ECE 417/598: Image formation

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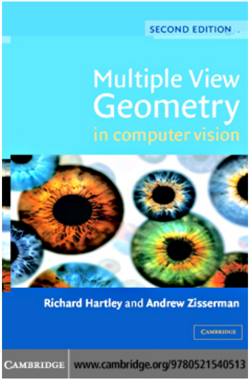
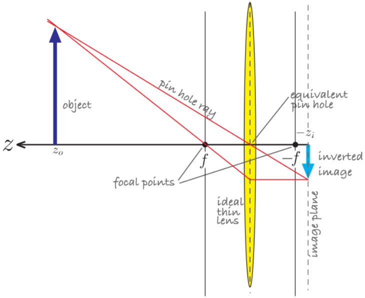
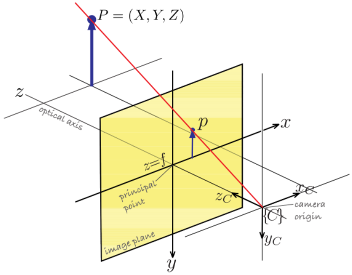
Additional reference

Chapter 6, 7, 8 of  [1]

[1] Lookup on libgen.rs





[2]

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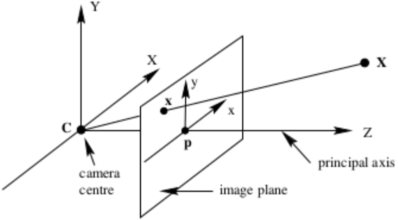
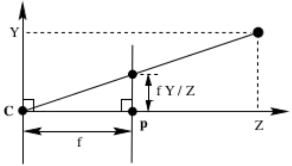
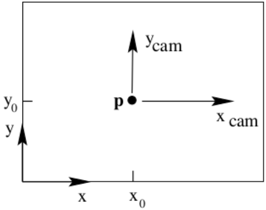
[2]Chapter 11. Corke.





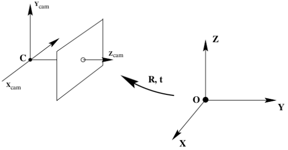
[3]

[3] Chapter 6. Hartley and Zisserman



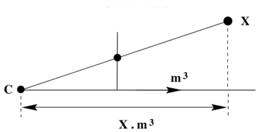
[4]

[4] Chapter 6. Hartley and Zisserman



[5]

[5]Chapter 6. Hartley and Zisserman



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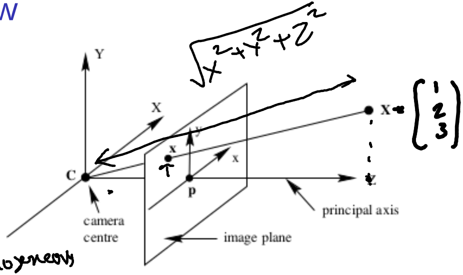
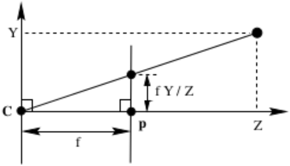
[6]Chapter 6. Hartley and Zisserman

Review





u = homogeneous

$$\lambda \begin{bmatrix} x \\ y \\ 1 \end{bmatrix} = \begin{bmatrix} f_x & s & u_0 \\ 0 & f_y & v_0 \\ 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} X \\ Y \\ Z \end{bmatrix}$$

$\lambda = Z$

$$\mathsf{K} = \begin{bmatrix} f_x & s & u_0 \\ 0 & f_y & v_0 \\ 0 & 0 & 1 \end{bmatrix} \quad (1)$$

camera intrinsic matrix

$$\mathsf{u} = [x, y]^\top \quad (2)$$

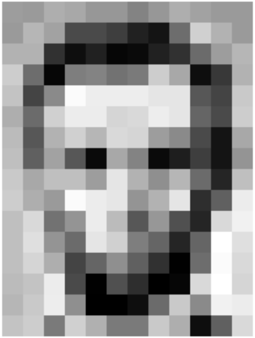
$$\underline{X} = [X, Y, Z]^\top \quad (3)$$

