CS6670: Computer Vision

Noah Snavely

Lecture 20: Two-view geometry

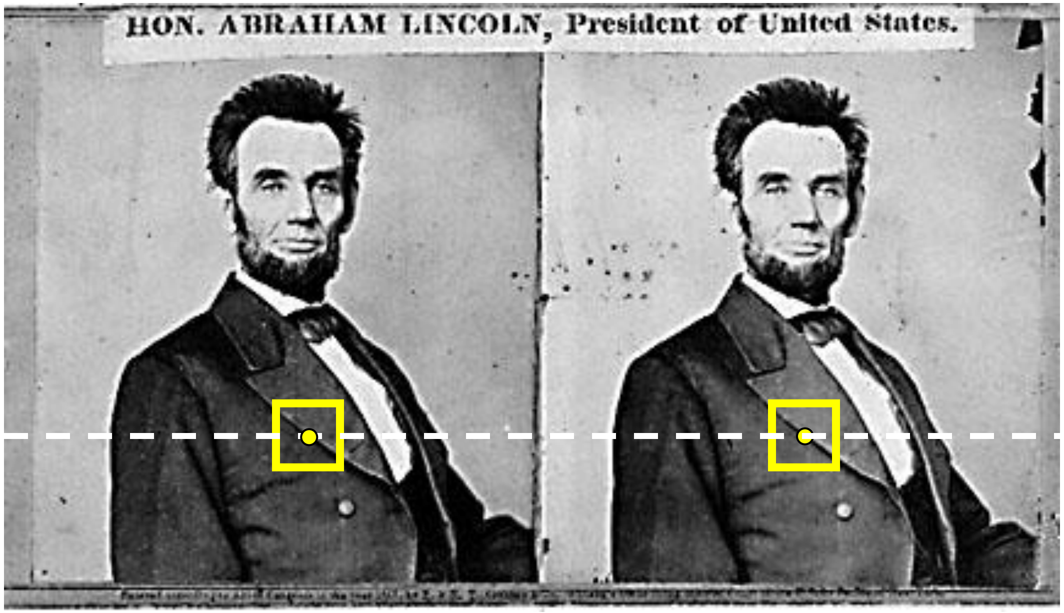
Readings

- Szeliski, Chapter 7.2
- “Fundamental matrix song”

Announcements

- Project 2b due next Tuesday, Nov 2, by 10:59pm
- Final project proposals due by this Friday, Oct 29, by 11:59pm
- See project webpage for project ideas

