Multiple View Geometry: Solution Exercise Sheet 6

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Part I: Theory

1. (a) E is essential matrix $\Rightarrow \Sigma = \text{diag}\{\sigma, \sigma, 0\}$:

$$R_z(\pm \frac{\pi}{2})\Sigma = \begin{pmatrix} 0 & \mp 1 & 0 \\ \pm 1 & 0 & 0 \\ 0 & 0 & 1 \end{pmatrix} \cdot \begin{pmatrix} \sigma & 0 & 0 \\ 0 & \sigma & 0 \\ 0 & 0 & 0 \end{pmatrix} = \begin{pmatrix} 0 & \mp \sigma & 0 \\ \pm \sigma & 0 & 0 \\ 0 & 0 & 0 \end{pmatrix} = -(R_z(\pm \frac{\pi}{2})\Sigma)^\top$$

$$-\hat{T}^{\top} = -(UR_z\Sigma U^{\top})^{\top}$$

$$= U(-R_z\Sigma)^{\top}U^{\top}$$

$$= UR_z\Sigma U^{\top}$$

$$= \hat{T}$$

(b) i. U, V are orthogonal matrices $\Rightarrow U^{\top}U = Id$ and $VV^{\top} = Id$ R_z is a rotation matrix $\Rightarrow R_z R_z^{\top} = Id$

$$R^{\top}R = (UR_z^{\top}V^{\top})^{\top}(UR_z^{\top}V^{\top})$$

$$= VR_zU^{\top}UR_z^{\top}V^{\top}$$

$$= VR_zR_z^{\top}V^{\top}$$

$$= VV^{\top}$$

$$= Ud$$

ii. U and V are special orthogonal matrices with $\det(U) = \det(V^\top) = 1$.

$$\det(R) = \det(UR_z^\top V^\top) = \underbrace{\det(U)}_1 \cdot \underbrace{\det(R_z^\top)}_1 \cdot \underbrace{\det(V^\top)}_1 = 1$$

2. (a) $H = R + Tu^{\top} \Leftrightarrow R = H - Tu^{\top}$.

$$E = \hat{T}R = \hat{T}(H - Tu^{\top}) = \hat{T}H - \underbrace{\hat{T}T}_{=T \times T = 0}u^{\top} = \hat{T}H$$

(b)

$$\begin{split} H^\top E + E^\top H &= H^\top (\hat{T}H) + (\hat{T}H)^\top H \\ &= H^\top (\hat{T}H) + H^\top \hat{T}^\top H \\ &= H^\top \hat{T}H - H^\top \hat{T}H \quad \text{(because } \hat{T} \text{ is skew-symmetric, i.e. } \hat{T}^\top = -\hat{T}) \\ &= 0 \end{split}$$

3.
$$\forall x_2: \quad l_1 = \{x_1 \mid x_2^\top F x_1 = 0\}$$

In particular: $e_1 \in l_1 \quad \Rightarrow \quad x_2^\top F e_1 = 0 \quad \forall \ x_2$
 $\Rightarrow \quad F e_1 = 0$

(The camera center o_2 is in the preimage of every $x_2 \Rightarrow$ The epipol e_1 (which is the projection of o_2 to the image plane of image 1) lies on all epipolar lines l_1)

Analogous:
$$e_2^{\top} F = 0$$
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