3D reconstruction from correspondences derived from perceived motion

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**Abstract**. 3D reconstruction from image pairs taken from different camera perspectives relies on finding corresponding points between the images and using those corresponding points to estimate a dense disparity map. Today's correspondence finding algorithms primarily use image features or pixel intensities common between image pairs. Some 3D computer vision applications, however, don't produce the desired results using correspondences derived from image features or pixel intensities. Two examples are the multimodal camera rig and the center region of a coaxial camera rig. In this paper we present an image correspondence finding technique that aligns image sequences using optical flow fields. Our method applies to applications where there is inherent motion between the camera rig and the scene and where the scene has enough visual texture to produce optical flow. We apply the technique to a traditional binocular stereo rig consisting of an RGB/IR camera pair and to a coaxial camera rig. We present results for synthetic flow fields and for real images sequences. With real image sequences we achieve flow field alignment of better than 1/10 of a pixel and reconstruction of relative camera/scene velocity of ??.

**Keywords**: image correspondence finding, 3D reconstruction, stereo endoscope, stereo borescope, multi-modal, graph cuts.

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# 1 Introduction

Finding corresponding points in image pairs taken from two different perspectives is one of the most active areas of research in computer vision [10, 18, 20]. It forms the basis of 3D reconstruction as well as being a critical component of many other computer vision and image processing applications that require pixel by pixel alignment between image pairs [9, 26].

Existing correspondence finding techniques are based on matching pixel intensity values or features which are derived from pixel intensity values. This, in turn, allows the estimation of dense disparity maps which, given the camera geometry, allows the estimation of dense depth maps. Where image registration is the ultimate goal, the correspondences provide the geometrical transformations that allows one image, the sensed image, to be transformed into the second image, the reference image.

There are computer vision applications, however, where traditional correspondence finding techniques do not produce the desired results. Two notably cases are multimodal camera rigs where the images produced from different sensor types are not similar enough to be aligned using pixel intensities or features [26] and the center region of a coaxial camera rig [17] where the disparity is too small to produce good triangulation. There are also multi-camera applications where it is desirable to augment the use of pixel intensities and/or image features to improve the finding of intra-camera correspondences.

In this paper we introduce a novel automated method for finding correspondences using the optical flow fields from two cameras. We apply the technique to images acquired by a multimodal stereo rig where one camera contains an RGB sensor and the other camera contains an IR sensor, as well as to a coaxial camera rig. In applications where there is sufficient motion between the camera rig and the scene (scanning security camera, camera mounted on a vehicle, endoscope, etc.) and where the scene exhibits enough texture to produce optical flow, our method finds correspondences between multi-view image sequences without using intra-camera pixel intensities or features. From these correspondences we estimate dense disparity maps with accuracies similar to, and in certain cases, substantially better than, techniques that align images based on image features or pixel intensities.

# 2 Related Work

## 2.1 Multimodal Binocular Stereo

Aligning images from stereo rigs consisting of cameras with multimodal sensors has been an active research area for the last decade and a half. Initially inspired by the work done to match medical images to models [23] it has more recently been motivated by the need for surveillance systems that use a combination of visible light and infrared cameras to detect targets. As noted by Yaman and Kalkan [24], traditional image alignment techniques used in stereo vision are not applicable to multimodal camera rigs because the pixel intensities can be substantially different in a visible light image vs. an IR image. Solutions to the multimodal problem fall into two broad categories. The first uses Mutual Information (MI). MI was original proposed by Viola and Wells [23] to match medical images to models. To our knowledge, Egnal [5] was the first to use MI as a similarity measure to match multimodal stereo images. Since then, numerous improvements have been made including adaptive windowing [6], incorporating prior probabilities [7], regions of interest [12-14], and extending MI using gradient information [4].

More recently, local self similarity (LSS), originally used in template matching, was proposed for use in a multimodal camera rig [21]. Most recently Yaman and Kalkan [24] used MI to generate dense disparity maps from multimodal camera rigs.

The method we present avoids using visual similarity measures between the images from the two different sensor types by computing the optical flow fields from the two sensors and then aligning the flow fields. This permits images with no common features to be aligned as long as there is motion between the camera and the scene and the scene has enough texture to produce optical flow.

Verri and Poggio [22] have shown that in many cases optical flow is not equivalent to the motion field. While optical flow algorithms have improved substantially since the Verri and Poggio paper (see [19] and [3] for summaries of the progression of optical flow algorithm development); optical flow errors caused by the aperture problem, non-Lambertian surfaces, and non-uniform changing illumination, still exist.