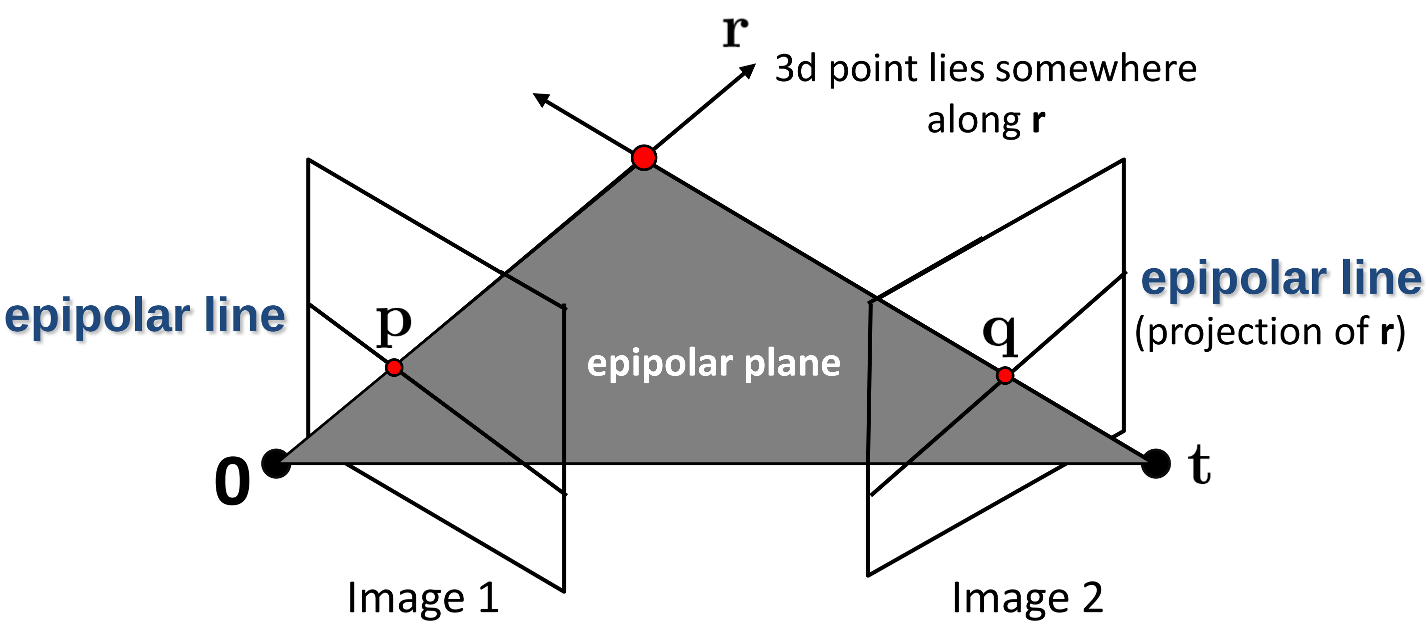
Back to stereo



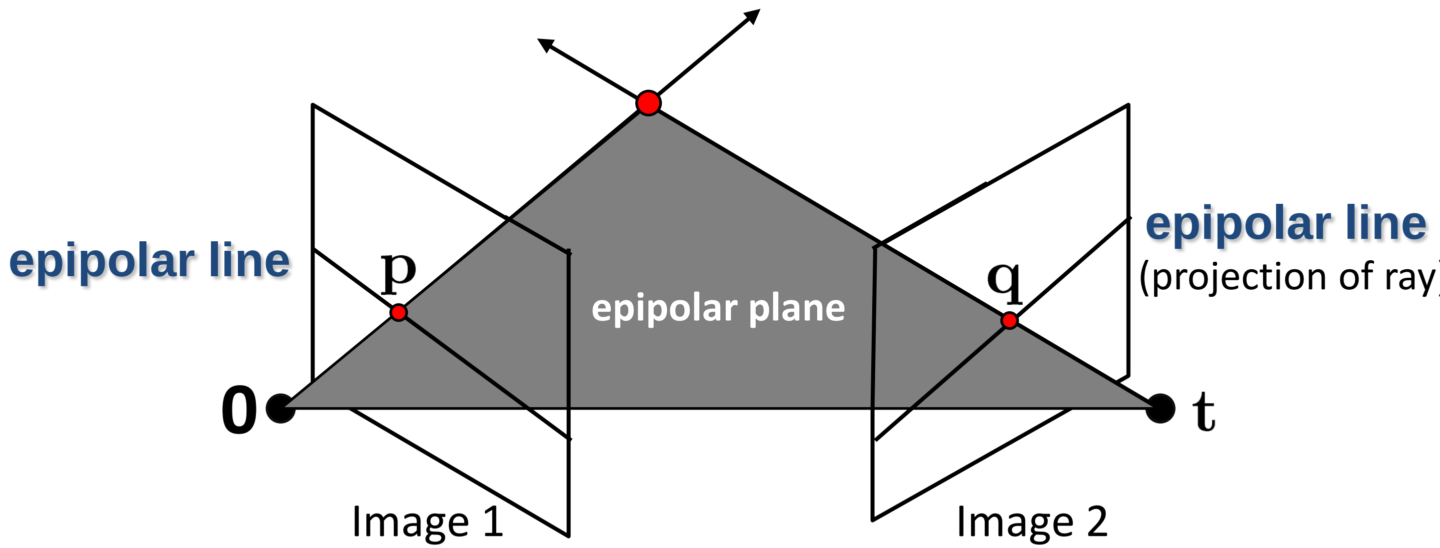
- Where do epipolar lines come from?

Two-view geometry

- Where do epipolar lines come from?

