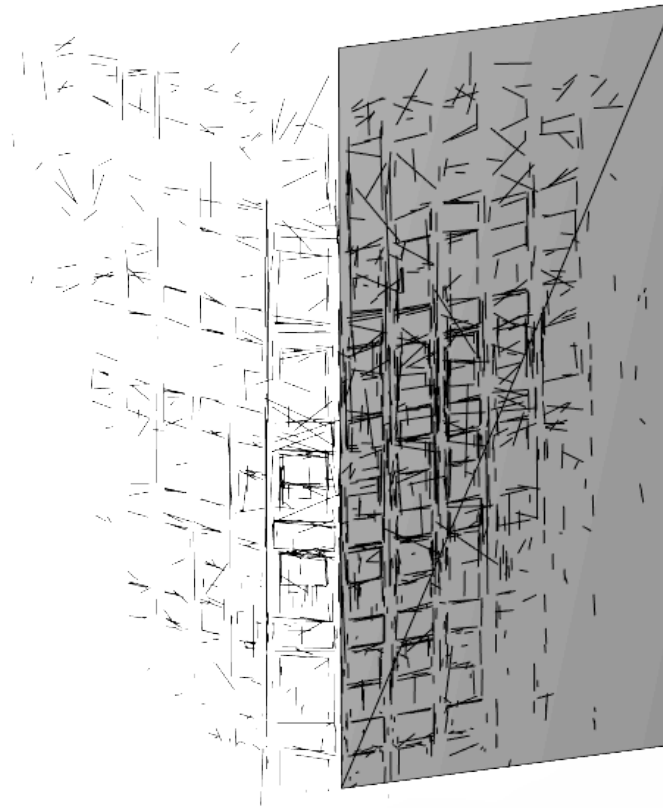
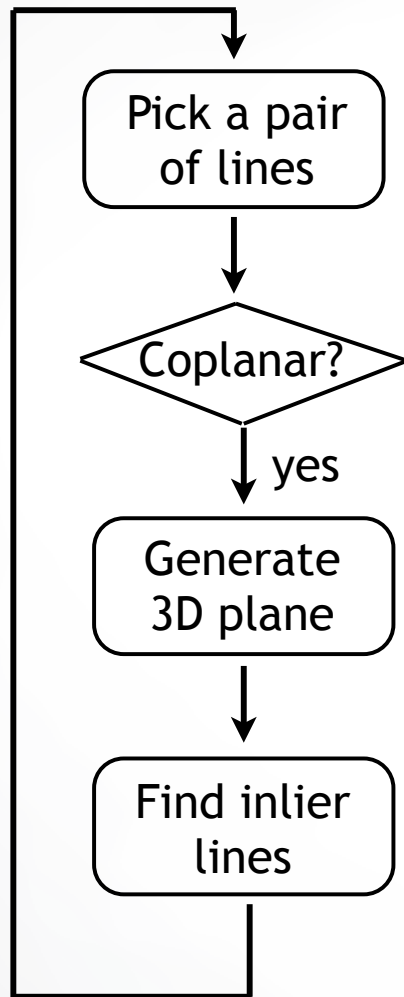
Candidate Plane Generation



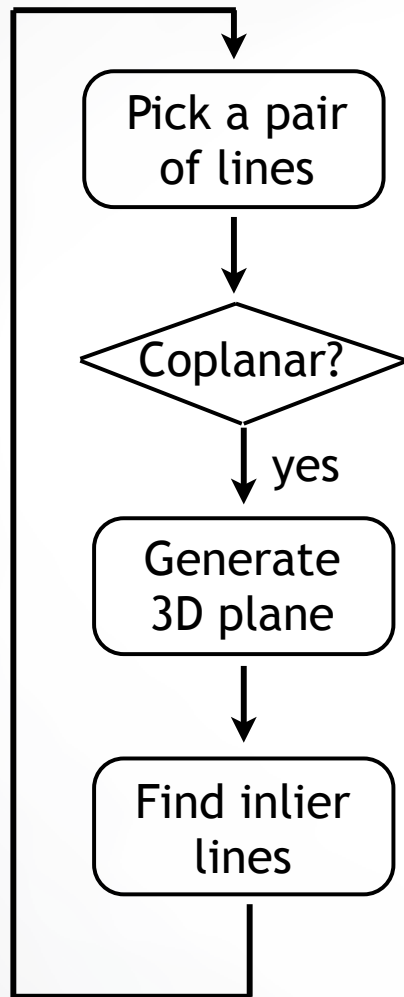
Candidate Plane Generation



Candidate Plane Generation



Candidate Plane Generation



Candidate Plane Generation

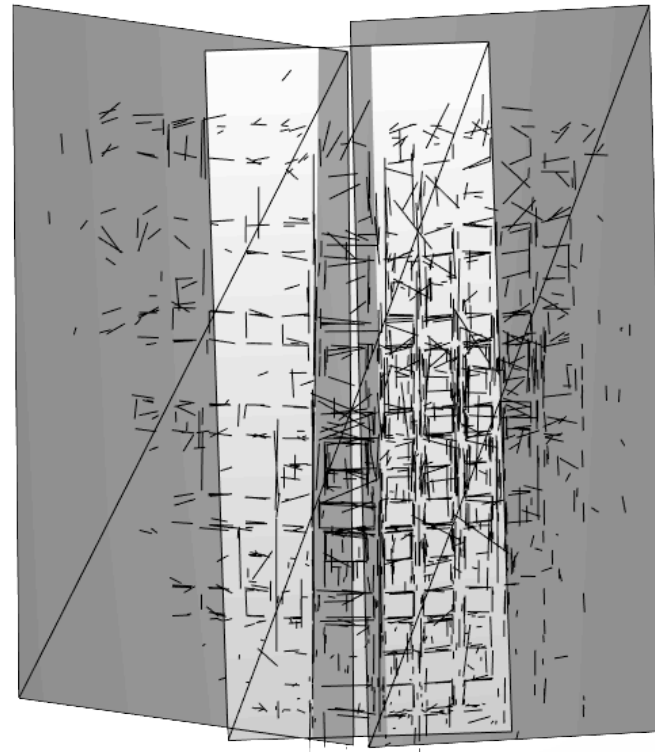
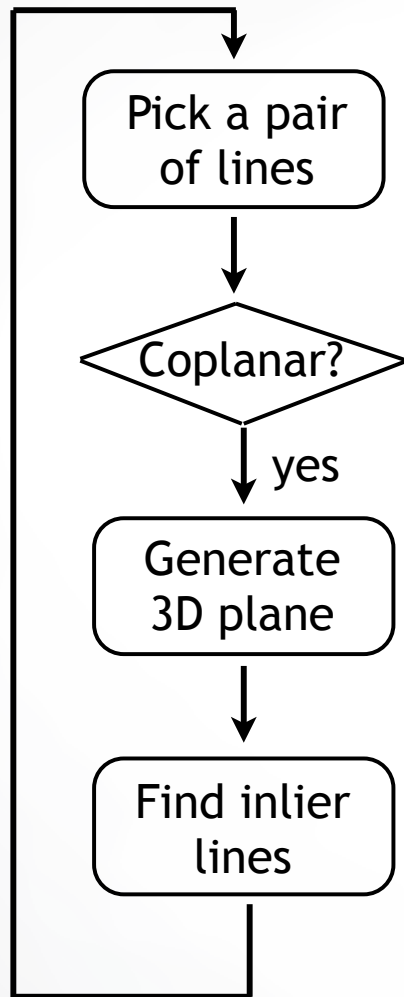


Image Segmentation

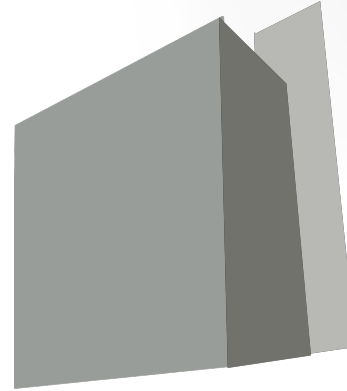
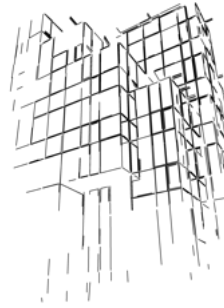
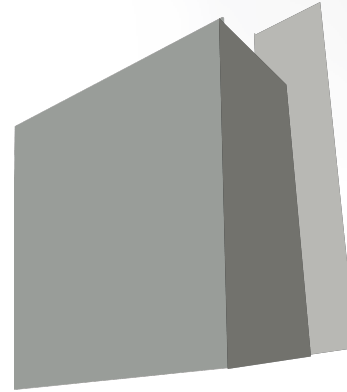
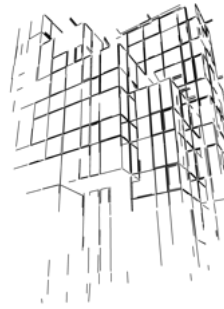
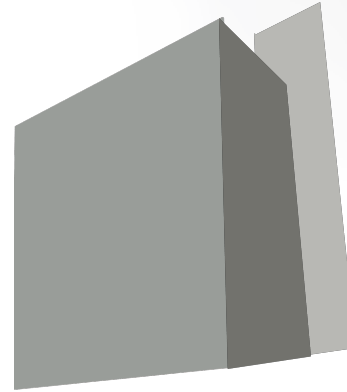
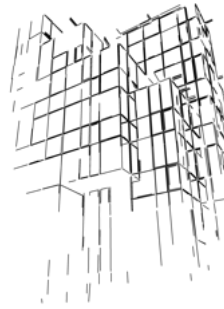


Image Segmentation



What is the most likely plane assignment for each pixel?