For finding image correspondences, however, the optical flow fields do not need to be equivalent to the motion fields. For example, errors caused by the aperture problem where only the motion tangential to edges is detected or errors caused by moving shadows, will be perceived by the two sensors identically and alignment is unaffected. The primary requirement is that the optical flow computation be invariant to different light wavelengths.

(a)

(b)

Fig. 1 Multimodal camera rig image pair: (a) IR and (b) RGB.

## 2.2 Depth from Zooming - Coaxial Camera

Depth from images taken at different focal lengths along a common optical axis was first proposed by Ma and Olsen [17]. Lavest et al. [16, 15] provide a proof for inferring 3D data from images taken at multiple focal lengths and models a revolving object. Asada et al. [1] and Baba et al. [2] present a method for doing 3D reconstruction using blur from zoom. Gao et al. [8] present a distance measurement system for mobile robots using zooming. Most recently, Zhang and Qi [25] describe a method for 3D reconstruction from multi-focal length images using a snake-search algorithm.

The primary reason researchers have focused on using a single camera at different focal lengths to do 3D reconstruction has been cost. However, there are several other advantages. Ma and Olsen alluded to the fact that a depth from zoom camera exhibits substantially smaller occlusions than an equivalent binocular stereo camera rig. Additionally, there are applications where a stereo baseline is prohibitive (endoscope or bore scope) and where the known correspondence point on the optical axis is an advantage to image registration. Finally, where image registration is the ultimate objective of the application (e.g. alignment of images from two different types of sensors without attempting 3D reconstruction), a coaxial camera produces substantially smaller disparity errors than a binocular stereo rig.

The coaxial camera rig [11] is equivalent to simultaneous depth from zooming, but instead of changing the focal length of a single fixed camera, two cameras are arranged such that the cameras form images along the same optical axis. This is done by splitting the optical path with a beam splitter and aligning the two cameras such that their optical centers image the same point in the 3D scene. The coaxial camera rig combined with image correspondences derived from perceived motion overcomes the two main problems of depth from zooming. First, simultaneous images taken at two different focal lengths overcomes the stationary scene constraint of depth from zooming. Second, using the flow field to align image pairs overcomes the unrecoverable point problem in the center region described by Ma and Olsen. This later advantage is due to the depth estimate being derived from the ratio of the flow fields taken at different focal lengths as opposed to the extremely small disparities found in the center region of a coaxial camera rig.

# 3 Energy Formulation

Make some comments here about relating the flow from one camera to the flow from the other camera and that we will show how this is done for two camera rig types.

## 3.1 Binocular Stereo

Referring to Figure 2, let , represent points in the image domain of the left and right cameras. Let the disparity between and such that and represent the same point in the scene. Let the focal lengths of the cameras and the distance between the optical center of the left camera and a point in the scene corresponding to at time and , the distance being measured along the optical axis. is then the difference along the Z axis for each point between and . the distance from the optical axis to a point in the scene and the change in the distance from the optical axis between time and . the stereo baseline. the projection of the 3D motion (the ideal flow) of point in the scene onto the image planes in the left and right cameras.

Using the projection equation to project the start point ( and end point ( of a point in the scene onto points in the image planes of each camera gives:

(1)

(2)

Where the second subscript of the points in the image plane represents the start or end of the projected motion.

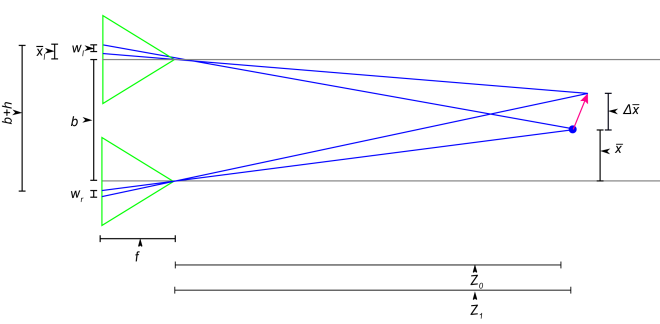


Fig. 2 Binocular stereo camera rig geometry.

Solving for the ratio of the two flows at corresponding points gives:

(3)

where:

(4)

has a physical interpretation. From equation (4) it can be seen that if . Referring to Figure 3, one can see that a change in Z introduces a slight parallax () in the finishing points of the optical flow detected by the two cameras along the image axis. compensates for this parallax and can be solved for directly from the camera geometry.

