Computer Vision - Lecture 17

Epipolar Geometry & Stereo Basics

13.01.2015

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Announcements

- Seminar in the summer semester
  - *"Current Topics in Computer Vision and Machine Learning"*
  - Block seminar, presentations in 1st week of semester break
  - Registration period: 14.01.2015 - 28.01.2015
  - http://web-info8.informatik.rwth-aachen.de/apse

  - Quick poll: Who would be interested in that?

Course Outline

- Image Processing Basics
- Segmentation & Grouping
- Object Recognition
- Local Features & Matching
- Object Categorization
- 3D Reconstruction
  - Epipolar Geometry and Stereo Basics
  - Camera calibration & Uncalibrated Reconstruction
  - Multi-view Stereo
- Optical Flow

Topics of This Lecture

- Geometric vision
  - Visual cues
  - Stereo vision
- Epipolar geometry
  - Depth with stereo
  - Geometry for a simple stereo system
  - Case example with parallel optical axes
  - General case with calibrated cameras
- Stereopsis & 3D Reconstruction
  - Correspondence search
  - Additional correspondence constraints
  - Possible sources of error
  - Applications

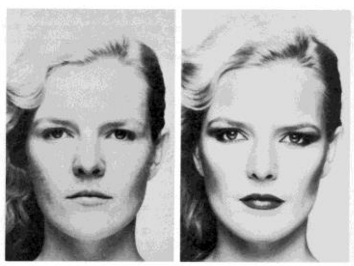
Geometric vision

- Goal: Recovery of 3D structure
  - What cues in the image allow us to do this?

Slide credit: Svetlana Lazebnik

Visual Cues

- Shading



Merle Norman Cosmetics, Los Angeles

Slide credit: Steve Seitz

Visual Cues

- Shading
- **Texture**

The Visual Cliff, by William Vandivert, 1960

Slide credit: Steve Seitz

Visual Cues

- Shading
- Texture
- **Focus**

From *The Art of Photography*, Canon

Slide credit: Steve Seitz

Visual Cues

- Shading
- Texture
- Focus
- **Perspective**

Slide credit: Steve Seitz

Visual Cues

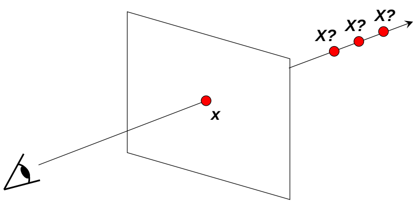
- Shading
- Texture
- Focus
- Perspective
- **Motion**

Figures from L. Zhang

Slide credit: Steve Seitz, Kristen Grauman http://www.brainconnection.com/teasers/?main=illusion/motion-shape

Our Goal: Recovery of 3D Structure

- We will focus on perspective and motion
- We need *multi-view geometry* because recovery of structure from one image is inherently ambiguous



Slide credit: Svetlana Lazebnik

To Illustrate This Point…

- Structure and depth are inherently ambiguous from single views.

Slide credit: Svetlana Lazebnik, Kristen Grauman

Stereo Vision

http://www.well.com/~jimg/stereo/stereo_list.html

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Slide credit: Kristen Grauman

What Is Stereo Vision?

- Generic problem formulation: given several images of the same object or scene, compute a representation of its 3D shape

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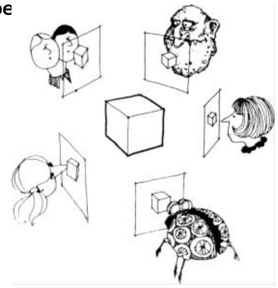

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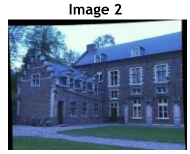
What Is Stereo Vision?

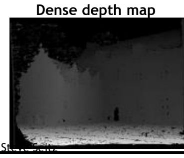
- Narrower formulation: given a calibrated binocular stereo pair, fuse it to produce a depth image

Image 1

Image 2



Dense depth map



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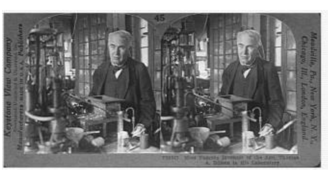
What Is Stereo Vision?