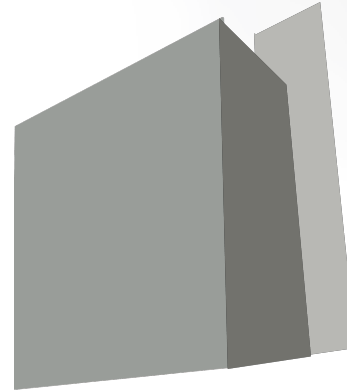
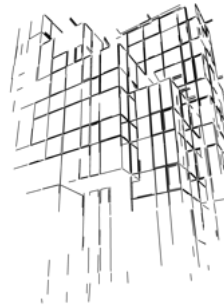
Image Segmentation



What is the most likely plane assignment for each pixel?

$$E = \sum_{p \in I_i} E_{data}(h_p) + \alpha \sum_{\{p, q\} \in N_p} E_{smooth}(h_p, h_q)$$

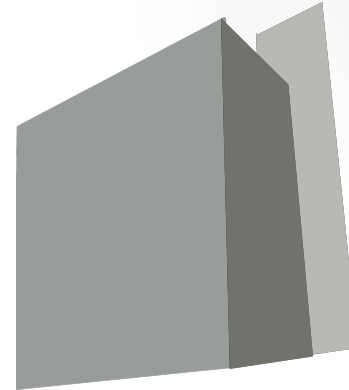
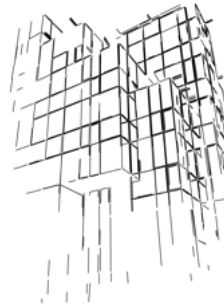
Image Segmentation



What is the most likely plane assignment for each pixel?

$$E = \sum_{p \in I_i} E_{data}(h_p) + \alpha \sum_{\{p,q\} \in N_p} E_{smooth}(h_p, h_q)$$

Image Segmentation



What is the most likely plane assignment for each pixel?

$$E = \sum_{p \in I_i} E_{data}(h_p) + \alpha \sum_{\{p, q\} \in N_p} E_{smooth}(h_p, h_q)$$

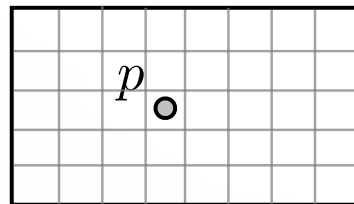
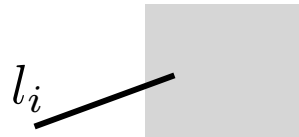
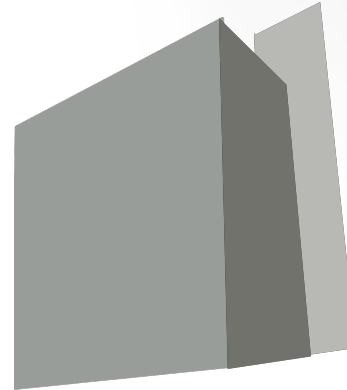
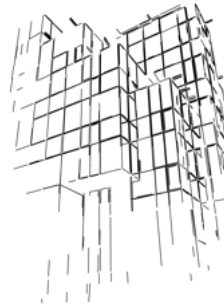


Image Segmentation



What is the most likely plane assignment for each pixel?

$$E = \sum_{p \in I_i} E_{data}(h_p) + \alpha \sum_{\{p,q\} \in N_p} E_{smooth}(h_p, h_q)$$

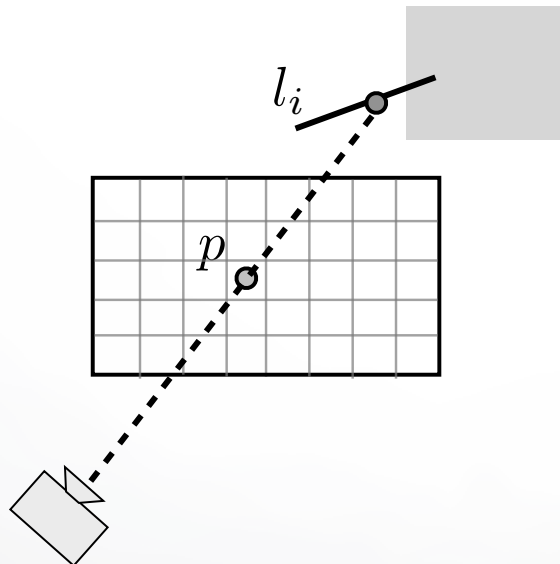
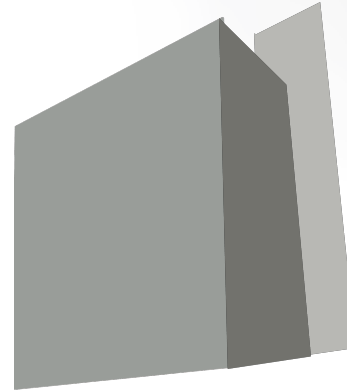
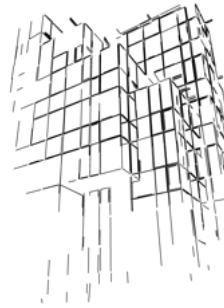


Image Segmentation



What is the most likely plane assignment for each pixel?

$$E = \sum_{p \in I_i} E_{data}(h_p) + \alpha \sum_{\{p, q\} \in N_p} E_{smooth}(h_p, h_q)$$

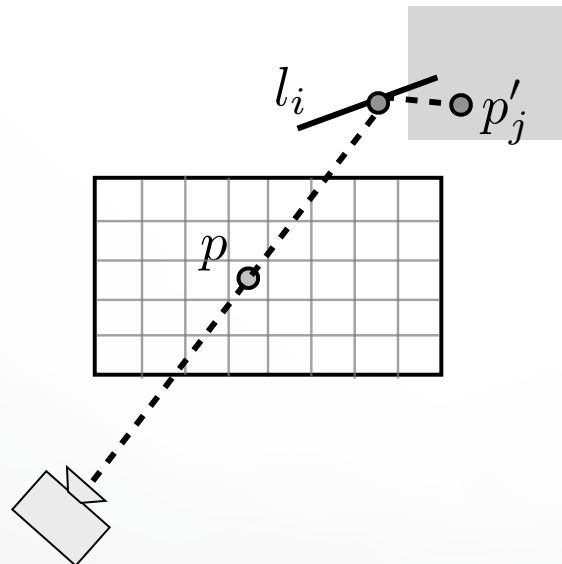
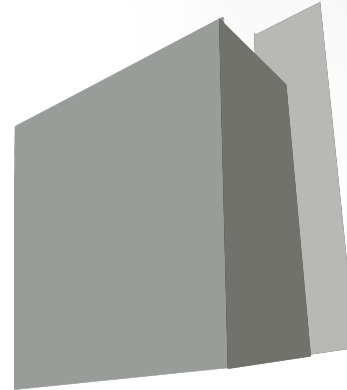
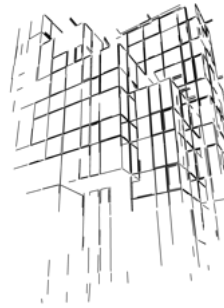


Image Segmentation



What is the most likely plane assignment for each pixel?

$$E = \sum_{p \in I_i} E_{data}(h_p) + \alpha \sum_{\{p, q\} \in N_p} E_{smooth}(h_p, h_q)$$

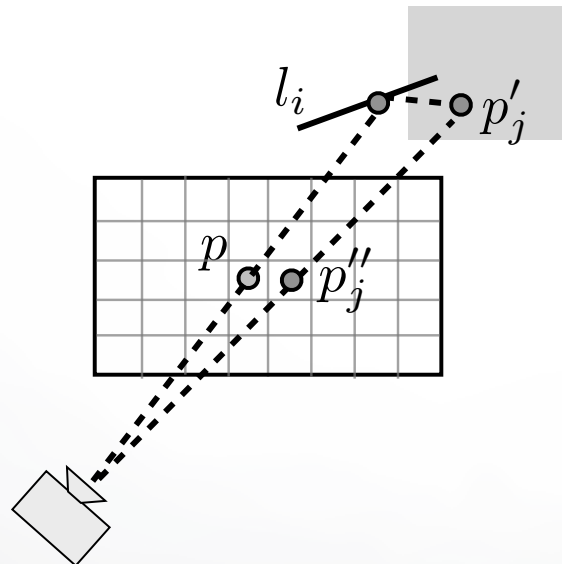
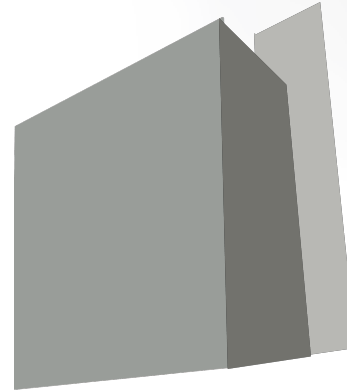
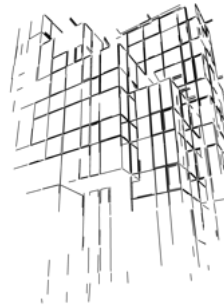


Image Segmentation



What is the most likely plane assignment for each pixel?

$$E = \sum_{p \in I_i} E_{data}(h_p) + \alpha \sum_{\{p, q\} \in N_p} E_{smooth}(h_p, h_q)$$

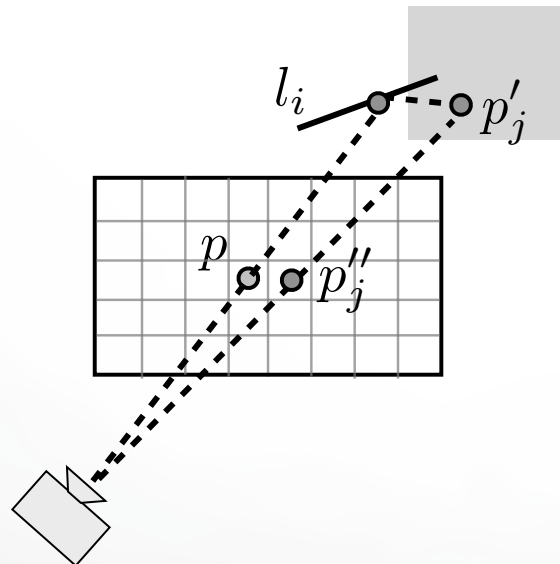
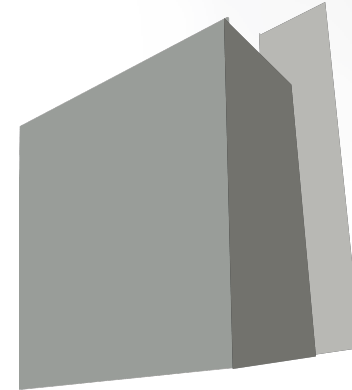
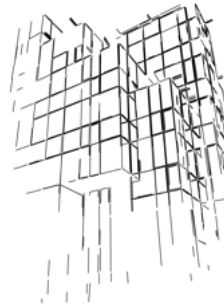


Image Segmentation



What is the most likely plane assignment for each pixel?

$$E = \sum_{p \in I_i} E_{data}(h_p) + \alpha \sum_{\{p, q\} \in N_p} E_{smooth}(h_p, h_q)$$