The first term in our variational model is an optical flow matching term:

(5)

The second term is a smoothness term:

(6)

The total energy that we want to minimize is:

(7)

where and are tuning constants.

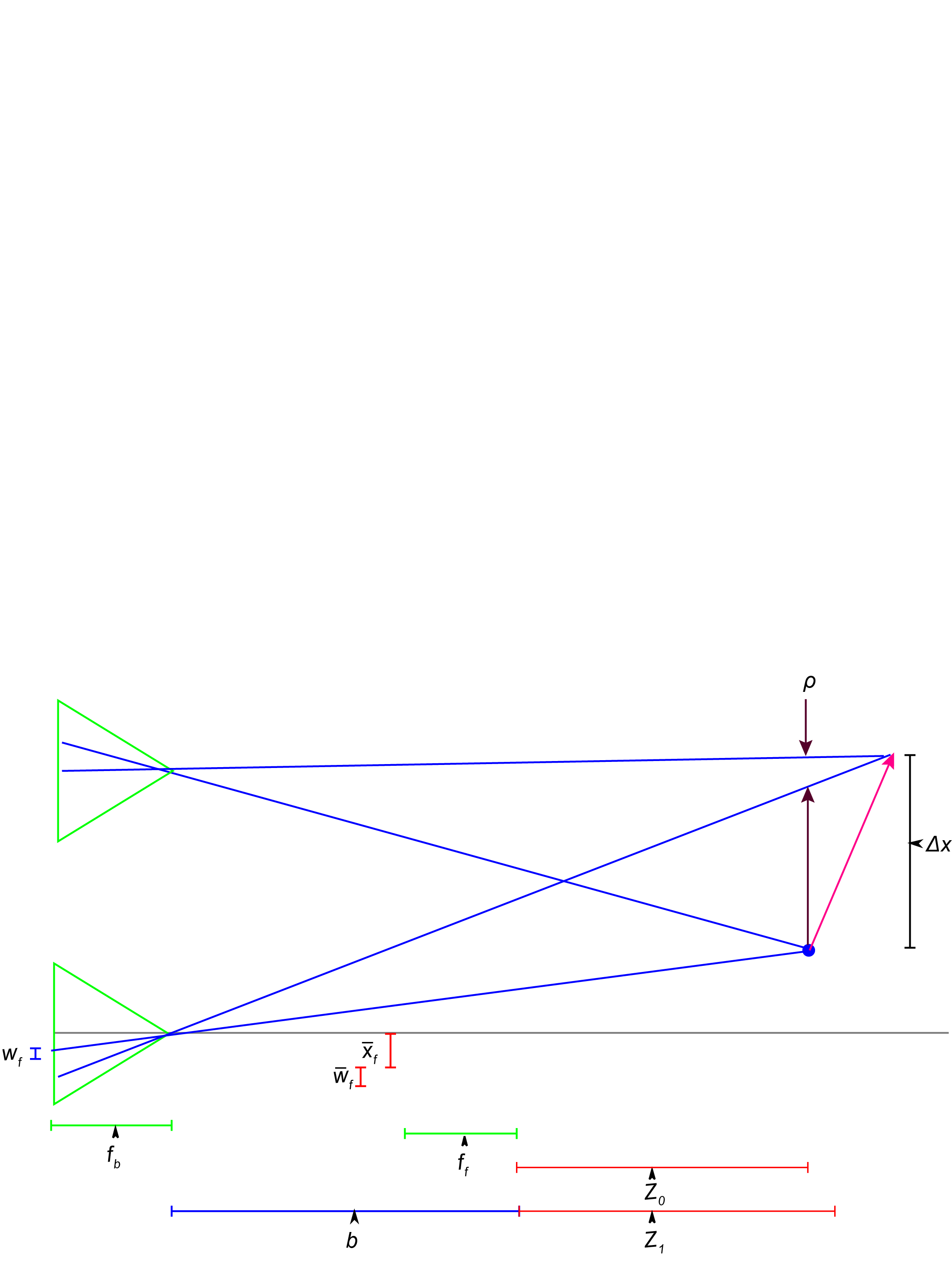


Fig. 3 Parallax caused by start and end points having a different depth.

