11/30/21, 2:26 PM Assignment2

# Assignment 2 - Epipolar Geometry and 3D Reconstruction

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The autoreload extension is already loaded. To reload it, use: %reload\_ext autoreload

## Part I: The Eight Point Algorithm

#### **Load Data**

```
In [8]:
    data_dir = './merton_college/'
    img1, img2, x1, x2 = load_homogeneous_coordinates(data_dir)
```

#### Estimate the fundamental matrix \_F

```
In [9]:    _F = eight_points_algorithm(x1, x2)
    assert np.linalg.matrix_rank(_F) == 2
    print('Estimated fundamental matrix: ')
    print(_F)

Estimated fundamental matrix:
    [[-1.02865053e-09 -3.20313590e-07 1.31896763e-04]
        [ 9.73707906e-07 4.12485323e-08 -3.65986291e-03]
        [-4.04920255e-04 3.42996433e-03 1.43956698e-01]]
```

#### Plot epipoles and epipolar lines

## What is an Epipolar line?

The plain which intersects both projection-centers (camera and object) is called the epipolar plane.

This epipolar plane intersects both images on one line, the epipolarline.

Only on the epipolar line, can a point on one image be connected to a point on another image.

### What is an Epipole?

11/30/21, 2:26 PM Assignment2

The line that connects the projection centers of both camera, intersects the image plane in the epipole.

Both epipoles may not change their position in their own image, as long as the camera remains fixed.

The epipole is also simulatenously the depiction of the projection centers of the other camera.

All epipolar lines of its own image pass through it.

```
In [10]: # compute the epipole
    e = right_epipole(_F)
```

```
plt.figure()
  plt.imshow(img1)
  plt.title('Image 1')

# plot each line individually, this gives nice colors
  for i in range(100, 105):
      plot_epipolar_line(img1, _F.T, x2[:, i], e)

plt.axis('off')
  plt.figure()
  plt.imshow(img2)
  plt.title('Image 2')

# plot each point individually, this gives same colors as the lines
  for i in range(100, 105):
      plt.plot(x2[0, i], x2[1, i], 'o')
      plt.axis('off')
```



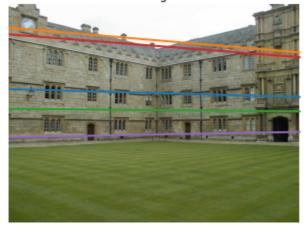


Image 2



11/30/21, 2:26 PM Assignment2

```
In [ ]:

In [ ]:
```