- Narrower formulation: given a calibrated binocular stereo pair, fuse it to produce a depth image.
  - Humans can do it



Stereograms: Invented by Sir Charles Wheatstone, 1838

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Autostereograms: http://www.magiceye.com

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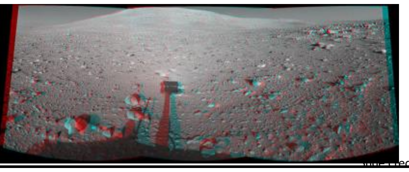
Application of Stereo: Robotic Exploration

Nomad robot searches for meteorites in Antartica

Real-time stereo on Mars



Slide credit: Steve Seitz

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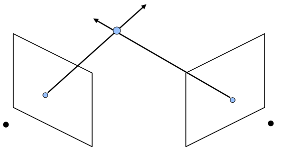
Depth with Stereo: Basic Idea



- Basic Principle: Triangulation
  - Gives reconstruction as intersection of two rays
  - Requires
    - Camera pose (calibration)
    - Point correspondence

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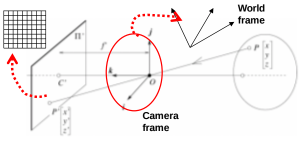
Camera Calibration



Extrinsic parameters:
Camera frame ↔ Reference frame

Intrinsic parameters:
Image coordinates relative to camera ↔ Pixel coordinates

- Parameters
  - *Extrinsic*: rotation matrix and translation vector
  - *Intrinsic*: focal length, pixel sizes (mm), image center point, radial distortion parameters

We'll assume for now that these parameters are given and fixed.

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Geometry for a Simple Stereo System

- First, assuming parallel optical axes, known camera parameters (i.e., calibrated cameras):

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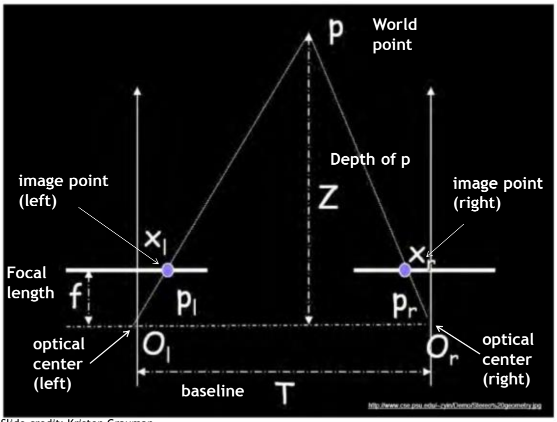

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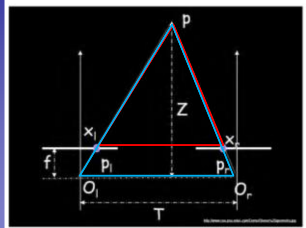
Geometry for a Simple Stereo System

- Assume parallel optical axes, known camera parameters (i.e., calibrated cameras). We can triangulate via:



Similar triangles (p_l, P, p_r) and (O_l, P, O_r):

$$\frac{T - (x_r - x_l)}{Z - f} = \frac{T}{Z}$$

$$Z = f\frac{T}{x_r - x_l}$$

"disparity"

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Depth From Disparity

Image $I(x,y)$ | Disparity map $D(x,y)$ | Image $I'(x',y')$

$$(x', y') = (x + D(x,y), y)$$

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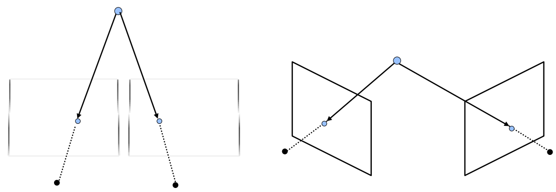
General Case With Calibrated Cameras

- The two cameras need not have parallel optical axes.



vs.

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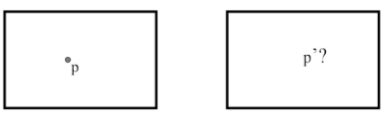
Stereo Correspondence Constraints



- Given p in the left image, where can the corresponding point p' in the right image be?