## 3.2 Coaxial Camera Rig

Referring to Figure 1, let , represent points in the image domain of the front and back cameras. Let the disparity between and such that and represent the same point in the scene. Let the focal lengths for the front camera and back cameras and the distance between the optical center of the front camera and a point in the scene corresponding to , the distance being measured along the optical axis. the distance between the optical center of the two cameras. the projection of the 3D motion field onto the image planes of the front and back cameras respectively.

# Figure3

Fig. 4 Coaxial camera rig geometry.

Using the projection equation to project the start point ( and end point ( of a point in the scene onto points in the image planes of each camera gives:

(1)

(2)

Where the second subscript of the points in the image plane represents the start or end of the projected motion.

Solving equations (1) and (2) for and setting them equal to each other gives:

(3)

where:

(4)

and

(5)

has a direct physical interpretation. From (5), it can be seen that if or when . Referring to Figure 2 one can see that a change in Z introduces a slight parallax () in the finishing points of the optical flow detected by the two cameras. corrects for the parallax and can also be solved for directly from the coaxial camera geometrically.

The first term in our coaxial camera variational model is an optical flow matching term:

(6)

The second term is a smoothness term:

(7)

The total energy that we want to minimize is:

(8)

where and are tuning constants.

# 4 Numerical Solution

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Authors may use this Microsoft (MS) Word template by employing the relevant styles from the Styles and Formatting list (which is accessed from the Styles group in the Home ribbon, Fig. 1):

