Computer Vision II: Multiple View Geometry (IN2228)

Chapter 06 2D-2D Geometry
(Part 1 Overview and Fundamentals)

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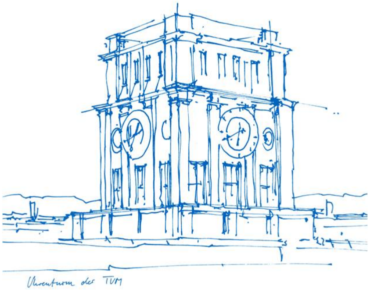


Outline

- Overview of 2D-2D Geometry
- Two-view Geometric Constraints
- Eight-point Method

Overview of Two-view Geometry

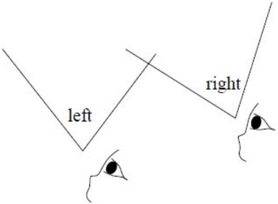
➢ Intuitive Illustration

✓ Camera pose estimation

We can easily imagine that the image A is obtained by the left camera (eye) and image B is obtained by the right camera (eye).

Image A

Image B



Camera motion can be inferred from two consecutive image frames.

Overview of Two-view Geometry

2D Motion → pixel shifted
contain 3D Rotation/T

➢ Intuitive Illustration

✓ Camera pose estimation

We infer the camera motion from some object **correspondences**. Objects can be further abstracted by points and lines.

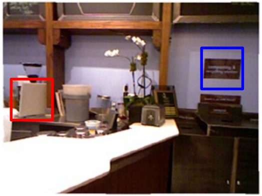


Image A

Image B

Image A

Image B

Object correspondences

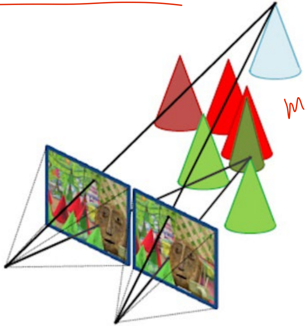
Point correspondences

Overview of Two-view Geometry

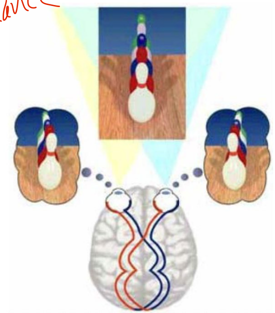
➢ Intuitive Illustration

✓ 3D reconstruction

measure the distance



3D perception from two human eyes



Two human eyes

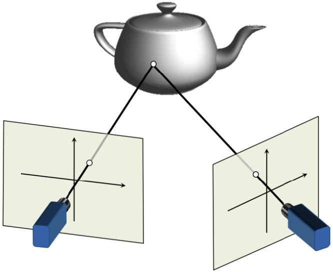
Brain

Overview of Two-view Geometry

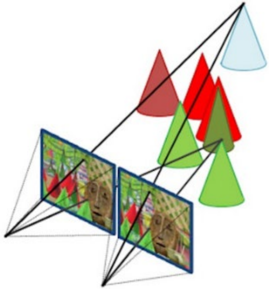
➢ Intuitive Illustration

✓ 3D reconstruction

Given a pair of 2D points in two images, the 3D point's position in space is found as the intersection of the two projection rays.



Triangulation



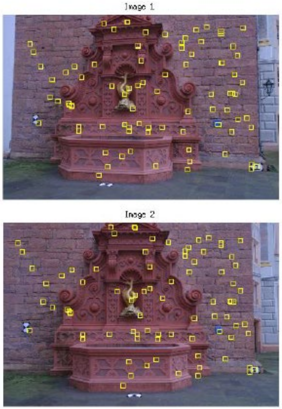
Depth from disparity

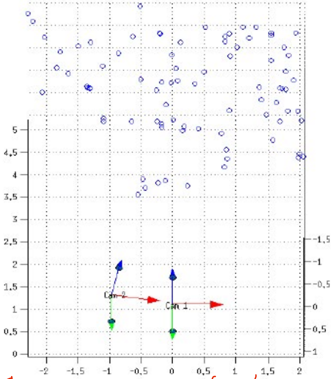
Overview of Two-view Geometry

➤ Problem Formulation

First get

⇒ 2D-2D point correspondence





Then use a set of correspondence

Estimated poses and 3D structure

Overview of Two-view Geometry

➢ Problem Formulation

? 我们能否独立于三维点的估计而解决相对运动的估计（RR,TT）？ 是的!接下来的几张幻灯片证明了这是可能的。

? 一旦（RR,TT）被知道，三维点就可以用三角化算法（即最小平方近似加重投影误差最小化）进行三角化。

✓ Can we solve the estimation of relative motion (R,T) independently of the estimation of the 3D points? Yes! The next couple of slides prove that this is possible.

