Rigid Geometric Transformations and the Pinhole Camera Model

COMPSCI 527 — Computer Vision

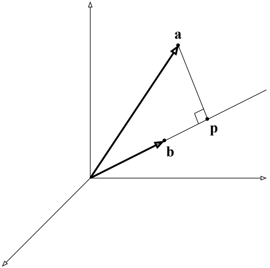
Outline

1. Coordinates and Vector Operators
   - Orthogonal Projection
   - Cross Product
   - Triple Product
2. Rigid Transformations
   - Rotations
   - Coordinate Transformations
3. The Pinhole Camera

Rigid Transformations

- 3D reconstruction: Given corresponding points in two (or more) images taken from different viewpoints, find the relative pose of the two cameras and 3D coordinates of the world points
- The relative motion between a camera and an otherwise static scene is a rigid transformation: rotation + translation
- Reconstruction techniques
  also require knowing about
  othogonal projection,
  cross product, triple product
- *All vectors are in* $\mathbb{R}^3$

Orthogonal Projection



- *Definition* of projection of $\mathbf{a}$ onto $\mathbf{b} \neq \mathbf{0}$:
  the point $\mathbf{p}$ on the line through $\mathbf{b}$ that is closest to $\mathbf{a}$
- $\mathbf{p}$ is on the line through $\mathbf{b}$: $\quad \mathbf{p} = x\mathbf{b}$ for some x
- $\mathbf{p}$ is closest to $\mathbf{a}$ when $(\mathbf{a}, \mathbf{p})$ is orthogonal to $\mathbf{b}$:
  $\mathbf{b}^T(\mathbf{a} - x\mathbf{b}) = 0$, which yields $x = \frac{\mathbf{b}^T\mathbf{a}}{\mathbf{b}^T\mathbf{b}}$ so that
  $\mathbf{p} = x\mathbf{b} = \mathbf{b}\,x = \frac{\mathbf{b}\mathbf{b}^T}{\mathbf{b}^T\mathbf{b}}\,\mathbf{a}$

The Orthogonal-Projection Matrix

- $\mathbf{p} = P_\mathbf{b}\,\mathbf{a}$ where $P_\mathbf{b} = \frac{\mathbf{b}\mathbf{b}^T}{\mathbf{b}^T\mathbf{b}}$
- $P_\mathbf{b}$ is rank 1, symmetric, and idempotent: $P_\mathbf{b}^n = P_\mathbf{b}$ for $n > 0$

- Norm squared of $\mathbf{p}$:
  $\|\mathbf{p}\|^2 =$

- When $\|\mathbf{b}\| = 1$,
- Note: Orthogonal projection is *not* camera projection

The Cross Product

- Geometry: The cross product of two three-dimensional vectors **a** and **b** is a vector **c** orthogonal to both **a** and **b**, oriented so that the triple **a**, **b**, **c** is right-handed, and with magnitude

$$\|\mathbf{c}\| = \|\mathbf{a} \times \mathbf{b}\| = \|\mathbf{a}\| \, \|\mathbf{b}\| \sin\theta$$

  where θ is the smaller angle between **a** and **b**
- The magnitude of $\mathbf{a} \times \mathbf{b}$ is the area of a parallelogram with sides **a** and **b**
- Algebra: $\mathbf{c} = \mathbf{a} \times \mathbf{b} = \begin{vmatrix} a_x & a_y & a_z \\ b_x & b_y & b_z \end{vmatrix}$

  $= (a_y b_z - a_z b_y \, , \; a_z b_x - a_x b_z \, , \; a_x b_y - a_y b_x)^T$
- Easy to check that $\mathbf{a} \times \mathbf{b} = -\mathbf{b} \times \mathbf{a}$

The Cross-Product Matrix

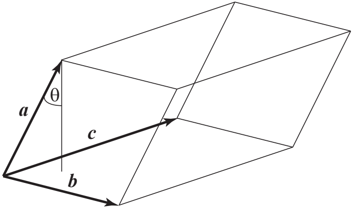
- $\mathbf{c} = (a_y b_z - a_z b_y\ ,\ a_z b_x - a_x b_z\ ,\ a_x b_y - a_y b_x)^T$ is linear in $\mathbf{b}$
- Therefore, there exists a 3×3 matrix $[\mathbf{a}]_\times$ such that