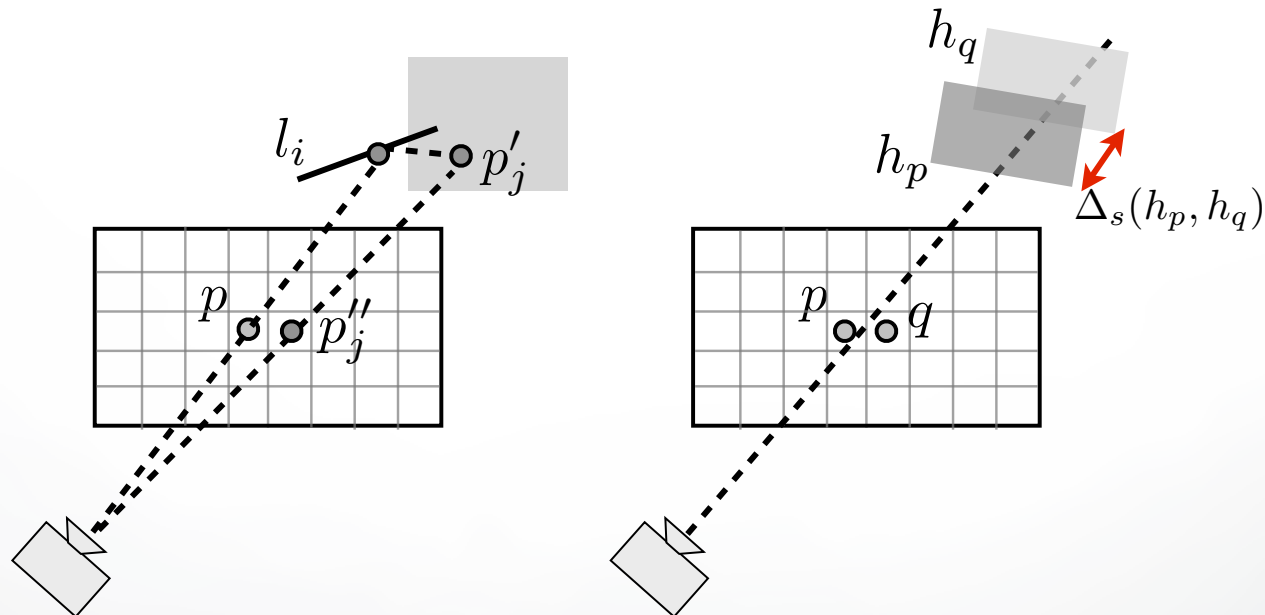
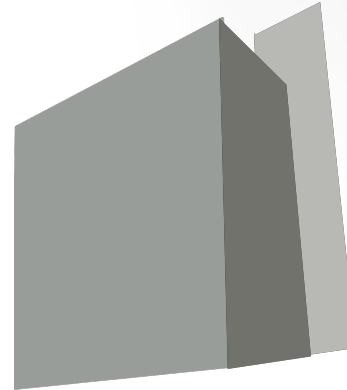
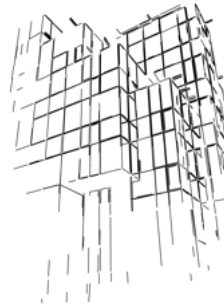
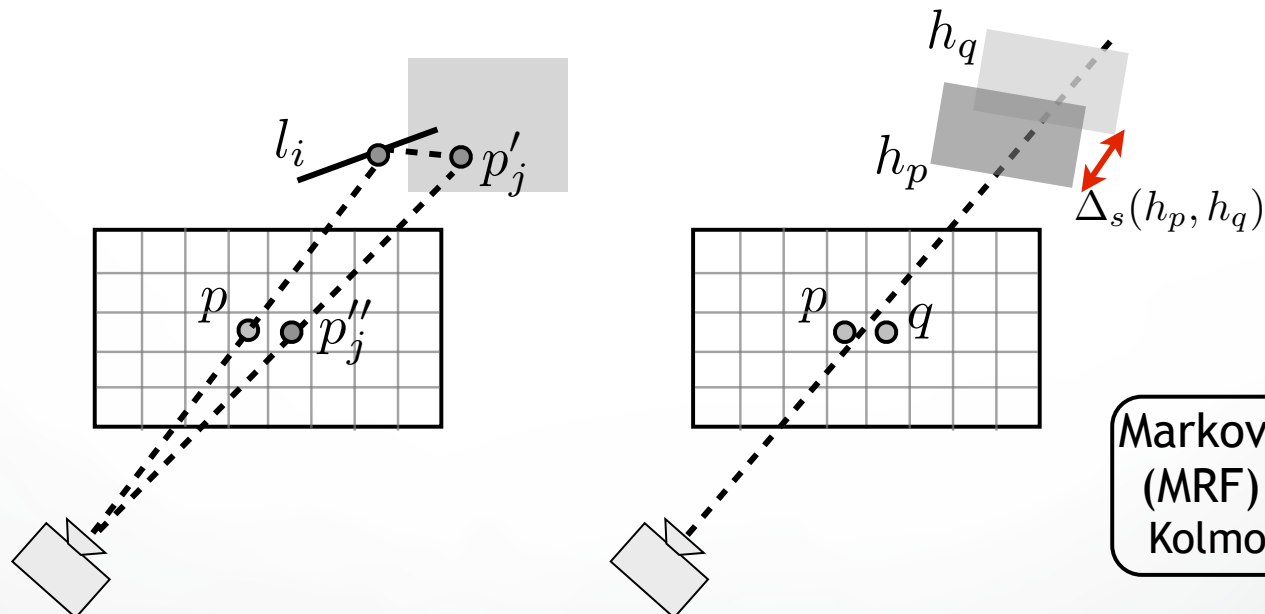


Image Segmentation



What is the most likely plane assignment for each pixel?

$$E = \sum_{p \in I_i} E_{data}(h_p) + \alpha \sum_{\{p, q\} \in N_p} E_{smooth}(h_p, h_q)$$



Markov Random Field
(MRF) Optimization
Kolmogorov Pami'06

Refined Segmentation



input



MRF optimization

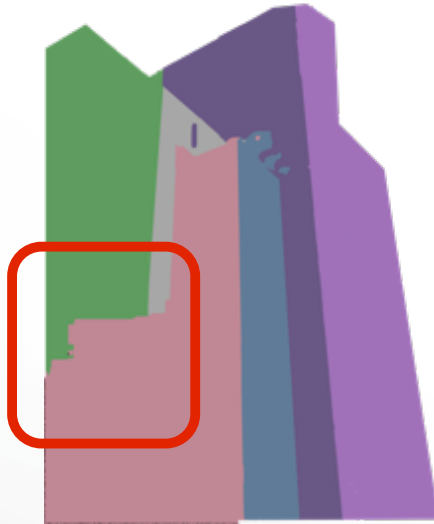
Refined Segmentation



input



MRF optimization



plane intersections

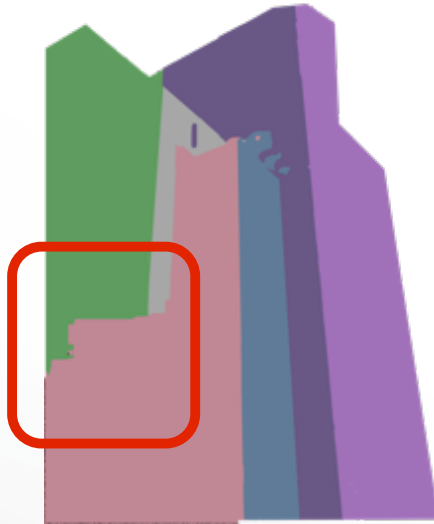
Refined Segmentation



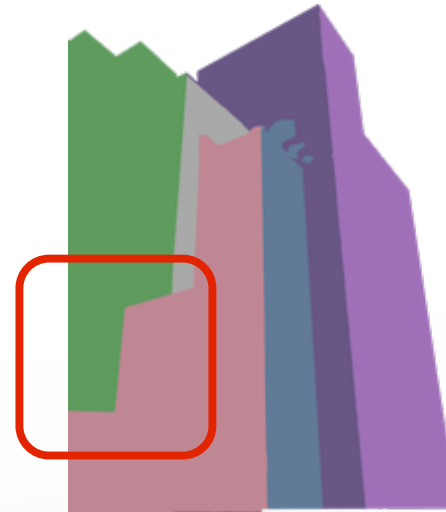
input



MRF optimization



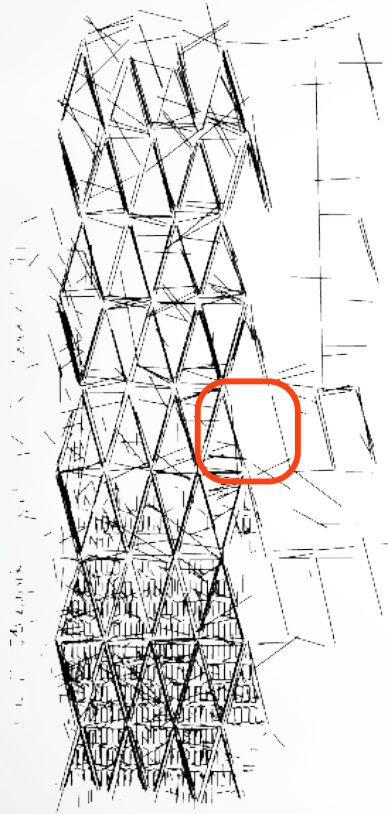
plane intersections



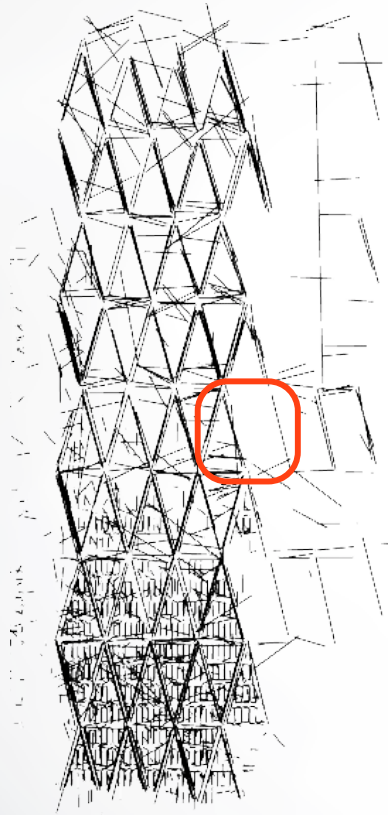
user correction

User Assistance

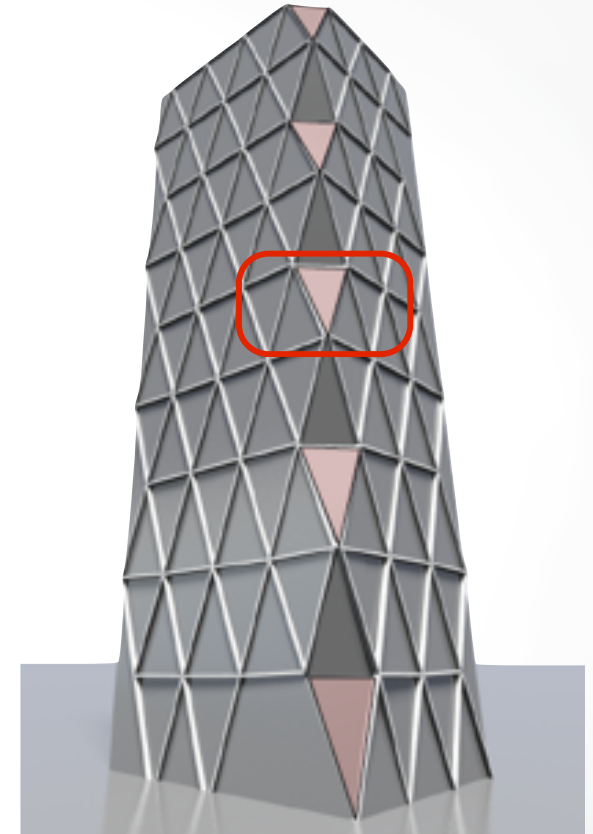
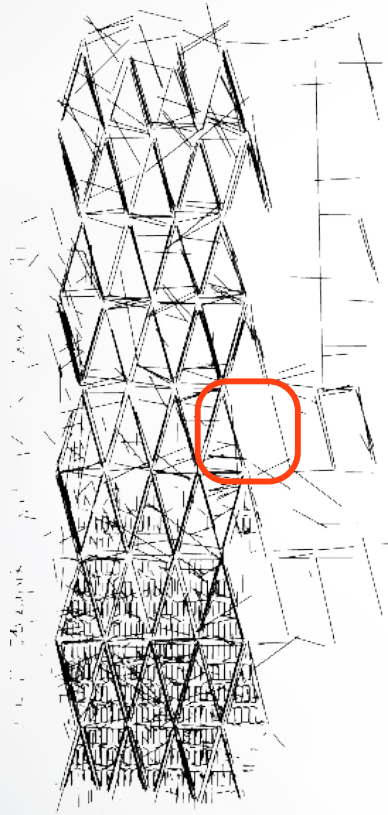
User Assistance