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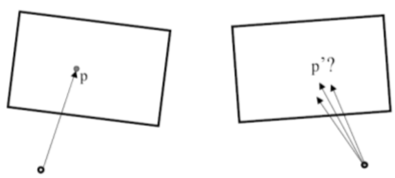
Stereo Correspondence Constraints



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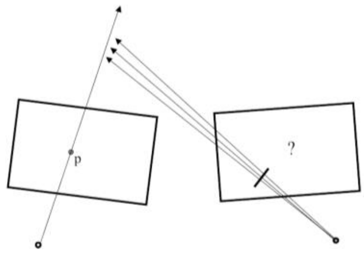
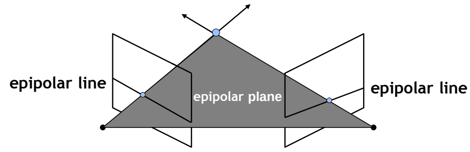
Stereo Correspondence Constraints



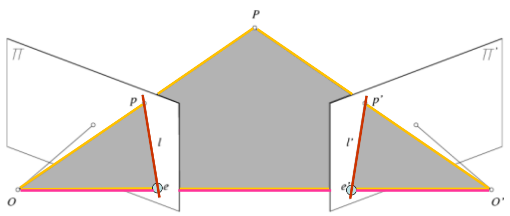
Stereo Correspondence Constraints

- Geometry of two views allows us to constrain where the corresponding pixel for some image point in the first view must occur in the second view.



- Epipolar constraint: Why is this useful?
  - Reduces correspondence problem to 1D search along conjugate epipolar lines.

Epipolar Geometry



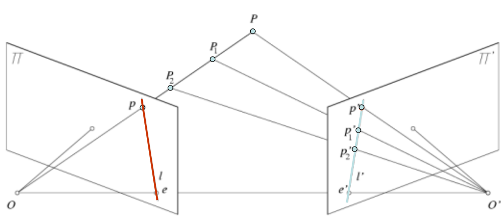
- Epipolar Plane
- Baseline
- Epipoles
- Epipolar Lines

Epipolar Geometry: Terms

- ***Baseline***
  - Line joining the camera centers
- ***Epipole***
  - Point of intersection of baseline with the image plane
- ***Epipolar plane***
  - Plane containing baseline and world point
- ***Epipolar line***
  - Intersection of epipolar plane with the image plane

- Properties
  - All epipolar lines intersect at the epipole.
  - An epipolar plane intersects the left and right image planes in epipolar lines.

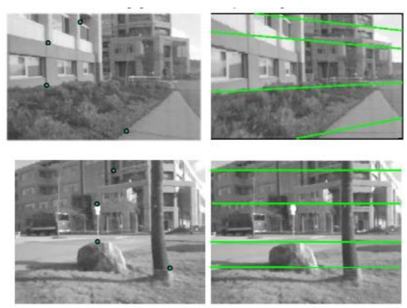
Epipolar Constraint



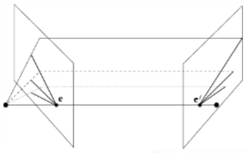
- Potential matches for p have to lie on the corresponding epipolar line l'.
- Potential matches for p' have to lie on the corresponding epipolar line l.

http://www.ai.sri.com/~luong/research/Meta3DViewer/EpipolarGeo.html

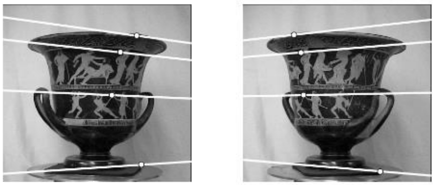
Example



Example: Converging Cameras



As position of 3D point varies, epipolar lines "rotate" about the baseline



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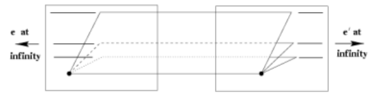
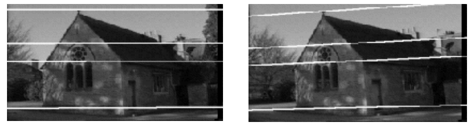
Example: Motion Parallel With Image Plane





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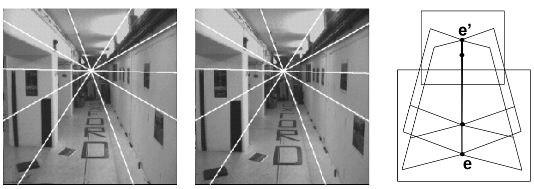
Example: Forward Motion



- Epipole has same coordinates in both images.
- Points move along lines radiating from e: "Focus of expansion"

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Let's Formalize This!

