Pose Estimation

4 questions

1
point

1.

What is the minimum number of points required for camera pose estimation given the perspective projections of points with known world coordinates?
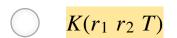
> **3** Enter answer here

1
point

2.

What is the maximum number of solutions obtained from solving the P3P?

> **4** Enter answer here

1
point

3.

Assume that all points in the world lie on the plane $Z_w = 0$. Let K denote the camera calibration matrix. The transformation from the world frame to the camera frame reads $RX_w + T$, where $R = (r_1 \ r_2 \ r_3)$. Which of the following is the projective transformation from the world plane to the camera?

   ○ $K(r_1 \ r_2 \ T)$

○ $K(r_1\ T\ r_3)$

○ $(r_1\ r_2\ T)$

○ $(T\ r_2\ r_3)$

1
point

4.

Assume that all points in the world lie on the plane $Y_w = 0$. Let K denote the camera calibration matrix. The transformation from the world frame to the camera frame reads $RX_w + T$, where $R = (r_1\ r_2\ r_3)$. Which of the following is the projective transformation from the world plane to the camera?

○ $K(r_1\ r_2\ T)$

○ $K(r_1\ r_3\ T)$

○ $K(r_1\ T\ r_3)$

○ $K(r_2\ r_3\ T)$

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4 questions unanswered

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