User Assistance

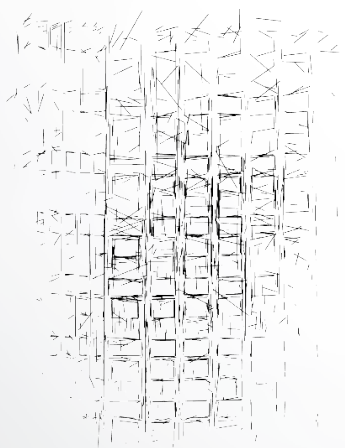


User Assistance





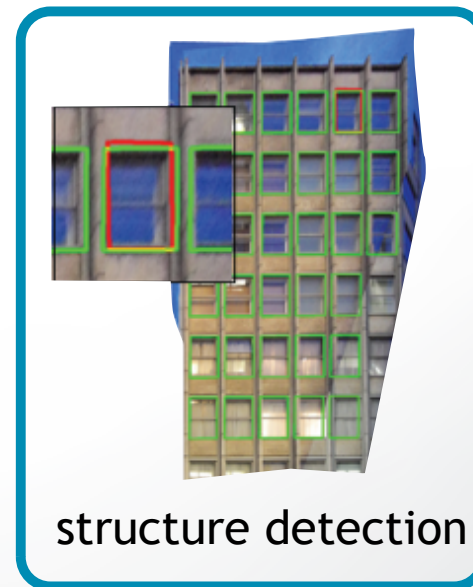
input images



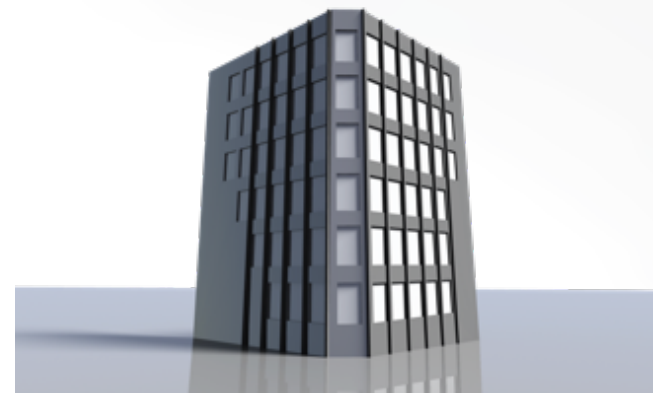
3D lines



plane fitting



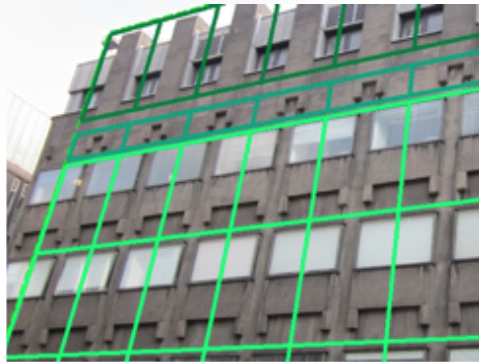
structure detection



output reconstruction

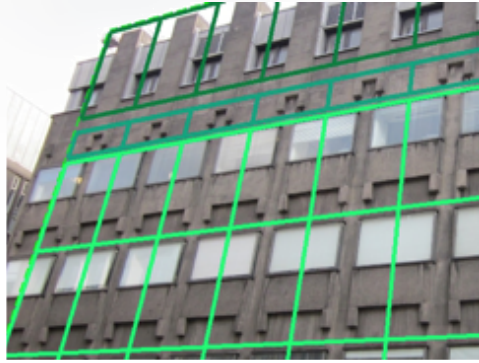
Symmetry Detection

Symmetry Detection



Wu et al. CVPR'10

Symmetry Detection

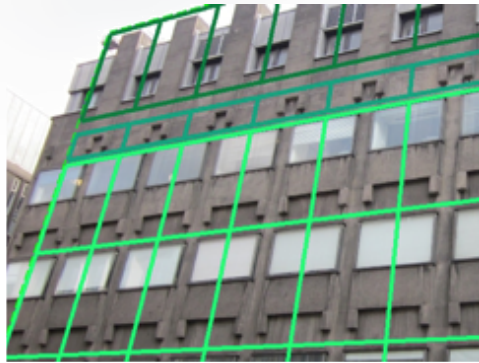


Wu et al. CVPR'10



user-guided selection

Symmetry Detection



Wu et al. CVPR'10

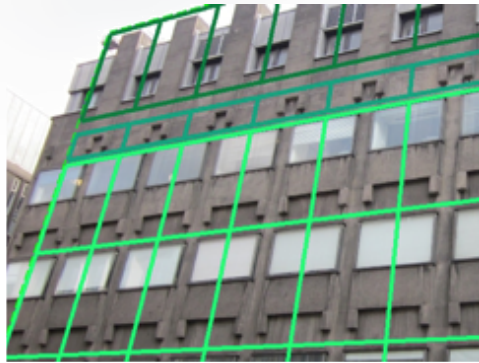


user-guided selection



texture-based similarity

Symmetry Detection



Wu et al. CVPR'10



user-guided selection

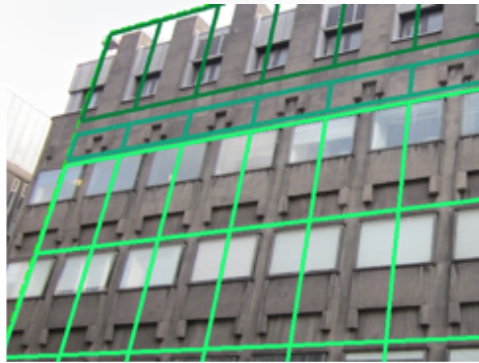


texture-based similarity



feature-line similarity

Symmetry Detection



Wu et al. CVPR'10



user-guided selection



$\alpha \cdot$

texture-based similarity



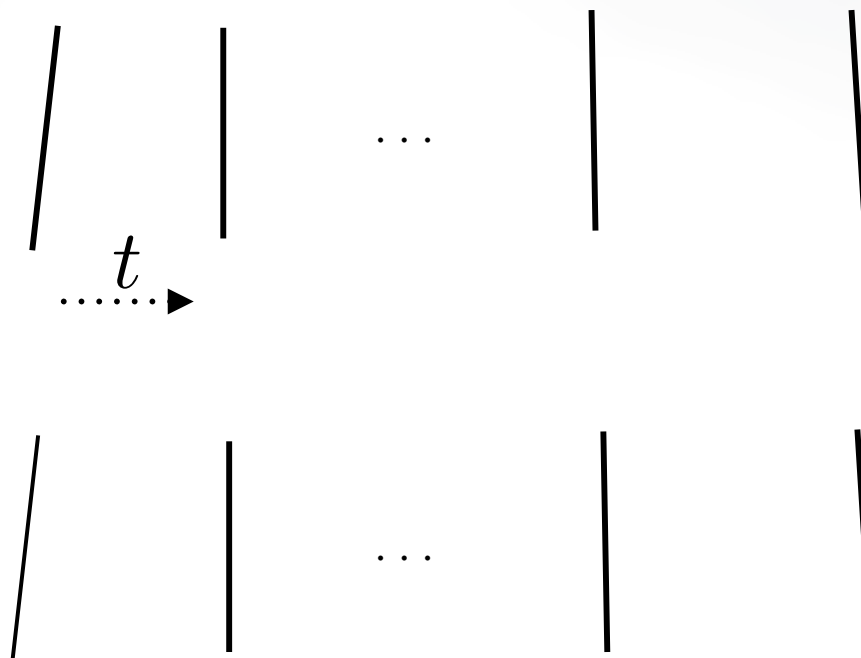
$+\beta \cdot$

feature-line similarity

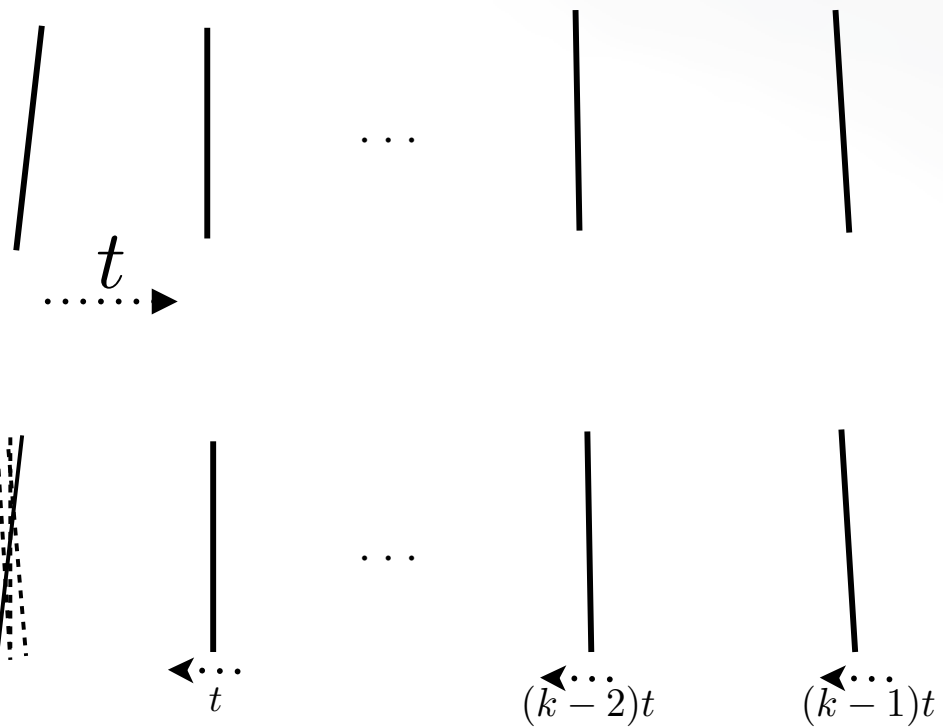
Symmetry Refinement



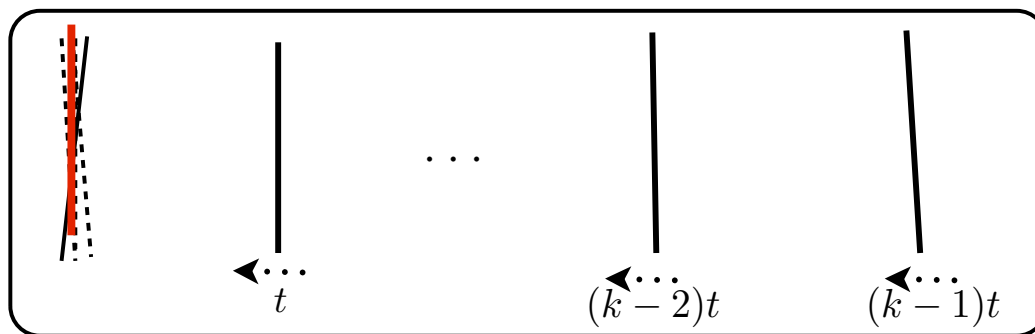
