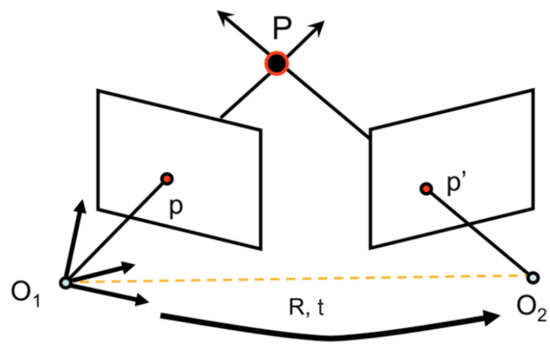
# Epipolar Constraint Derivation

## For the Fundamental Matrix

November 15, 2018




Let $p$, $p'$ be corresponding points in image 1 and 2 respectively, with cameras related by rotation $R$ and translation $t$. Let the intrinsic matrices of cameras 1 and 2 be $K$ and $K'$ respectively.

Then $p'$ in camera 1 coordinates is

$$R^T((K')^{-1}p' - t) = R^T(K')^{-1}p' - R^T t$$

This point, along with $R^T t$, lies in the epipolar plane. So a normal to the epipolar plane is

$$\begin{aligned} R^T t \times (R^T(K')^{-1}p' - R^T t) &= R^T t \times R^T(K')^{-1}p' - R^T t \times R^T t \\ &= R^T(t \times (K')^{-1}p') \end{aligned}$$

Since $K^{-1}p$ also lies in the epipolar plane, $K^{-1}p$ dotted with this normal should equal 0:

$$\begin{aligned} (R^T(t \times (K')^{-1}p'))^T K^{-1}p &= 0 \\ (t \times (K')^{-1}p')^T R K^{-1}p &= 0 \\ (T_x(K')^{-1}p')^T R K^{-1}p &= 0 \\ p'^T(K')^{-T}T_x^T R K^{-1}p &= 0 \\ p'^T(K')^{-T}T_x R K^{-1}p &= 0 \\ p'^T F p &= 0 \end{aligned}$$

where $F = (K')^{-T}T_x R K^{-1}$ is the fundamental matrix.
$T_x$ is a skew-symmetric matrix constructed from the translation vector $t$:

$$\begin{bmatrix} 0 & -t_z & t_y \\ t_z & 0 & -t_x \\ -t_y & t_x & 0 \end{bmatrix}$$