- For a given stereo rig, how do we express the epipolar constraints algebraically?
- For this, we will need some linear algebra.
- But don't worry! We'll go through it step by step…

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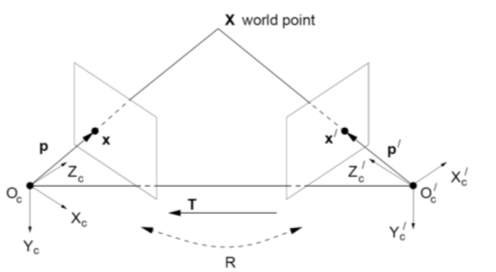
Stereo Geometry With Calibrated Cameras



- If the rig is calibrated, we know:
  - How to rotate and translate camera reference frame 1 to get to camera reference frame 2.
    - Rotation: 3 x 3 matrix; translation: 3 vector.

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Rotation Matrix

$$\mathbf{R}_x(\alpha) = \begin{bmatrix} 1 & 0 & 0 \\ 0 & \cos\alpha & -\sin\alpha \\ 0 & \sin\alpha & \cos\alpha \end{bmatrix}$$

$$\mathbf{R}_y(\beta) = \begin{bmatrix} \cos\beta & 0 & \sin\beta \\ 0 & 1 & 0 \\ -\sin\beta & 0 & \cos\beta \end{bmatrix}$$

$$\mathbf{R}_z(\gamma) = \begin{bmatrix} \cos\gamma & -\sin\gamma & 0 \\ \sin\gamma & \cos\gamma & 0 \\ 0 & 0 & 1 \end{bmatrix}$$

Express 3D rotation as series of rotations around coordinate axes by angles α, β, γ

Overall rotation is product of these elementary rotations:

$$\mathbf{R} = \mathbf{R}_x \mathbf{R}_y \mathbf{R}_z$$

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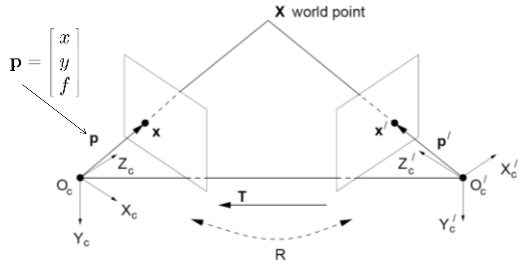
3D Rigid Transformation

$$\begin{bmatrix} X' \\ Y' \\ Z' \end{bmatrix} = \begin{bmatrix} r_{11} & r_{12} & r_{13} \\ r_{21} & r_{22} & r_{23} \\ r_{31} & r_{32} & r_{33} \end{bmatrix} \begin{bmatrix} X \\ Y \\ Z \end{bmatrix} + \begin{bmatrix} T_x \\ T_y \\ T_z \end{bmatrix}$$

$$\mathbf{X}' = \mathbf{R}\mathbf{X} + \mathbf{T}$$

Stereo Geometry With Calibrated Cameras



- Camera-centered coordinate systems are related by known rotation $\mathbf{R}$ and translation $\mathbf{T}$:

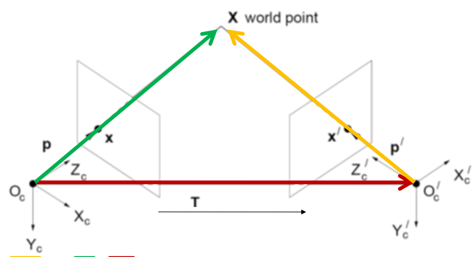
$$\mathbf{X}' = \mathbf{R}\mathbf{X} + \mathbf{T}$$

Excursion: Cross Product

$$\vec{a} \times \vec{b} = \vec{c} \qquad \begin{aligned} \vec{a} \cdot \vec{c} &= 0 \\ \vec{b} \cdot \vec{c} &= 0 \end{aligned}$$

- Vector cross product takes two vectors and returns a third vector that's perpendicular to both inputs.
- So here, c is perpendicular to both a and b, which means the dot product is 0.