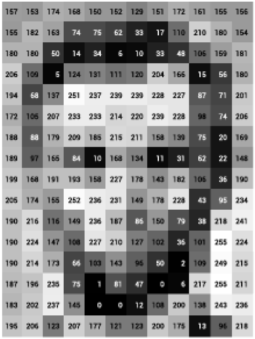
$$\underline{\mathsf{u}} = [\mathsf{u}^\top, 1]^\top \quad (4)$$

$$\underline{\mathsf{u}} = K\underline{X} \quad (5)$$

A numerical example

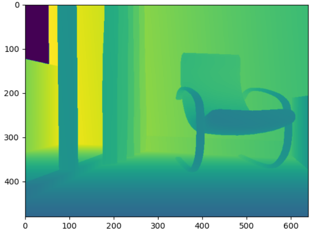
Image is a grid of numbers. The ~~vale~~ value in the grid represents intensity values.

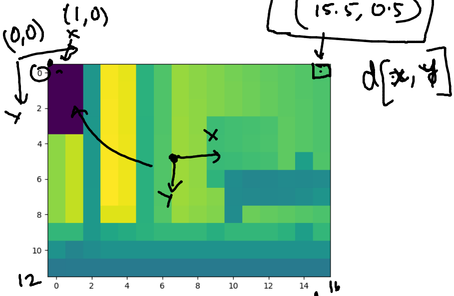




157	153	174	168	150	152	129	151	172	161	155	156
155	182	163	74	75	62	33	17	110	210	180	154
180	180	50	14	34	6	10	33	48	106	159	181
206	109	5	124	131	111	120	204	166	15	56	180
194	68	137	251	237	239	239	228	227	87	71	201
172	105	207	233	233	214	220	239	228	98	74	206
188	88	179	209	185	215	211	158	139	75	20	169
189	97	165	84	10	168	134	11	31	62	22	148
199	168	191	193	158	227	178	143	182	106	36	190
205	174	155	252	236	231	149	178	228	43	95	234
190	216	116	149	236	187	86	150	79	38	218	241
190	224	147	108	227	210	127	102	36	101	255	224
190	214	173	66	103	143	96	50	2	109	249	215
187	196	235	75	1	81	47	0	6	217	255	211
183	202	237	145	0	0	12	108	200	138	243	236
195	206	123	207	177	121	123	200	175	13	96	218

A Depth Image is an array of numbers. The value in the grid represents ~~intensity~~ depth values.





$$K = \begin{bmatrix} 500 & 0 & 8 \\ 0 & 500 & 6 \\ 0 & 0 & 1 \end{bmatrix}$$

$$\underline{u} = K \underline{X}$$

$$\lambda \begin{bmatrix} 15.5 \\ 0.5 \\ 1 \end{bmatrix} = K \begin{bmatrix} X \\ Y \\ Z \end{bmatrix}$$

$$\begin{bmatrix} X \\ Y \\ Z \end{bmatrix} = \lambda K^{-1} \begin{bmatrix} 15.5 \\ 0.5 \\ 1 \end{bmatrix} = \lambda K^{-1} \underline{u}$$

$$\begin{bmatrix} X \\ Y \\ Z \end{bmatrix} = \lambda K^{-1} \underline{u} = \lambda \begin{bmatrix} 1/500 & 0 & -8/500 \\ 0 & 1/500 & -6/500 \\ 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} 15.5 \\ 0.5 \\ 1 \end{bmatrix}$$

$$= \begin{bmatrix} \lambda 15.5 \\ \lambda 0.5 \\ \lambda \end{bmatrix} \Rightarrow \lambda = 10$$