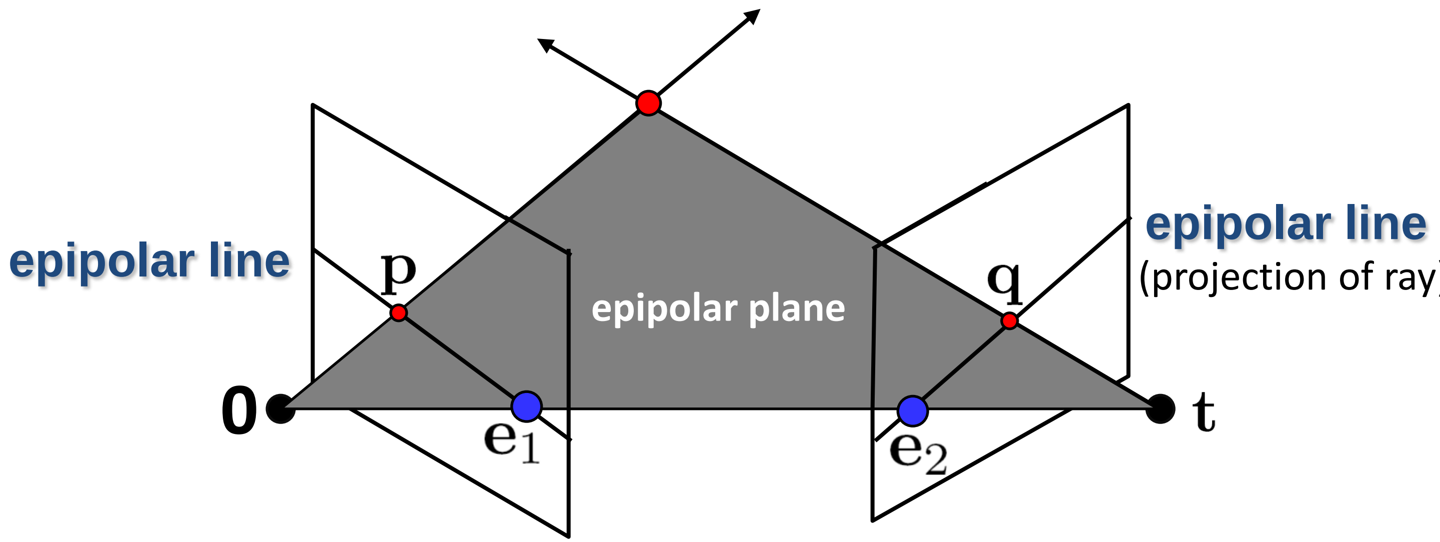


Fundamental matrix



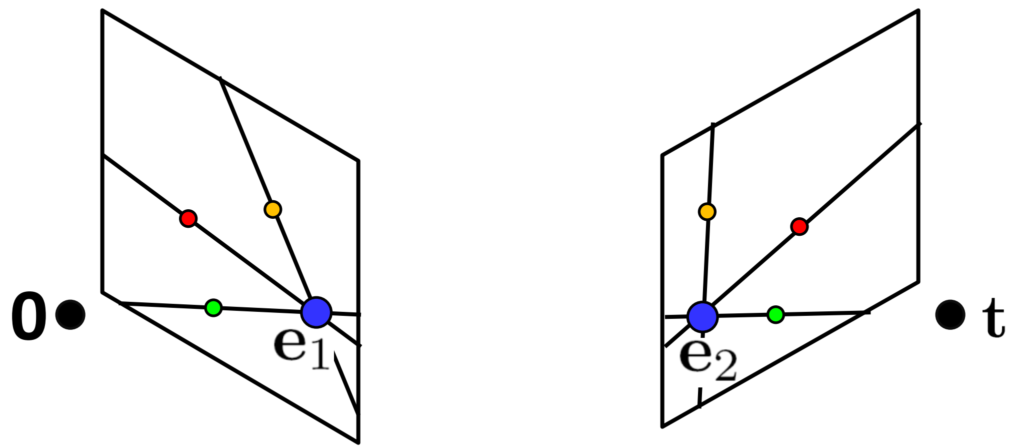
- This *epipolar geometry* of two views is described by a Very Special 3x3 matrix $\mathbf{F}$, called the *fundamental matrix*
- $\mathbf{F}$ maps (homogeneous) *points* in image 1 to *lines* in image 2!
- The epipolar line (in image 2) of point **p** is: $\mathbf{F}\mathbf{p}$
- *Epipolar constraint* on corresponding points: $\mathbf{q}^T\mathbf{F}\mathbf{p} = 0$

