

## Homework 1

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### 1 Theory (55 Points)

#### 1.1 $H$ for mirror reflection image (8 Points)

Suppose that a scene is a plane and that it is projected to an image assuming the normal pinhole model. Suppose that the points on the plane are related by a symmetry about a line  $L$  (for example, imagine a painting in which the “left” and “right” half are identical).

- Show that there exists a planar homography  $H$  in the image such that any point  $p$  on the image matches other point  $p' = Hp$  on the image plane.
- Show that  $H^2 = I$ .
- Show that  $H$  has an eigenvector which is the vanishing point of  $L$ .

#### 1.2 Center of a virtual camera (image of an image); (10 Points)

Let  $I_1$  be an image of a scene, using a general projective model. Let  $I_2$  be the image obtained by seeing through another camera (an image of an image). We can think of  $I_2$  as an image of the original scene through some virtual camera. Show that the center  $C$  of this virtual camera is the same as the center of the projection used for  $I_1$ .

#### 1.3 Fun with pencils of lines (12 Points)

- A line in the plane is represented by a 3-vector  $l = [u \ v \ w]^T$ . What is the slope  $s$  of the line? (Ignoring the one case of infinite slope)
- Consider a pencil of lines in the plane. Explain why any line in the pencil can be represented canonically by a linear combination of two distinct lines represented by two 3-vectors  $l_1$  and  $l_2$ . (Simple answer, just use an argument based on the dimension of the subspaces involved.)
- Now consider two pencils of lines and a homography  $H$  between the two pencils. What is the dimension of the matrix representing  $H$ ? (again, no equations; 1-sentence answer based on the dimensions of the spaces involved) Be careful that we are asking about the homography from one set of lines to another, not about a planar homography.
- Show that if  $l'$  is the transformed of  $l$  by the line homography  $H$ , then the slopes are related by a function of the form (ignoring the infinities):

$$s' = \frac{as + b}{cs + d}$$

- Conversely, assume that a transformation between the two pencils is of that form, state what condition the coefficients  $a, b, c, d$  must satisfy for the transformation to be a line homography? What is the matrix representing that homography?

## 1.4 Rodrigues's rotation formula (++) (25 Points)

- Rodrigues's rotation formula is a convenient way of expressing rotations of a vector  $\mathbf{p}$  as a function of the rotation angle  $\theta$  and the axis of rotation  $\mathbf{w}$ :

$$\mathbf{R}\mathbf{p} = \mathbf{p} + \sin(\theta)\mathbf{w} \times \mathbf{p} + (1 - \cos(\theta))\mathbf{w} \times (\mathbf{w} \times \mathbf{p})$$

Write Rodrigues's formula in matrix form:

$$\mathbf{R}\mathbf{p} = \dots$$

- Suppose now that  $\theta$  is very small (e.g., the small rotation between two consecutive frames in a video sequence). What would be an approximation of  $\mathbf{R}\mathbf{p}$ , denoting  $\omega = \theta\mathbf{w}$ ?
- Consider now 2 cameras separated by a small rotation  $R$  and a translation  $t$ . Assuming  $K = I$  (calibrated cameras) and using the approximation above, what is the essential matrix  $E$ ?
- We know that the epipole in one image is  $t$ . What is the epipole in the other image if the axis of rotation  $w$  is parallel to  $t$ ?
- Consider now a pixel of coordinates  $(u, v)$  in one image, projection of a point  $(X, Y, Z)$ . The corresponding point in the other image is  $(u', v')$ . Assuming again small motion we have:  $u' = u + du$  and  $v' = v + dv$  (we can think of  $du$  and  $dv$  as the apparent motion of the point corresponding to  $(u, v)$  in the image.)

Express  $du$  and  $dv$  as function of  $u, v, \Omega, t, Z$  (remember to write first that  $(u, v)$  are the projection in the image of  $X, Y, Z$  from the trivial projection matrix  $[I \ 0]$ .)

- Show that if  $P$  is known to be on a plane  $(n, d)$ , then  $(du, dv)$  does not depend on  $Z$ , the "depth" of the point.
- In that case, also show that  $(du, dv)$  are quadratic expressions in  $u, v$ .
- The reasoning above used derivatives ( $du$  and  $dv$ ). Another angle on the problem is to compute the homography  $H$  induced by a plane  $(n, d)$  assuming small rotation  $\Omega$  and a translation  $t$ . Write an expression for  $H$  using the small-angle rotation expression above.
- Given this expression of  $H$ , which point remains invariant under  $H$  if  $\Omega$  is orthogonal to  $n$ ? (e.g., if the plane is the ground plane and the cameras are on a robot moving on the ground plane).