✓ Once (R,T) are known, the 3D points can be triangulated using the triangulation algorithm (i.e., least square approximation plus reprojection error minimization)

$\boxed{P_i = ?}$ points

R,T camera pose

$\boxed{K_1, R_1, T_1 = ? \quad K_2, R_2, T_2 = ?}$

=

First step

unknown

$\boxed{K_1, R_1, T_1 = ? \quad K_2, R_2, T_2 = ?}$

+

Second step $\boxed{P_i = ?}$

unknown

known.

$\boxed{K_1, R_1, T_1 \quad K_2, R_2, T_2}$

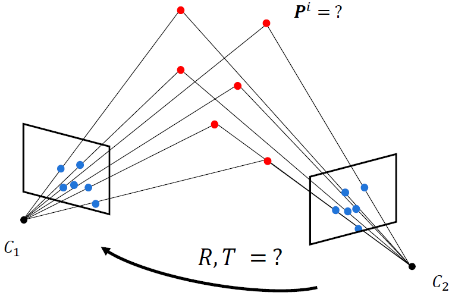
Overview of Two-view Geometry

➢ Problem Formulation

unknown dof: scale

✓ Recover simultaneously 3D scene structure and camera poses (up to scale) from two images. (More specifically, camera pose first, followed by 3D structure.)

✓ Intrinsic parameters of camera is known from calibration. We can also handle uncalibrated case.



Overview of Two-view Geometry

➢ Problem Formulation

✓ Given a set of n point correspondences $\{p^i{}_1 = (u^i{}_1, v^i{}_1),\ p^i{}_2 = (u^i{}_2, v^i{}_2)\}$ between two images, where i = 1 … n, the goal is to simultaneously

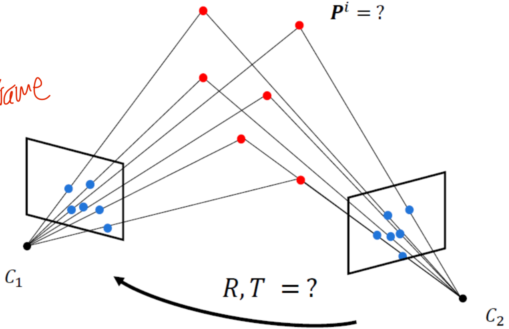
- estimate the 3D points $\boldsymbol{P}^i$ and
- the camera relative-motion parameters ($\boldsymbol{R}$, $\boldsymbol{T}$)

$$\lambda_1^i \begin{bmatrix} u^i{}_1 \\ v^i{}_1 \\ 1 \end{bmatrix} = K_1 [I|0] \cdot \begin{bmatrix} X^i{}_w \\ Y^i{}_w \\ Z^i{}_w \\ 1 \end{bmatrix}$$

$$\lambda_2^i \begin{bmatrix} u^i{}_2 \\ v^i{}_2 \\ 1 \end{bmatrix} = K_2 [R|T] \cdot \begin{bmatrix} X^i{}_w \\ Y^i{}_w \\ Z^i{}_w \\ 1 \end{bmatrix}$$

Talk in left camera frame

Perspective projection



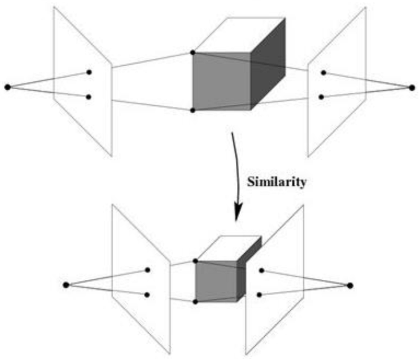
Overview of Two-view Geometry

➢ Scale Ambiguity

2 DoF = loss scale

If we rescale the entire scene and camera views, the projections (in pixels) of the scene points in both images remain exactly the same:

如果我们重新缩放整个场景和摄像机视图，两幅图像中的场景点的投影（以像素为单位）保持完全相同：



- Reduce the size of 3D object: smaller projection

- 缩小三维物体的尺寸：更小的投影

- Reduce the distance from camera to 3D object: bigger projection

- 缩小相机与3D物体的距离：更大的投影

- **Simultaneously** reduce the size of 3D object and reduce the distance from camera to 3D object?