Fundamental matrix



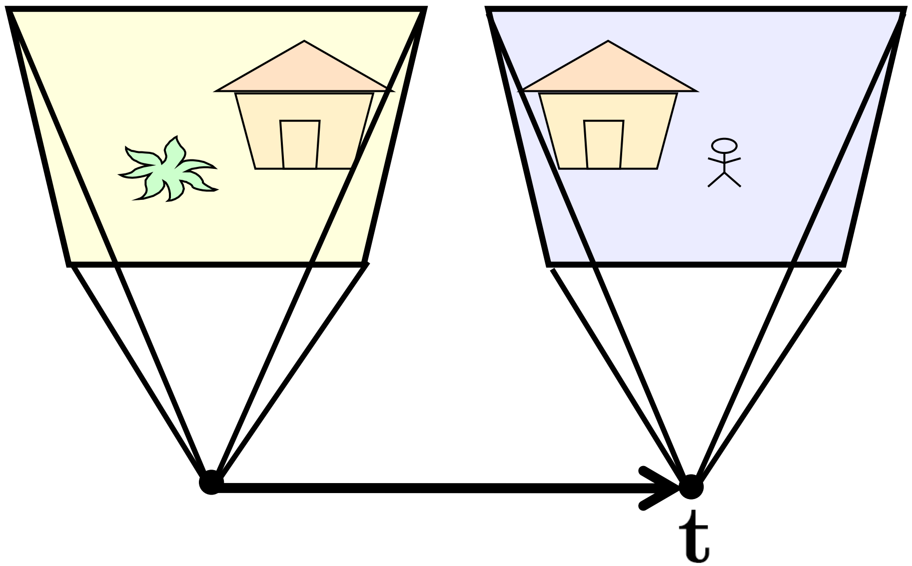
- Two special points: **e**$_1$ and **e**$_2$ (the *epipoles*): projection of one camera into the other

Fundamental matrix



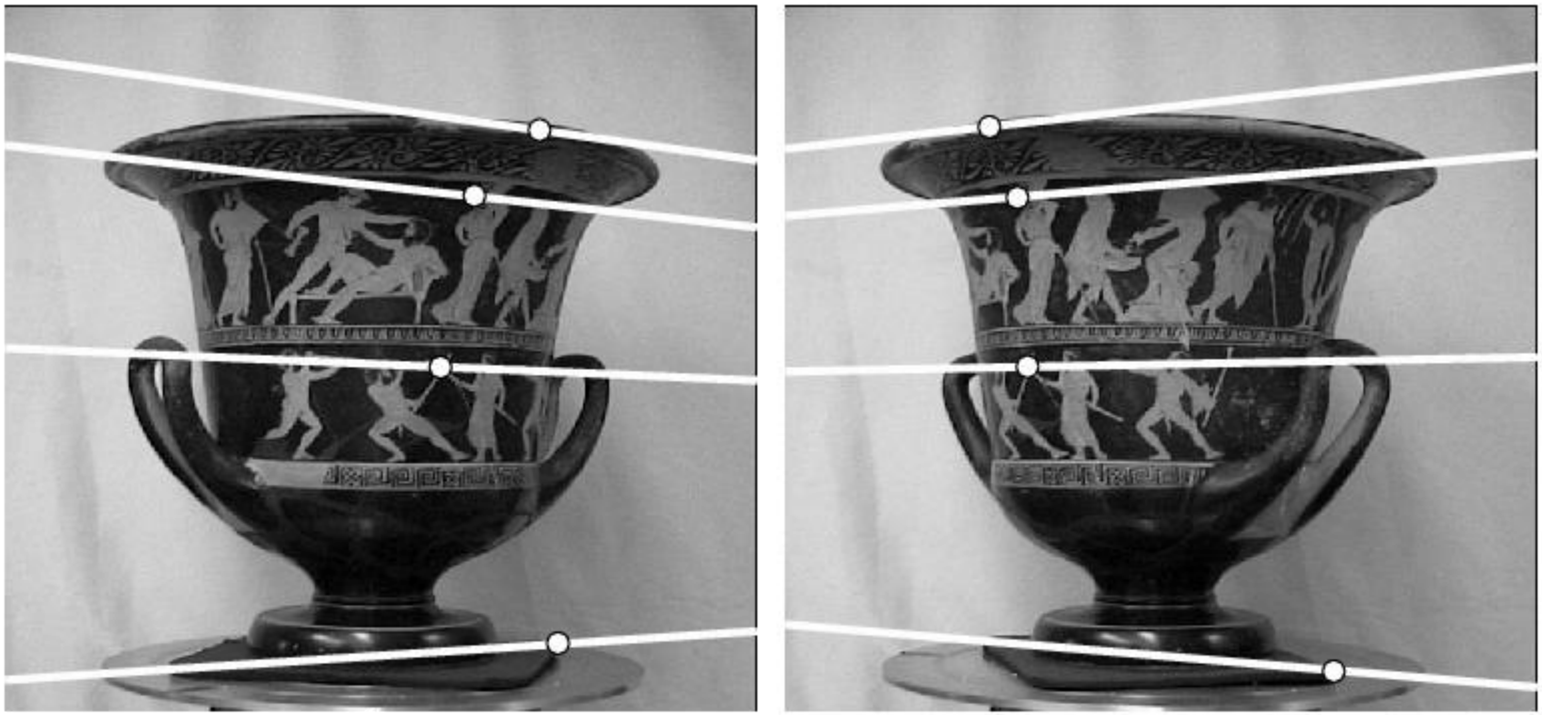
- Two special points: $\mathbf{e}_1$ and $\mathbf{e}_2$ (the *epipoles*): projection of one camera into the other
- All of the epipolar lines in an image pass through the epipole

