WALKER HOUSE – CAMERA ACCURACY

We were provided with measured survey information in plan and elevation (0-1 and 02) form of the existing surroundings. We were able to identify and plot 'camera-matching' points within our 3D model based on this data (03) You can see on the black and white images attached where these data points are located on the photos (04 and 05). The software has a script that identifies where these points are in 3D space and calculates backwards where they would be seen in the same relationship to each other as is seen on the picture plane of the host photographs. Due to the phenomenon of parallax, it means you can only see these points in this relationship from one point in space. This means that the camera the script generates in the model, as long as frame sizes and so on are copied, matches the position of the real camera in the real world (06) . So a render from the model will be an exact match to what is seen in the photo. So the introduction of our model into this same space (07), means that its geometry is also seen in the correct position in relation to the photo (08).The image of the model is rendered from that camera (09) and we then use photoshop to mask out foreground items and retouch the image in other ways to tidy up inconsistencies (10)

This is the same methodology we use in creating verified views. The main difference being that we normally commission specific survey points for matching purposes. However, as we had a surfeit of accurate survey data available, we were able to deduce the points we needed to create camera matches.

Regards,
Paul Bagnall
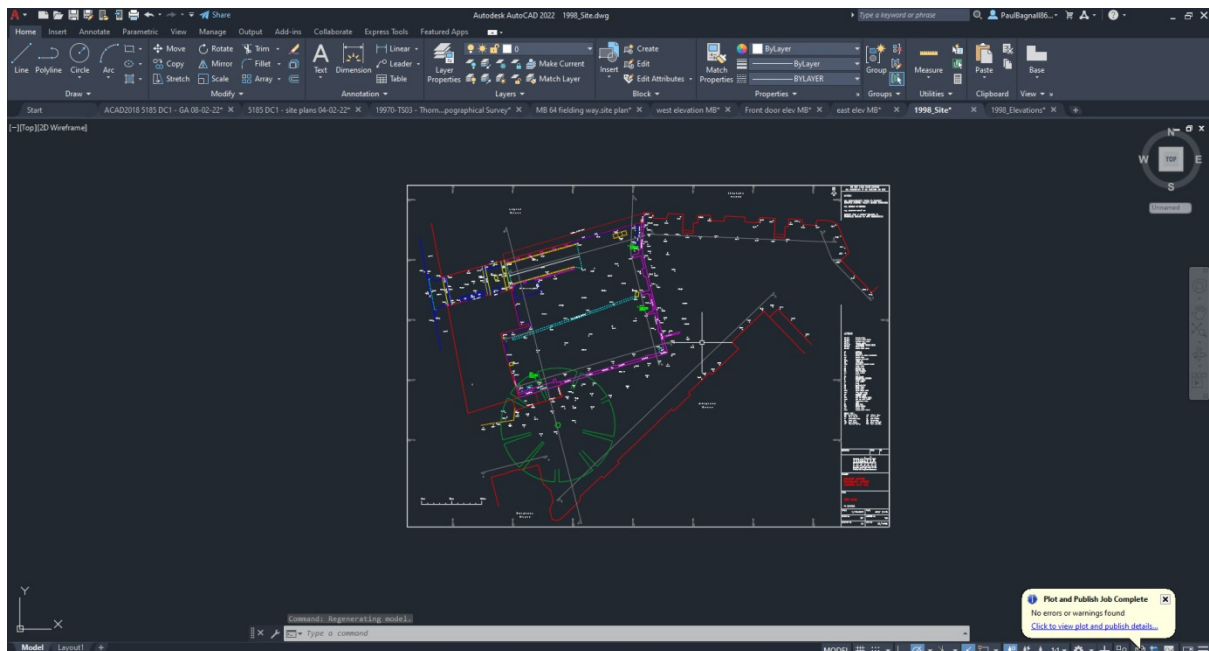Registered Architect
ARB - 057634D
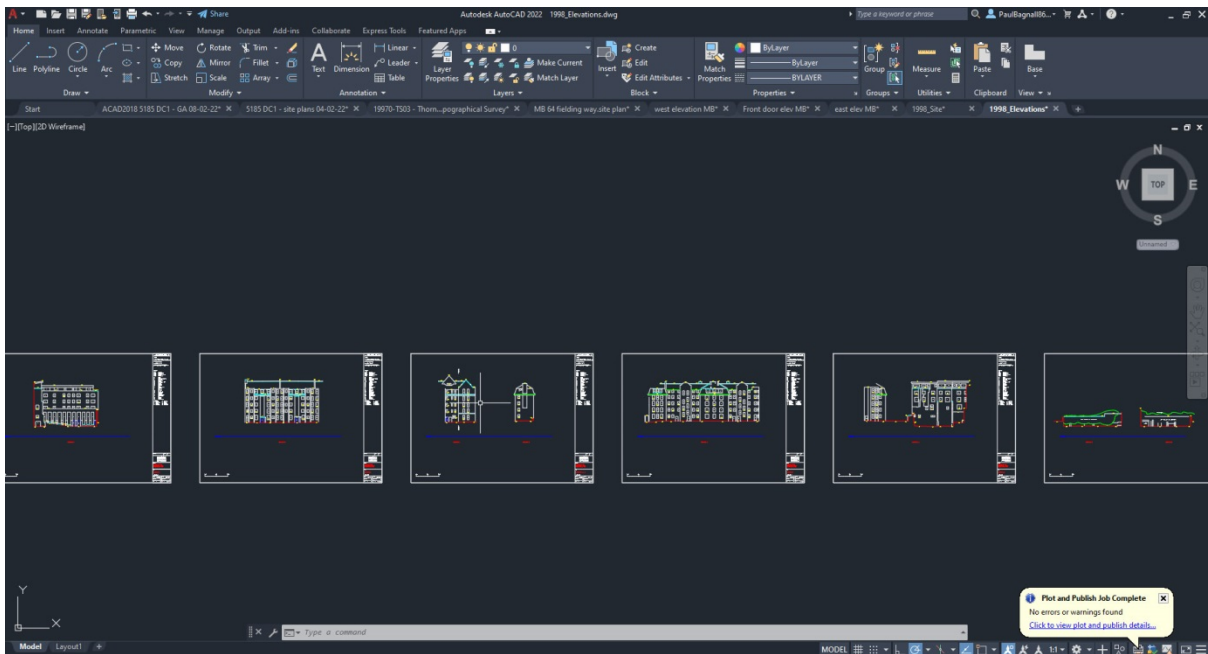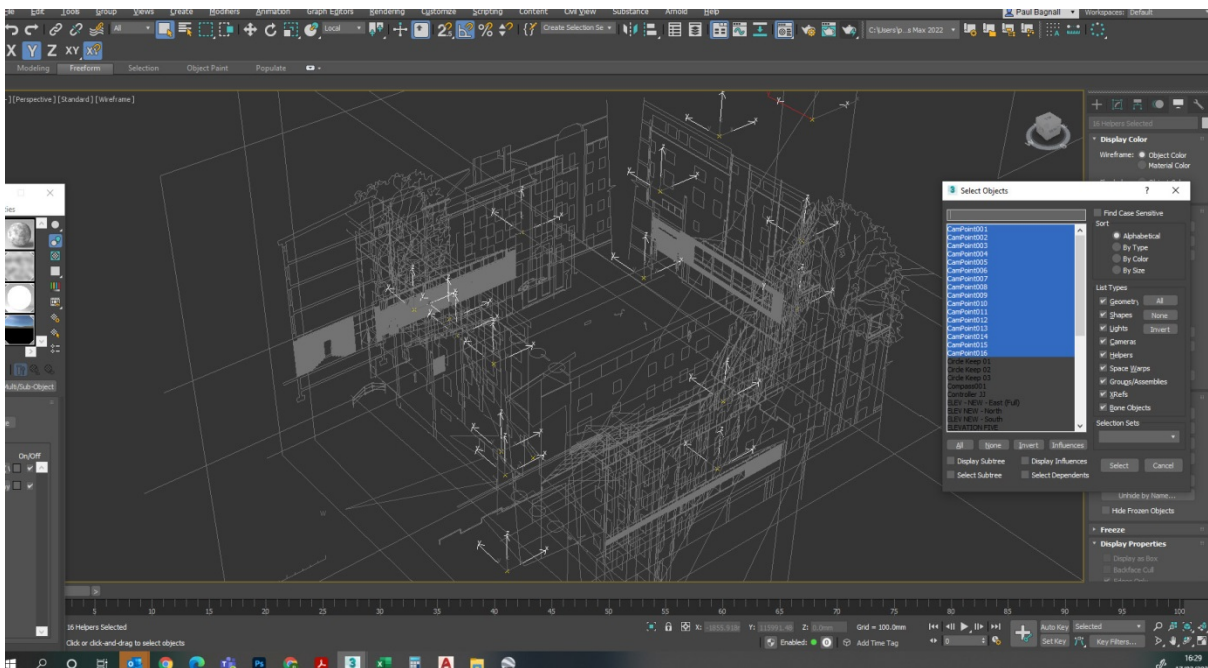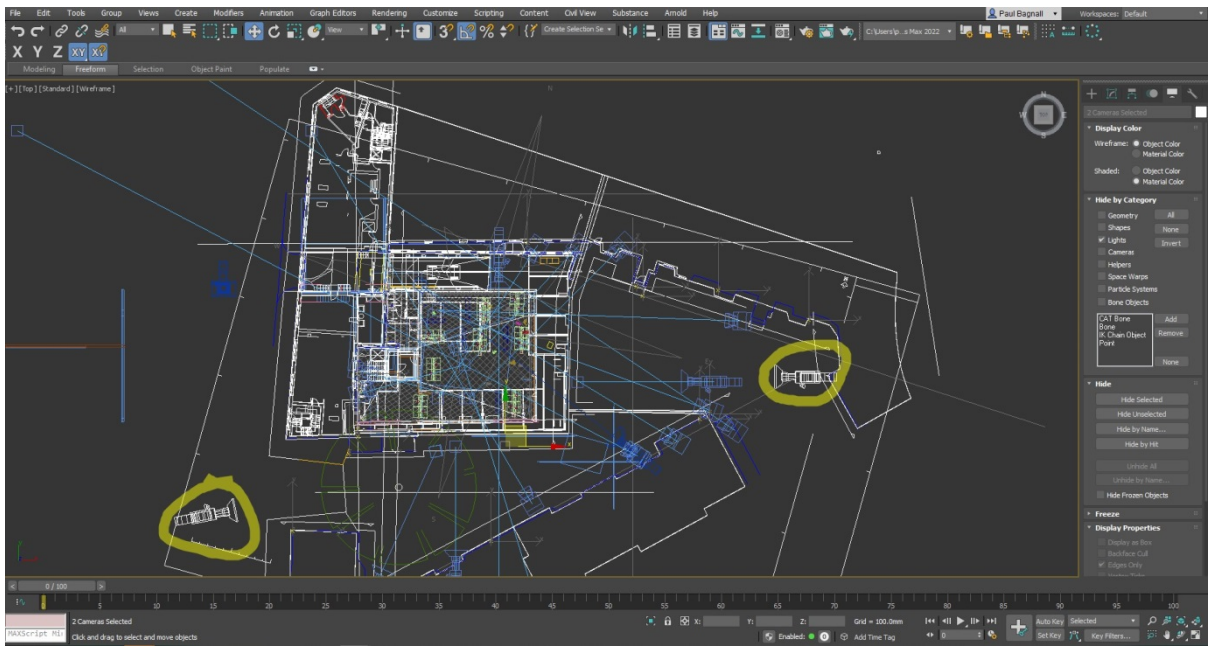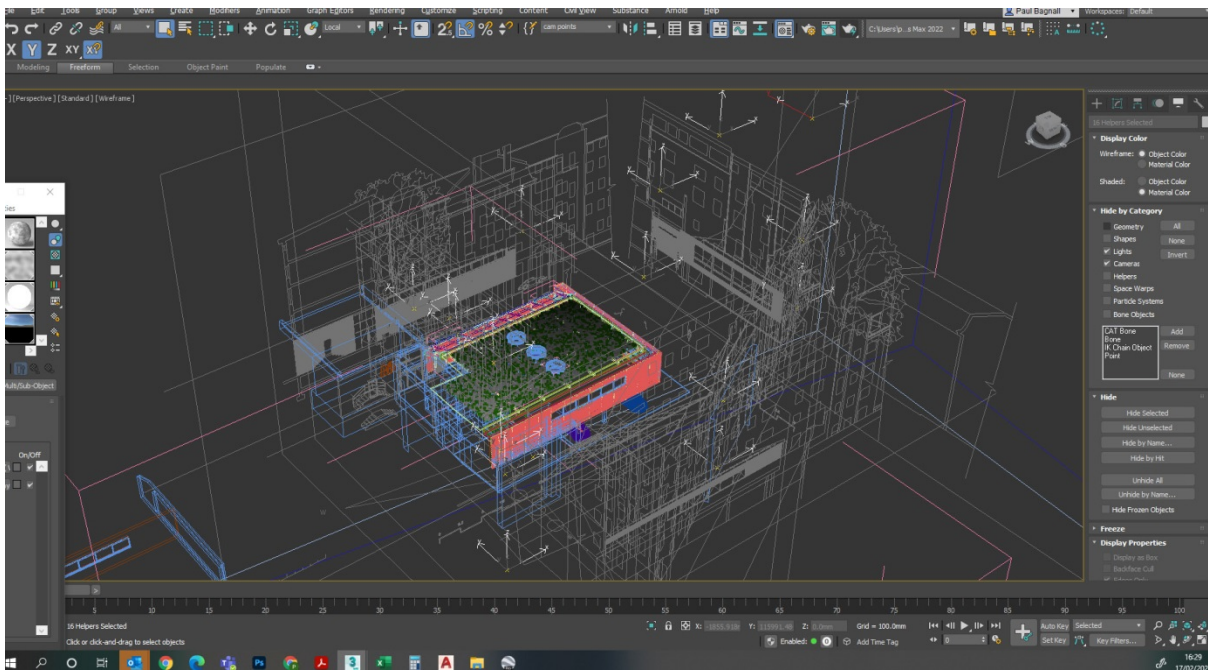RIBA - 5612129
EMPEROR VISION