## 2 Extra Credits for Theory (20 Points)

### 2.1 Projection of Lines (8 Points)

- Given a pair of cameras of projection matrices  $M$  and  $M'$  and the lines  $l$  and  $l'$  projections of a line  $L$  in 3D space. Write a formula expressing  $L$  as a function of  $l, l', M$ , and  $M'$ , using linear algebra operations and one of the meet/join operators. Simply write an equation of the form  $L = \dots$ . Do *not* try to make explicit the coordinates of  $L$  any further.
- Given a pair of projective cameras with fundamental matrix  $F$ , let  $L_1$  (resp.  $L_2$ ) be a line in space,  $l_1$  (resp.  $l_2$ ) its projection in one of the cameras, and  $l'_1$  (resp.  $l'_2$ ) its projection in the other camera. Prove that if  $L_1$  and  $L_2$  are coplanar, then:  $(l'_1 \times l'_2)^T F(l_1 \times l_2) = 0$ .

## 2.2 P projects to same points in 2 images ( $MP = p = p' = M'P$ ); (12 points)

Consider a pair of cameras of fundamental matrix  $F$ . We are interested in the set  $E$  of points that project to the same point in both images. In other words, we are interested in the set of point  $P$  such that  $MP = p = p' = M'P$  (but we know only  $F$ , not  $M$  and  $M'$ ). This is an interesting set of points because, in a stereo system, there is no disparity at those points, so that the images are locally the same at those points. The matching will be the most accurate at the points of  $E$ .

- Show that the points  $p$  projection of points  $P$  in  $E$  satisfy  $p^T F p = 0$ .
- Show that any fundamental matrix  $F$  can always be decomposed into the sum of a symmetric matrix  $S$  ( $S = S^T$ ) and a skew-symmetric  $X$  ( $X = -X^T$ ).
- Show that the locus of points such that  $p^T F p = 0$  is a conic with matrix  $S$ .
- Show that both epipoles belong to this conic.

## 3 Having fun by implementing what we have learnt! (55 Points)

In this part of the homework, we will try to generate metrically correct view of a warped image. You can use any method you prefer as long as it conforms to the descriptions below:

**What you have to do:**

- Given an example image, write a function that returns metrically rectified image as well as the  $H$  used to perform rectification. Follow this function definition:

```
function [rectI, H] = rectifyImage(filename, debug)
```

If `debug=1`, you should provide whatever manual input (annotation) you require (e.g., marking parallel or perpendicular lines, planes etc.). MATLAB's `ginput` might come in handy.

```
[x y] = ginput(4); pt1 = [x(1) y(1) 1]'; pt2 = [x(2) y(2) 1]';
```

Save all the information you entered, so that it can be evaluated. You can use any format for saving, as long as it is consistent with your load commands.

If `debug=0`, you should load whatever information you manually entered and return `[rectI, H]`. Follow this convention for saving/loading:

```
[d, fname] = fileparts(filename);  
data = load(fullfile(strrep(d, '/images', '/data'), [fname '.mat']));
```

where `fname.mat` is the file that stores the annotations (above code assumes images and annotated data are in '`anypath/images/`' and '`anypath/data/`' directories respectively.)

- Find (or click) **3** images. Ideally, capture/find images that have substantial perspective distortion. (See figure 1)
- Run your code on at least **7 out of the given 13** images as well as on the images you captured/found. Put your images in the sub-folder `./images/` and the `mat` files with annotations in the sub-folder `./data/`.
- See what you need to submit in the end.



(a) Good input! (b) Bad input...

Figure 1: The good and bad inputs.

### What you can use:

- You can use **any method you prefer**. You might get ideas from material taught in class (16822) and Computer Vision (16720). Also, material from Hartley&Zisserman, and Faugeras might be helpful. Any variations on the ideas for rectification mentioned in stated materials, e.g., there are other combinations of parallel/perpendicular points and lines, as well as methods using distances which Martial mentioned in class are fine.
- You can also use advanced material from any papers/research/reports that you find, as long as you understand them.
- Code to manually select points or planar regions in the image. (e.g., MATLABs ginput)
- MATLAB's functions or your code from 16720 used for warping. This might be helpful as well:

```

1 function rectI = applyH(img, H)
2     tform = maketform('projective',H');
3     %H or H' depending on your convention
4     [boxx boxy]=tformfwd(tform, [1 1 size(img,2) size(img,2)], [1 ...
5         size(img,1) 1 size(img,1)]);
6     minx=min(boxx); maxx=max(boxx);
7     miny=min(boxy); maxy=max(boxy);
8     rectI =imtransform(img,tform,'XData',[minx maxx],'YData',[miny ...
9         maxy],'Size',[size(img,1),round(size(img,1)*(maxx-minx)/(maxy-miny))]);
10    % imshow(rectI);
11 end

```

- Non-linear distortion compensation code if the images you choose are too distorted. (Try not to choose such images).

### What you *can not* do:

- Download code, except for the distortion and manual input (see above.)
- Use any measurement in the scene provided apriori (the only information available as input is the image itself, and whatever you annotate).
- Use any calibration parameters for the camera.
- Make any assumption about the camera parameters, except that it is a perspective camera.

