

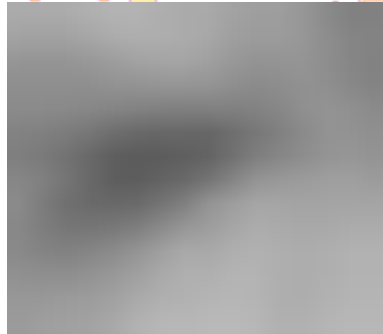
IMAGE FORMATION



From 3-D physical world to 2-D image:

- Analog vs digital images
- Camera geometry
- Radiometry and sensing

ANALOG IMAGES



An image can be understood as a 2D light intensity function $f(x,y)$ where:

- x and y are spatial coordinates
- The value of f at any point (x, y) is proportional to the brightness or gray value of the image at that point.

→ Cannot be stored as such on a digital computer.

DIGITAL IMAGES

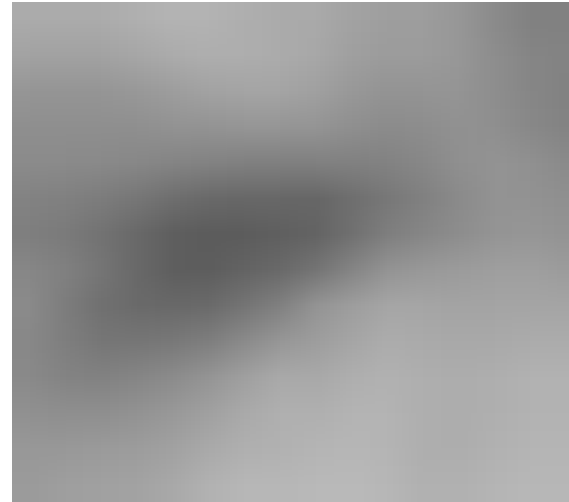


A digitized image is one in which:

- Spatial and grayscale values have been made discrete.
- Intensities measured across a regularly spaced grid in x and y directions are sampled to
 - 8 bits (256 values) per point for black and white,
 - 3x8 bits per point for color images.

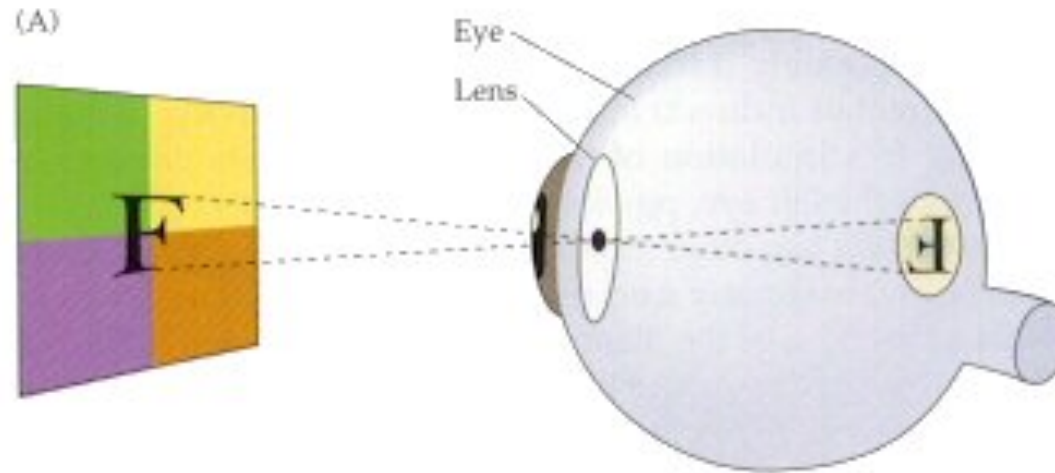
They are stored as a two dimensional arrays of gray-level values. The array elements are called pixels and identified by their x, y coordinates.

PIXELS



136 134 161 159 163 168 171 173 173 171 166 159 157 155
152 145 136 130 151 149 151 154 158 161 163 163 159 151
145 149 149 145 140 133 145 143 145 145 146 148 148
148 143 141 145 145 145 141 136 136 135 135 136 135 133
131 131 129 129 133 136 140 142 142 138 130 128 126 120
115 111 108 106 106 110 120 130 137 142 144 141 129 123
117 109 098 094 094 094 100 110 125 136 141 147 147 145
136 124 116 105 096 096 100 107 116 131 141 147 150 152
152 152 137 124 113 108 105 108 117 129 139 150 157 159
159 157 157 159 135 121 120 120 121 121 136 147 158 163
165 165 163 163 163 166 136 131 135 138 140 145 154 163
166 168 170 168 166 168 170 173 145 143 147 148 152 159
168 173 173 175 173 171 170 173 177 178 151 151 153 156
161 170 176 177 177 179 176 174 174 176 177 179 155 157
161 162 168 176 180 180 180 182 180 175 175 178 180 180

