Two-view geometry

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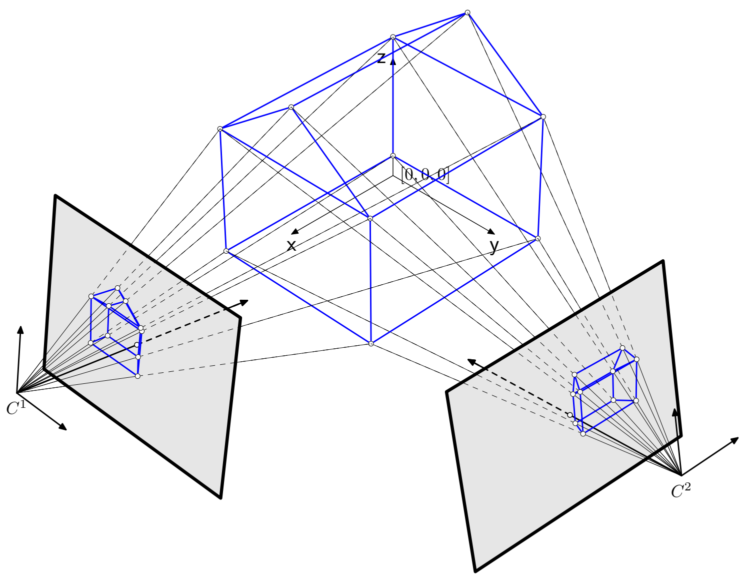
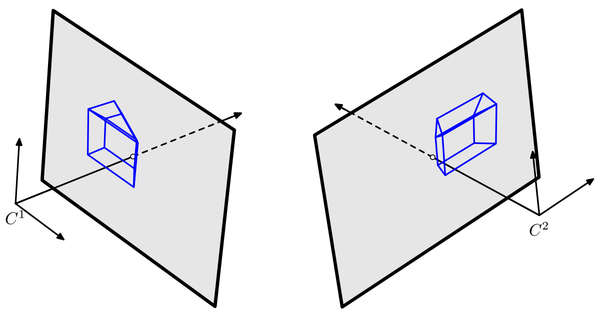
Talk Outline

- Epipolar geometry
- Estimation of the Fundamental matrix
- Camera motion
- Reconstruction of scene structure

Motivation



Two projections of a rigid 3D scene

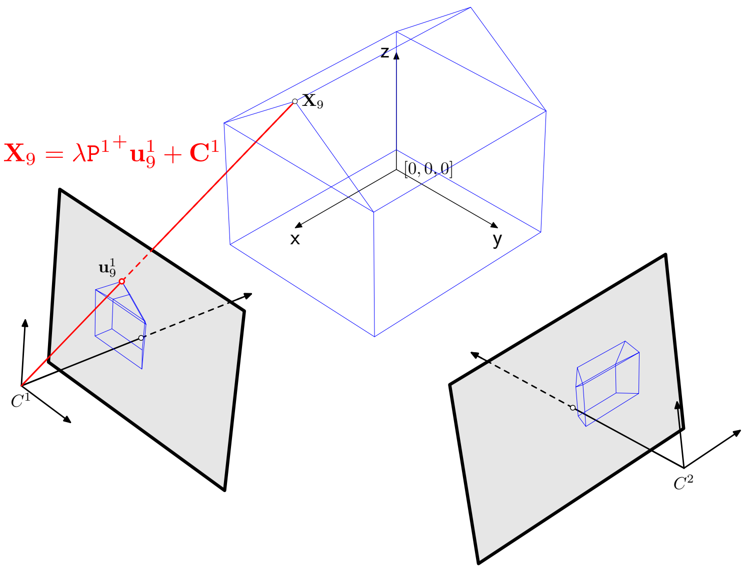


- The projections are clearly different.
- Can the difference tell something about the camera positions?
- and about the scene structure?

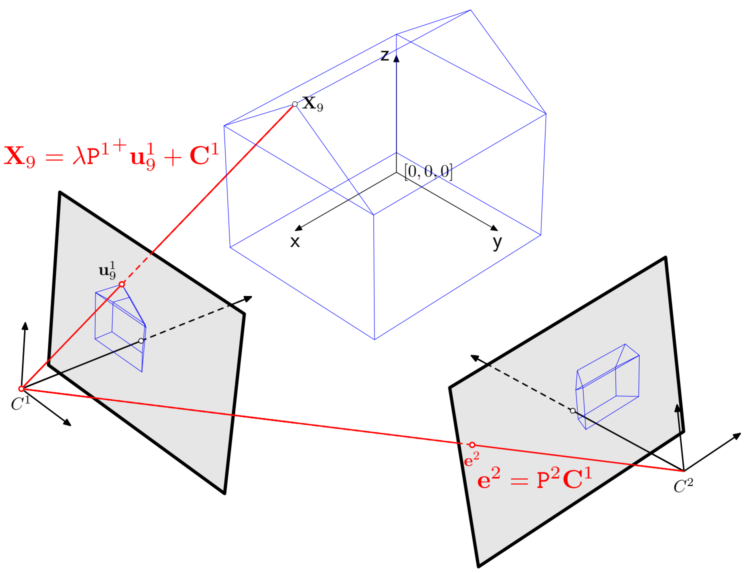
It can! (to both)

Can we find a relation between corresponding projections regardless of the scene structure?