Rectified case

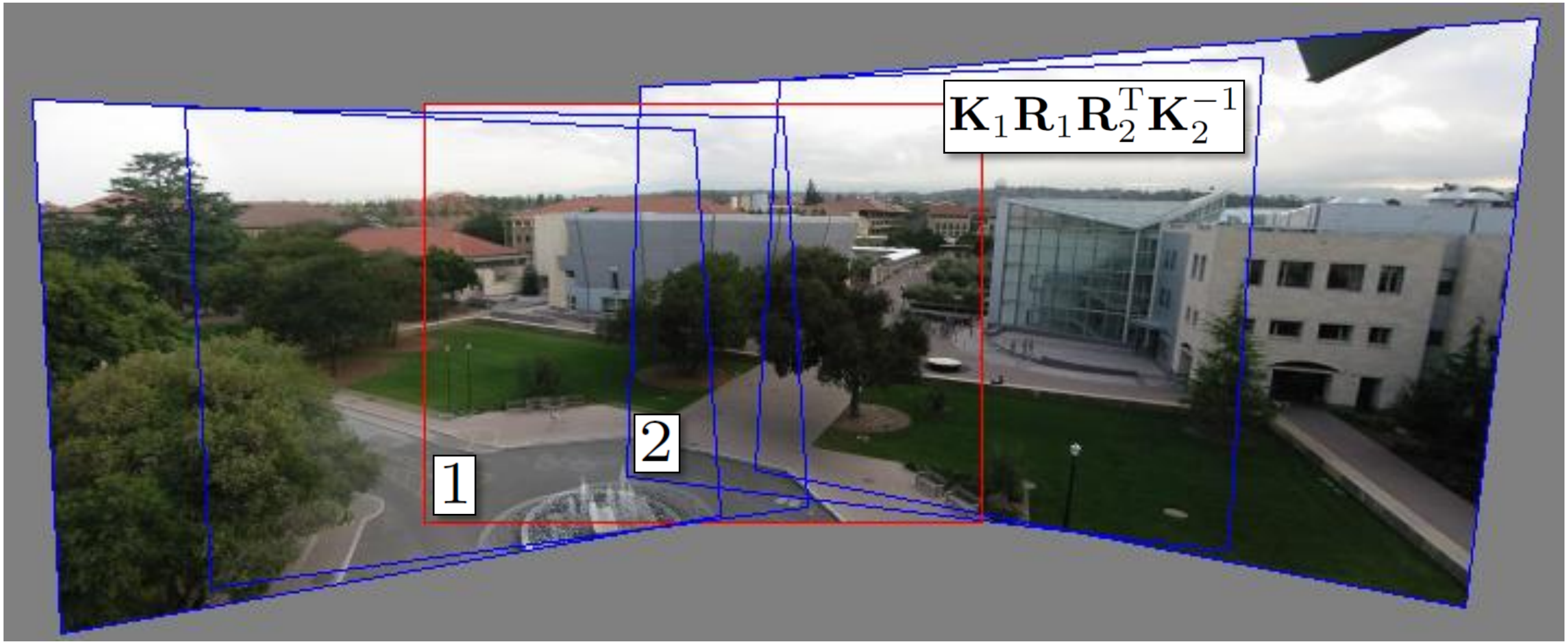


- Images have the same orientation, **t** parallel to image planes
- Where are the epipoles?