- 同时缩小三维物体的尺寸和减少摄像机到三维物体的距离?

Overview of Two-view Geometry

➢ Scale Ambiguity

✓ For monocular case, it is not possible to recover the absolute scale of the scene.

✓ Thus, only 5 degrees of freedom are measurable:

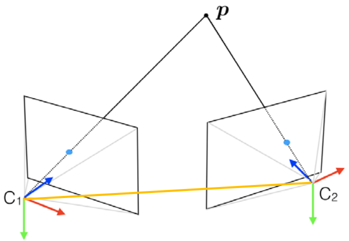
- Three parameters to describe the rotation
- Two parameters for the parameters for the translation up to a scale (we can only compute the direction of translation but not its length)

对于单眼的情况，不可能恢复场景的绝对比例。

因此，只有5个自由度是可以测量的：

- 三个参数来描述旋转

- 两个参数用于描述平移到一个尺度的参数（我们只能计算平移的方向，但不能计算其长度）



Overview of Two-view Geometry

➢ Number of Point Correspondences

✓ $\boldsymbol{4n}$ knowns:

- n correspondences; each one $(u^i{}_1, v^i{}_1)$ and $(u^i{}_2, v^i{}_2)$, i=1…n

✓ $\boldsymbol{5+3n}$ unknowns

- 5 for the motion up to a scale (3 for rotation, 2 for translation)
- $3n$ is number of coordinates of n 3D points (*x, y, z*)

✓ If and only if the number of independent equations ≥ number of unknowns

$$4n \geq 5 + 3n \quad \Rightarrow \quad \boxed{n \geq 5}$$

Overview of Two-view Geometry

- Number of Point Correspondences

- ✓ In 1913, Kruppa showed that 5 image correspondences is the minimal case and that there can be at up to 11 solutions [1].
- ✓ In 1981, the first popular solution uses 8 points and is called the 8 point algorithm or Longuet Higgins algorithm [2].
- ✓ In 2004 , Nister proposed the first efficient and non-iterative solution . It uses Groebner basis decomposition [3].

[1] E. Kruppa, Zur Ermittlung eines Objektes aus zwei Perspektiven mit Innerer Orientierung, Sitz. Ber. Akad. Wiss., Wien, Math. Naturw. Kl., Abt. IIa. IIa., 1913
[2] H. Christopher Longuet Higgins, A computer algorithm for reconstructing a scene from two projections, Nature, 1981.
[3] D. Nister , An Efficient Solution to the Five Point Relative Pose Problem, PAMI, 2004.

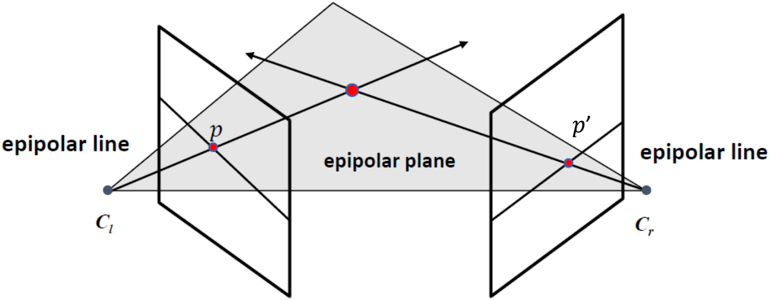
Geometric Constraints

摄像机中心 ll和 $C\ rr$以及图像点 pp和 pp' 确定所谓的外极平面。

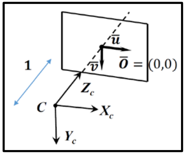
➢ Epipolar planes and lines

[?] 上极平面与两个影像平面的交点被称为上极点线。

- ✓ The camera centers C_l and C_r and the image point p and p' determine the so-called epipolar plane.
- ✓ The intersections of the epipolar plane with the two image planes are called epipolar lines.