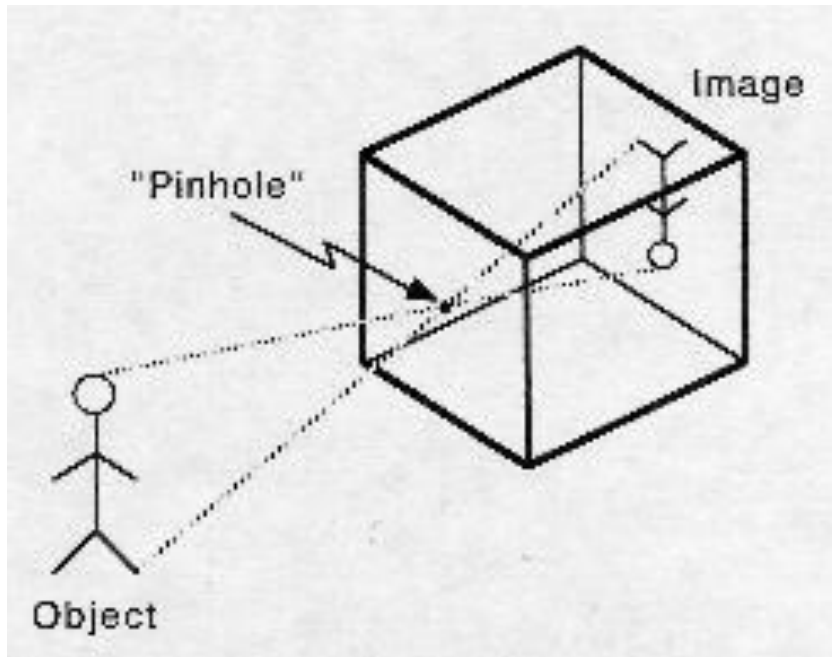
IMAGE FORMATION



Projection from surfaces to 2-D sensor.

- Where: Geometry
- How bright: Radiometry
- Stored how: Sensing

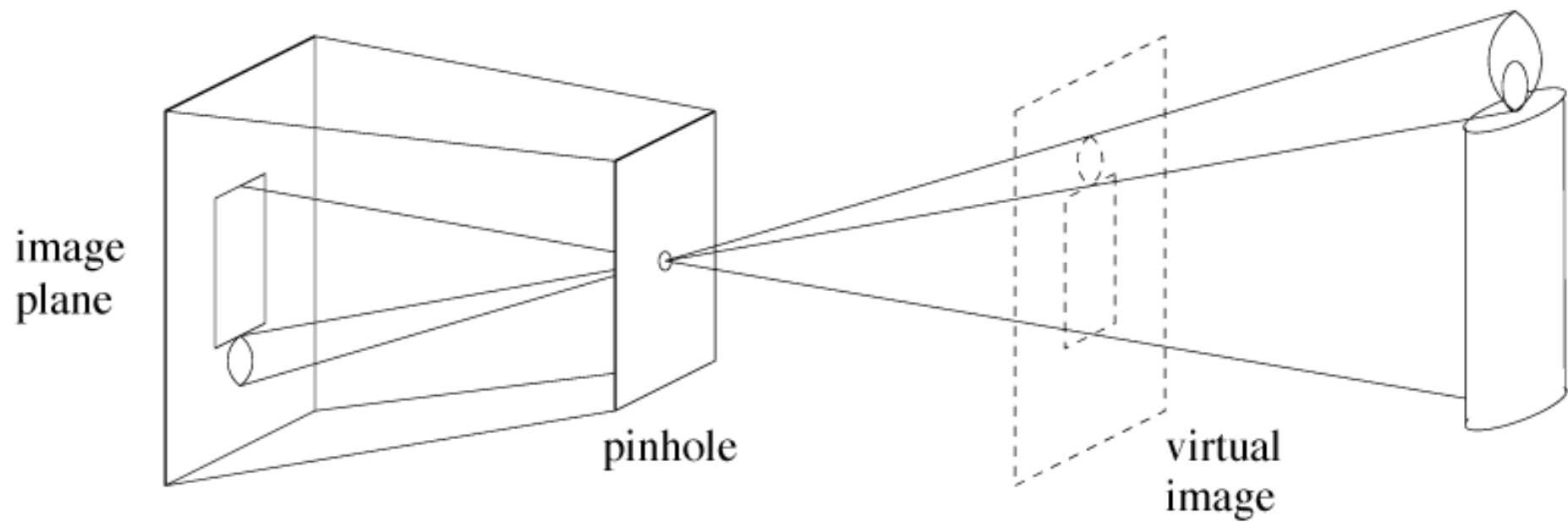
PINHOLE CAMERA MODEL



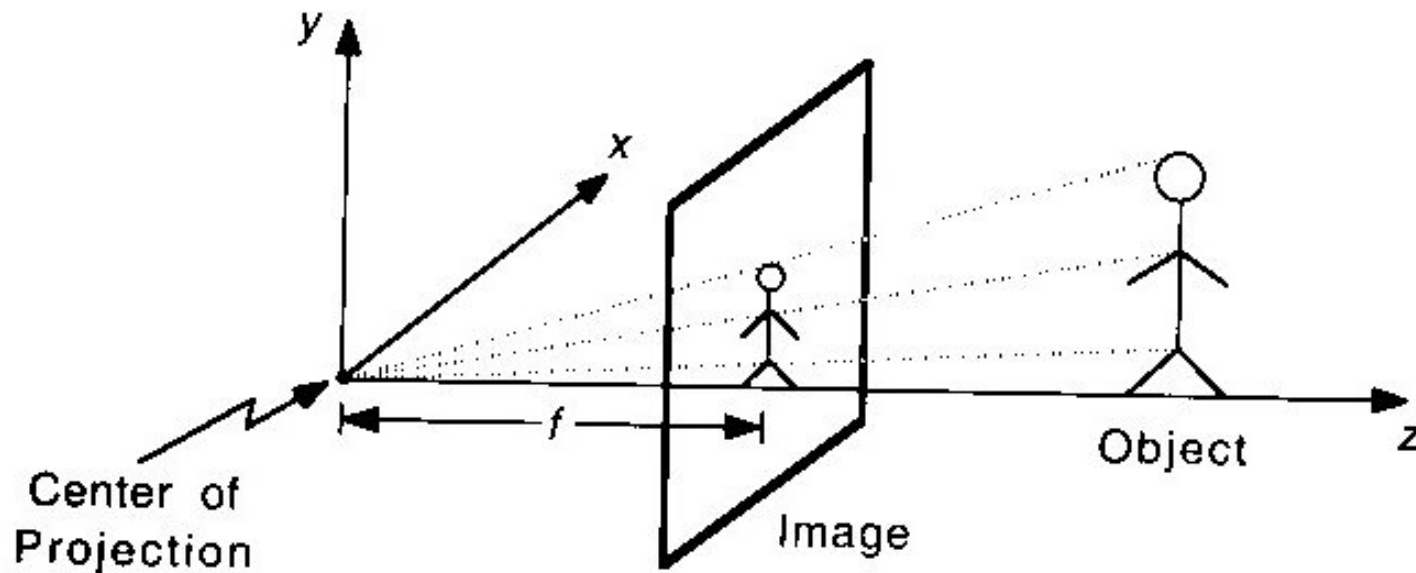
Idealized model that defines perspective projection:

- All rays go through a hole and form a star of lines
- The hole acts as a selector of rays that allows the formation of an inverted image.

VIRTUAL IMAGE



CAMERA GEOMETRY



Pinhole geometry without image reversal

COORDINATE SYSTEMS



World, Camera, Image Coordinate Systems

World Coordinate System:

$$(X_w, Y_w, Z_w)$$


Camera Coordinate System:

$$(X_c, Y_c, Z_c)$$

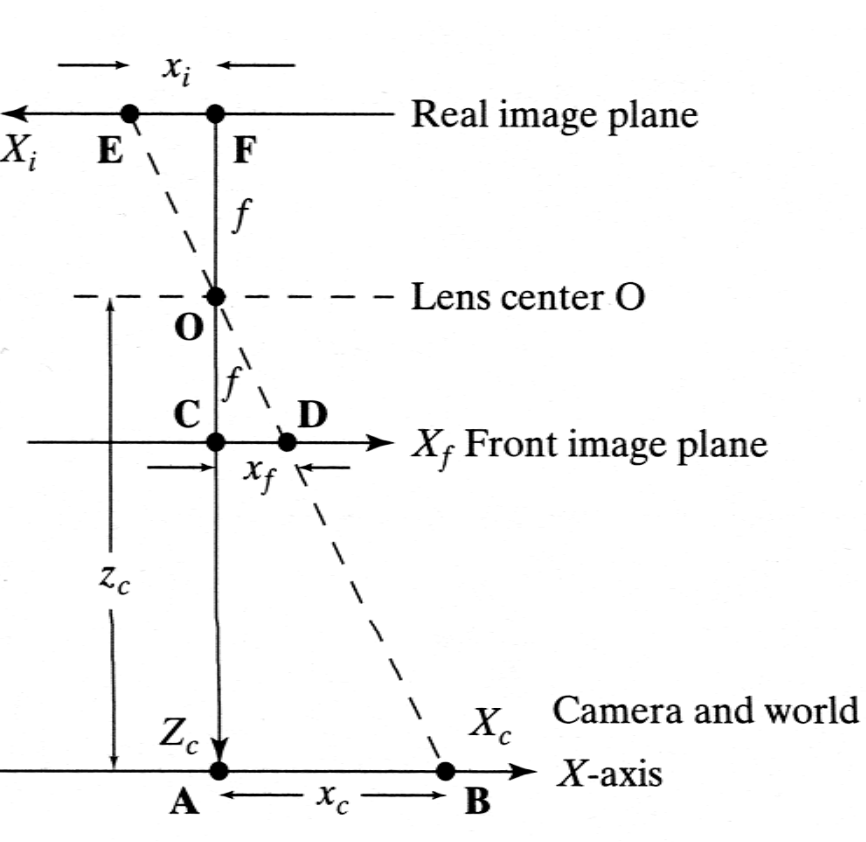
Image Coordinate System:

$$(X_i, Y_i, Z_i)$$

CAMERA COORDINATE SYSTEM



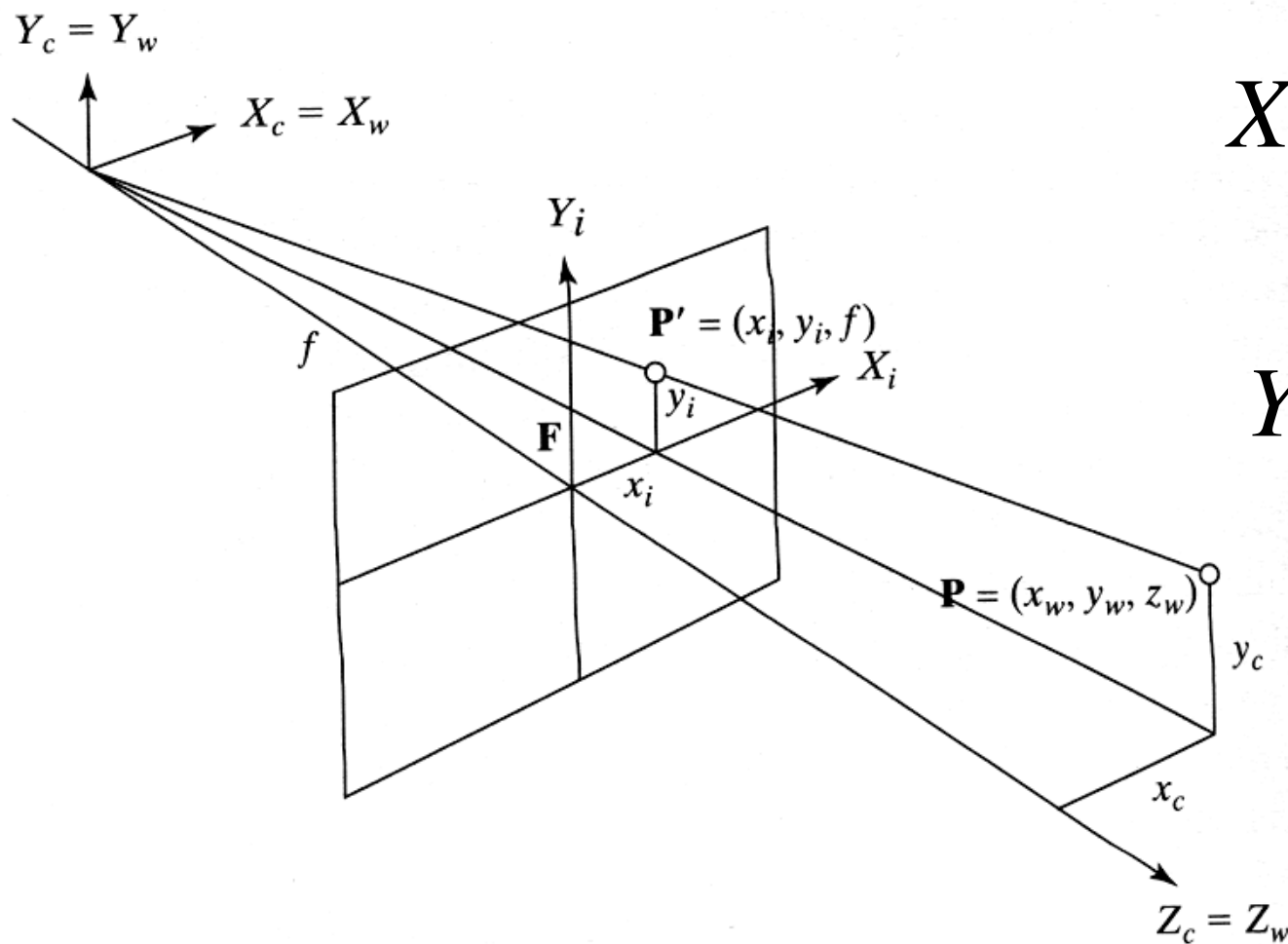
- The center of the projection coincides with the origin of the world.
- The camera axis (optical axis) is aligned with the world's z-axis.
- To avoid image inversion, the image plane is in front of the center of projection.



$$X_f / f = X_c / Z_c$$

$$X_f = f \frac{X_c}{Z_c}$$

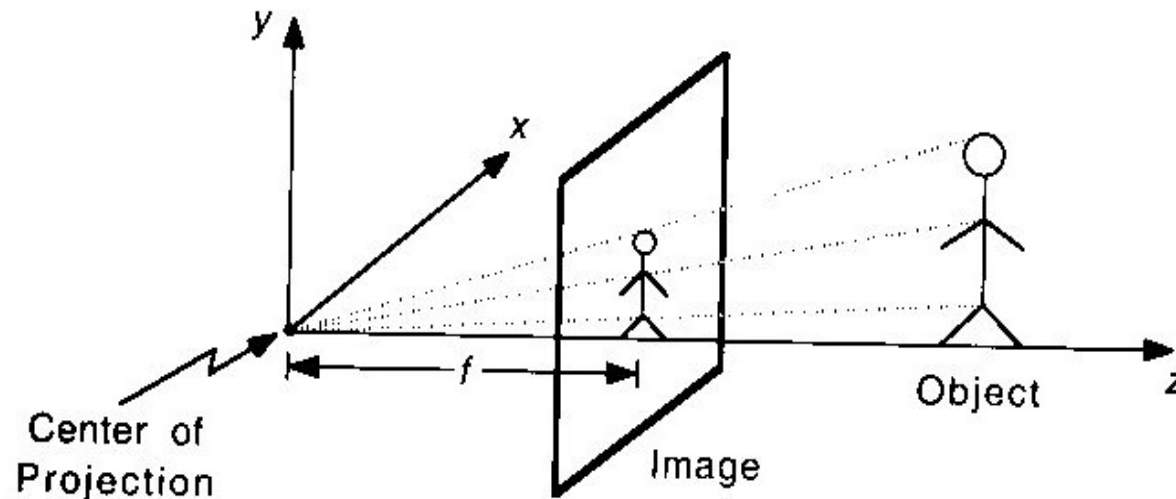
2D IMAGE



$$X_i = f \frac{X_c}{Z_c}$$

$$Y_i = f \frac{Y_c}{Z_c}$$

PROJECTION IS NON LINEAR



$$u = X_i = f \frac{X_c}{Z_c}$$

$$v = Y_i = f \frac{Y_c}{Z_c}$$

→ Reformulate it as a linear operation.

VANISHING POINTS



- The projections of parallel lines all meet at one point, called the vanishing point.
- As focal length and distance to camera increase, the image remains the same size but perspective effects diminish.