Epipolar geometry demo

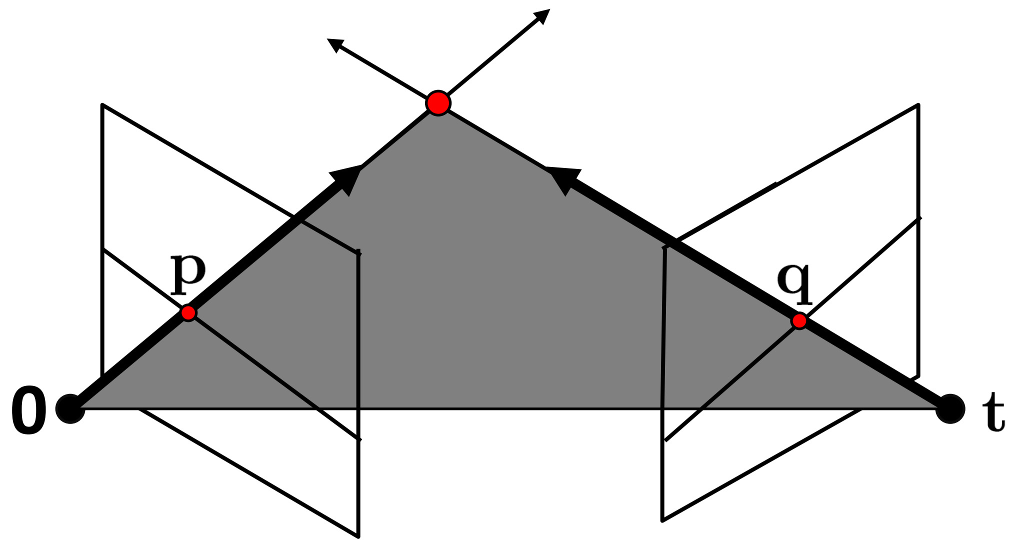


Relationship with homography?



Images taken from the same center of projection? Use a homography!

Fundamental matrix – uncalibrated case



$\mathbf{K}_1$: intrinsics of camera 1

$\mathbf{K}_2$: intrinsics of camera 2

$\mathbf{R}$: rotation of image 2 w.r.t. camera 1

$$\mathbf{q}^T \underbrace{\mathbf{K}_2^{-T} \mathbf{R} [\mathbf{t}]_\times \mathbf{K}_1^{-1}}_{\mathbf{F}} \mathbf{p} = 0$$