From Geometry to Algebra



$$\boxed{\mathbf{X}'} = \mathbf{R}\boxed{\mathbf{X}} + \boxed{\mathbf{T}}$$

$$\underbrace{\mathbf{T} \times \mathbf{X}'}_{\text{Normal to the plane}} = \mathbf{T} \times \mathbf{R}\mathbf{X} + \mathbf{T} \times \mathbf{T}$$

$$= \mathbf{T} \times \mathbf{R}\mathbf{X}$$

$$\mathbf{X}' \cdot (\mathbf{T} \times \mathbf{X}') = \mathbf{X}' \cdot (\mathbf{T} \times \mathbf{R}\mathbf{X})$$

$$0 = \mathbf{X}' \cdot (\mathbf{T} \times \mathbf{R}\mathbf{X})$$

Matrix Form of Cross Product

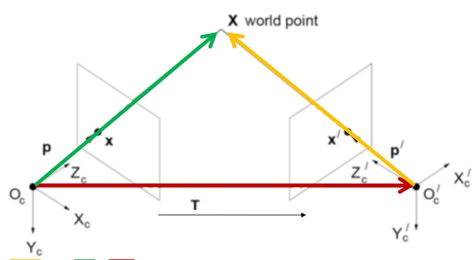
$$\vec{a} \times \vec{b} \qquad = \vec{c} \qquad \begin{aligned} \vec{a} \cdot \vec{c} &= 0 \\ \vec{b} \cdot \vec{c} &= 0 \end{aligned}$$

"skew symmetric" matrix

$$[a_\times] = \begin{bmatrix} 0 & -a_z & a_y \\ a_z & 0 & -a_x \\ -a_y & a_x & 0 \end{bmatrix}$$

$$\boxed{\vec{a} \times \vec{b} = [a_\times]\vec{b}}$$

From Geometry to Algebra



$$\boxed{\mathbf{X}'} = \mathbf{R}\boxed{\mathbf{X}} + \boxed{\mathbf{T}}$$

$$\underbrace{\mathbf{T} \times \mathbf{X}'}_{\text{Normal to the plane}} = \mathbf{T} \times \mathbf{R}\mathbf{X} + \mathbf{T} \times \mathbf{T}$$

$$= \mathbf{T} \times \mathbf{R}\mathbf{X}$$

$$\mathbf{X}' \cdot (\mathbf{T} \times \mathbf{X}') = \mathbf{X}' \cdot (\mathbf{T} \times \mathbf{R}\mathbf{X})$$

$$\boxed{0 = \mathbf{X}' \cdot (\mathbf{T} \times \mathbf{R}\mathbf{X})}$$

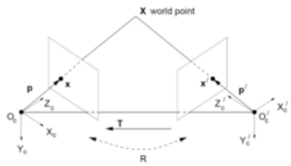
Essential Matrix

$$\boxed{\mathbf{X}'\cdot(\mathbf{T}\times\mathbf{R}\mathbf{X})=0}$$

$$\mathbf{X}'\cdot(\mathbf{T}_x\ \mathbf{R}\mathbf{X})=0$$

Let $\mathbf{E}=\mathbf{T}_x\mathbf{R}$

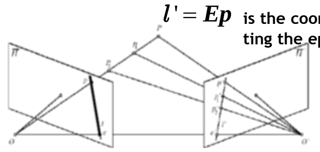
$$\mathbf{X}'^T\mathbf{E}\mathbf{X}=0$$



- This holds for the rays p and p' that are parallel to the camera-centered position vectors X and X', so we have: $\boxed{\mathbf{p}'^T\ \mathbf{E}\mathbf{p}=0}$
- $\mathbf{E}$ is called the essential matrix, which relates corresponding image points [Longuet-Higgins 1981]

Essential Matrix and Epipolar Lines

$\boxed{\mathbf{p}'^{\mathrm{T}}\mathbf{E}\mathbf{p}=0}$ Epipolar constraint: if we observe point p in one image, then its position p' in second image must satisfy this equation.