HOMOGENEOUS COORDINATES



Homogeneous representation of 2D point:

$$\mathbf{x} = (x_1, x_2, x_3) \text{ represents } \left(\frac{x_1}{x_3}, \frac{x_2}{x_3} \right)$$

Homogeneous representation of 3D point:

$$\mathbf{x} = (x_1, x_2, x_3, x_4) \text{ represents } \left(\frac{x_1}{x_4}, \frac{x_2}{x_4}, \frac{x_3}{x_4} \right)$$

→ **Projections become linear transformations.**

SIMPLE PROJECTION MATRIX

$$\begin{bmatrix} x \\ y \\ z \end{bmatrix} = \begin{bmatrix} f & 0 & 0 & 0 \\ 0 & f & 0 & 0 \\ 0 & 0 & 1 & 0 \end{bmatrix} \begin{bmatrix} X_c \\ Y_c \\ Z_c \\ 1 \end{bmatrix} \quad \text{with } X_i = \frac{x}{z} = f \frac{X_c}{Z_c} \text{ and } Y_i = \frac{y}{z} = f \frac{Y_c}{Z_c}$$

$$= \begin{bmatrix} f & 0 & 0 \\ 0 & f & 0 \\ 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} 1 & 0 & 0 & 0 \\ 0 & 1 & 0 & 0 \\ 0 & 0 & 1 & 0 \end{bmatrix} \begin{bmatrix} X_c \\ Y_c \\ Z_c \\ 1 \end{bmatrix}$$

INTRINSIC AND EXTRINSIC PARAMETERS



- Camera may not be at the origin, looking down the z-axis
→ Extrinsic parameters
- One unit in camera coordinates may not be the same as one unit in world coordinates
→ Intrinsic parameters

$$\begin{pmatrix} x \\ y \\ z \end{pmatrix} = \begin{pmatrix} \text{Transformation} \\ \text{representing} \\ \text{intrinsic parameters} \end{pmatrix} \begin{pmatrix} 1 & 0 & 0 & 0 \\ 0 & 1 & 0 & 0 \\ 0 & 0 & 1 & 0 \end{pmatrix} \begin{pmatrix} \text{Transformation} \\ \text{representing} \\ \text{extrinsic parameters} \end{pmatrix} \begin{pmatrix} X \\ Y \\ Z \\ 1 \end{pmatrix}$$

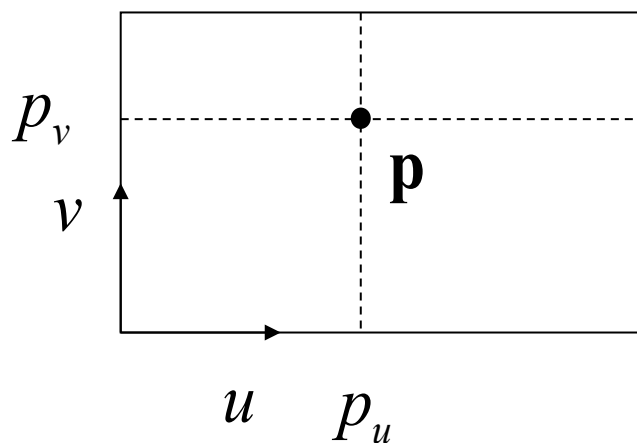
LINEAR CAMERA MODEL



$$\begin{pmatrix} x \\ y \\ z \end{pmatrix} = \begin{pmatrix} \text{Transformation} \\ \text{representing} \\ \text{intrinsic parameters} \end{pmatrix} \begin{pmatrix} 1 & 0 & 0 & 0 \\ 0 & 1 & 0 & 0 \\ 0 & 0 & 1 & 0 \end{pmatrix} \begin{pmatrix} \text{Transformation} \\ \text{representing} \\ \text{extrinsic parameters} \end{pmatrix} \begin{pmatrix} X \\ Y \\ Z \\ 1 \end{pmatrix}$$
$$= \mathbf{K} \begin{pmatrix} 1 & 0 & 0 & 0 \\ 0 & 1 & 0 & 0 \\ 0 & 0 & 1 & 0 \end{pmatrix} \mathbf{Rt} \begin{pmatrix} X \\ Y \\ Z \\ 1 \end{pmatrix},$$

where \mathbf{K} is a 3x3 matrix and \mathbf{Rt} a 4x4 matrix.

PRINCIPAL POINT



$$u = X_i + p_u = fX / Z + p_u$$

$$v = Y_i + p_v = fY / Z + p_v$$

$$\mathbf{K} = \begin{bmatrix} f & p_u \\ & f & p_v \\ & & 1 \end{bmatrix}$$

INHOMOGENEOUS SCALING



$$u = \alpha_u X_i + p_u = \alpha_u X / Z + p_u$$

$$v = \alpha_v Y_i + p_v = \alpha_v Y / Z + p_v$$

$$\mathbf{K} = \begin{bmatrix} \alpha_u & & p_u \\ & \alpha_v & p_v \\ & & 1 \end{bmatrix}$$

The pixels are not necessarily square.

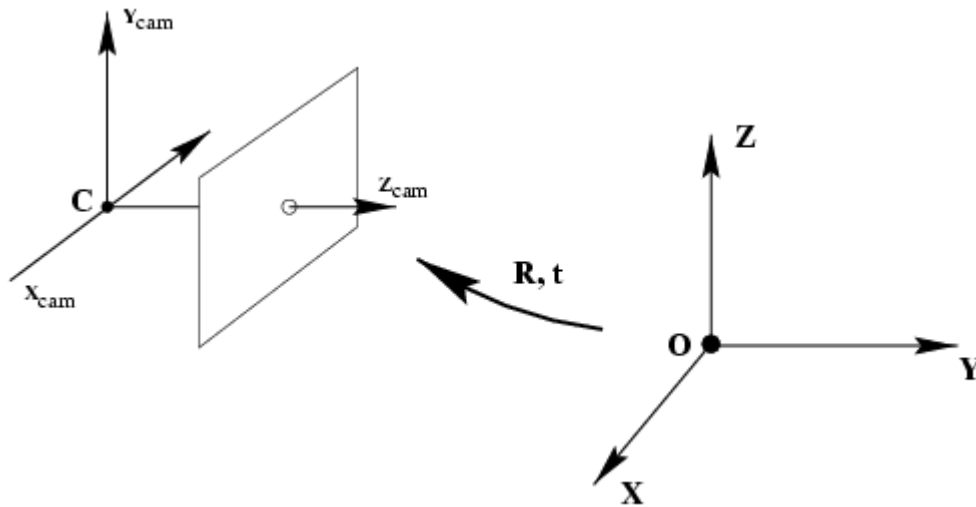
AXIS SKEW



$$\mathbf{K} = \begin{bmatrix} \alpha_u & s & p_u \\ & \alpha_v & p_v \\ & & 1 \end{bmatrix}$$

s encodes the non-orthogonality of the u and v directions. Very close to zero in modern cameras.

