

APG4011F Assignment 3

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1 Introduction

The purpose of this assignment is to gain an understanding into the principles of image restitution and bundle adjustment. A python program will be used to demonstrate and simulate how image restitution and bundle adjustment is performed. The main tasks of this assignment involve creating appropriate fictitious data so that an image ray intersection, resection and multiple bundle adjustment can be performed. Thereafter, the actual intersection, resection and bundle adjustment will be carried out and results will be compared to the original fictitious data.

2 Background

Image restitution and bundle adjustment has many applications in various fields such as computer vision and photogrammetry. The objective of image restitution is to reconstruct image rays and camera attitude in space, as they existed during the moment of photography. This means that a single image ray will pass through a perspective center, image point, and homologous object point, and so in order to reconstruct an image ray, various parameters need to be taken into consideration: Perspective center coordinates, camera tilt/attitude, camera focal length/principal distance, image point coordinate (in the image coordinate system), and corresponding object point coordinate. The process of reconstructing image rays and camera characteristics can be broken down into two main parts, interior and exterior orientation. Exterior orientation involves parameters concerning the camera, while interior orientation involves parameters of actual image rays.

2.1 Interior Orientation

Interior or Inner orientation is described as the reconstruction of the geometry of the bundle of image rays as they existed at the time of photography. It is defined by: the calibrated principle distance of the camera, the position of the principal point in the image plane, and the geometric distortion characteristics of the lens system. In this assignment, fictitious image and object points will be created such that an intersection, resection and full bundle adjustment can be carried out.

Figure 1: Interior Orientation depiction.

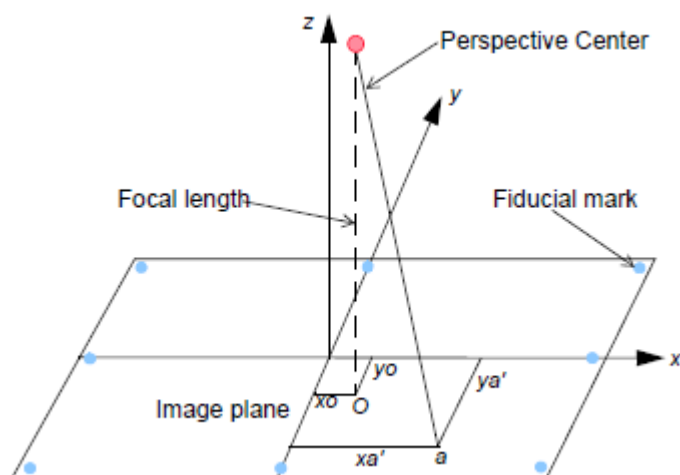


Figure 2: Interior orientation equations.

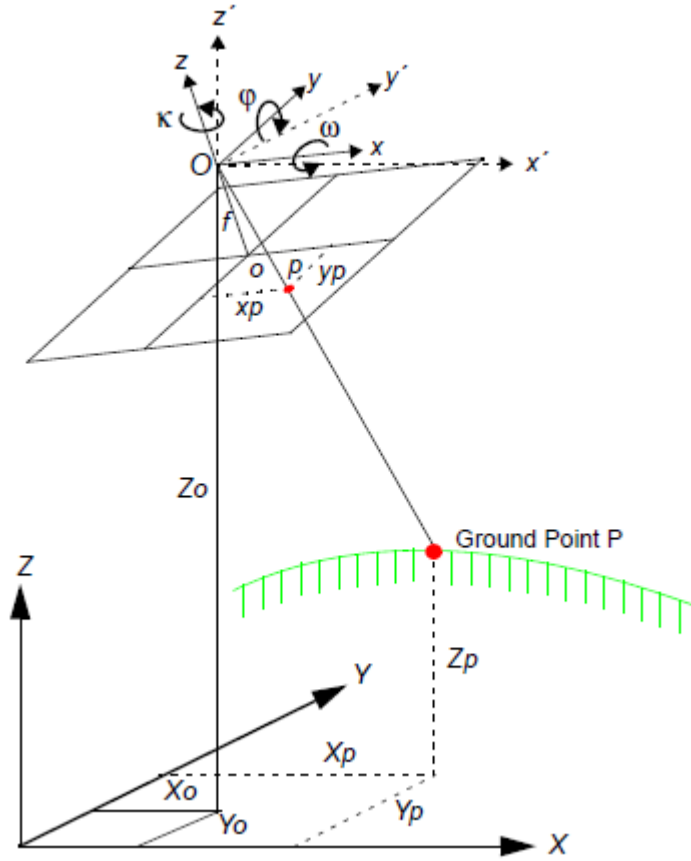
$$\begin{pmatrix} x \\ y \\ z \end{pmatrix} = \begin{pmatrix} x \\ y \\ 0 \end{pmatrix} + \begin{pmatrix} 0 \\ 0 \\ -c \end{pmatrix} = \begin{pmatrix} x_f \\ y_f \\ 0 \end{pmatrix} + \begin{pmatrix} x_o \\ y_o \\ 0 \end{pmatrix} + \begin{pmatrix} 0 \\ 0 \\ -c \end{pmatrix} + \begin{pmatrix} f(x) \\ g(y) \\ 0 \end{pmatrix}$$

