

ENGN4528 Practice Exercise – Week 9

Q1: Describe an algorithm to recover a fundamental matrix between two cameras given a set of 50 putative matching points between the cameras (that may contain errors).

Q2: Given two cameras and a fundamental matrix that describes their respective epipolar geometry, describe how to recover the relative depth of points in the scene that fall into the view of both cameras.

What additional information would you need to know to compute the absolute depth?

Q3: What are the requirements of the placement of a set of points in the world that you are able to compute a homography from them based on two camera images with overlapping (but not identical) views?