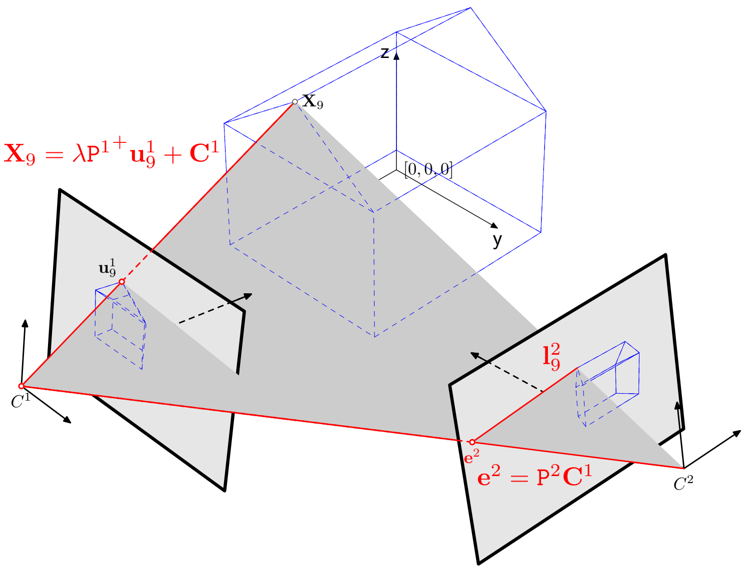
Back project the ray



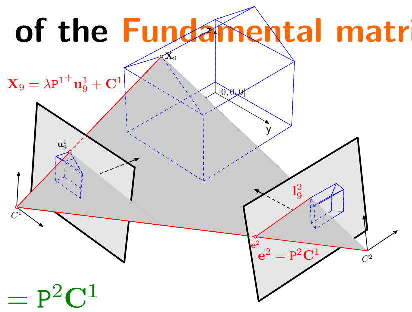
Project the camera center to the second image



The correponding projection must lie on a specific line



Derivation of the Fundamental matrix



We already know: $\mathbf{e}^2 = \mathtt{P}^2\mathbf{C}^1$

Projection to the camera 2: $\mathbf{u}_9^2 = \mathtt{P}^2(\lambda \mathtt{P}^{1+}\mathbf{u}_9^1 + \mathbf{C}^1)$

Line is a cross product of the points lying on it: $\mathbf{e}^2 \times \mathbf{u}_9^2 = \mathbf{l}_9^2$

Putting together: $\mathbf{e}^2 \times (\mathtt{P}^2\lambda \mathtt{P}^{1+}\mathbf{u}_9^1 + \mathtt{P}^2\mathbf{C}^1) = \mathbf{l}_9^2$

Clearly $\mathbf{e}^2 \times \mathtt{P}^2\mathbf{C}^1 = 0$, then: $\mathbf{e}^2 \times \lambda \mathtt{P}^2\mathtt{P}^{1+}\mathbf{u}_9^1 = \mathbf{l}_9^2$

But we also know ${\mathbf{l}_9^2}^\top \mathbf{u}_9^2 = 0$ since the point $\mathbf{u}_9^2$ must lie on the line $\mathbf{l}_9^2$.

Derivation of the Fundamental matrix, cont.

$\mathbf{e}^2 \times \lambda \mathtt{P}^2\mathtt{P}^{1+}\mathbf{u}_9^1 = \mathbf{l}_9^2$

But we also know ${\mathbf{l}_9^2}^\top \mathbf{u}_9^2 = 0$ since the point $\mathbf{u}_9^2$ must lie on the line.

Introducing a small matrix trick $[\mathbf{e}]_\times = \begin{bmatrix} 0 & -e_3 & e_2 \\ e_3 & 0 & -e_1 \\ -e_2 & e_1 & 0 \end{bmatrix}$