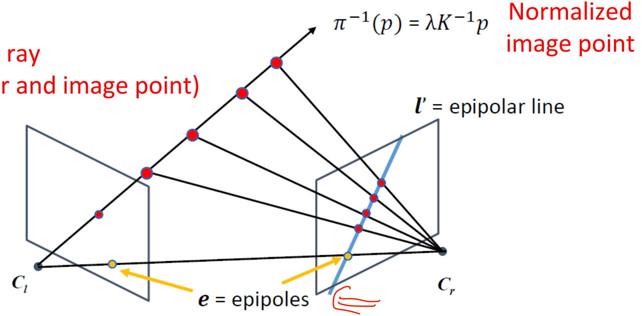


Geometric Constraints



➢ Epipolar planes and lines

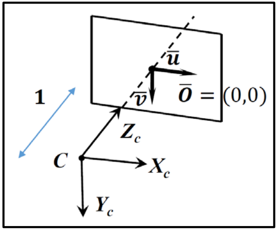
- ✓ The epipolar line is the projection of a back projected ray $\pi^{-1}(p)$ onto the other camera image
- ✓ The epipole is the projection of the optical center on the other camera image
- ✓ A pair of images has two epipoles.



Geometric Constraints

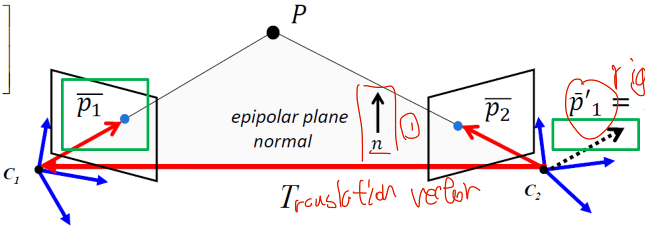
- Essential Matrix

Coplanarity constraint



$$\bar{p}_1 = \begin{bmatrix} \bar{u}_1 \\ \bar{v}_1 \\ 1 \end{bmatrix} \qquad \bar{p}_2 = \begin{bmatrix} \bar{u}_2 \\ \bar{v}_2 \\ 1 \end{bmatrix}$$

Normalized image coordinates



$\bar{p}'_1 = R\bar{p}_1$ right camera frame

$\bar{p}_1, \bar{p}_2, T$ **are coplanar**

Right camera frame

Left camera frame

$$2 \quad \underbrace{\bar{p}_2^T \cdot n}_{\text{orthogonality}} = 0 \Rightarrow 1 \quad \bar{p}_2^T \cdot \underbrace{(T \times \bar{p}'_1))}_{\text{Normal of epipolar plane}} = 0 \quad \Rightarrow \bar{p}_2^T (T \times (R\boxed{\bar{p}_1})) = 0$$

From dot product to matrix multiplication

Geometric Constraints

$$\mathbf{a} \times \mathbf{b} = [\mathbf{a}]_\times \mathbf{b} = \begin{bmatrix} 0 & -a_3 & a_2 \\ a_3 & 0 & -a_1 \\ -a_2 & a_1 & 0 \end{bmatrix} \begin{bmatrix} b_1 \\ b_2 \\ b_3 \end{bmatrix}$$

- Essential Matrix

Coplanarity constraint

Skew-symmetric matrix

$$\bar{p}_2^T (T \times (R\bar{p}_1)) = 0 \quad \Rightarrow \bar{p}_2^T \, [T_\times] R \, \bar{p}_1 = 0 \quad \Rightarrow \boxed{\bar{p}_2^T \, E \, \bar{p}_1 = 0}$$

Associative law

Definition of essential matrix

$$\boxed{\mathrm{E} = [T_\times] R \quad essential\ matrix}$$

R and T can be computed from E

Geometric Constraints

- From Essential Matrix to Fundamental Matrix

到目前为止，我们假设相机的内在参数是已知的，我们使用归一化的图像坐标来获得校准相机的外极约束：

So far, we have assumed that the camera intrinsic parameters are **known** and we have used **normalized** image coordinates to get the epipolar constraint for calibrated cameras:

$$\bar{p}_2^T \, E \, \bar{p}_1 = 0 \qquad \begin{bmatrix} \bar{u}_2^i \\ \bar{v}_2^i \\ 1 \end{bmatrix}^T E \begin{bmatrix} \bar{u}_1^i \\ \bar{v}_1^i \\ 1 \end{bmatrix} = 0$$

$$\begin{bmatrix} \bar{u}_1^i \\ \bar{v}_1^i \\ 1 \end{bmatrix} = K_1^{-1} \begin{bmatrix} u_1^i \\ v_1^i \\ 1 \end{bmatrix} \qquad \begin{bmatrix} \bar{u}_2^i \\ \bar{v}_2^i \\ 1 \end{bmatrix} = K_2^{-1} \begin{bmatrix} u_2^i \\ v_2^i \\ 1 \end{bmatrix}$$

