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%=====
% Name:          hw3_3.m
%
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%
%=====

% Transformation matrix
gWC = [4.32978028117747e-17,0.707106781186548,0.707106781186548,4;-0.866025403784439,0.353553390593274,-0.353553390593274,3;-0.500000000000000,-0.6123'
p1_C = [24;-9.50000000000000;25];
p2_W = [12.8926822012171;-78.3963768496259;10.5141258557173];
psi = [250,0,240;0,250,320;0,0,1];
r3 = [251;57];

% a) Give the ray (in camera units/pixels) that the point
%   pC1 = (24.0000, 29.5000, 25.0000)T lies on.
%   Also give it as a ray with the last element normalized
%   (this would be the actual pixel location in the image that the point
%   projects to, modulo the quantization).

ray1 = psi * p1_C;
ray1normalized = ray1(1:2) / ray1(3);

fprintf('a1) Ray 1:\n');
disp(ray1);

fprintf('a2) Ray 1 normalized:\n');
disp(ray1normalized);

% b) Give the ray (in camera units/pixels) that the point
%   pW2 = (12.8927, 278.3964, 10.5141)T lies on.
%   Please take care that this point is in world coordinates.

R_WC = gWC(1:3,1:3);
T_WC = gWC(1:3,4);
gCW = [R_WC',-R_WC'*T_WC;0,0,0,1];
gCWp2 = (gCW * [p2_W;1]);
ray2 = psi * gCWp2(1:3,:);

fprintf('b1) Ray 2:\n');
disp(ceil(ray2));

ray2normalized = ray2(1:2) / ray2(3);

fprintf('b2) Ray 2 normalized:\n');
disp(ceil(ray2normalized));

% c) Give the ray (in world units) that the image point
%   ?r3 = (251.0000, 57.0000)T maps to when back-projecting the pixel
%   back out into the world. Back-projection is the partial inversion
%   process discussed in class that maps the 2D image point back out
%   to a 3D ray. Let the ray be given in camera frame coordinates.

q3_W = gWC * [inv(psi) * [r3;1];1];
p3_W = q3_W(1:3,:);

fprintf('c) Back projection of ray 3:\n');
disp(p3_W);

% Check that it projects to same ray
gCWp3 = (gCW * [p3_W;1]);
r3check = psi * gCWp3(1:3,:) / gCWp3(3,1);

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a1) Ray 1:
    12000
    5625
     25

a2) Ray 1 normalized:
    480
    225

b1) Ray 2:
    26226
    5964
     41

b2) Ray 2 normalized:
    652
    149

c) Back projection of ray 3:
    3.9632
    2.2364
    3.2346

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