IMAGE 1)

IMAGE 2)

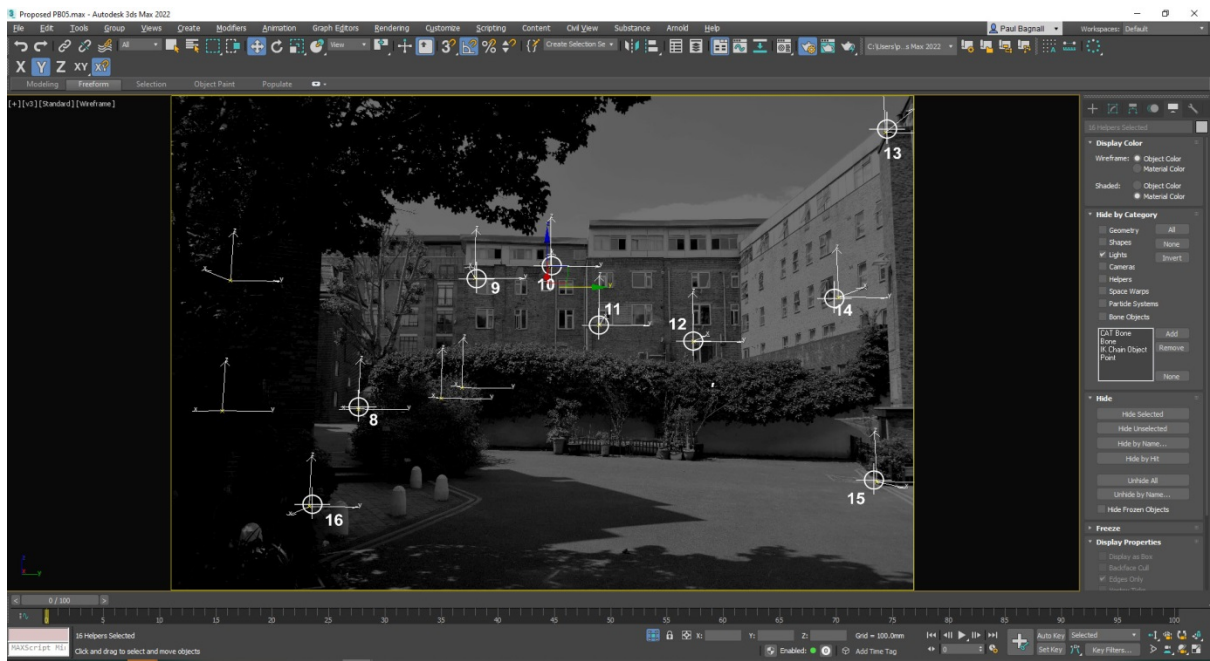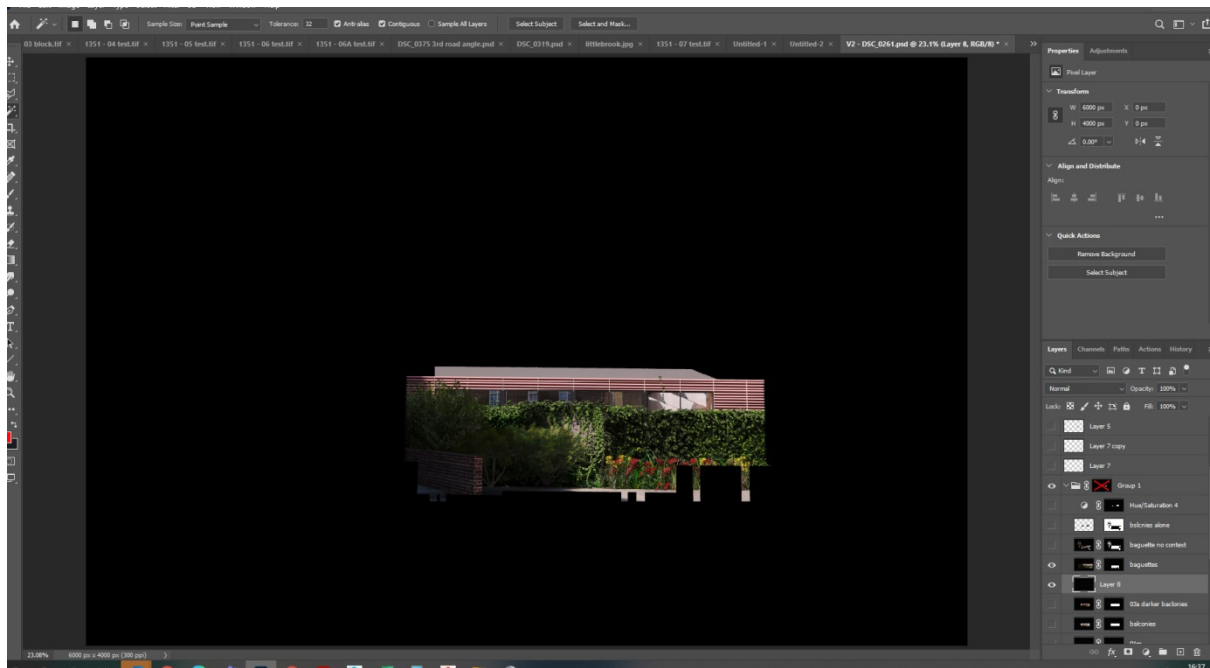
IMAGE 3)

IMAGE 4)

IMAGE 5)

IMAGE 6)

IMAGE 7)

IMAGE 8)

IMAGE 9)

IMAGE 10)