Normalized image coordinates

$$\Rightarrow \quad \begin{bmatrix} u_2^i \\ v_2^i \\ 1 \end{bmatrix}^T K_2^{-T} \, E \, K_1^{-1} \begin{bmatrix} u_1^i \\ v_1^i \\ 1 \end{bmatrix} = 0$$

Geometric Constraints

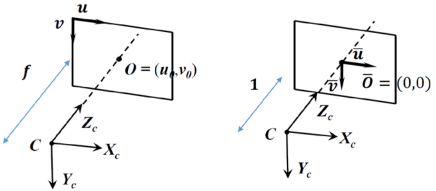
➢ Fundamental Matrix

✓ Definition of fundamental matrix

$$\begin{bmatrix} u_2^i \\ v_2^i \\ 1 \end{bmatrix}^T \boxed{K_2^{-T}\ E\ K_1^{-1}} \begin{bmatrix} u_1^i \\ v_1^i \\ 1 \end{bmatrix} = 0 \quad \Rightarrow \quad \begin{bmatrix} u_2^i \\ v_2^i \\ 1 \end{bmatrix}^T \boxed{F} \begin{bmatrix} u_1^i \\ v_1^i \\ 1 \end{bmatrix} = 0$$

Fundamental Matrix $F = K_2^{-T}\ E\ K_1^{-1}$

Advantage: Based on fundamental matrix, we work directly in ordinary image plane, instead of normalized image plane.



Geometric Constraints

➢ Computation of Fundamental/Essential Matrix

✓ Eight-point method (Direct linear transform--DLT)

- Essential matrix
- Fundamental matrix

✓ Five-point method (introduce in the next class)

- Essential matrix

Eight-point Method

$$\begin{bmatrix}\bar{u}_2\\ \bar{v}_2\\ 1\end{bmatrix}^T \bar{E} \begin{bmatrix}\bar{u}_1\\ \bar{v}_1\\ 1\end{bmatrix} = 0$$

$$K_2^{-1}\begin{bmatrix}u_2\\ v_2\\ 1\end{bmatrix} \bar{E} K \begin{bmatrix} u_1 \end{bmatrix}$$

➢ Classical Version

✓ We first take essential matrix estimation for example [1].

✓ Each pair of point correspondences $\bar{\boldsymbol{p}}_1 = (\bar{u}_1, \bar{v}_1, 1)^T$, $\bar{\boldsymbol{p}}_2 = (\bar{u}_2, \bar{v}_2, 1)^T$ provides a linear equation:

$$(K_2^{-1} p_2)^T \bar{E} \cdot (K_1^{-1} p_1) = 0$$

$$p_2 \cdot K_2^{-T} \bar{E} \cdot K_1^{-1}$$

$$\bar{p}_2^T \, E \, \bar{p}_1 = 0 \qquad E = \begin{bmatrix} e_{11} & e_{12} & e_{13} \\ e_{21} & e_{22} & e_{23} \\ e_{31} & e_{32} & e_{33} \end{bmatrix}$$

Normalized image coordinates

[1] H. Christopher Longuet-Higgins, A computer algorithm for reconstructing a scene from two projections, Nature, 1981

Eight-point Method

- Classical Version

$$\bar{u}_2\bar{u}_1e_{11} + \bar{u}_2\bar{v}_1e_{12} + \bar{u}_2e_{13} + \bar{v}_2\bar{u}_1e_{21} + \bar{v}_2\bar{v}_1e_{22} + \bar{v}_2e_{23} + \bar{u}_1e_{31} + \bar{v}_1e_{32} + e_{33} = 0$$

Note:

- ✓ The 8-point algorithm assumes that the entries of E are all independent. This is not true since, for the calibrated case, they depend on 5 parameters (R and T).
- ✓ The 5-point algorithm (introduced later) uses the epipolar constraint considering the dependencies among all entries.