ROTATION / TRANSLATION



$$\begin{bmatrix} X_c \\ Y_c \\ Z_c \end{bmatrix} = \mathbf{R} \begin{bmatrix} X_w \\ Y_w \\ Z_w \end{bmatrix} - \tilde{\mathbf{C}} \quad \text{with } \mathbf{R}^t \mathbf{R} = \mathbf{I}$$
$$\begin{bmatrix} X_c \\ Y_c \\ Z_c \\ 1 \end{bmatrix} = \begin{bmatrix} \mathbf{R} & \mathbf{T} \\ 0 & 1 \end{bmatrix} \begin{bmatrix} X_w \\ Y_w \\ Z_w \\ 1 \end{bmatrix} \quad \text{with } \mathbf{T} = -\mathbf{R}\tilde{\mathbf{C}}$$

→ Rotations and translations also expressed in terms of matrix multiplications in projective space.

FULL PROJECTION MATRIX

$$\begin{bmatrix} x \\ y \\ z \end{bmatrix} = \begin{bmatrix} \alpha_u & s & p_u \\ 0 & \alpha_v & p_v \\ 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} 1 & 0 & 0 & 0 \\ 0 & 1 & 0 & 0 \\ 0 & 0 & 1 & 0 \end{bmatrix} \begin{bmatrix} \mathbf{R} & \mathbf{T} \\ 0 & 1 \end{bmatrix} \begin{bmatrix} X \\ Y \\ Z \\ 1 \end{bmatrix} \text{ with } \mathbf{T} = -\mathbf{R}\tilde{\mathbf{C}} \text{ and } \mathbf{R}^t \mathbf{R} = \mathbf{I}$$

$$= \begin{bmatrix} p_{11} & p_{12} & p_{13} & p_{14} \\ p_{21} & p_{22} & p_{23} & p_{24} \\ p_{31} & p_{32} & p_{33} & 1 \end{bmatrix} \begin{bmatrix} X \\ Y \\ Z \\ 1 \end{bmatrix}$$

$$\mathbf{x} = \mathbf{K}[\mathbf{R} \mid -\mathbf{R}\tilde{\mathbf{C}}]\mathbf{X} = \mathbf{K}\mathbf{R}[\mathbf{I} \mid -\tilde{\mathbf{C}}]\mathbf{X} = [\mathbf{M} \mid \mathbf{m}]\mathbf{X} = \mathbf{P}\mathbf{X}$$

CAMERA CALIBRATION



Internal Parameters:

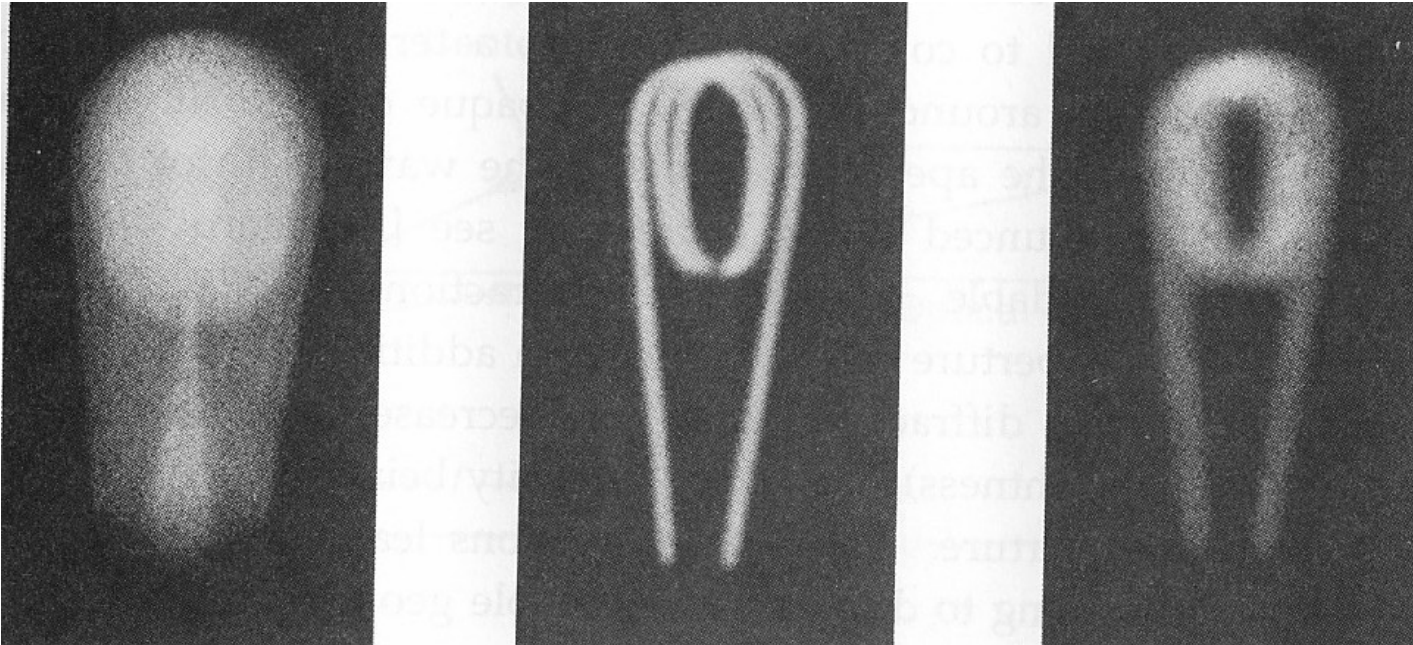
- Horizontal and vertical scaling (2)
- Principal points (2)
- Skew of the axis (1)

External Parameters:

- Rotations (3)
- Translations (3)

→ 11 free parameters.