Symmetry Refinement



Symmetry Refinement

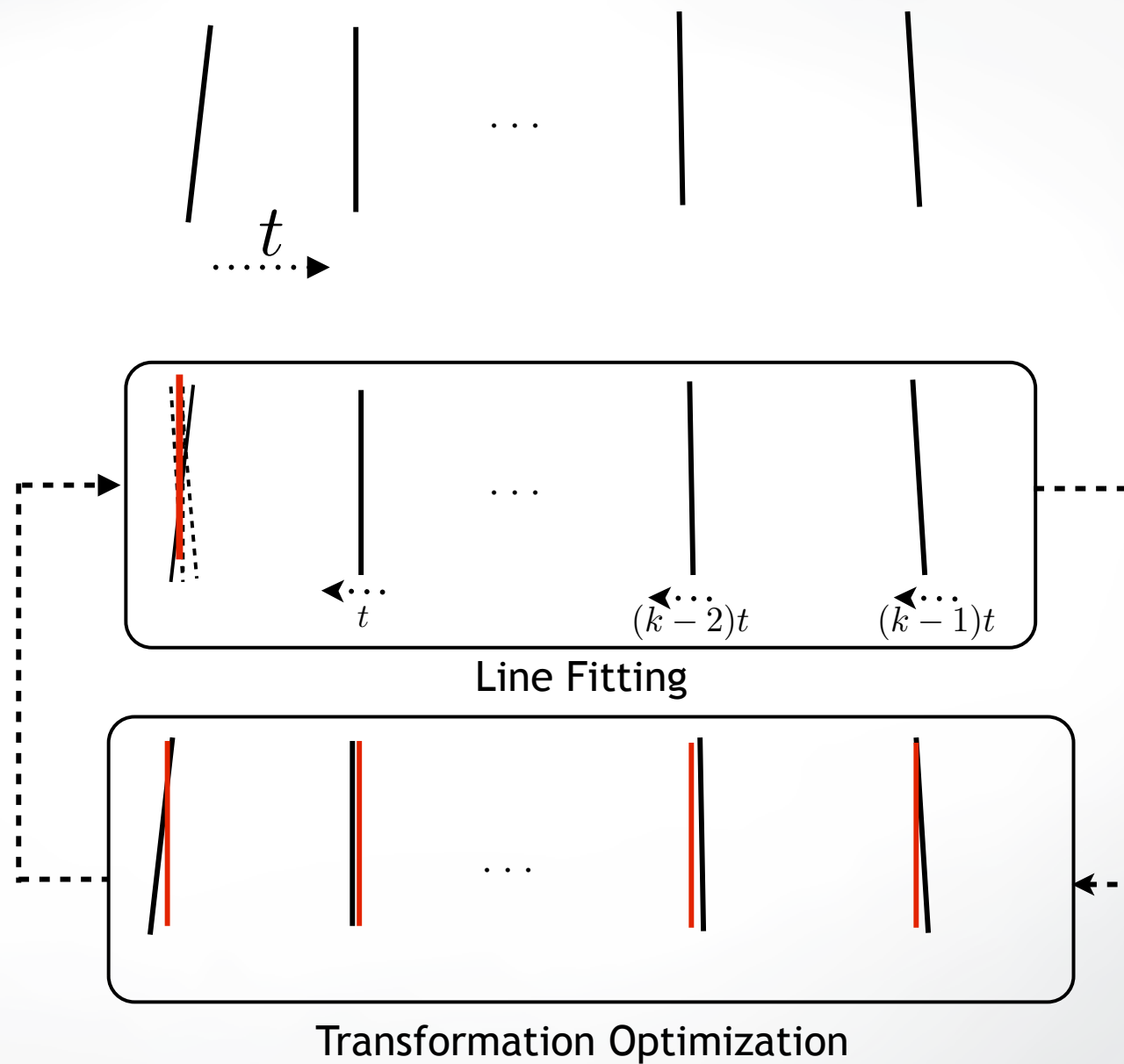


Symmetry Refinement



Line Fitting

Symmetry Refinement



Structure Completion



input

Structure Completion



input



initial detection

Structure Completion



input



initial detection



initial refinement

Structure Completion



input



initial detection



initial refinement

projected 3D lines

Structure Completion



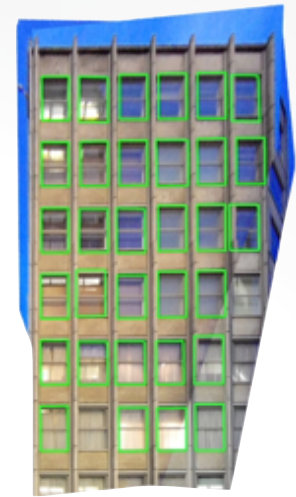
input



initial detection



initial refinement



completion

projected 3D lines

Structure Completion



input

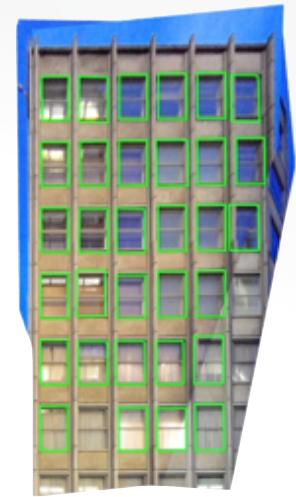


initial detection



initial refinement

projected 3D lines



completion

2D lines

Structure Completion



input

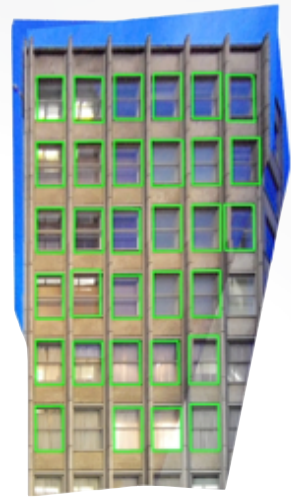


initial detection



initial refinement

projected 3D lines



completion

2D lines

final refinement:

Structure Completion



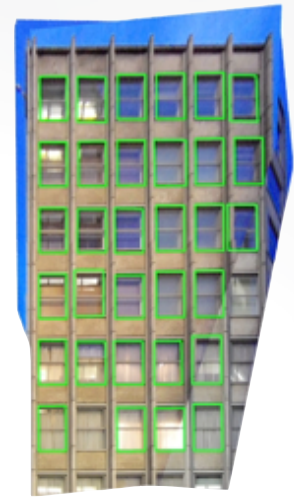
input



initial detection



initial refinement



completion

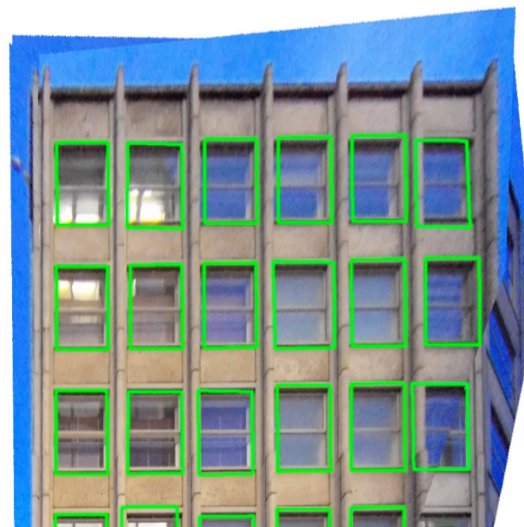
projected 3D lines

2D lines

final refinement:

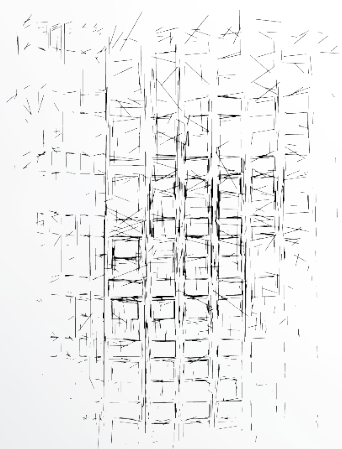


repetition completion





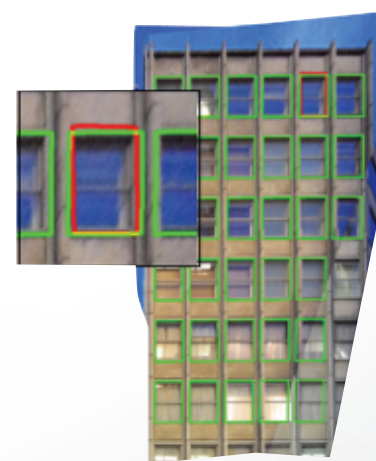
input images



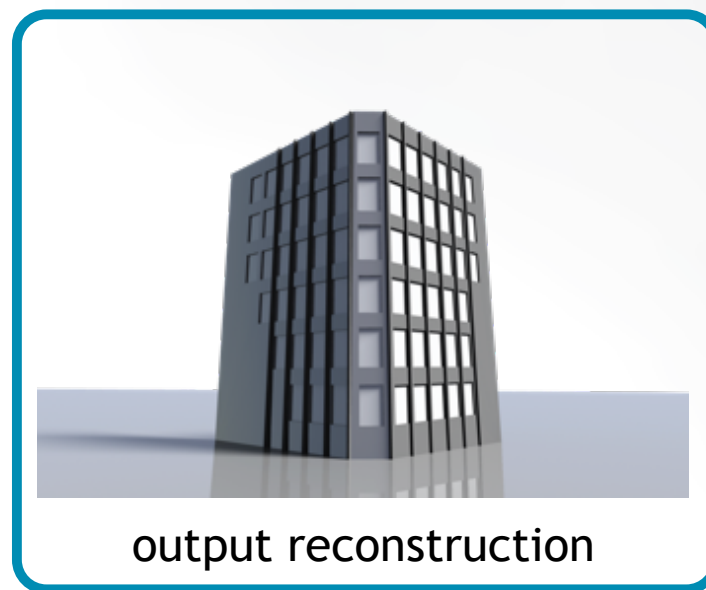
3D lines



plane fitting



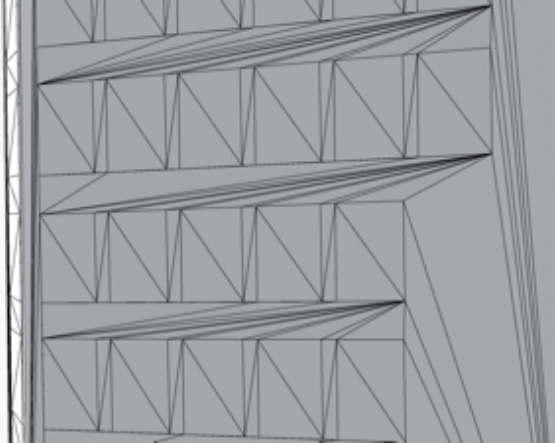
structure detection



output reconstruction

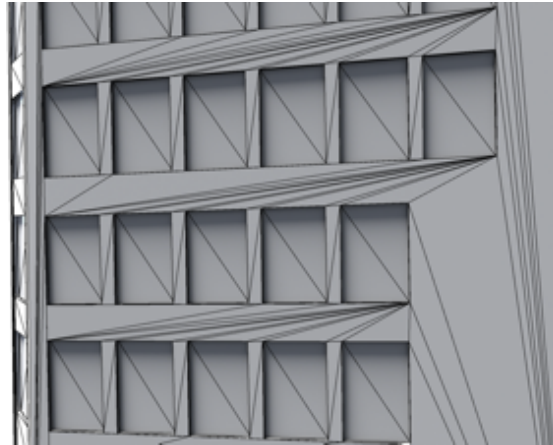
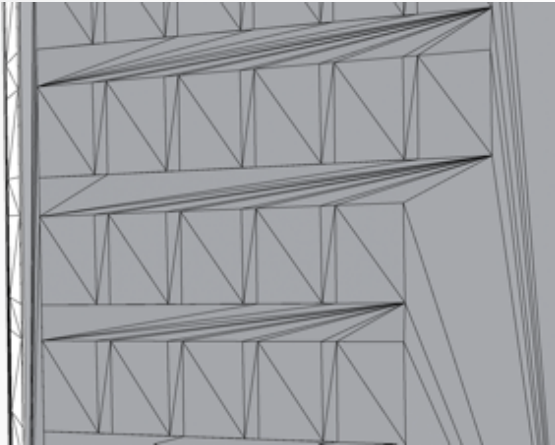
Procedural Depth Refinement

Procedural Depth Refinement



no user edit

Procedural Depth Refinement

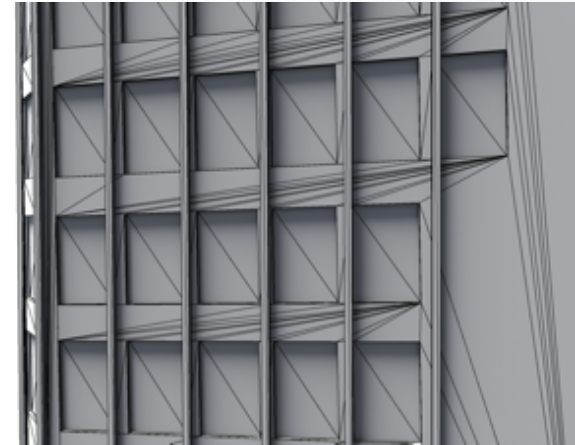
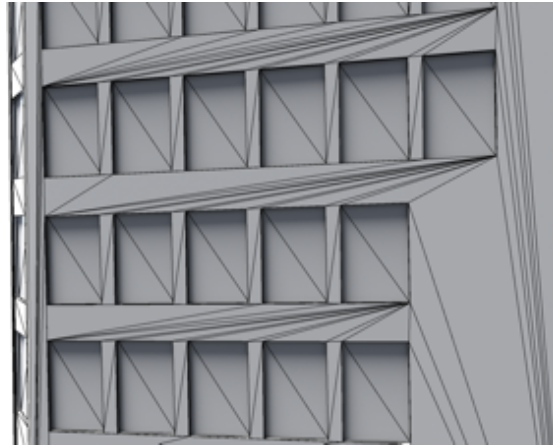
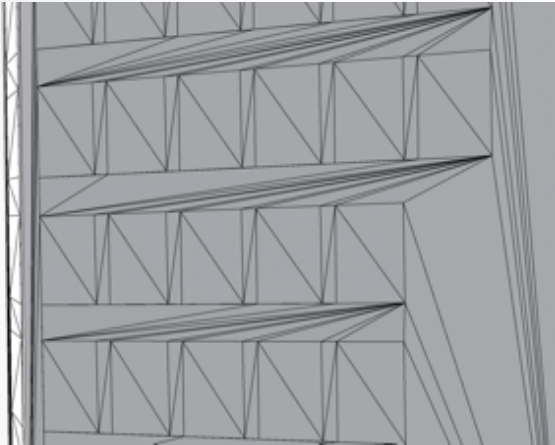