  $\mathbf{c} = \mathbf{a} \times \mathbf{b} = [\mathbf{a}]_\times \mathbf{b}$

  $$\mathbf{c} = \begin{bmatrix} c_x \\ c_y \\ c_z \end{bmatrix} = \begin{bmatrix} & & \\ & & \\ & & \end{bmatrix} \begin{bmatrix} b_x \\ b_y \\ b_z \end{bmatrix}$$
- The matrix $[\mathbf{a}]_\times$ is skew-symmetric: $[\mathbf{a}]_\times^T = -[\mathbf{a}]_\times$

The Triple Product

- Definition: $\det([\mathbf{a}, \mathbf{b}, \mathbf{c}]) = \mathbf{a}^T(\mathbf{b} \times \mathbf{c})$
  $= a_x(b_y c_z - b_z c_y) - a_y(b_x c_z - b_z c_x) + a_z(b_x c_y - b_y c_x)$
- Signed volume of parallelepiped



- Easy to check: $\mathbf{a}^T(\mathbf{b} \times \mathbf{c}) = \mathbf{b}^T(\mathbf{c} \times \mathbf{a}) = \mathbf{c}^T(\mathbf{a} \times \mathbf{b}) = -\mathbf{a}^T(\mathbf{c} \times \mathbf{b}) = -\mathbf{c}^T(\mathbf{b} \times \mathbf{a}) = -\mathbf{b}^T(\mathbf{a} \times \mathbf{c})$

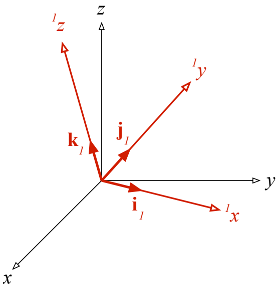
Multiple Reference Frames

- If we associate a reference system to a camera and the camera moves, or we consider multiple cameras, or we consider one camera and the world, we have multiple reference systems
- Point coordinates are x, y, z
- Left superscript denotes which reference system coordinates are expressed in: ${}^1y$
- Subscripts denote which point or reference system we are talking about: x_2
- ${}^2y_3$ is the y coordinate of point 3 in reference system 2

Multiple Reference Frames

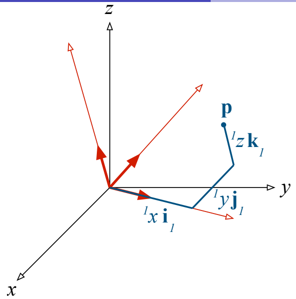
- A zero left superscript can be omitted: ${}^0z = z$
- The origin of a reference system is $\mathbf{t}$ (for "translation")
- We always have ${}^i\mathbf{t}_i = \begin{bmatrix} 0 \\ 0 \\ 0 \end{bmatrix}$
- If $\mathbf{i}$, $\mathbf{j}$, $\mathbf{k}$ are the unit points of a reference system, we always have $\begin{bmatrix} {}^i\mathbf{i}_i & {}^i\mathbf{j}_i & {}^i\mathbf{k}_i \end{bmatrix} = I$, the 3×3 identity matrix

Rotations



- No translation: ${}^0\mathbf{t}_1 = \mathbf{t}_1 = \begin{bmatrix} 0 \\ 0 \\ 0 \end{bmatrix}$
- Both systems right-handed
- $\mathbf{i}_1, \mathbf{j}_1, \mathbf{k}_1$ are the unit vectors of reference system 1 expressed in reference system 0
- Given $\mathbf{p} = {}^0\mathbf{p}$, what is ${}^1\mathbf{p}$?

Rotations



$$\mathbf{p} = {}^1x\,\mathbf{i}_1 + {}^1y\,\mathbf{j}_1 + {}^1z\,\mathbf{k}_1$$

$${}^1x = \mathbf{i}_1^T\mathbf{p} \quad , \quad {}^1y = \mathbf{j}_1^T\mathbf{p} \quad , \quad {}^1z = \mathbf{k}_1^T\mathbf{p}$$

$${}^1\mathbf{p} = \begin{bmatrix} {}^1x \\ {}^1y \\ {}^1z \end{bmatrix} = \begin{bmatrix} \mathbf{i}_1^T\mathbf{p} \\ \mathbf{j}_1^T\mathbf{p} \\ \mathbf{k}_1^T\mathbf{p} \end{bmatrix} = R_1\,\mathbf{p}$$