LIMITATIONS

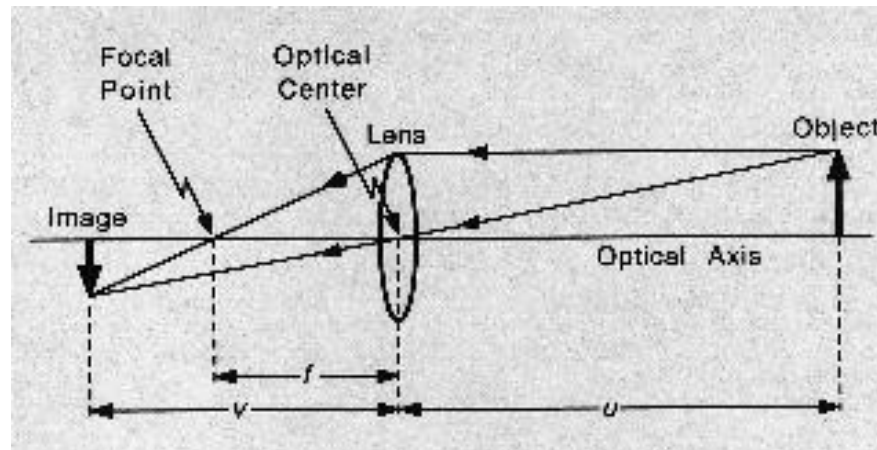


Idealization because the hole cannot be infinitely small

- Image would be infinitely dim
- Diffraction effects

→ Use of Lenses.

IMAGING WITH A LENS



Thin lens Equation:

$$\frac{1}{u} + \frac{1}{v} = \frac{1}{f}$$

→ Lens with focal distance f equivalent to pinhole camera with similar focal distance but larger aperture.

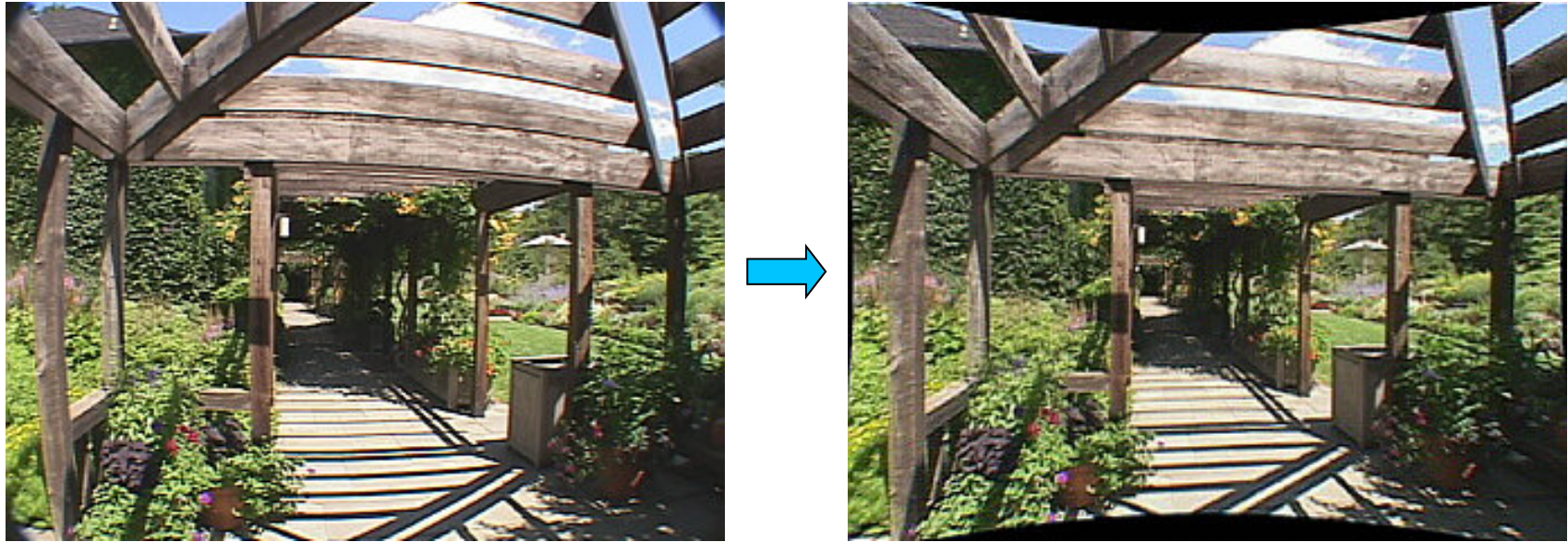
DISTORTIONS



The lens is not exactly a “thin lens:”