no user edit



window extrusion

Procedural Depth Refinement



no user edit

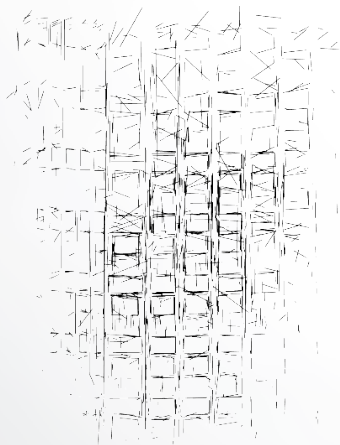
window extrusion

beam extrusion

Summary



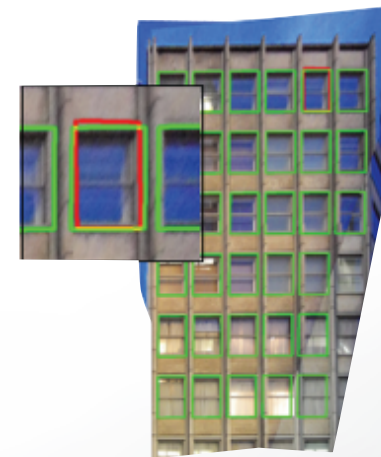
input images



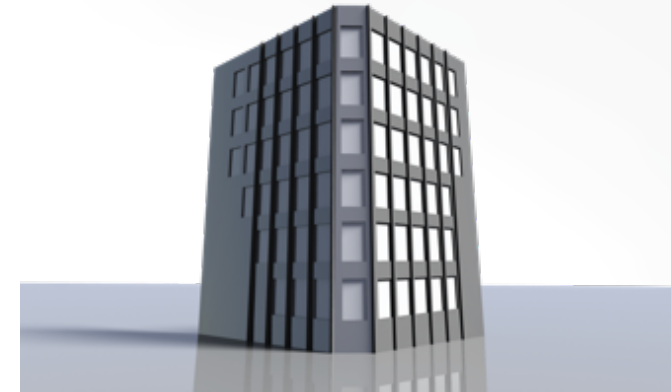
3D lines



plane fitting



structure detection

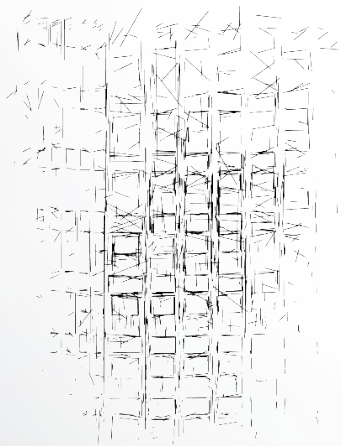


output reconstruction

Summary



input images

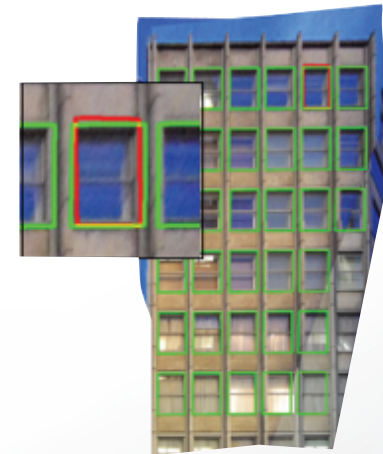


3D lines



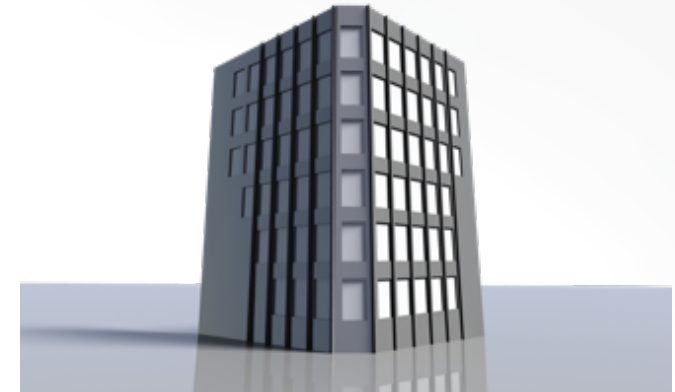
plane fitting

geometric priors



structure detection

structural priors



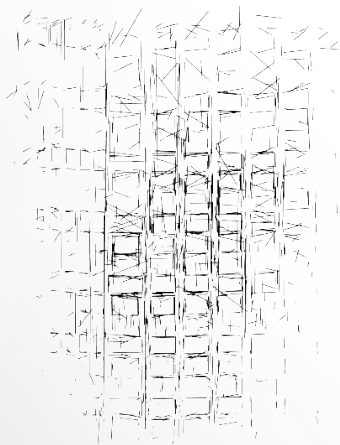
output reconstruction



Summary



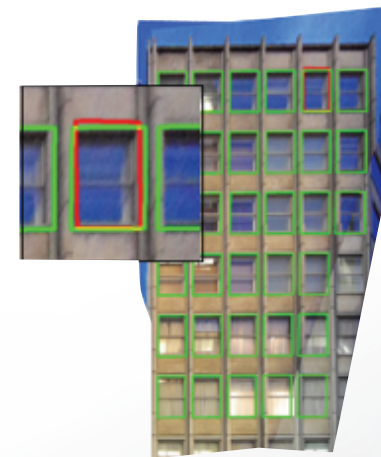
input images



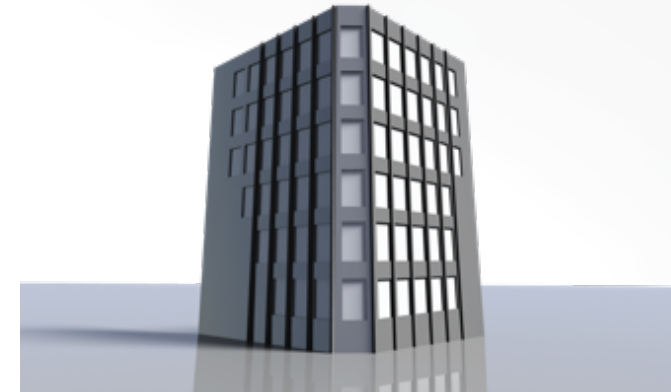
3D lines



plane fitting



structure detection

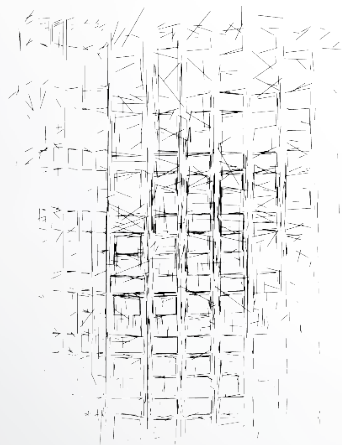


output reconstruction

Summary



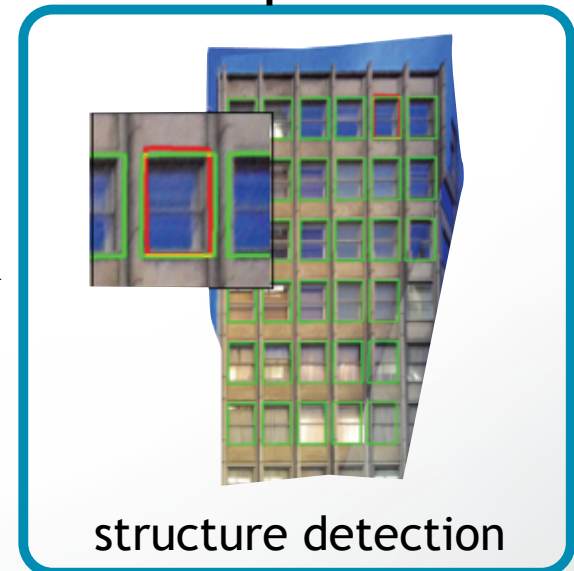
input images



3D lines

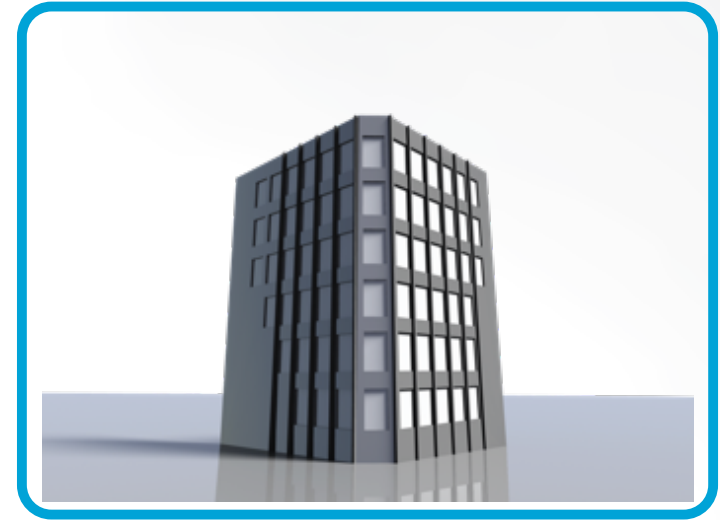


plane fitting



structure detection

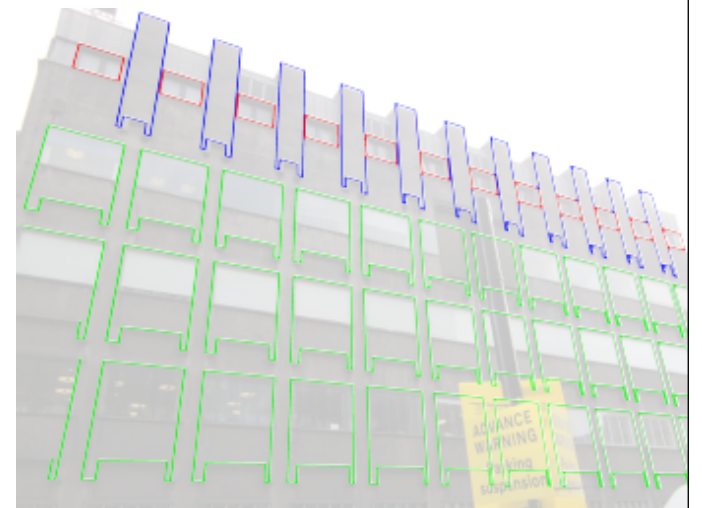
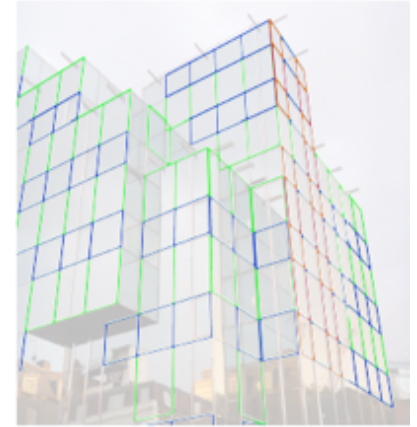
user assistance



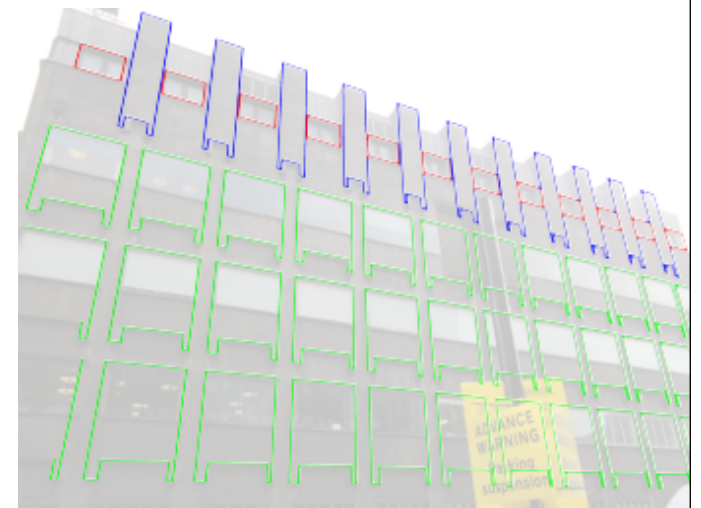
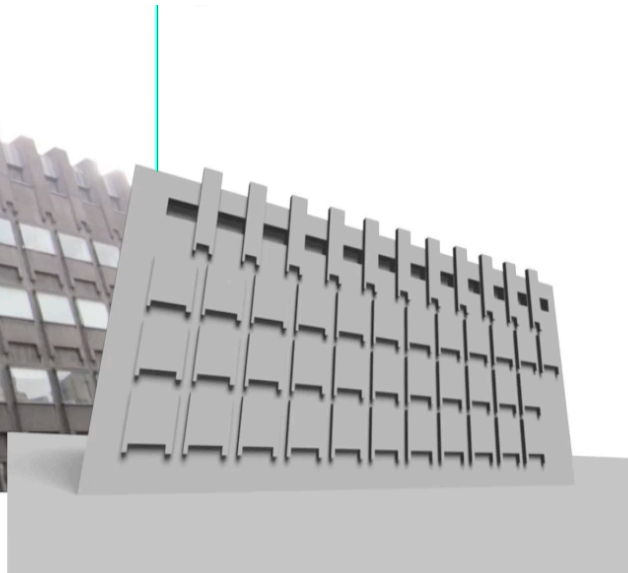
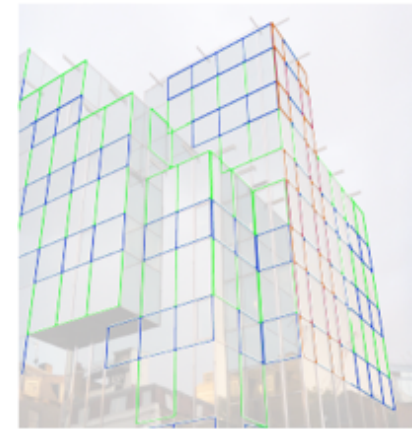
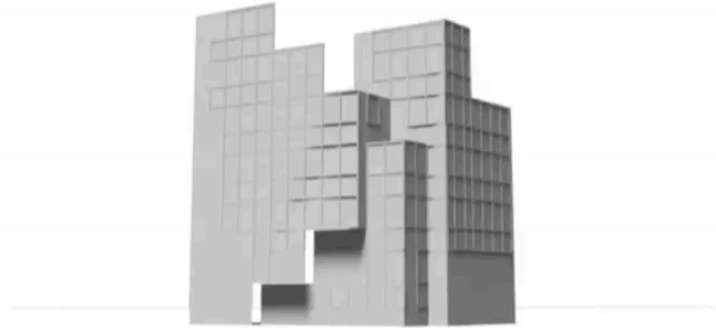
output reconstruction