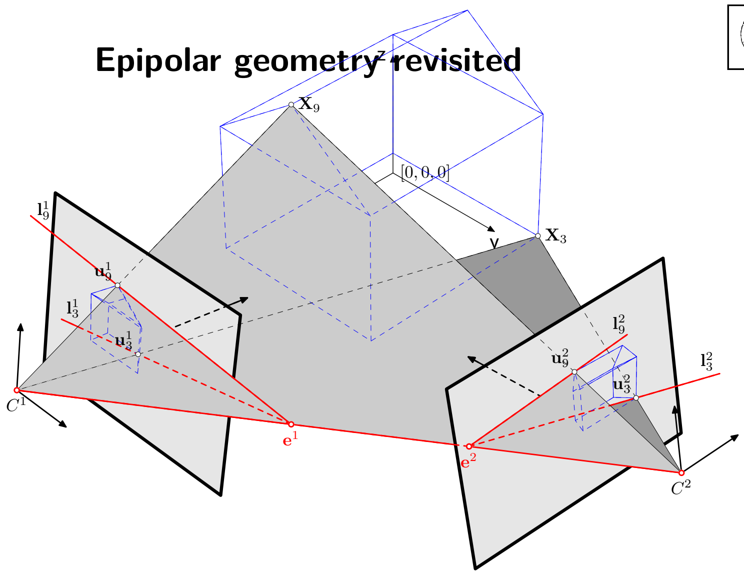
we may rewrite the cross product as a matrix multiplication
$\mathbf{l}_9^2 = \left([\mathbf{e}^2]_\times \lambda \mathtt{P}^2\mathtt{P}^{1+}\right)\mathbf{u}_9^1$

Inserting into ${\mathbf{l}_9^2}^\top \mathbf{u}_9^2 = 0$ yields:

$${\mathbf{u}_9^1}^\top \underbrace{\left([\mathbf{e}^2]_\times \lambda \mathtt{P}^2\mathtt{P}^{1+}\right)^\top}_{\mathtt{F}} \mathbf{u}_9^2 = 0$$

$$\boxed{{\mathbf{u}_9^2}^\top \mathtt{F}\mathbf{u}_9^1 = 0}$$

Epipolar geometry revisited

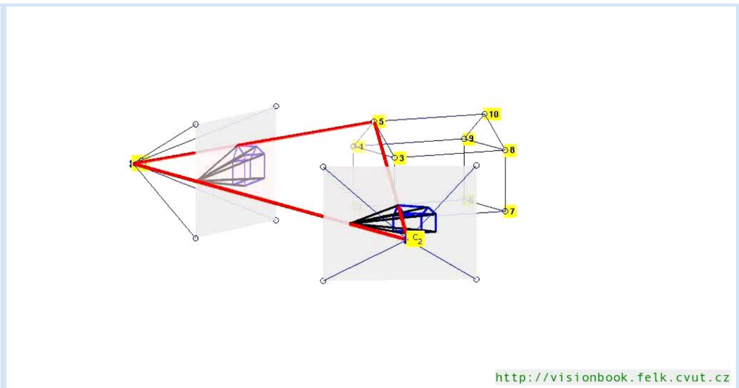


${\mathbf{u}_i^2}^\top \mathbf{F} \mathbf{u}_i^1 = 0$ holds for any corresponding pair $\mathbf{u}_i^1, \mathbf{u}_i^2$.

$\mathtt{F}$ does not depend on the scene structure, only on cameras.

All epipolar lines intersect in epipoles.

Epipolar geometry—overview



video: 3D sketch of Epipolar geometry

Epipolar geometry—what is it good for

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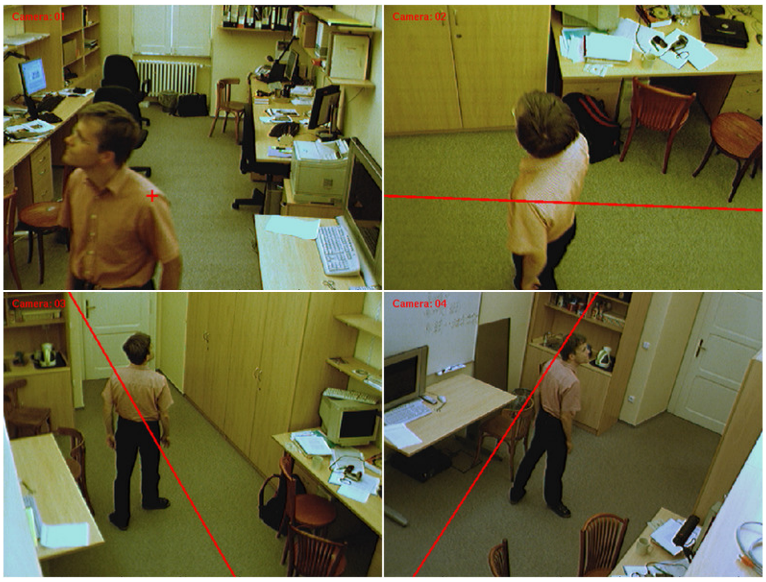


Epipolar geometry—what is it good for

Epipolar geometry—what is it good for

Fundamental matrix, so what . . .

Motion and 3D structure is where?