- Different wave lengths refracted differently
- Barrel Distortion

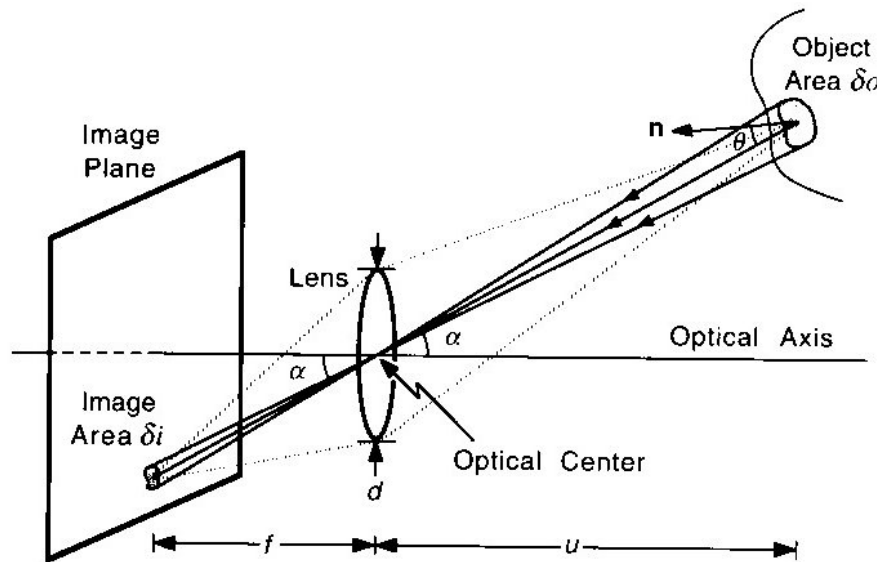
UNDISTORTING



Once the image is undistorted, the camera projection can be formulated as a projective transform.

→ The pinhole camera model applies.

RADIOMETRY



Scene Radiance: Amount of light radiation from a surface point (Watt / m² / Steradian)

Image Irradiance: Amount of light incident at the image of the surface point. (Watt / m²)

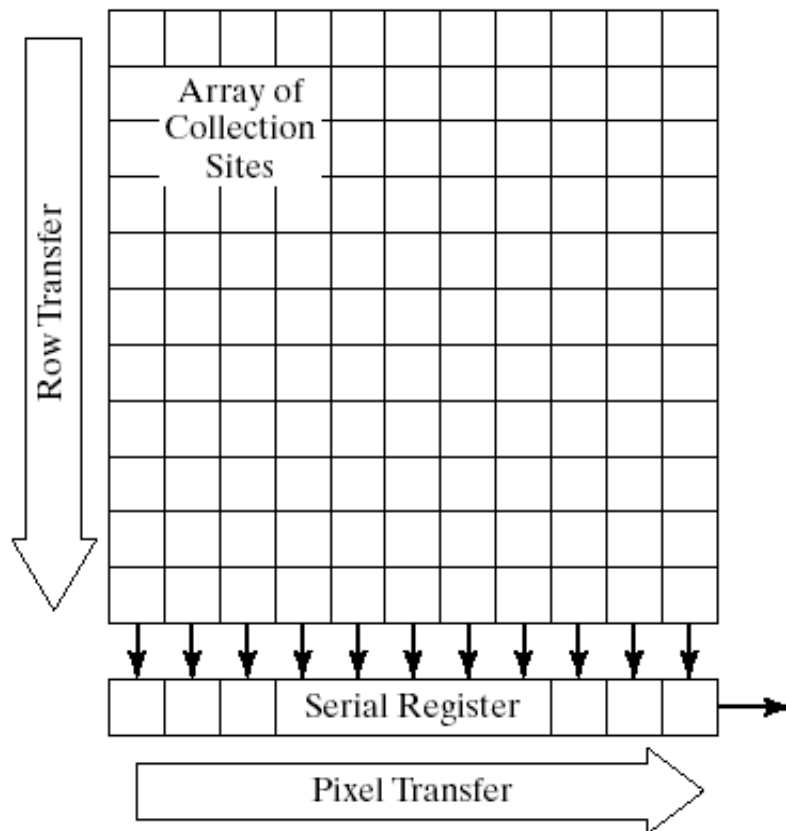
Fundamental Radiometric Equation:

$$Irr = \frac{\pi}{4} \left(\frac{d}{f} \right)^2 \cos^4(\alpha) Rad$$

DE VIGNETTING

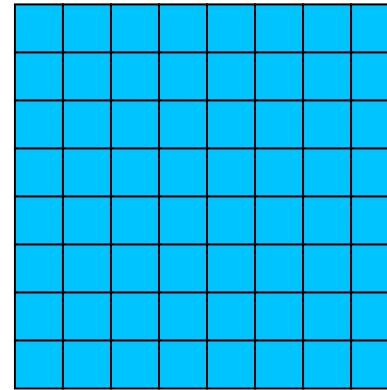
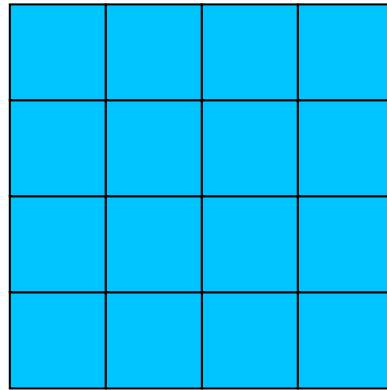


SENSOR ARRAY



- Photons free up electrons that are then captured by a potential well.
- Charges are transferred row by row wise to a register.
- Pixel values are read from the register.

SENSING



Conversion of the “optical image” into an “electrical image”:

$$E(x, y) = \iint \text{Irrad}(x, y, t, \lambda) s(\lambda) \tau(t - t_0) d\lambda dt$$

$$I(m, n) = \text{Quantize}(\iint E(x, y) \omega(x - m, y - n) dx dy)$$

→ Quantization in

- Time
- Space

IN SHORT



- Camera geometry can be modeled in terms of the pinhole camera model, which is linear in projective space.
- Image radiance is roughly proportional to surface radiance and the two can be used interchangeably for our purposes.