Results

Results



Results



Comparison to PMVS



input



PMVS
Furukawa et al. '09

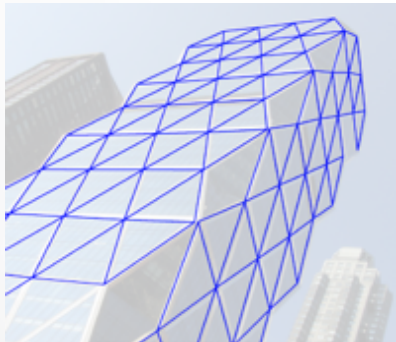


PMVS + Poisson

Comparison to PMVS



input



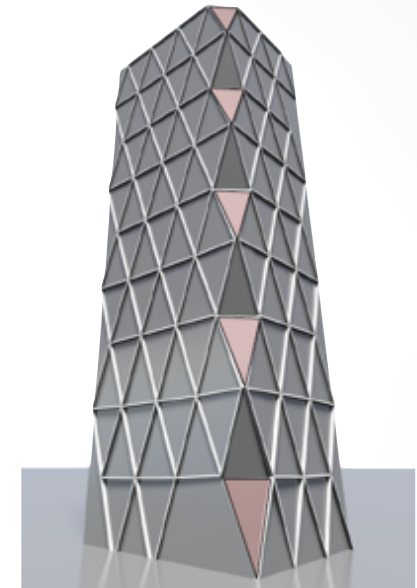
repetition detection



PMVS
Furukawa et al. '09



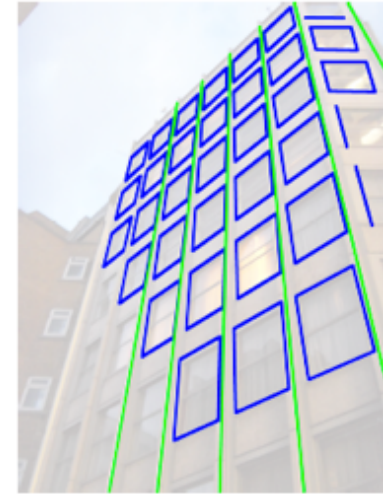
PMVS + Poisson



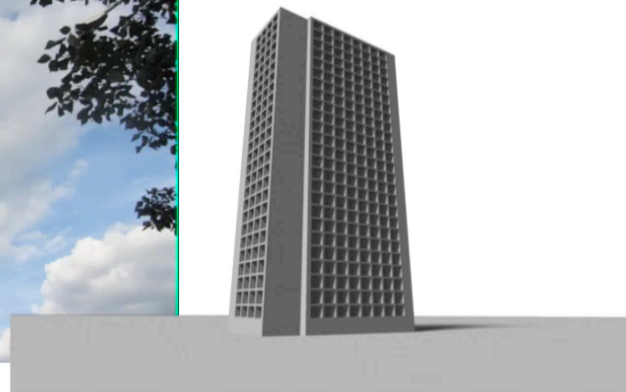
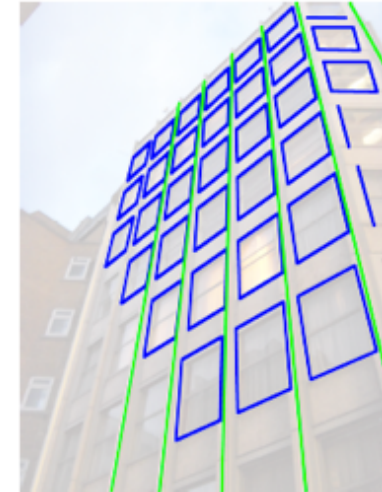
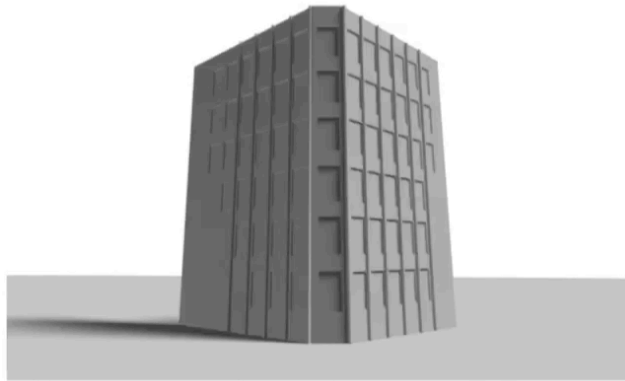
our reconstruction

More Results

More Results

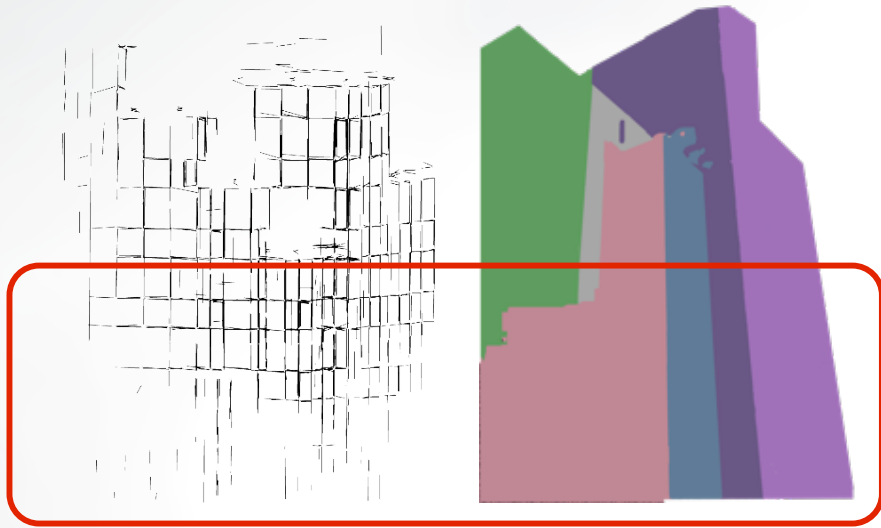


More Results



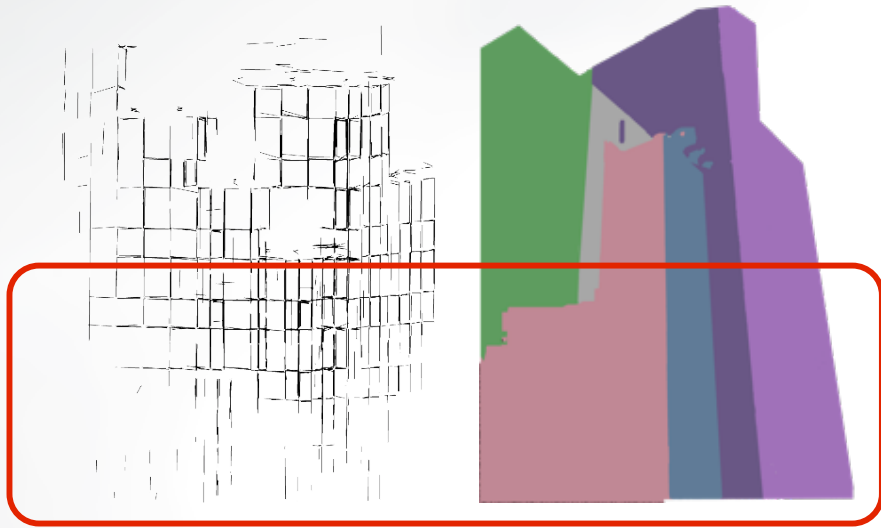
Limitations

Limitations



insufficient lines

Limitations

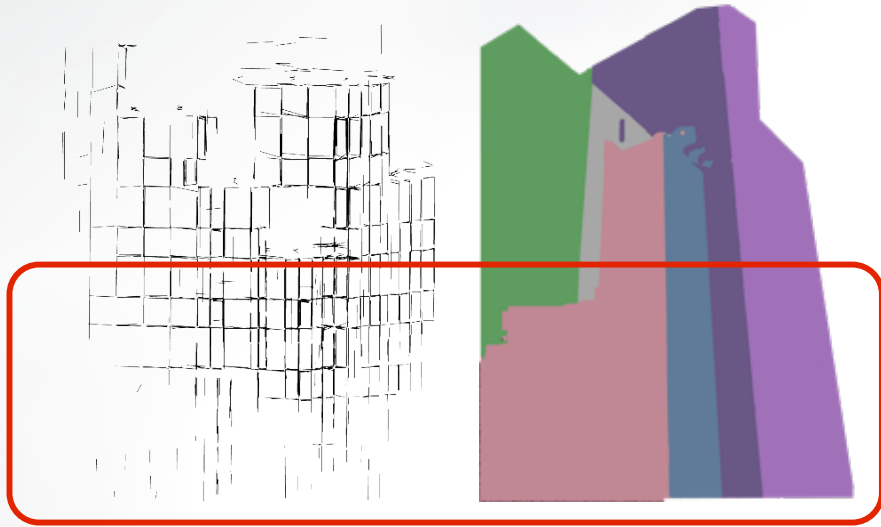


insufficient lines



variations in repetitions

Limitations



insufficient lines

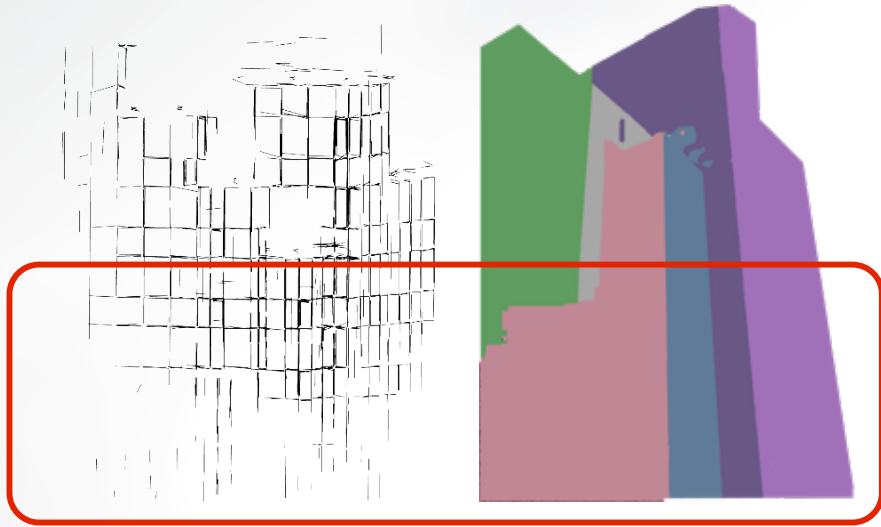


variations in repetitions



curved features

Limitations



insufficient lines



variations in repetitions



curved features



no repetitions

What's Next?



building colonies



similar architecture style



Structure-from-Motion

Acknowledgements

ERC Starting Grant 257453 COSYM

KAUST Visiting Student Grant

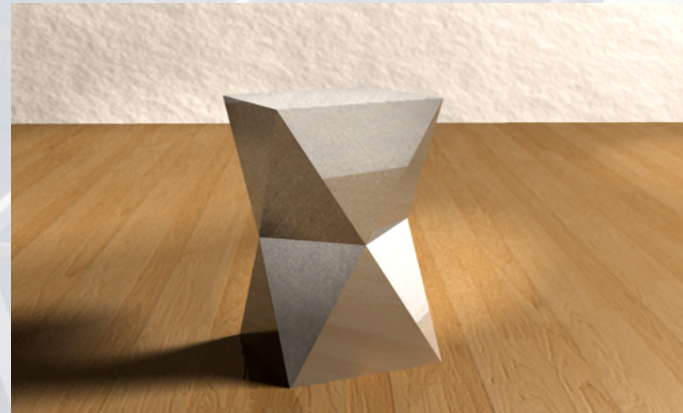
Marie Curie Career Integration Grant 303541

Thanks...

?



input



output

<http://www.duygu-ceylan.com/duygu-ceylan/symmFacade.html>