Essential matrix

For the Fundamental matrix we derived

$$\mathbf{u}_i^{1\top}\underbrace{\left([\mathbf{e}^2]_\times \mathtt{P}^2\mathtt{P}^{1+}\right)^\top}_{\mathtt{F}}\mathbf{u}_i^2 = 0$$

$\mathbf{u}$ denote point coordinates in pixels.

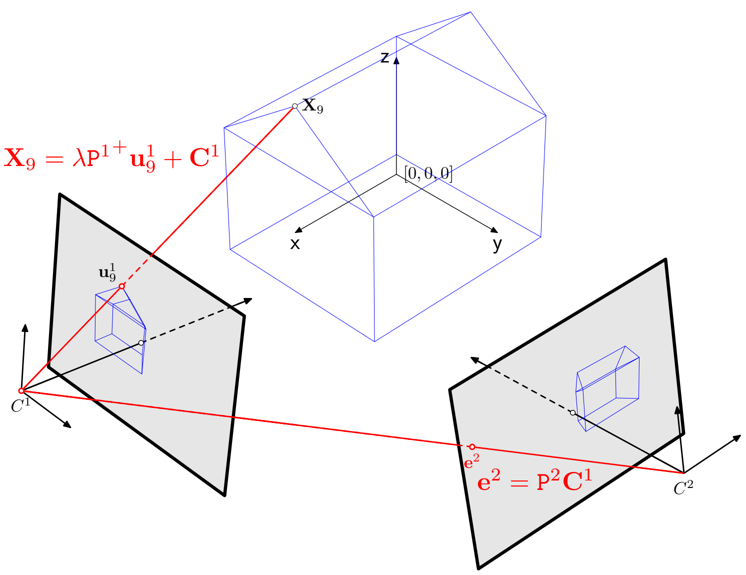
$$\mathbf{u}^1 = \mathtt{K}^1 \left[\ \mathtt{R}^1 \quad \mathbf{t}^1\ \right] \mathbf{X} \qquad \mathbf{u}^2 = \mathtt{K}^2 \left[\ \mathtt{R}^2 \quad \mathbf{t}^2\ \right] \mathbf{X}$$

Remind the normalized image coordinates $\mathbf{x} = \mathtt{K}^{-1}\mathbf{u}$. We can define normalized cameras $\mathbf{x} = \hat{\mathtt{P}}\mathbf{X}$ and insert the equation above.

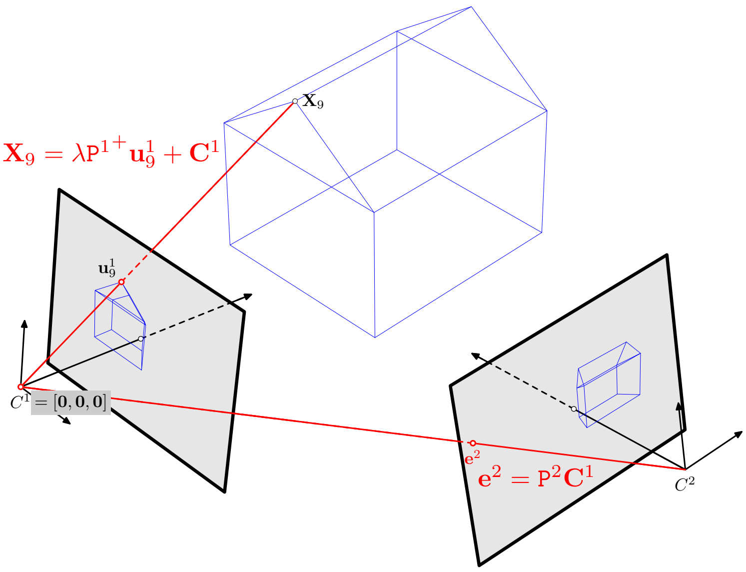
$$\mathbf{x}_i^{1\top}\underbrace{\left([\mathbf{x}_\mathrm{e}^2]_\times \hat{\mathtt{P}}^2(\hat{\mathtt{P}}^1)^+\right)^\top}_{\mathtt{E}}\mathbf{x}_i^2 = 0$$

where $\mathtt{E}$ is the Essential matrix

Where to set the origin of the world?



Where to set the origin of the world?



What do we gain?

$$\mathbf{u}^1 = \mathtt{K}^1 \left[\, \mathtt{R}^1 \quad \mathbf{t}^1 \,\right] \mathbf{X} \qquad \mathbf{u}^2 = \mathtt{K}^2 \left[\, \mathtt{R}^2 \quad \mathbf{t}^2 \,\right] \mathbf{X}$$

$$\mathbf{u}^1 = \mathtt{K}^1 \left[\, \mathtt{I} \quad \mathbf{0} \,\right] \mathbf{X} \qquad \mathbf{u}^2 = \mathtt{K}^2 \left[\, \mathtt{R} \quad \mathbf{t} \,\right] \mathbf{X}$$

Few variables vanished, $\mathtt{R}$ and $\mathbf{t}$ now denote motion of the camera. One can call it camera displacement, or ego-motion.