$l'=Ep$ is the coordinate vector representing the epipolar line for point p

(i.e., the line is given by: $l'^{\mathrm{T}}\mathbf{x}=0$)

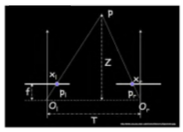
$l=E^T p'$ is the coordinate vector representing the epipolar line for point p'

Essential Matrix: Properties

- Relates image of corresponding points in both cameras, given rotation and translation.
- Assuming intrinsic parameters are known

$$\mathbf{E}=\mathbf{T}_x\mathbf{R}$$

Essential Matrix Example: Parallel Cameras



$\mathbf{R}=$

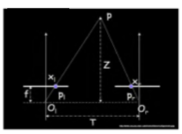
$\mathbf{T}=$

$\mathbf{E}=[\mathbf{T}_x]\mathbf{R}=$

$$\mathbf{p}'^{\mathrm{T}}\mathbf{E}\mathbf{p}=0$$

For the parallel cameras, image of any point must lie on same horizontal line in each image plane.

Essential Matrix Example: Parallel Cameras



$\mathbf{R}=\mathbf{I}$

$\mathbf{T}=[-d,0,0]^{\mathrm{T}}$

$\mathbf{E}=[\mathbf{T}_x]\mathbf{R}=\begin{pmatrix}0&0&0\\0&0&d\\0&-d&0\end{pmatrix}$

$$\mathbf{p}'^{\mathrm{T}}\mathbf{E}\mathbf{p}=0$$

$$\begin{bmatrix}x' & y' & f\end{bmatrix}\begin{bmatrix}0&0&0\\0&0&d\\0&-d&0\end{bmatrix}\begin{bmatrix}x\\y\\f\end{bmatrix}=0$$

$$\Leftrightarrow\begin{bmatrix}x' & y' & f\end{bmatrix}\begin{bmatrix}0\\df\\-dy\end{bmatrix}=0$$

$$\boxed{\Leftrightarrow y=y'}$$

For the parallel cameras, image of any point must lie on same horizontal line in each image plane.

More General Case

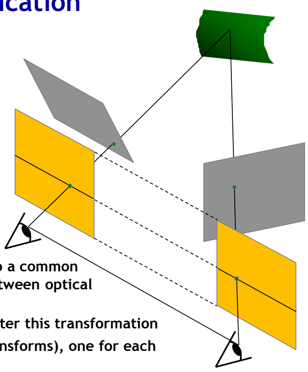
Image $I(x,y)$ — Disparity map $D(x,y)$ — Image $I'(x',y')$

$$(x',y')=(x+D(x,y),y)$$

What about when cameras' optical axes are not parallel?

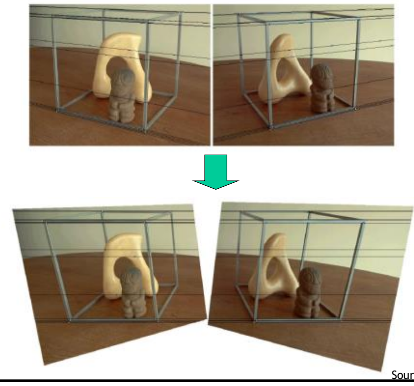
Stereo Image Rectification

- In practice, it is convenient if image scanlines are the epipolar lines.



- Algorithm
  - Reproject image planes onto a common plane parallel to the line between optical centers
  - Pixel motion is horizontal after this transformation
  - Two homographies (3×3 transforms), one for each input image reprojection

Stereo Image Rectification: Example



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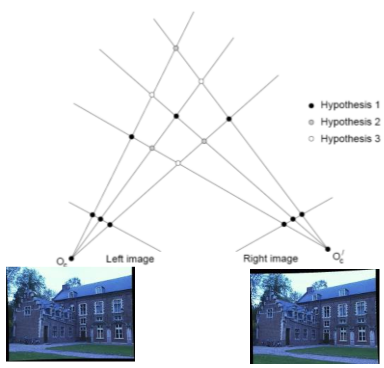
  - Applications

Stereo Reconstruction

- Main Steps
  - Calibrate cameras
  - Rectify images
  - Compute disparity
  - Estimate depth

Correspondence Problem

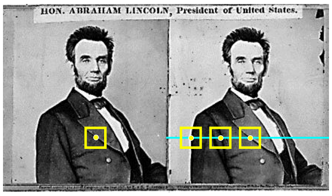


Multiple match hypotheses satisfy epipolar constraint, but which is correct?