Eight-point Method

$\bar{u}_1$ $\bar{v}_1$ $\bar{u}_2$ $\bar{v}_2$

0 1 2 3

➢ Classical Version

For n points, we can write

need 8 correspondences

$$\begin{pmatrix} X_w^1 & Y_w^1 & Z_w^1 & 1 & 0 & 0 & 0 & 0 & -u_1X_w^1 & -u_1Y_w^1 & -u_1Z_w^1 & -u_1 \\ 0 & 0 & 0 & 0 & X_w^1 & Y_w^1 & Z_w^1 & 1 & -v_1X_w^1 & -v_1Y_w^1 & -v_1Z_w^1 & -v_1 \\ & & & & & & \vdots & & & & & \\ X_w^n & Y_w^n & Z_w^n & 1 & 0 & 0 & 0 & 0 & -u_nX_w^n & -u_nY_w^n & -u_nZ_w^n & -u_n \\ 0 & 0 & 0 & 0 & X_w^n & Y_w^n & Z_w^n & 1 & -v_nX_w^n & -v_nY_w^n & -v_nZ_w^n & -v_n \end{pmatrix} \begin{pmatrix} m_{11} \\ m_{12} \\ m_{13} \\ m_{14} \\ m_{21} \\ m_{22} \\ m_{23} \\ m_{24} \\ m_{31} \\ m_{32} \\ m_{33} \\ m_{34} \end{pmatrix} = \begin{pmatrix} 0 \\ 0 \\ \vdots \\ 0 \\ 0 \end{pmatrix} \Rightarrow Q \cdot M = 0$$

Q (this matrix is **known**)

M (this matrix is **unknown**)

Linear system of Tsai's method

Normalized image coordinates

$$\begin{bmatrix} \bar{u}_2^1\bar{u}_1^1 & \bar{u}_2^1\bar{v}_1^1 & \bar{u}_2^1 & \bar{v}_2^1\bar{u}_1^1 & \bar{v}_2^1\bar{v}_1^1 & \bar{v}_2^1 & \bar{u}_1^1 & \bar{v}_1^1 & 1 \\ \bar{u}_2^2\bar{u}_1^2 & \bar{u}_2^2\bar{v}_1^2 & \bar{u}_2^2 & \bar{v}_2^2\bar{u}_1^2 & \bar{v}_2^2\bar{v}_1^2 & \bar{v}_2^2 & \bar{u}_1^2 & \bar{v}_1^2 & 1 \\ \vdots & \vdots & \vdots & \vdots & \vdots & \vdots & \vdots & \vdots & \vdots \\ \bar{u}_2^n\bar{u}_1^n & \bar{u}_2^n\bar{v}_1^n & \bar{u}_2^n & \bar{v}_2^n\bar{u}_1^n & \bar{v}_2^n\bar{v}_1^n & \bar{v}_2^n & \bar{u}_1^n & \bar{v}_1^n & 1 \end{bmatrix} \begin{bmatrix} e_{11} \\ e_{12} \\ e_{13} \\ e_{21} \\ e_{22} \\ e_{23} \\ e_{31} \\ e_{32} \\ e_{33} \end{bmatrix} = 0 \quad \Rightarrow \quad Q \cdot \bar{E} = 0$$

Q (this matrix is **known**)

$\bar{E}$ (this matrix is **unknown**)

Eight-point Method

最小的解决方案
- Q (n ×9)应该有8级，才能有唯一的(在一定范围内)非微不足道的解
- 不同的 E 矩阵在一定范围内会导致相同的旋转和平移结果（规范=1）。
- 每个点的对应关系提供了一个独立的方程
- 因此，需要8个点的对应关系

$$\mathrm{Q} \cdot \bar{\mathrm{E}} = 0$$

➢ Classical Version

Minimal solution

- $Q_{(n\times 9)}$ should have rank 8 to have a unique (up to a scale) non-trivial solution $\bar{E}$
- Different E matrices up to scale lead to the same result of rotation and translation (norm=1)
- Each point correspondence provides 1 independent equation
- Thus, 8 point correspondences are needed

