

image plane. And in this case, as the second camera only differs from the first camera by a pure translation parallel to the image plane, the intersection of the baseline with the image plane is at intinity, the epiples are at infinity. As epipolar line is the intersection of an epipolar plane defined by baseline & P and with an image plane, and all epipolar lines are projection of baseline on image planes, since there this is a pure translation from

camera 1 to camera 2, all epipolar lines are parallel to the baseline. (We can also verify that epipolar lines on an image plane are parallel by saying epipole is at the infinity).

1.2. sp= k[I 0]P

(p'= k'ER t]P

Generally, we look at the above equation to fixel the p, p'
However, in this special case, P is the intersection

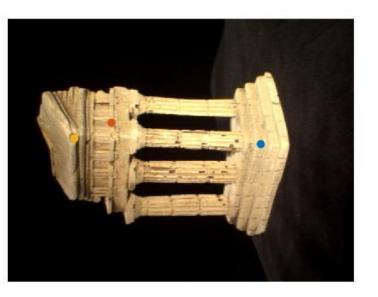
of two principal axes and the rimage coordinates are
normalized so that (0,0) coincides with the principal p
point (not in the corner ary more). From this special
senario, we observe that p = [v] = [o]

p' = [v'] = [o]

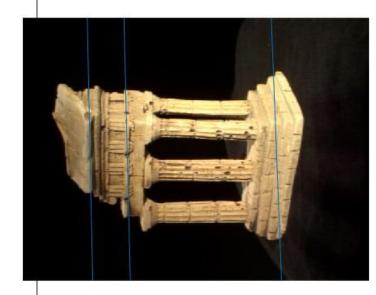
Then we get [v' i] = [o] = [o] = [o]

Then we get [fis] = F33 = 0

F33 Thus, F33 is zero.

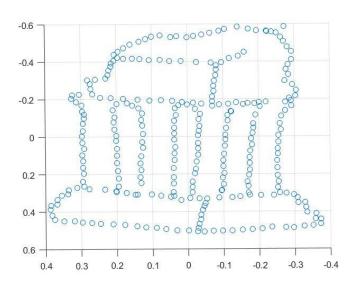


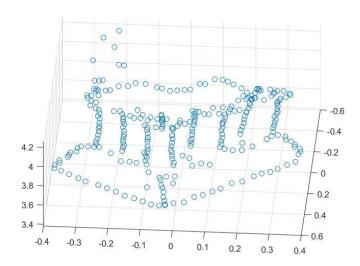
Select a point in this image (Right-click when finished)

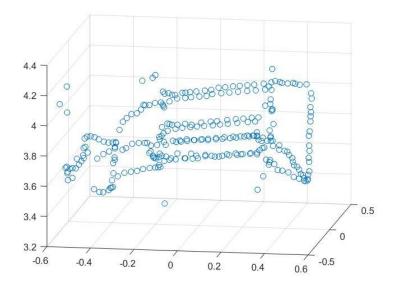


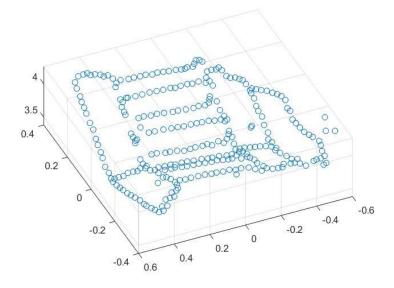
Verify that the corresponding point is on the epipolar line in this image

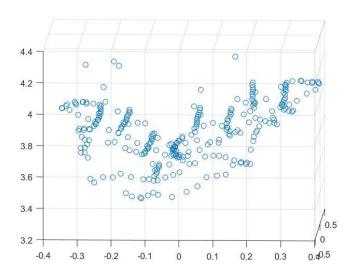
## 2.2

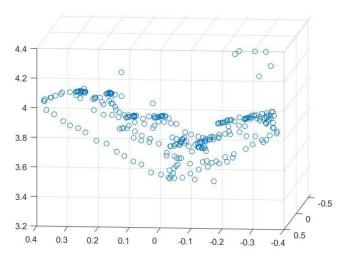




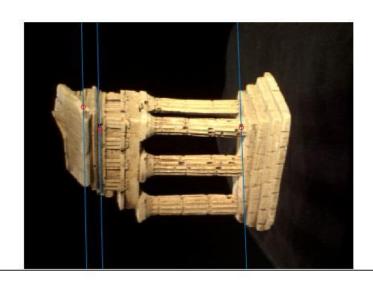












Select a point in this image (Right-click when finished)

Verify that the corresponding point is on the epipolar line in this image

~10 hours