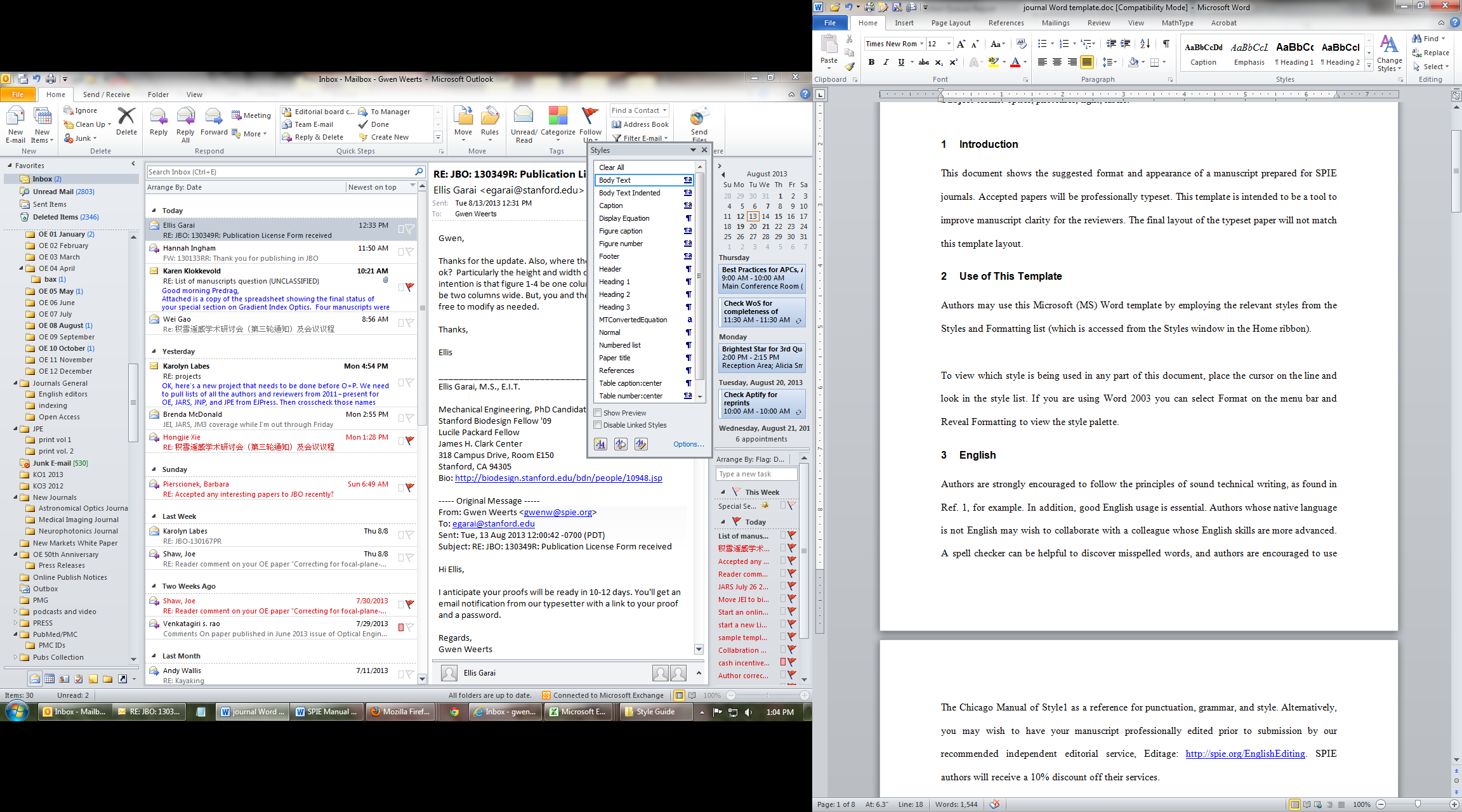


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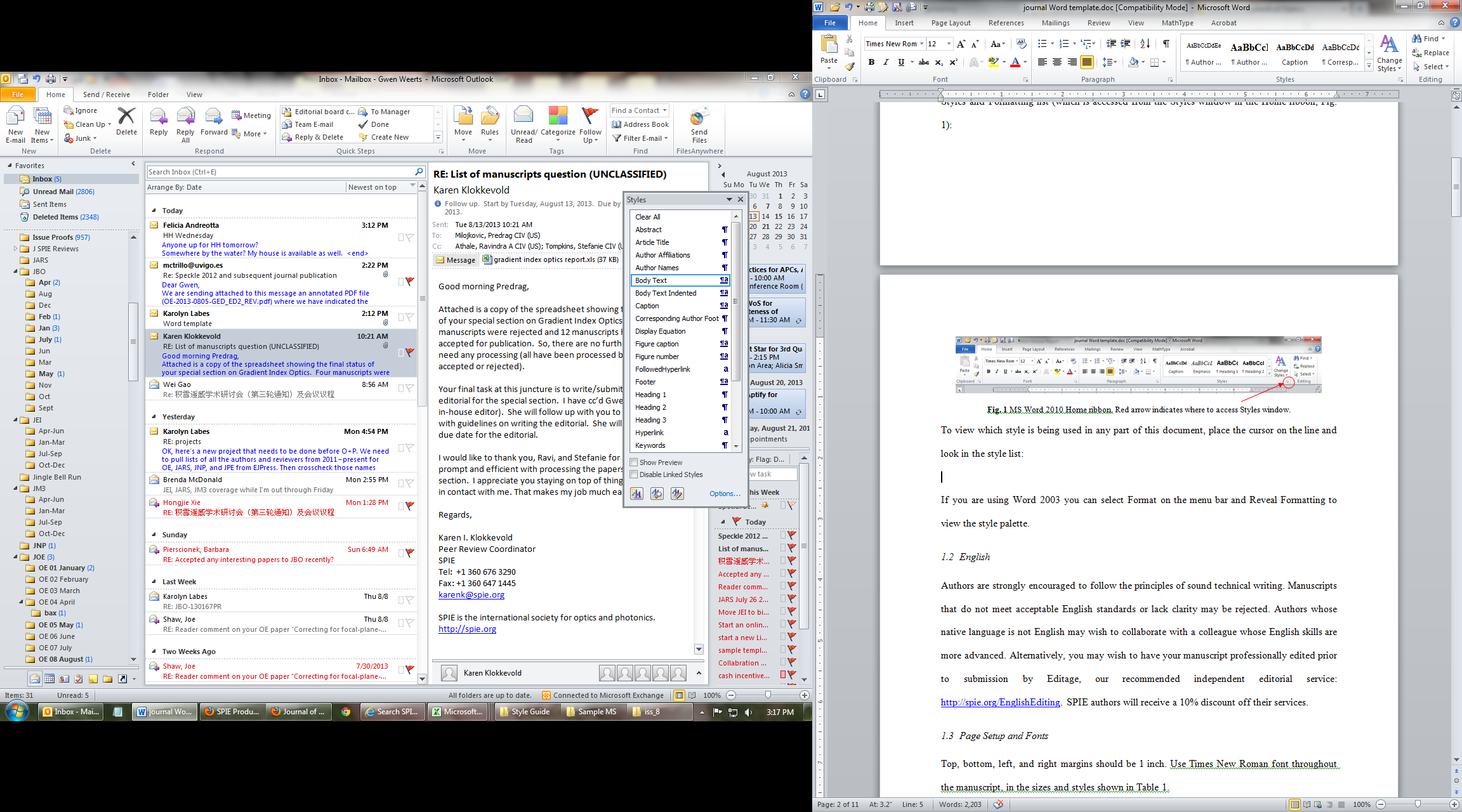


Fig. 2 Styles window.