Over-determined solution

- n > 8 points
- A solution is to minimize $||Q\bar{E}||^2$ subject to the constraint $||\bar{E}||^2 = 1$
- The solution is the eigenvector corresponding to the smallest eigenvalue of the matrix $Q^T Q$

过度确定的解决方案
- n > 8点
- 一个解决方案是在约束条件下最小化
- 解决方案是与矩阵的最小特征值相对应的特征向量

Eight-point Method

➢ Extension to Fundamental matrix

✓ Similarly, eight-point method for fundamental matrix can be formulated as

$$\begin{bmatrix} u_2^i \\ v_2^i \\ 1 \end{bmatrix}^{\mathrm{T}} \mathrm{F} \begin{bmatrix} u_1^i \\ v_1^i \\ 1 \end{bmatrix} = 0 \quad \Rightarrow \quad \begin{bmatrix} u_2^1 u_1^1 & u_2^1 v_1^1 & u_2^1 & v_2^1 u_1^1 & v_2^1 v_1^1 & v_2^1 & u_1^1 & v_1^1 & 1 \\ u_2^2 u_1^2 & u_2^2 v_1^2 & u_2^2 & v_2^2 u_1^2 & v_2^2 v_1^2 & v_2^2 & u_1^2 & v_1^2 & 1 \\ \vdots & \vdots & \vdots & \vdots & \vdots & \vdots & \vdots & \vdots & \vdots \\ u_2^n u_1^n & u_2^n v_1^n & u_2^n & v_2^n u_1^n & v_2^n v_1^n & v_2^n & u_1^n & v_1^n & 1 \end{bmatrix} \begin{bmatrix} f_{11} \\ f_{12} \\ f_{13} \\ f_{21} \\ f_{22} \\ f_{23} \\ f_{31} \\ f_{32} \\ f_{33} \end{bmatrix} = 0$$

✓ We use the original image coordinates instead of normalized image coordinates.

Eight-point Method

$$\begin{bmatrix} u_2^1 u_1^1 & u_2^1 v_1^1 & u_2^1 & v_2^1 u_1^1 & v_2^1 v_1^1 & v_2^1 & u_1^1 & v_1^1 & 1 \\ u_2^2 u_1^2 & u_2^2 v_1^2 & u_2^2 & v_2^2 u_1^2 & v_2^2 v_1^2 & v_2^2 & u_1^2 & v_1^2 & 1 \\ \vdots & \vdots & \vdots & \vdots & \vdots & \vdots & \vdots & \vdots & \vdots \\ u_2^n u_1^n & u_2^n v_1^n & u_2^n & v_2^n u_1^n & v_2^n v_1^n & v_2^n & u_1^n & v_1^n & 1 \end{bmatrix} \begin{bmatrix} f_{11} \\ f_{12} \\ f_{13} \\ f_{21} \\ f_{22} \\ f_{23} \\ f_{31} \\ f_{32} \\ f_{33} \end{bmatrix} = 0$$

- ➢ Normalized Version

Motivation

- ✓ Orders of magnitude difference between column of data matrix.
- ✓ Least-square method yields poor results.

250906.36	183269.57	921.81	200931.10	146766.13	738.21	272.19	198.81	1.00
2692.28	131633.03	176.27	6196.73	302975.59	405.71	15.27	746.79	1.00
416374.23	871684.30	935.47	408110.89	854384.92	916.90	445.10	931.81	1.00
191183.60	171759.40	410.27	416435.62	374125.90	893.65	465.99	418.65	1.00
48988.86	30401.76	57.89	298604.57	185309.58	352.87	846.22	525.15	1.00
164786.04	546559.67	813.17	1998.37	6628.15	9.86	202.65	672.14	1.00
116407.01	2727.75	138.89	169941.27	3982.21	202.77	838.12	19.64	1.00
135384.58	75411.13	198.72	411350.03	229127.78	603.79	681.28	379.48	1.00
~10000	~10000	~100	~10000	~10000	~100	~100	~100	1

$$\begin{bmatrix} f_{11} \\ f_{12} \\ f_{13} \\ f_{21} \\ f_{22} \\ f_{23} \\ f_{31} \\ f_{32} \\ f_{33} \end{bmatrix} = 0$$

Orders of magnitude difference between column of data matrix → least-squares yields poor results