Estimation of $\mathtt{R}$ and $\mathbf{t}$ is often called camera tracking.

Essential matrix — cont'd

$$\begin{aligned} \mathtt{E} &= [\mathbf{x}_e^2]_\times \hat{\mathtt{P}}^2 (\hat{\mathtt{P}}^1)^+ \\ &= [\mathbf{x}_e^2]_\times \left[\, \mathtt{R} \quad \mathbf{t} \,\right] \left[\, \mathtt{I} \quad \mathbf{0} \,\right]^+ \\ &= [\mathbf{x}_e^2]_\times \mathtt{R} \end{aligned} \qquad \begin{aligned} \mathbf{x}_e^2 &= \hat{\mathtt{P}}^2 \mathbf{C}^1 \\ &= \left[\, \mathtt{R} \quad \mathbf{t} \,\right] \begin{bmatrix} \mathbf{0} \\ 1 \end{bmatrix} \\ &= \mathbf{t} \end{aligned}$$

$$\boxed{\mathtt{E} = [\mathbf{t}]_\times \mathtt{R}}$$

$\mathtt{E}$ comprises the motion between cameras!

after simple manipulation, we see $\mathtt{E} = \mathtt{K}^{2\top} \mathtt{F} \mathtt{K}^1$

Decomposition of the $\mathtt{E}$

Suppose $\mathtt{E} = \mathtt{U}\,\mathrm{diag}(1,1,0)\,\mathtt{V}^\top$ and

$$\mathtt{W} = \begin{bmatrix} 0 & -1 & 0 \\ 1 & 0 & 0 \\ 0 & 0 & 1 \end{bmatrix} \quad \text{and} \quad \mathtt{Z} = \begin{bmatrix} 0 & 1 & 0 \\ -1 & 0 & 0 \\ 0 & 0 & 0 \end{bmatrix}$$

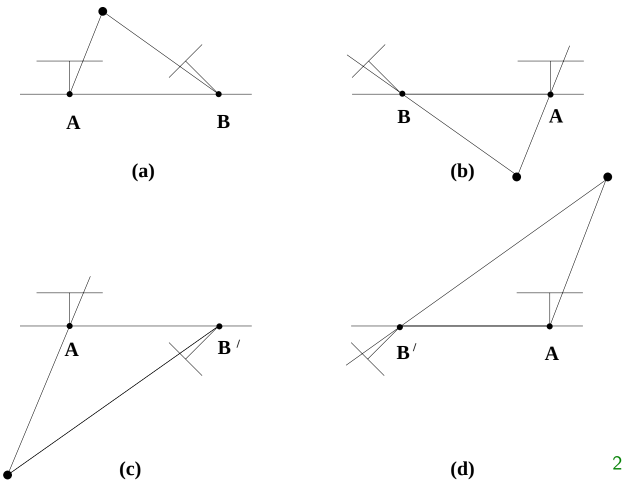
then, for a given $\mathtt{E}$ and $\hat{\mathtt{P}}^1 = [\mathtt{I}|0]$, there are four possible solutions for $\hat{\mathtt{P}}^2$

$$\hat{\mathtt{P}}^2 = [\mathtt{UVW}^\top| + \mathbf{u}_3] \text{ or } [\mathtt{UVW}^\top| - \mathbf{u}_3] \text{ or } [\mathtt{UV}^\top\mathtt{W}^\top| + \mathbf{u}_3] \text{ or } [\mathtt{UV}^\top\mathtt{W}^\top| - \mathbf{u}_3]$$

More details in [3][1].

[1] The relevant chapter 9, is available on the web, http://www.robots.ox.ac.uk/~vgg/hzbook/hzbook2/HZepipolar.pdf, see pages 20-21

Fourfold ambiguity of the $\mathtt{E}$ decomposition



[2]

Which one?

[2] Sketch from [2].

3D scene reconstruction—Linear method

A scene point $\mathbf{X}$ is observed by two cameras $\mathtt{P}^1$ and $\mathtt{P}^2$. Assume we know its projections $[u^j, v^j]^\top$

$\mathbf{u} = \mathtt{P}\mathbf{X}$, $u = \frac{\mathbf{p}_1^\top \mathbf{X}}{\mathbf{p}_3^\top \mathbf{X}}$, $u(\mathbf{p}_3^\top \mathbf{X}) - \mathbf{p}_1^\top \mathbf{X} = 0$, the same derivation for v and for both cameras:

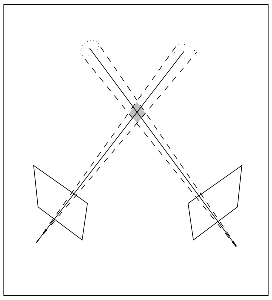
$$\begin{bmatrix} u^1 \mathbf{p}_3^{1\top} - \mathbf{p}_1^{1\top} \\ v^1 \mathbf{p}_3^{1\top} - \mathbf{p}_2^{1\top} \\ u^2 \mathbf{p}_3^{2\top} - \mathbf{p}_1^{2\top} \\ v^2 \mathbf{p}_3^{2\top} - \mathbf{p}_2^{2\top} \end{bmatrix} \left[\, \mathbf{X} \,\right] = \left[\, \mathbf{0} \,\right]$$

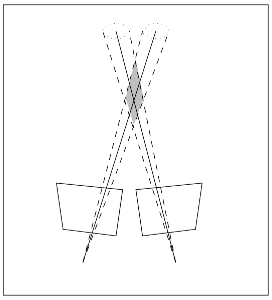
Set of linear homogeneous equations. A standard LSQ solution[3] may be used.

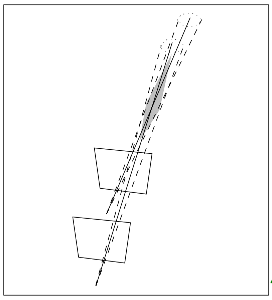
Not an optimal solution. It minimizes algebraic not geometric error. More methods can be found in [3, Chapter 12]

[3] file:///home.zam/svoboda/Vyuka/ComputerVision/Lectures.eng/Supporting/constrained_lsq.pdf

Errors in reconstruction



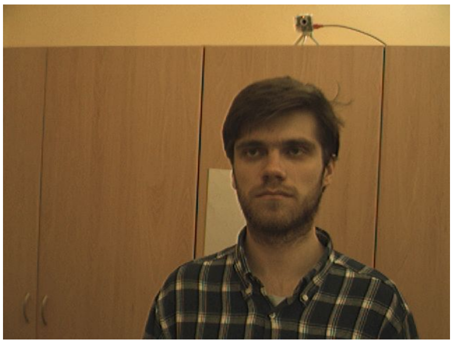



[4]

- the bigger angle between rays the better reconstruction, however . . .
- also the more difficult image matching

[4] Sketch borrowed from [2]

Problems with image matching



Good for matching, bad for reconstruction

Problems with image matching

Good for recontruction, bad for matching

Estimation of $\mathtt{F}$ or $\mathtt{E}$ from corresponding point pairs

$$\mathbf{u}_i^{2\top}\mathbf{F}\mathbf{u}_i^1 = 0$$

for any pair of matching points. Each matching pair gives one linear equation

$$u^2u^1f_{11} + u^2v^1f_{12} + u^2f_{13}\ldots = 0$$

which may be rewritten an a vector inner product

$$[u^2u^1, u^2v^1, u^2, v^2u^1, v^2v^1, v^2, u^1, v^1, 1]\mathbf{f} = 0$$

A set of n pairs forms a set of linear equations

$$\mathtt{A}\mathbf{f} = \begin{bmatrix} u_1^2u_1^1 & u_1^2v_1^1 & u_1^2 & v_1^2u_1^1 & v_1^2v_1^1 & v_1^2 & u_1^1 & v_1^1 & 1 \\ \vdots & \vdots & \vdots & \vdots & \vdots & \vdots & \vdots & \vdots & \vdots \\ u_n^2u_n^1 & u_n^2v_n^1 & u_n^2 & v_n^2u_n^1 & v_n^2v_n^1 & v_n^2 & u_n^1 & v_n^1 & 1 \end{bmatrix}\mathbf{f} = \mathbf{0}$$

Estimation of $\mathtt{F}$—normalized 8-point algorithm

Solution of

$$\mathtt{A}\mathbf{f} = \begin{bmatrix} u_1^2u_1^1 & u_1^2v_1^1 & u_1^2 & v_1^2u_1^1 & v_1^2v_1^1 & v_1^2 & u_1^1 & v_1^1 & 1 \\ \vdots & \vdots & \vdots & \vdots & \vdots & \vdots & \vdots & \vdots & \vdots \\ u_n^2u_n^1 & u_n^2v_n^1 & u_n^2 & v_n^2u_n^1 & v_n^2v_n^1 & v_n^2 & u_n^1 & v_n^1 & 1 \end{bmatrix}\mathbf{f} = \mathbf{0}$$

is a standard LSQ solution[5]

Point normalization

Consider a point pair $\mathbf{u}^1 = [150, 250, 1]^\top$, $\mathbf{u}^2 = [250, 350, 1]^\top$. It is clear that row elements in $\mathtt{A}$ are unbalanced.

$$\mathbf{a}^\top = [10^6, 10^6, 10^3, 10^6, 10^6, 10^3, 10^3, 10^3, 10^0]$$

This influences the numerical stability. Solution: normalization of the point coordinates before computation.