If you are using Word 2003 you can select Format on the menu bar and Reveal Formatting to view the style palette.

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Top, bottom, left, and right margins should be 1 inch. Use Times New Roman font throughout the manuscript, in the sizes and styles shown in Table 1.

**Table 1** Recommended fonts and sizes.

|  |  |
| --- | --- |
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## 2.2 Abstract

The abstract should be a summary of the paper and not an introduction. Because the abstract may be used in abstracting journals, it should be self-contained (i.e., no numerical references) and substantive in nature, presenting concisely the objectives, methodology used, results obtained, and their significance. It should be 200 words, maximum. For further guidelines, please read the brief article titled "[How to Write an Abstract (PDF)](http://spie.org/Documents/Publications/How%20to%20Write%20an%20Abstract.pdf)," by Philip Koopman. (Courtesy of Philip Koopman, Carnegie Mellon University.)

## 2.3 Subject Terms/Keywords

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## 2.4 Body of Paper

The body of the paper consists of numbered sections that present the main findings. These sections should be organized to best present the material.

It is often important to refer back (or forward) to specific sections. Such references are made by indicating the section number, for example, “In Sec. 2 we showed…” or “Section 2.1 contained a description….” If the word Section, Reference, Equation, or Figure starts a sentence, it is spelled out. When occurring in the middle of a sentence, these words are abbreviated Sec., Ref., Eq., and Fig.

At the first occurrence of an acronym, spell it out followed by the acronym in parentheses, e.g., charge-coupled diode (CCD).

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Use textual footnotes only when necessary to present important documentary or explanatory material whose inclusion in the text would be distracting.[[1]](#footnote-1)

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Type each section heading on a separate line using the appropriate style from the style list. Sections should be numbered sequentially.

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### 3.1.1 Sub-subsection headings (Heading 3)

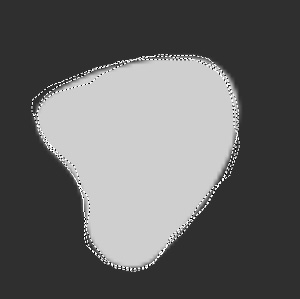
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sy00590_

(b)

(a)

Fig. 3 Example of a figure caption: (a) sun and (b) blob.

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Video 1 Example of a multimedia still image (MPEG, 2.5 MB).

# Appendix A: Miscellaneous Formatting Details

## A.1 Formatting Equations

Equations may appear inline with the text, if they are simple, short, and not of major importance; e.g., a = b/c. Important equations appear on their own line. For example, “The expression for the field of view is

, (1)

where *a* is the …” Principal equations are numbered, with the equation number placed within parentheses and right justified. Authors are strongly encouraged to use MS Word Equation Editor or MathType to create both in-text and display equations. Equations are considered to be part of a sentence and should be punctuated accordingly.

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To include theorems in a formal way, the theorem identification should appear in a 10-pt, bold font, left justified and followed by a period. Formal statements of lemmas and algorithms receive a similar treatment. The text of the theorem continues on the same line in normal, 10-pt font. For example,

**Theorem 1.** For any unbiased estimator…

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## Acknowledgments

This unnumbered section is used to identify people who have aided the authors in accomplishing the work presented and to acknowledge sources of funding.

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Biographies and photographs for the other authors are not available.

**Caption List**

Fig. 1 MS Word 2010 Home ribbon. Red arrow indicates where to access Styles window.

**Fig. 2** Styles window.

**Fig. 3** Example of a figure caption: (a) sun and (b) blob.

Video 1 Example of a multimedia still image (MPEG, 2.5 MB).

**Table 1** Recommended font sizes and styles.

[1] N. Asada, m. Baba, and A. Oda, "Depth from Blur by Zooming," in *Proceedings of the Vision Interface Annual Conference*, Ottawa, Canada, 2001.

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1. Due to problems with HTML display, use of footnotes should be avoided. If absolutely necessary, the footnote mark must come at the end of a sentence. To insert a footnote, use the Insert menu, select Reference, then Footnote, change the number format to the style of asterisk, dagger, double-dagger, etc., and click OK. [↑](#footnote-ref-1)