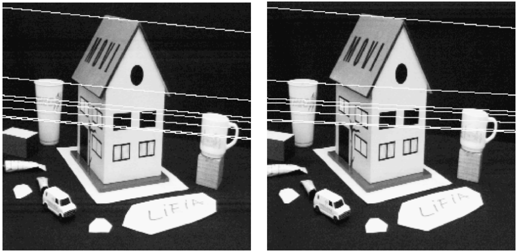
Eight-point Method

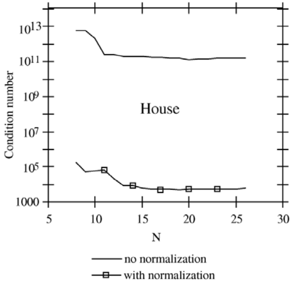
➢ Normalized Version

Motivation

✓ Poor numerical conditioning, which makes results very sensitive to noise

✓ This problem can be fixed by rescaling the data: Normalized 8-point algorithm [1]



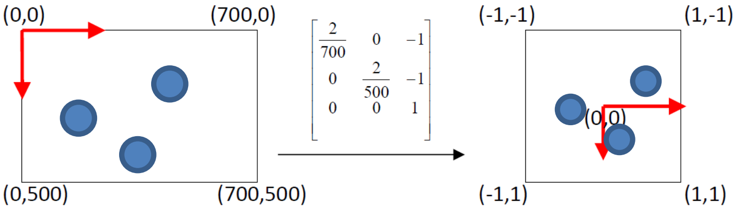


[1] R. Hartley, In defense of the eight point algorithm, IEEE Transactions of Pattern Analysis and Machine Intelligence (TPAMI), 1997

Eight-point Method

- Normalized Version

In the original 1997 paper, Hartley proposed to rescale the two 2D point sets such that the centroid of each set is 0 and the mean standard deviation $\sqrt{2}$ (equivalent to having the points distributed around a circled passing through the four corners of the $[-1,1] \times [-1,1]$ square).



$$\begin{bmatrix} \frac{2}{700} & 0 & -1 \\ 0 & \frac{2}{500} & -1 \\ 0 & 0 & 1 \end{bmatrix}$$

Eight-point Method

➢ Normalized Version

✓ This can be done for every point as follows $\widehat{p^i} = \frac{\sqrt{2}}{\sigma}(p^i - \mu)$

where $\mu = (\mu_x, \mu_y) = \frac{1}{N}\sum_{i=1}^{n} p^i$ is the centroid and $\sigma = \frac{1}{N}\sum_{i=1}^{n} \left\| p^i - \mu \right\|^2$ is the mean standard deviation of the point set.

✓ This transformation can be expressed in matrix form using homogeneous coordinates:

$$\widehat{p^i} = \begin{bmatrix} \frac{\sqrt{2}}{\sigma} & 0 & -\frac{\sqrt{2}}{\sigma}\mu_x \\ 0 & \frac{\sqrt{2}}{\sigma} & -\frac{\sqrt{2}}{\sigma}\mu_y \\ 0 & 0 & 1 \end{bmatrix} p^i$$

Eight-point Method

➢ Normalized Version

The Normalized 8-point algorithm can be summarized in three steps:

1. Normalize the point correspondences: $\widehat{p_1} = \boxed{B_1} p_1$, $\widehat{p_2} = \boxed{B_2} p_2$
2. Estimate normalized $\hat{F}$ with 8 point algorithm using normalized coordinates $\widehat{p_1}, \widehat{p_2}$
3. Compute unnormalized *F* from $\hat{F}$

Normalized 2D coordinates (known)

$$\widehat{p_2}^T \hat{F} \widehat{p_1} = 0$$

Output of second step

Original 2D coordinates

$$\underbrace{\boxed{p_2^T B_2^T} \; \hat{F} \; \boxed{B_1 p_1}}_{F = \boxed{B_2^T} \hat{F} \boxed{B_1}}$$

Eight-point Method

➢ Normalized Version

Comparison between Normalized and non-normalized versions

high error

	8-point	Normalized 8-point	Nonlinear refinement
Avg. Ep. Line Distance	2.33 pixels	0.92 pixel	0.86 pixel

Summary

- Overview of 2D-2D Geometry
- Two-view Geometric Constraints
- Eight-point Method

Thank you for your listening!

If you have any questions, please come to me :-)