→ **Image + lens distortions**

2.2 Exterior Orientation

Exterior or Outer orientation is described as the reconstruction of the position and attitude of the camera as it existed at the time of photography and is defined by: the position of the projection center, and the rotation angles for each 3D axis.

Figure 3: Exterior Orientation depiction.



2.3 Collinearity Condition

In order to relate these two systems, the collinearity condition is used and it states that assuming no unmodelled image and lens distortions, the projection center, object point and corresponding image point should lie on a straight line.

Figure 4: Collinearity Condition Equations.

$$\begin{pmatrix} X \\ Y \\ Z \end{pmatrix} = sR^T \begin{pmatrix} x \\ y \\ -c \end{pmatrix} + \begin{pmatrix} X_o \\ Y_o \\ Z_o \end{pmatrix}$$
$$\begin{pmatrix} x \\ y \\ -c \end{pmatrix} = kR \begin{pmatrix} X - X_o \\ Y - Y_o \\ Z - Z_o \end{pmatrix}$$

Bundle adjustment can be defined as the simultaneous refining of 3D coordinates describing a scene geometry as well as the parameters of the relative motion and optical characteristics of the cameras used to acquire images, according to an optimal criterion involving the corresponding image projections of all points.

3 Problem Statement

There are three main questions which will be addressed in this assignment. They are listed below:

3.1 Intersection

Given a set of object points which have homologous points in two separate images, with each image having unique exterior orientation parameters, set up a least squares adjustment using the collinearity equations to redetermine the object points from each pair of homologous points from each image. Thereafter, compare the new object coordinates to those original, pregenerated object coordinates.

3.2 Resection

Given a set of object points, which each have a homologous point in two separate images, set up a least squares adjustment to determine the exterior orientation parameters of each image,

3.3 Bundle Adjustment

Given a set of object points, treat 80% of them as control, and the remainder as tie points. Then, use the collinearity equations to set up a least squares adjustment to simultaneously determine the exterior orientation parameters of the two images as well as the object coordinates of the tie points.

4 Method

A python program was created which is used to run the various adjustments and calculations pertaining to the questions in this assignment.

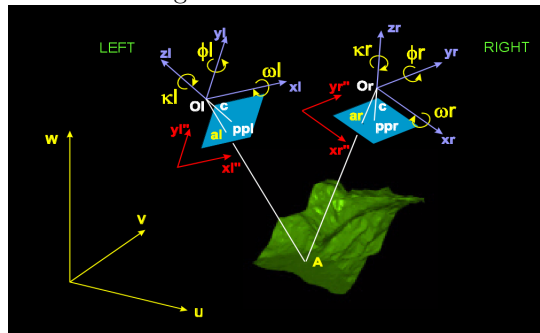
4.1 Creating fictitious Object Points

In order to create fictitious object points, each with two homologous points in different images, two camera positions were created, each with a unique perspective center. Parameters for the first image were set up and thirty random points were generated in the first image's image coordinate system. These random points were then projected down into the object coordinate system using the collinearity equations and predefined rotations and scales. Then, in order to create the homologous points in the second image, the object points were reprojected to the second image again using the collinearity equations. This resulted in three sets of homologous points, namely, those in the first image's image system, those in the object system, and those in the second image's image system.

4.2 Intersection

The intersection in the context of image resititution and bundle adjustment, requires two perspective centers (two images), each which contain the same object point in them. This allows for two imaging rays to be constructed and intersected which allows for the determination of the intersection point's coordinates. An imaging ray passes through a perspective center, image point, and object point once interior and exterior orientation has taken place. Given that three sets of perfectly homologous points had been created, small random errors were added to the second image's image points to allow for a meaningful comparison of the results of the intersected object points to the existing object points.

Figure 5: Intersection.



4.3 Resection

5 Results

6 Discussion

7 Conclusion