[5] file:///home.zam/svoboda/Vyuka/ComputerVision/Lectures.eng/Supporting/constrained_lsq.pdf

Estimation of $\mathtt{F}$—normalized 8-point algorithm

Transform the coordinates of points so that the centroid is at the origin of coordinates nad RMS distance is equal to $\sqrt{2}$.

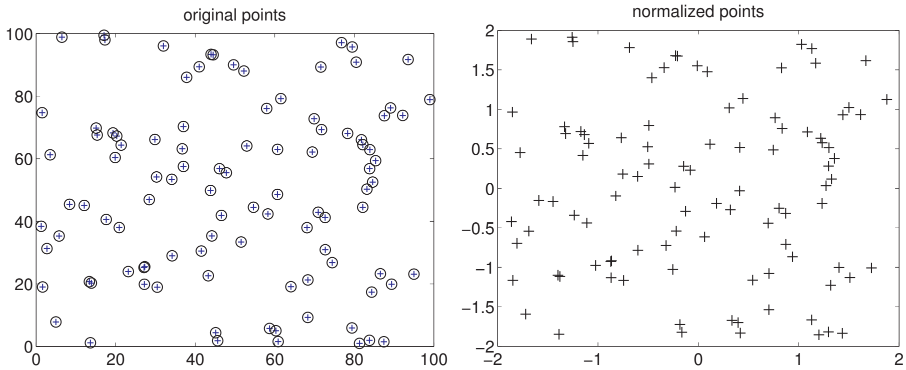
$\hat{\mathbf{u}}^1 = \mathtt{T}^1\mathbf{u}^1$ and $\hat{\mathbf{u}}^2 = \mathtt{T}^2\mathbf{u}^2$, where $\mathtt{T}^i$ are 3×3 normalizing matrices including translation nad scaling.

Compute $\hat{\mathtt{F}}$ by using the standard LSQ method, $\hat{\mathbf{u}}^{2\top}\hat{\mathtt{F}}\hat{\mathbf{u}}^1 = 0$. Denormalize the solution $\mathtt{F} = \mathtt{T}^{2\top}\hat{\mathtt{F}}\mathtt{T}^1$

Historical remarks

The linear algorithm for estimation epipolar geometry (calibrated case—essential matrix) was suggest in [5]. The normalization for the uncalibrated case (fundamental matrix) was introduced in [4].

Point normalization

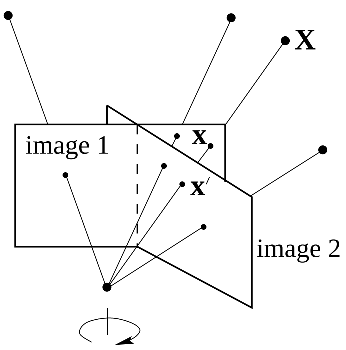


Zero motion

we derived

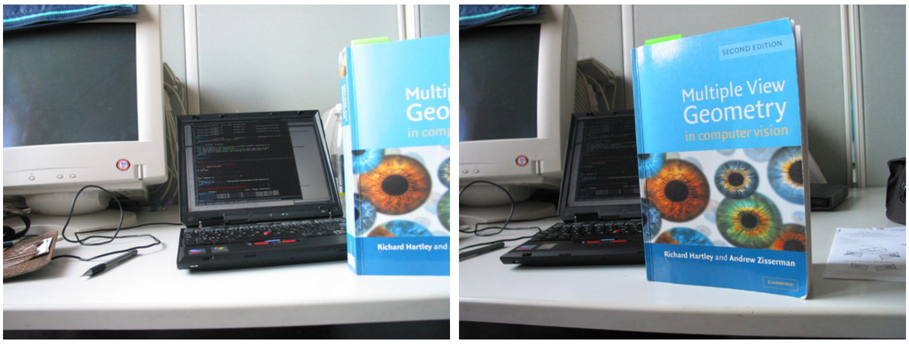
$$\mathtt{E} = [\mathbf{t}]_\times \mathtt{R}$$

what happens if $\mathbf{t} = \mathbf{0}$?

