COMPUTER VISION										
1	Course Title:	COMPU	TER VISION							
2	Course Code:	BM5113								
3	Type of Course:	Optional								
4	Level of Course:	Second	Cycle							
5	Year of Study:	1								
6	Semester:	1								
7	ECTS Credits Allocated:	6.00								
8	Theoretical (hour/week):	3.00								
9	Practice (hour/week):	0.00								
10	Laboratory (hour/week):	0								
11	Prerequisites:	None								
12	Language:	Turkish								
13	Mode of Delivery:	Face to t	face							
14	Course Coordinator:	Dr. Ögr.	Üyesi CEYDA NUR ÖZTÜRK							
15	Course Lecturers:									
16	Contact information of the Course Coordinator:	ceydanur@uludag.edu.tr								
17	Website:									
18	Objective of the Course:	To introduce matching, classification, detection, segmentation, registration, tracking, and reconstruction-like problems that should be solved to provide computers with ability to see and to examine necessary representations, techniques, and algorithms for solution of these problems.								
19	Contribution of the Course to Professional Development:	Develops skills to use proper methods for understanding information that is asked for in various images and hence to manage the visual perception tasks of high-level intelligent systems.								
20	Learning Outcomes:									
		1	Being able to describe the relationships between camera images and physical world							
		2	Being able to extract image features and produce descriptors for them							
		3	Being able to obtain foreground and flow information in moving images							
		4	Being able to classify and segment objects of interest in images							
		5	Being able to provide alignment between source and destination images							
		6	Knowing the approaches of depth estimation from images							
		7	Being able to use convolutional neural networks for some vision problems							
		8								
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21	Course Content:									
14.		Сс	ourse Content:							
	Theoretical		Practice							
1	Overview of computer vision probler formation	ns, image								

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		Number	Duration (hour	Total Work Load (hour)				
Object tracking in moving images: Lu	icas-							
and shape modelling, classification,								
camera calibration								
subtraction and optical flow								
matching, image warping, homograpl estimation and RANSAC algorithm	hy							
Transforms: Hough, Fourier, Haar an wavelet transforms	d							
Interest point detectors and descriptor SURF, ORB, HOG, LBP algorithms, spatiotemporal interest points	ors: SIFT,							
Image features: edge, corner, line, ar detection, template matching	nd circle							
edge detection, morphological operate	tions							
	transformations, noise types, linear a nonlinear filtering Fundamental image processing: historedge detection, morphological operations and detection, template matching Interest point detectors and descriptor SURF, ORB, HOG, LBP algorithms, spatiotemporal interest points Transforms: Hough, Fourier, Haar and wavelet transforms Alignment: geometric transformations matching, image warping, homograph estimation and RANSAC algorithm Moving image processing: backgrour subtraction and optical flow Camera parameters, perspective processing and dense depth maps, 3-D reconstruction of the detection and segmentation: the and shape modelling, classification, clustering, and registration approached the detection and segmentation: the same matching in moving images: Luckanade, mean shift, MOSSE and Kotalanorithms es **Classification**, detection, and segmentation and segmentation in the same shift, mosse and kotalanorithms es **Classification**, detection, and segmentation and segm	Fundamental image processing: histograms, edge detection, morphological operations Image features: edge, corner, line, and circle detection, template matching Interest point detectors and descriptors: SIFT, SURF, ORB, HOG, LBP algorithms, spatiotemporal interest points Transforms: Hough, Fourier, Haar and wavelet transforms Alignment: geometric transformations, point matching, image warping, homography estimation and RANSAC algorithm Moving image processing: background subtraction and optical flow Camera parameters, perspective projection, camera calibration Stereo vision and epipolar geometry, sparse and dense depth maps, 3-D reconstruction Object detection and segmentation: texture and shape modelling, classification, clustering, and registration approaches Object tracking in moving images: Lucas-Kanade, mean shift, MOSSE and KCF algorithms es Classification, detection, and segmentation of chicate with convolutional natural naturals allowers. Jesticopies Beferences and/or Other works Jesticopies Beferences and/or Other works	transformations, noise types, linear and nonlinear filtering Fundamental image processing: histograms, edge detection, morphological operations Image features: edge, corner, line, and circle detection, template matching Interest point detectors and descriptors: SIFT, SURF, ORB, HOG, LBP algorithms, spatiotemporal interest points Transforms: Hough, Fourier, Haar and wavelet transforms Alignment: geometric transformations, point matching, image warping, homography estimation and RANSAC algorithm Moving image processing: background subtraction and optical flow Camera parameters, perspective projection, camera calibration Stereo vision and epipolar geometry, sparse and dense depth maps, 3-D reconstruction Object detection and segmentation: texture and shape modelling, classification, clustering, and registration approaches Object tracking in moving images: Lucas-Kanade, mean shift, MOSSE and KCF algorithms es Number Glassification, detection, and segmentation of balacta with convolutional poursel potentials. A signification of als/Labs 7 Padhicological poursel potentials. A signification of als/Labs 7 Padhicological poursel potentials. A signification of als/Labs 7 Padhicological poursel potentials. A signification of als/Labs 8 2 Padhich, A lability of the particular poursel policy. A significant poursel policy. A significant pol	transformations, noise types, linear and nonlinear filtering Fundamental image processing: histograms, edge detection, morphological operations Image features: edge, corner, line, and circle detection, template matching Interest point detectors and descriptors: SIFT, SURF, ORB, HOG, LBP algorithms, spatiotemporal interest points Transforms: Hough, Fourier, Haar and wavelet transforms Alignment: geometric transformations, point matching, image warping, homography estimation and RANSAC algorithm Moving image processing: background subtraction and optical flow Camera parameters, perspective projection, camera calibration Stereo vision and epipolar geometry, sparse and dense depth maps, 3-D reconstruction Object detection and segmentation: texture and shape modelling, classification, clustering, and registration approaches Object tracking in moving images: Lucas-Kanade, mean shift, MOSSE and KCF allocithms es Number Duration (hour labstication)				

25	CONTRIBUTION OF LEARNING OUTCOMES TO PROGRAMME QUALIFICATIONS																
	PQ1	PQ2	PQ3	PQ4	PQ5	PQ6	PQ7	PQ8	PQ9	PQ1 0	PQ11	PQ12	PQ1	PQ14	PQ15	PQ16	
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ÖK2	5	4	5	2	2	2	0	0	0	0	0	0	0	0	0	0	
ÖK3	5	3	4	1	1	1	0	0	0	0	0	0	0	0	0	0	
ÖK4	5	4	5	4	2	3	0	0	0	0	0	0	0	0	0	0	
ÖK5	5	3	4	2	1	1	0	0	0	0	0	0	0	0	0	0	
ÖK6	4	2	3	1	1	1	0	0	0	0	0	0	0	0	0	0	
ÖK7	5	4	5	4	2	3	0	0	0	0	0	0	0	0	0	0	
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Contrib ution Level:	n í l			2	2 low			3 Medium			4 High			5 Very High			