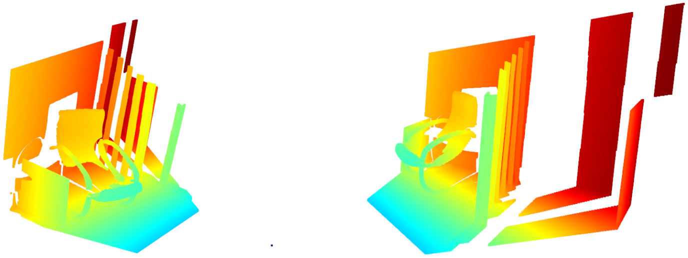
$$d[x,y] = 10 \qquad = Z$$

$$\lambda \left[K^{-1} \underline{u} \right]_3 = 10' \Rightarrow \lambda = \frac{d[x,y]}{[K^{-1} u]_3}$$

$$\begin{pmatrix} X \\ Y \\ Z \end{pmatrix} = \frac{d[x,y]}{[K^{-1} u]_3} K^{-1} \underline{u}$$

$$\begin{bmatrix} X \\ Y \\ Z \end{bmatrix} = \begin{pmatrix} 155 \\ 5 \\ 10 \end{pmatrix}$$

From what we have learned, how can we convert the depth image to a point cloud?



Pseudo-Inverse

$A \quad \frac{A^{\dagger}}{PI}$

$\underline{u} = K[{}^{c}R_w \mid {}^{c}t_w]\,\underline{X} \rightarrow \underline{X} = \begin{bmatrix} X \\ Y \\ Z \\ 1 \end{bmatrix}$

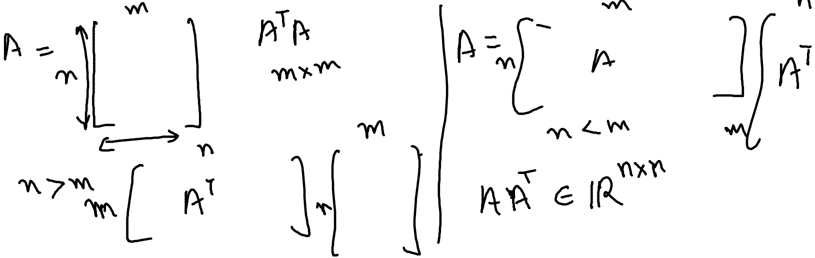
$\underline{u} = P\underline{X} \Rightarrow \underline{X} = P^{\dagger}\underline{u}$ ← dagger

$$AA^{\dagger}A = A \tag{6}$$

~~If SVD of A is given by $A = U\Sigma V^{\top}$ then $A^{\dagger} = U\Sigma^{-1}V^{\top}$~~ (7)

$$\text{if A is tall, then } A^{\dagger} = (A^{\top}A)^{-1}A^{\top} \tag{8}$$

$$\text{if A is fat, then } A^{\dagger} = A^{\top}(AA^{\top})^{-1} \tag{9}$$



Least square solutions

$$\underset{n\times n}{A}x = b$$

$$\begin{bmatrix} a_{11} & a_{12} & a_{13} \\ \cdot & \cdot & \cdot \\ & & \end{bmatrix} \underset{n\times 1}{\begin{pmatrix} x_1 \\ x_2 \\ x_3 \end{pmatrix}} = \underset{n\times 1}{\begin{pmatrix} b_1 \\ b_2 \\ b_3 \end{pmatrix}}$$

$$X = A^{-1} b$$

Tall

$n > m$ $\quad A_{n\times m}\, x_{m\times 1} = b_{n\times 1}$

$$\begin{bmatrix} a_{11} & a_{12} \\ a_{21} & a_{22} \\ a_{31} & a_{32} \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \end{bmatrix} = \begin{bmatrix} b_1 \\ b_2 \\ b_3 \end{bmatrix}$$

$$\min_x \|Ax - b\|_2^2$$

$$\min_x (Ax-b)^T(Ax-b)$$

$$\min_x (x^TA^T - b^T)(Ax-b)$$

$$\min_x x^TA^TAx - b^TAx - x^TA^Tb + b^Tb$$

$$\|\underline{u}\|_2^2 = \underline{u}^T\underline{u}$$

$$\left(\sqrt{u_1^2+u_2^2+u_3^2}\right)^2 = [u_1\, u_2\, u_3]\begin{bmatrix} u_1 \\ u_2 \\ u_3 \end{bmatrix}$$

