Im Oberseminar

Deformationsquantisierung

spricht am **08.12.2017 um 14 Uhr c.t.,**

im Seminarraum 00.009 (Physik Ost)

Thomas Bendokat

über das Thema:

Encoding camera positions in a Riemannian manifold

Reconstructing the positioning of two cameras at different locations from visual data can be done by using essential matrices. We give an introduction about what essential matrices are and then show how they form a Riemannian quotient manifold. We compare different ways of describing this manifold and their respective advantages and disadvantages, and give an outlook towards a suitable matrix description as well as its use for geodesics, parallel transport and curvatures.

gez. Knut Hüper