$\mathbf{F}$ ← the Fundamental matrix

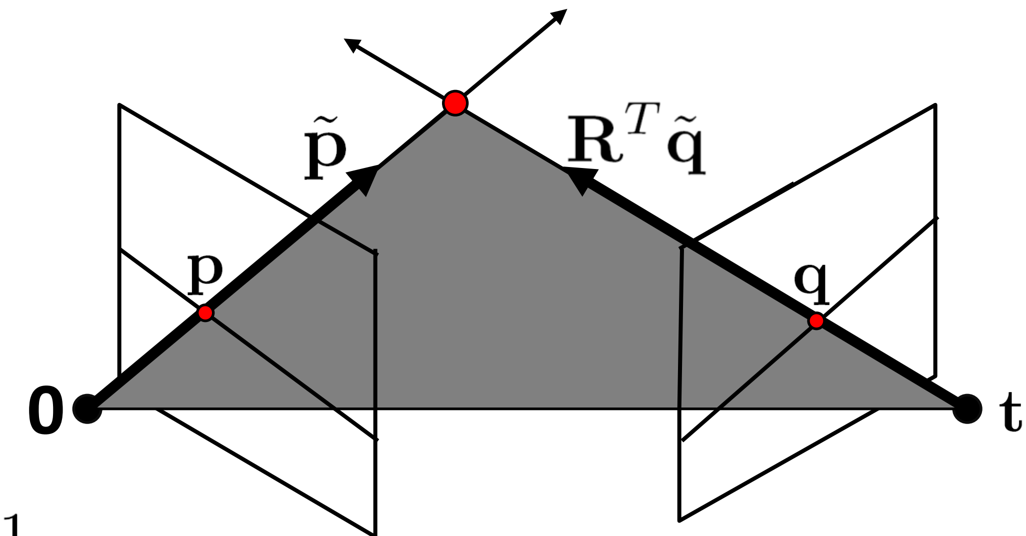
Cross-product as linear operator

Useful fact: Cross product with a vector **t** can be represented as multiplication with a (*skew-symmetric*) 3x3 matrix

$$[\mathbf{t}]_\times = \begin{bmatrix} 0 & -t_z & t_y \\ t_z & 0 & -t_x \\ -t_y & t_x & 0 \end{bmatrix}$$

$$\mathbf{t} \times \tilde{\mathbf{p}} = [\mathbf{t}]_\times \tilde{\mathbf{p}}$$

Fundamental matrix – calibrated case



$\tilde{\mathbf{p}} = \mathbf{K}_1^{-1}\mathbf{p}$: ray through **p** in camera 1's (and world) coordinate system

$\tilde{\mathbf{q}} = \mathbf{K}_2^{-1}\mathbf{q}$: ray through **q** in camera 2's coordinate system

$$\tilde{\mathbf{q}}^T \underbrace{\mathbf{R}\,[\mathbf{t}]_\times}_{\mathbf{E}} \tilde{\mathbf{p}} = 0$$

$$\tilde{\mathbf{q}}^T \mathbf{E} \tilde{\mathbf{p}} = 0$$

$\mathbf{E}$ ← the Essential matrix

Properties of the Fundamental Matrix

- $\mathbf{F}\mathbf{p}$ is the epipolar line associated with $\mathbf{p}$

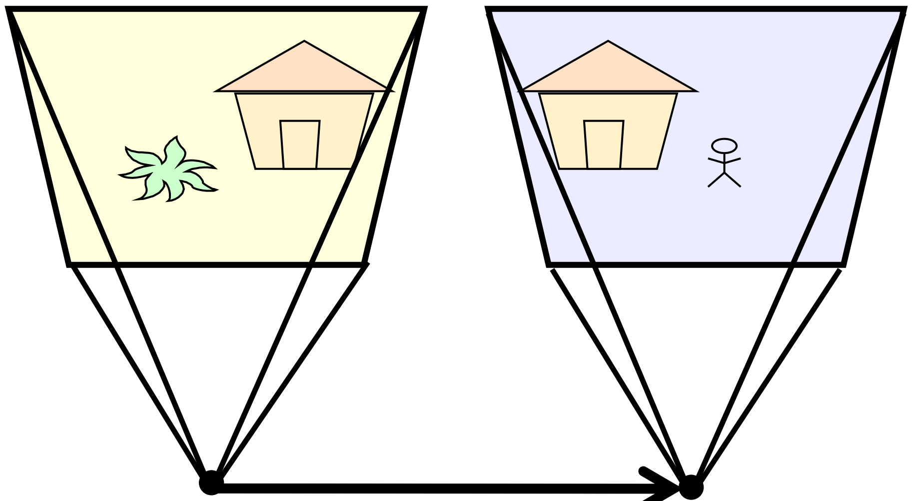
- $\mathbf{F}^T\mathbf{q}$ is the epipolar line associated with $\mathbf{q}$

- $\mathbf{F}\mathbf{e}_1 = \mathbf{0}$ and $\mathbf{F}^T\mathbf{e}_2 = \mathbf{0}$

- $\mathbf{F}$ is rank 2

- How many parameters does **F** have?