$$(AB)^T = B^TA^T$$

$A \in \mathbb{R}^{n \times m}$

$x \in \mathbb{R}^{m \times 1}$

$b \in \mathbb{R}^{n \times 1}$

$$b^T A x = x^T A^T b$$

$$b^T A x = \left(b^T A x\right)^T = x^T A^T \left(b^T\right)^T = x^T A^T b$$

$$\min_{x} \|Ax - b\|_2^2$$

$$\frac{\partial f(x)}{\partial x}\Big| = 0$$

$$\min_{x} \; x^T A^T A x - 2 b^T A x + b^T b$$

$$\frac{\partial}{\partial x}\left(x^T A^T A x - 2 b^T A x + b^T b \right)\Big|_{x = x^*} = 0$$

$$2 A^T A x - 2 A^T b = 0$$

$$x = \begin{bmatrix} x_1 \\ \vdots \\ x_n \end{bmatrix}$$

$$\frac{\partial}{\partial x} x^T B x = 2 B x$$

$$A^T A \underline{x} = A^T b \Rightarrow \underline{x} = (A^T A)^{-1} A^T b$$

$$\underline{x} = \underbrace{(A^T A)^{-1} A^T}_{A^+} b$$

$$\underline{x} = A^+ b$$

$$\underline{b}^T \underline{x} = b_1 x_1 + b_2 x_2 + b_3 x_3$$

$$\frac{\partial}{\partial \underline{x}} \underline{b}^T x = \begin{bmatrix} \frac{\partial}{\partial x_1} b^T x \\ \frac{\partial}{\partial x_2} b^T x \\ \frac{\partial}{\partial x_3} b^T x \end{bmatrix} = \begin{pmatrix} b_1 \\ b_2 \\ b_3 \end{pmatrix} = \underline{b}$$

Fat matrix or undetermined system

$$\begin{bmatrix} a_{11} & a_{12} & a_{13} \\ a_{21} & a_{22} & a_{23} \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \\ x_3 \end{bmatrix} = \begin{bmatrix} b_1 \\ b_2 \end{bmatrix}$$

$$\min_x \|x\|_2^2 \quad \text{s.t. } Ax = b$$

$$x = \underbrace{A^T (AA^T)^{-1}}_{A^{+}} b$$

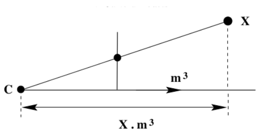
will need lagrange multiplier.

A topic in optimization

Skipping this

KKT condition

Points as rays: aka Prospective geometry



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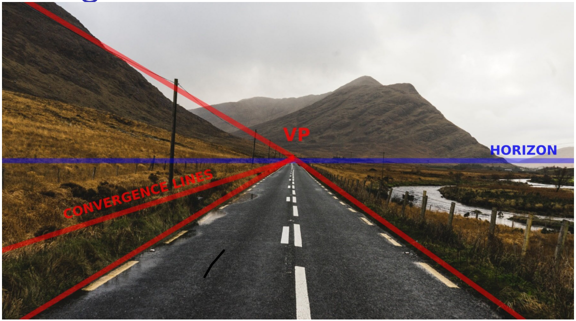
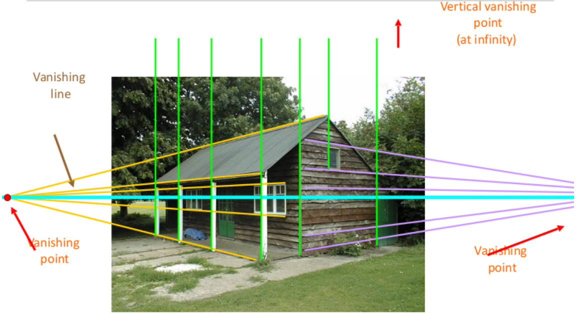
[7]Chapter 6. Hartley and Zisserman

Vanishing Point





e Courtesy Antonio Criminisi

Vanishing Point