Camera Calibration using Vanishing Point Estimation

Image Analysis and Computer Vision Course

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Overview

Segments detection

From edge detection to selection of straight lines

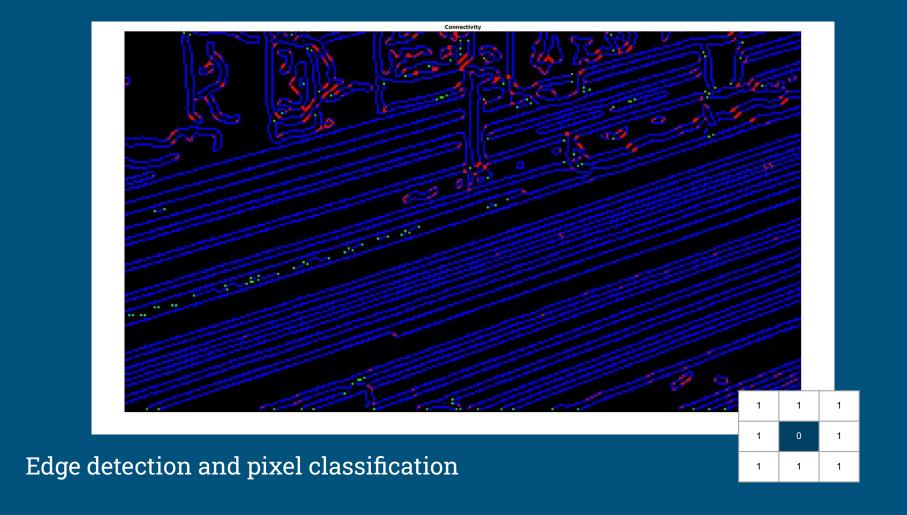
Edges classification

Cluster the edges based on their compatibility with the hypothetical vanishing points

