CSE 573

Homework 1

1 ). Camera Parameters

1. Rotation Matrix

R=Rx\*Ry\*Rz

Angles formed with X, Y, Z axis are 30­­O, 50O, 70O

Rx = Ry =

Rz =

Therefore, R=Rx\*Ry\*Rz

R =

2.Translation Vector

The vector t can be interpreted as the position of the world origin in camera coordinates.

We have t= -R \*

Thus t =

3.

4.

Citations

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<http://ksimek.github.io/2012/08/22/extrinsic/>

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