Correspondence Problem

- To find matches in the image pair, we will assume
  - Most scene points visible from both views
  - Image regions for the matches are similar in appearance

Dense Correspondence Search



- For each pixel in the first image
  - Find corresponding epipolar line in the right image
  - Examine all pixels on the epipolar line and pick the best match (e.g. SSD, correlation)
  - Triangulate the matches to get depth information
- This is easiest when epipolar lines are scanlines
  ⇒ Rectify images first

Example: Window Search

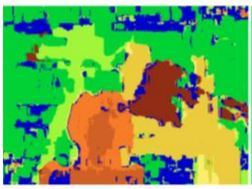
- Data from University of Tsukuba

Scene

Ground truth

Example: Window Search

- Data from University of Tsukuba

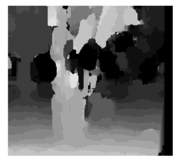


Window-based matching
(best window size)

Ground truth

Effect of Window Size

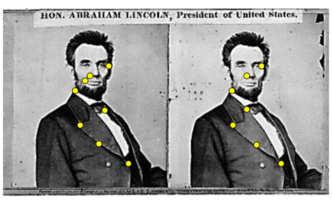
$W = 3$



$W = 20$

Want window large enough to have sufficient intensity variation, yet small enough to contain only pixels with about the same disparity.

Alternative: Sparse Correspondence Search



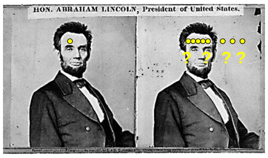
- Idea: Restrict search to sparse set of detected features
- Rather than pixel values (or lists of pixel values) use *feature descriptor* and an associated *feature distance*
- Still narrow search further by epipolar geometry

What would make good features?

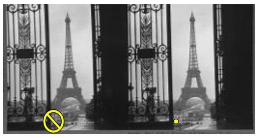
Dense vs. Sparse

- Sparse
  - Efficiency
  - Can have more reliable feature matches, less sensitive to illumination than raw pixels
  - But…
    - Have to know enough to pick good features
    - Sparse information
- Dense
  - Simple process
  - More depth estimates, can be useful for surface reconstruction
  - But…
    - Breaks down in textureless regions anyway
    - Raw pixel distances can be brittle
    - Not good with very different viewpoints

Difficulties in Similarity Constraint



Untextured surfaces



Occlusions

Possible Sources of Error?

- Low-contrast / textureless image regions
- Occlusions
- Camera calibration errors
- Violations of *brightness constancy* (e.g., specular reflections)
- Large motions

Application: View Interpolation

Right Image

Application: View Interpolation

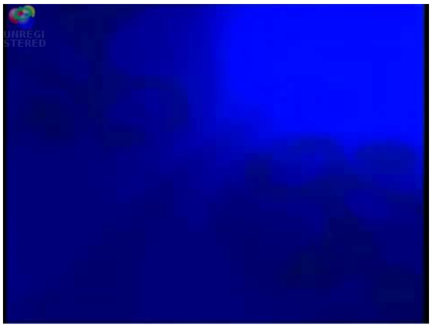
Left Image

Application: View Interpolation

Disparity

Application: View Interpolation

Application: Free-Viewpoint Video



http://www.liberovision.com

Summary: Stereo Reconstruction

- Main Steps
  - Calibrate cameras
  - Rectify images
  - Compute disparity
  - Estimate depth

- So far, we have only considered calibrated cameras…

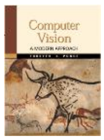
- Next lecture
  - Uncalibrated cameras
  - Camera parameters
  - Revisiting epipolar geometry
  - Robust fitting

Slide credit: Kristen Grauman

References and Further Reading

- Background information on epipolar geometry and stereopsis can be found in Chapters 10.1-10.2 and 11.1-11.3 of

  D. Forsyth, J. Ponce,
  Computer Vision - A Modern Approach.
  Prentice Hall, 2003



- More detailed information (if you really want to implement 3D reconstruction algorithms) can be found in Chapters 9 and 10 of

  R. Hartley, A. Zisserman
  Multiple View Geometry in Computer Vision
  2nd Ed., Cambridge Univ. Press, 2004