Calibration

Extract the vanishing points on the Manhattan directions and calibrate

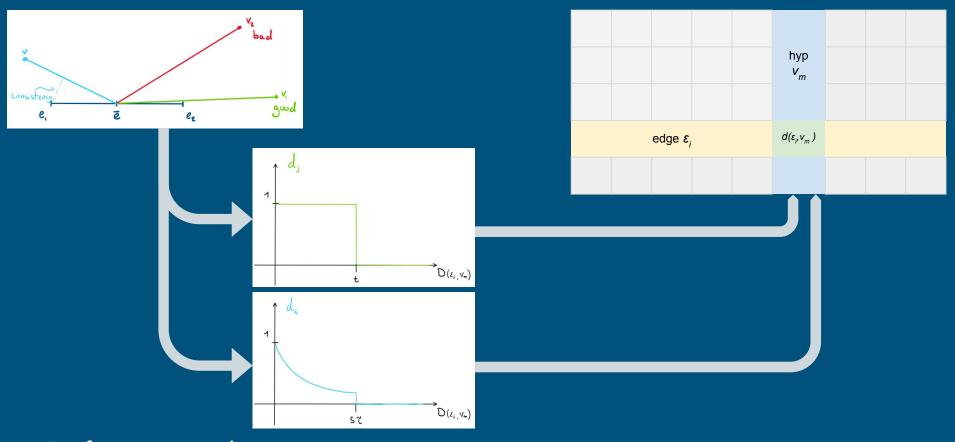
Segments detection



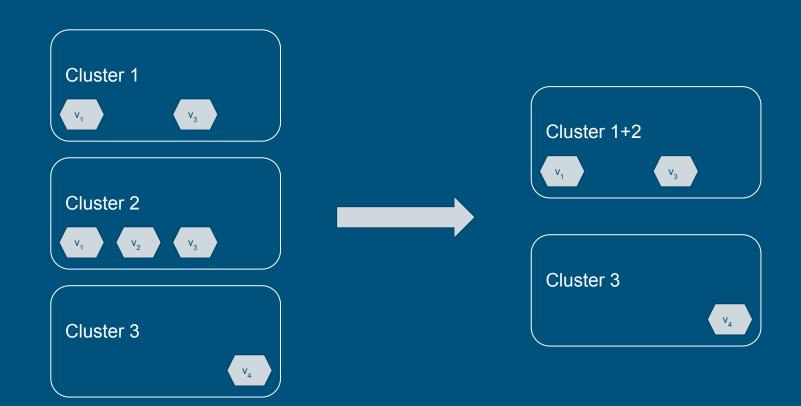


Straight lines detection

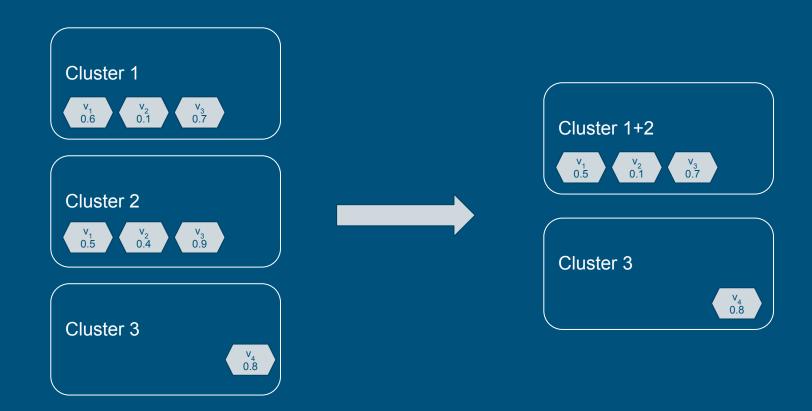
Edges classification



Preference matrix



Clustering - Jaccard



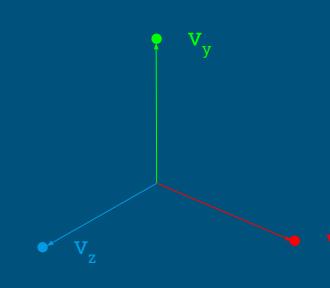
Clustering - Tanimoto

Calibration

$$\omega = (K K^{T})^{-1}$$

$$f \quad 0 \quad u_{o}^{-1}$$

$$K = \begin{bmatrix} 0 & f & v_{o} \\ 0 & 0 & 1 \\ & & -1 \end{bmatrix}$$



$$\mathbf{v}^T \omega \mathbf{u} = \mathbf{0}$$
 $\forall \mathbf{v}' \perp \mathbf{u}'$ s.t.

v is the image of v' u is the image of u'

Assumptions:

$$\bullet \quad f_{_{X}} = f_{_{Y}} \quad = \quad f$$

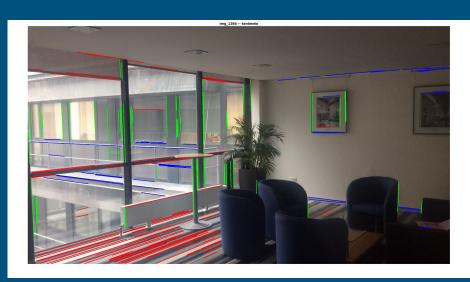
no skew

Orthogonality constraints

Results

Jaccard Tanimoto





Classified edges

Jaccard Tanimoto

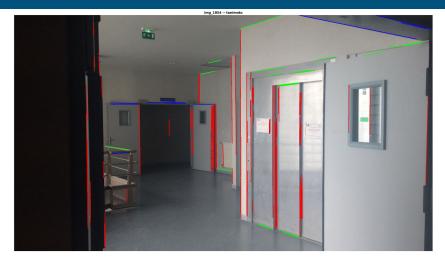




Classified edges

Jaccard Tanimoto





Classified edges

Vanishing Points quality assessment

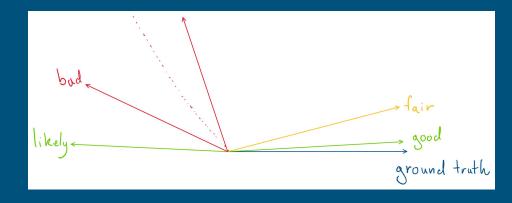
Problems

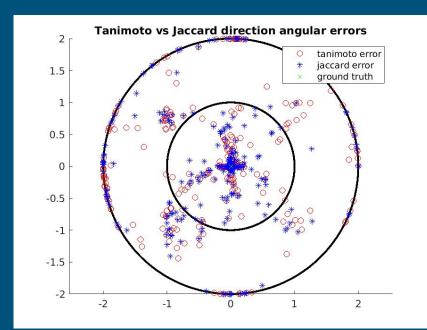
- The farther the VP, the more likely it is to get it wrong
- Associate our VPs with the ground truth ones correctly
- Slight errors in the lines' slopes can cause vanishing points to end on the opposite side of the image