Rectified case

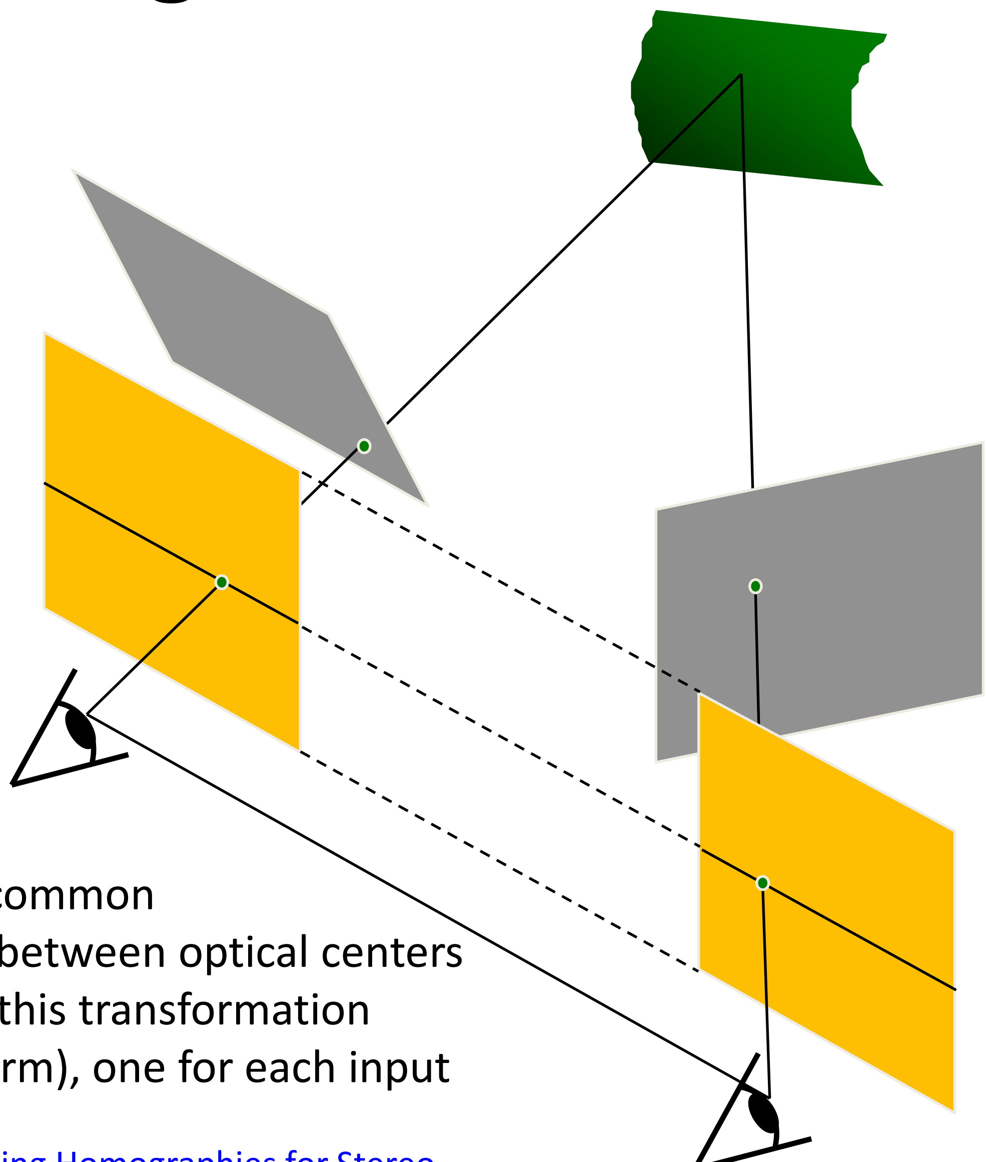


$$\mathbf{R} = \mathbf{I}_{3\times 3}$$

$$\mathbf{t} = \left[\begin{array}{ccc} 1 & 0 & 0 \end{array} \right]^T$$

$$\mathbf{E} = \left[\begin{array}{ccc} 0 & 0 & 0 \\ 0 & 0 & -1 \\ 0 & 1 & 0 \end{array} \right]$$

Stereo image rectification



- reproject image planes onto a common
- plane parallel to the line between optical centers
- pixel motion is horizontal after this transformation
- two homographies (3x3 transform), one for each input image reprojection

➢ C. Loop and Z. Zhang. [Computing Rectifying Homographies for Stereo Vision](). IEEE Conf. Computer Vision and Pattern Recognition, 1999.

Questions?