### What you have to submit:

- Input images
- Output images: Rectified image and intermediate images color coded annotation that you used. Display of the lines that were used, including the vanishing line if you use it in your method. (See figure 2)
- Angles (more precisely, the cosines) of at least 3 pairs of perpendicular lines before and after rectification (provide annotations in the mat file as well). This will show how far from 0 the cosines are in the original image and how close to correct the final metric rectification is. (See figure 3 and table 1).
- Description of your implementation (i.e., the algorithm you followed with relevant equations, what were the annotations used) and (most importantly) what problems were encountered (e.g., numerical issues, etc.).
- **CODE.**

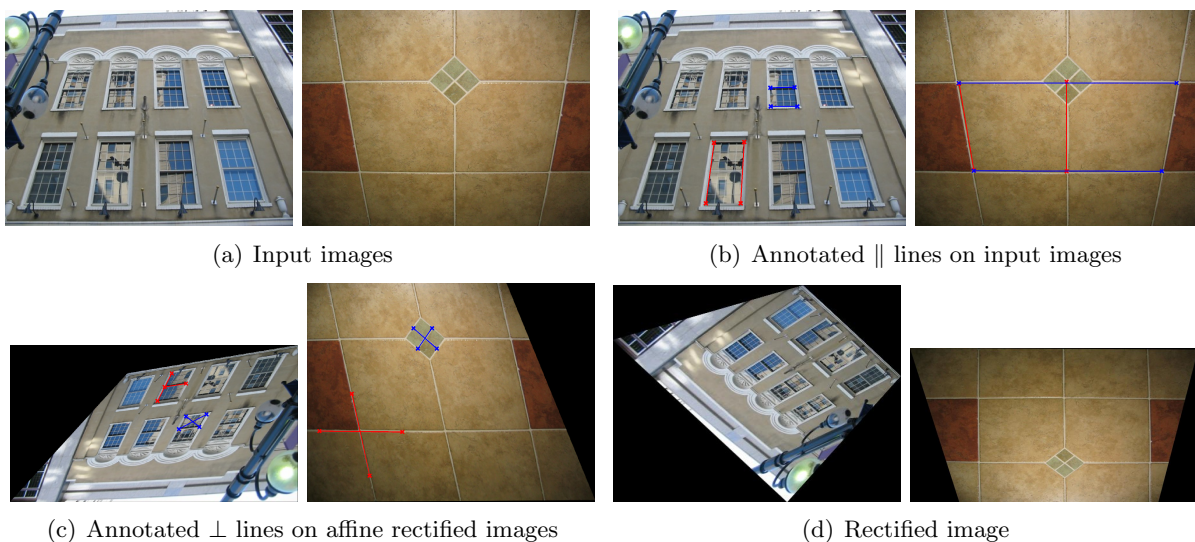


Figure 2: An example of Output Images to be submitted for the rectification algorithm

Before	After
-0.15073	-0.00624
0.10344	0.004659
0.159543	-0.001270

Table 1: An example of cosine  $\theta$  between lines.

### Tips:

- Make sure to keep “sanity checks” in your code while you are debugging, by checking an equation that you know should be true. (e.g.,  $l^T C m = 0$ ). Keep such code commented when you submit, so that I can see and appreciate it!

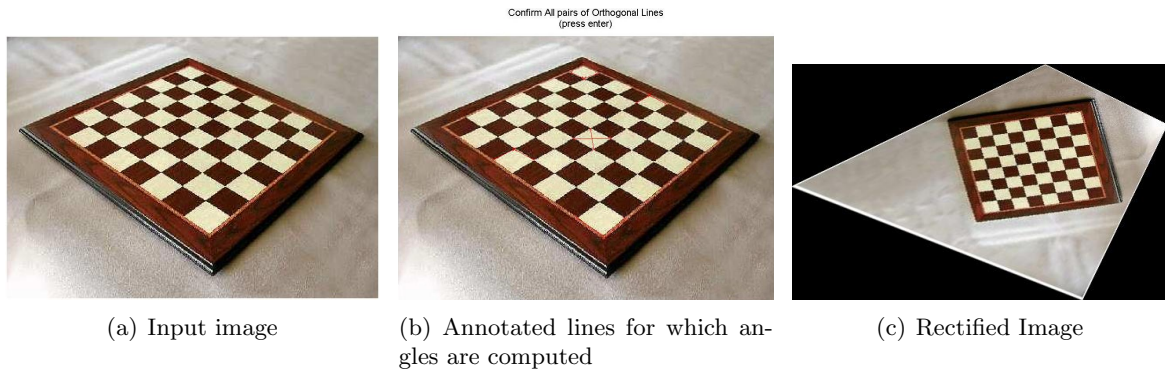


Figure 3: An example of Output Images to submit for angle between lines.

- Nomalize coordinates of points before doing anything.
- Remember the transformations that you are estimating are up to a scale.
- Be careful about all the things Martial mentioned in class!
- Remember Homework Policy available on Piazza.
- **Start Early! Start Early!! Start Early!!!**
- Have fun!!