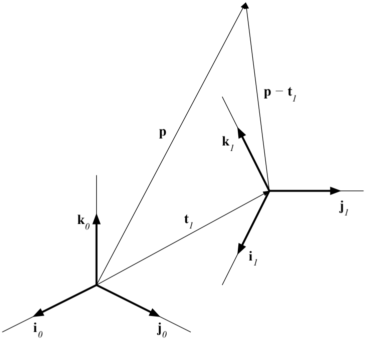
where $R_1 = {}^0R_1 = \begin{bmatrix} \mathbf{i}_1^T \\ \mathbf{j}_1^T \\ \mathbf{k}_1^T \end{bmatrix}$ (unit vectors are the *rows*)

Rotations in General

- More generally, $\quad {}^b\mathbf{p} = {}^aR_b\,{}^a\mathbf{p} \quad$ where $\quad {}^aR_b = \begin{bmatrix} {}^a\mathbf{i}_b^T \\ {}^a\mathbf{j}_b^T \\ {}^a\mathbf{k}_b^T \end{bmatrix}$
- Rotations are reversible, so there exists ${}^bR_a = {}^aR_b^{-1}$
- ${}^bR_a = {}^aR_b^T$ because ${}^aR_b$ is orthogonal
- Cross-product is covariant with rotations:

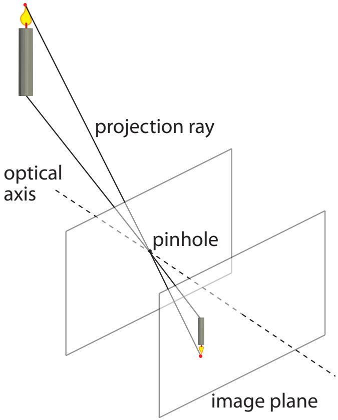
  $(R\mathbf{a}) \times (R\mathbf{b}) = R\,(\mathbf{a} \times \mathbf{b})$

Coordinate Transformation

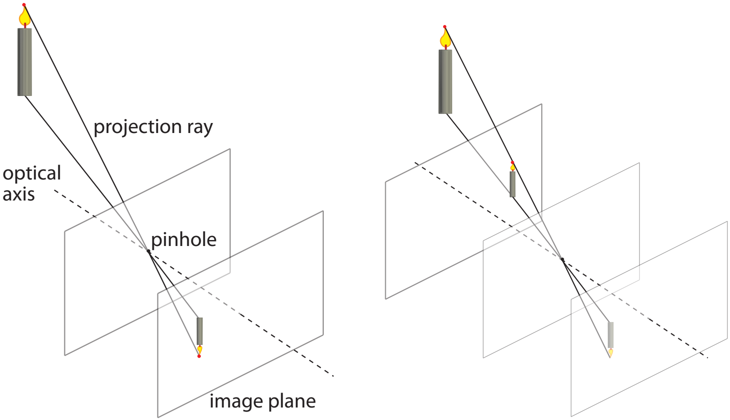


- A.k.a. rigid transformation
- First translate, then rotate: ${}^{1}\mathbf{p} = R_1(\mathbf{p} - \mathbf{t}_1)$
- Inverse: $\mathbf{p} = R_1^T\,{}^{1}\mathbf{p} + \mathbf{t}_1$
- Generally, if ${}^{b}\mathbf{p} = {}^{a}R_b({}^{a}\mathbf{p} - {}^{a}\mathbf{t}_b)$ then ${}^{a}\mathbf{p} = {}^{b}R_a({}^{b}\mathbf{p} - {}^{b}\mathbf{t}_a)$ where ${}^{b}R_a = {}^{a}R_b^T$ and ${}^{b}\mathbf{t}_a = -{}^{a}R_b\,{}^{a}\mathbf{t}_b$

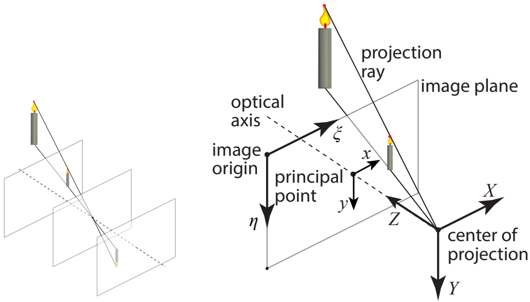
The Pinhole Camera



Putting the Image Plane in Front?



In Math, We Can



- *Camera reference system* (X, Y, Z) is right-handed, Z toward scene
- Distance btw center of projection and principal point: *focal distance f*
- *Canonical image reference system* (x, y) has origin at principal point
- *Pixel image reference system* (ξ, η) has origin at top left of sensor
- $\xi = s_x x + \xi_0$ and $\eta = s_y y + \eta_0$ $(s_x, s_y$ in pixels/mm)

The Projection Equations