Solution

Compare their directions

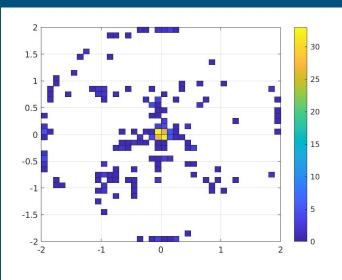


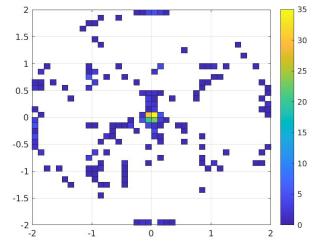


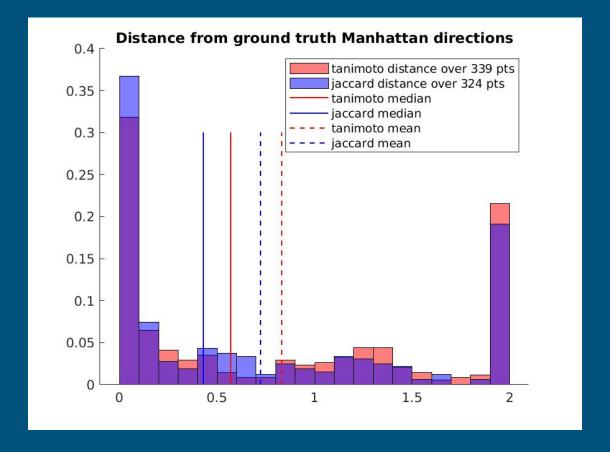
Jaccard

Tanimoto

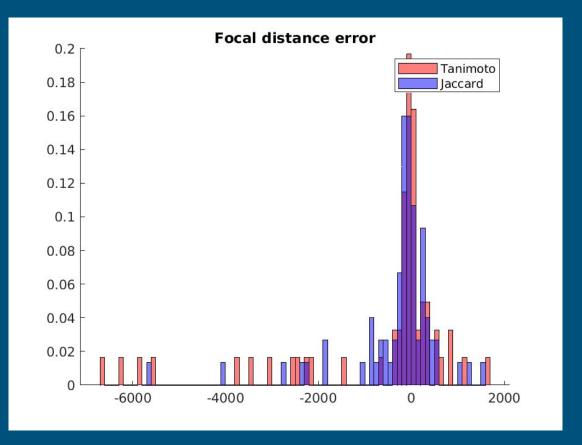
Angular errors of the vanishing points



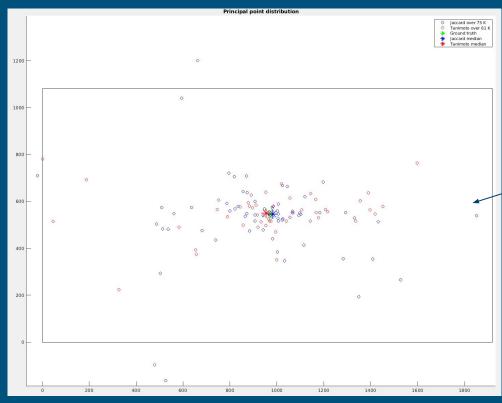




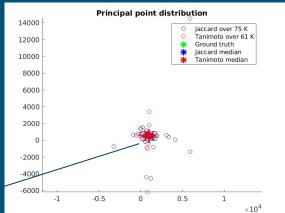
Vanishing points angular error distribution

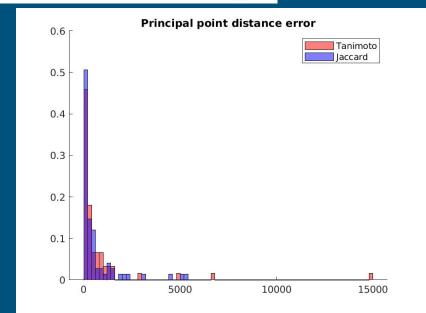


Focal distance absolute error



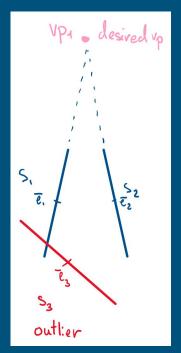


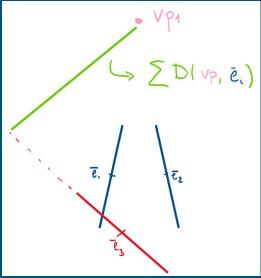


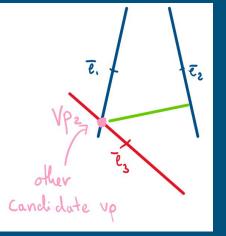


Possible improvements

 The cumulative consistency can suffer severely from outliers: replace function to find better vanishing points







Possible improvements

- Collinear edges' vanishing point is uninformative, and the same for very close lines. Solution: merge these.
- Not all the images had 3 vanishing points: improve segment detection
- Using Tanimoto didn't improve the results: improve the parameters