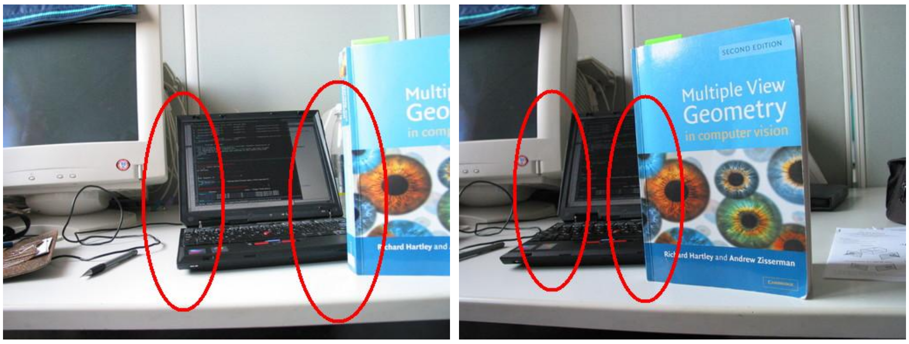


Common $\mathbf{t} = \mathbf{0}$ case—Image Panoramas

What are the differences in images
general motion

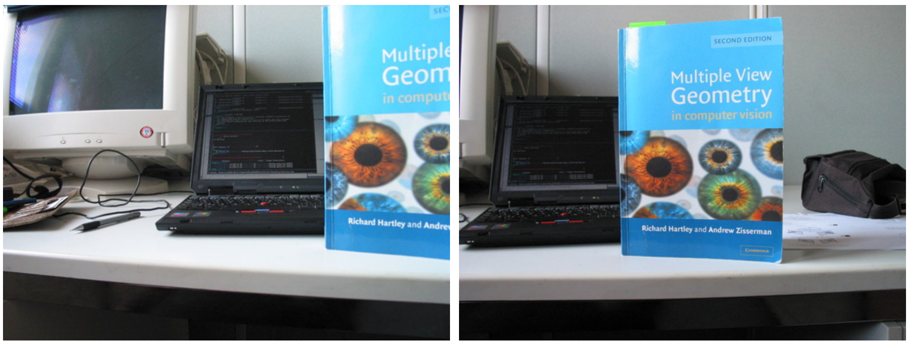


What are the differences in images
general motion

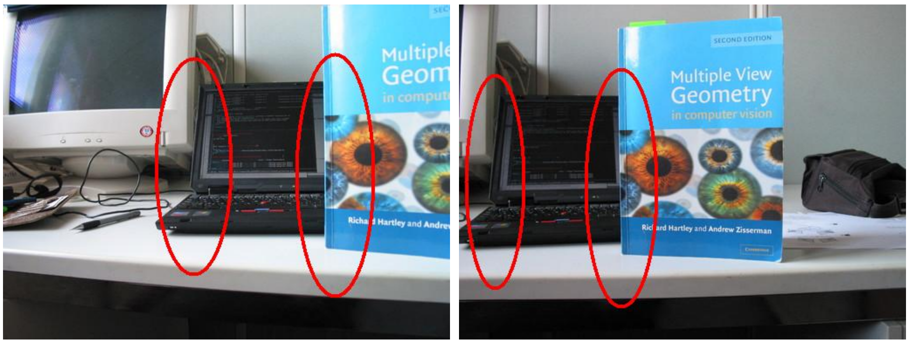


- objects in different depths make occlusions
- the mapping is certainly not 1:1

What are the differences in images
rotation

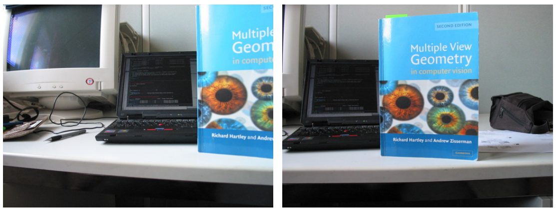


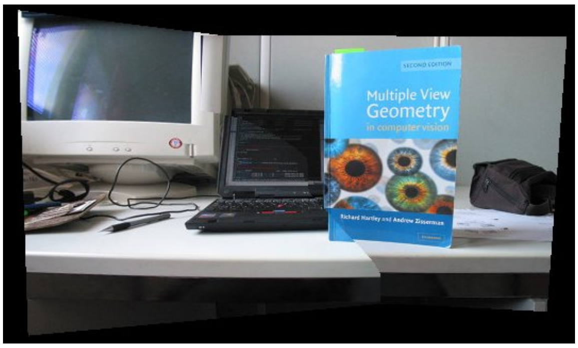
What are the differences in images rotation



- no occlusions
- the mapping may be 1:1

Mapping between images





References

The book [3] is the ultimate reference. It is a must read for anyone wanting use cameras for 3D computing.

Details about matrix decompositions used throughout the lecture can be found at [1]

[1] Gene H. Golub and Charles F. Van Loan. Matrix Computation. Johns Hopkins Studies in the Mathematical Sciences. Johns Hopkins University Press, Baltimore, USA, 3rd edition, 1996.

[2] R. Hartley and A. Zisserman. Multiple View Geometry in Computer Vision. Cambridge University Press, Cambridge, UK, 2000. On-line resources at: `http://www.robots.ox.ac.uk/~vgg/hzbook/hzbook1.html`.

[3] Richard Hartley and Andrew Zisserman. Multiple view geometry in computer vision. Cambridge University, Cambridge, 2nd edition, 2003.

[4] Richard I. Hartley. In defense of the eight-point algorithm. IEEE Transaction on Pattern Analysis and Machine Intelligence, 19(6):580–593, June 1997.

[5] H.C. Longuett-Higgins. A computer algorithm for reconstruction a scene from two projections. Nature, 293:133–135, 1981.

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