

# Tomasi-Kanade Factorization

Shree K. Nayar  
Columbia University

Topic: Structure from Motion, Module: Reconstruction II  
First Principles of Computer Vision



# Rank of Observation Matrix

$$\begin{matrix} W & = & M & \times & S \\ 2F \times N & & 2F \times 3 & & 3 \times N \end{matrix}$$

We know:

$$\text{Rank}(MS) \leq \text{Rank}(M) \quad \text{Rank}(MS) \leq \text{Rank}(S)$$

$$\Rightarrow \text{Rank}(MS) \leq \min(3, 2F) \quad \text{Rank}(MS) \leq \min(3, N)$$

$$\Rightarrow \text{Rank}(W) = \text{Rank}(MS) \leq \min(3, N, 2F)$$

**Rank Theorem:**  $\text{Rank}(W) \leq 3$



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$$\underset{2F \times N}{W} = \underset{2F \times 3}{M} \times \underset{3 \times N}{S}$$

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**Rank Theorem:**  $\text{Rank}(W) \leq 3$

We can “factorize”  $W$  into  $M$  and  $S$ !





# Singular Value Decomposition (SVD)

---

For any matrix  $A$  there exists a factorization:

$$A_{M \times N} = U_{M \times M} \cdot \Sigma_{M \times N} \cdot V^T_{N \times N}$$



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$$\Sigma_{M \times N} = \begin{pmatrix} \sigma_1 & 0 & 0 & 0 & \dots & 0 \\ 0 & \sigma_2 & 0 & 0 & \dots & 0 \\ 0 & 0 & \sigma_3 & 0 & \dots & 0 \\ 0 & 0 & 0 & \sigma_4 & \dots & 0 \\ 0 & 0 & 0 & 0 & \ddots & 0 \\ 0 & 0 & 0 & 0 & \dots & \sigma_N \\ 0 & 0 & 0 & 0 & \dots & 0 \\ \vdots & \vdots & \vdots & \vdots & \dots & \vdots \end{pmatrix}$$

$\sigma_1, \dots, \sigma_N$ : **Singular Values**



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$\sigma_1, \dots, \sigma_N$ : **Singular Values**

If  $\text{Rank}(A) = r$  then  $A$  has  $r$  non-zero singular values.





# Enforcing Rank Constraint

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Using SVD:  $W = U \Sigma V^T$

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# Enforcing Rank Constraint

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$$= \begin{pmatrix} U \\ \end{pmatrix} \begin{pmatrix} \begin{matrix} \sigma_1 & 0 & 0 & 0 & \dots & 0 \\ 0 & \sigma_2 & 0 & 0 & \dots & 0 \\ 0 & 0 & \sigma_3 & 0 & \dots & 0 \\ 0 & 0 & 0 & \sigma_4 & \dots & 0 \\ 0 & 0 & 0 & 0 & \ddots & 0 \\ 0 & 0 & 0 & 0 & \dots & \sigma_N \\ 0 & 0 & 0 & 0 & \dots & 0 \\ \vdots & \vdots & \vdots & \vdots & \dots & \vdots \end{matrix} \end{pmatrix} \begin{pmatrix} V^T \\ \end{pmatrix}$$

$2F \times 2F$                        $2F \times N$                        $N \times N$









## Using SVD:

$$W = U \Sigma V^T$$

$$= \begin{bmatrix} U \\ \vdots \end{bmatrix}_{2F \times 2F} \begin{bmatrix} \sigma_1 & 0 & 0 & 0 & \dots & 0 \\ 0 & \sigma_2 & 0 & 0 & \dots & 0 \\ 0 & 0 & \sigma_3 & 0 & \dots & 0 \\ 0 & 0 & 0 & 0 & \dots & 0 \\ 0 & 0 & 0 & 0 & \ddots & 0 \\ 0 & 0 & 0 & 0 & \dots & 0 \\ 0 & 0 & 0 & 0 & \dots & 0 \\ \vdots & \vdots & \vdots & \vdots & \dots & \vdots \end{bmatrix}_{2F \times N} \begin{bmatrix} V^T \\ \vdots \end{bmatrix}_{N \times N}$$

Since  $\text{Rank}(W) \leq 3$ ,  $\text{Rank}(\Sigma) \leq 3$ .



# Enforcing Rank Constraint

Using SVD:

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$$= \begin{pmatrix} \begin{matrix} U_1 \\ U_2 \end{matrix} \end{pmatrix} \begin{pmatrix} \begin{matrix} \sigma_1 & 0 & 0 & 0 & \dots & 0 \\ 0 & \sigma_2 & 0 & 0 & \dots & 0 \\ 0 & 0 & \sigma_3 & 0 & \dots & 0 \\ 0 & 0 & 0 & 0 & \dots & 0 \\ 0 & 0 & 0 & 0 & \ddots & 0 \\ 0 & 0 & 0 & 0 & \dots & 0 \\ 0 & 0 & 0 & 0 & \dots & 0 \\ \vdots & \vdots & \vdots & \vdots & \dots & \vdots \end{matrix} \end{pmatrix} \begin{pmatrix} V_1^T \\ V_2^T \end{pmatrix}$$

$\begin{matrix} 3 & 2F-3 \\ 2F \times 2F \end{matrix} \qquad \begin{matrix} 2F \times N \end{matrix} \qquad \begin{matrix} 3 \\ N-3 \\ N \times N \end{matrix}$

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Submatrices  $U_2$  and  $V_2^T$  do not contribute to  $W$ .



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$$W \Rightarrow U_1 \Sigma_1 V_1^T$$

$(2F \times 3) (3 \times 3) (3 \times P)$



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## Factorization (Finding $M, S$ )

---

$$W = U_1 (\Sigma_1)^{1/2} (\Sigma_1)^{1/2} V_1^T$$



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$$W = \underbrace{U_1 (\Sigma_1)^{1/2}}_{(2F \times 3)} \underbrace{(\Sigma_1)^{1/2} V_1^T}_{(3 \times N)}$$



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$$W = \underbrace{U_1 (\Sigma_1)^{1/2}}_{(2F \times 3)} \underbrace{(\Sigma_1)^{1/2} V_1^T}_{(3 \times N)}$$
$$= M? \quad = S?$$





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Not so fast. Decomposition not unique!

For any  $3 \times 3$  non-singular matrix  $Q$ :

$$W = \underbrace{U_1 (\Sigma_1)^{1/2} Q}_{(2F \times 3)} \underbrace{Q^{-1} (\Sigma_1)^{1/2} V_1^T}_{(3 \times N)} \text{ is also valid.}$$



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$$= M \quad = S \dots \text{ for some } Q.$$

How to find the matrix  $Q$  ?





# Factorization (Finding $M, S$ )

$$W = \underbrace{U_1 (\Sigma_1)^{1/2}}_{(2F \times 3)} \underbrace{(\Sigma_1)^{1/2} V_1^T}_{(3 \times N)}$$

$$= M? \quad = S?$$

Not so fast. Decomposition not unique!

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# Orthonormality of $M$

The Motion Matrix  $M$ :

$$M = \begin{bmatrix} \mathbf{i}_1^T \\ \vdots \\ \mathbf{i}_F^T \\ \mathbf{j}_1^T \\ \vdots \\ \mathbf{j}_F^T \end{bmatrix} = \underbrace{U_1(\Sigma_1)^{1/2}}_{\text{Computed}} Q$$



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Scene Structure





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# Results

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Input Image Sequence



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Input Image Sequence



Estimated 3D Points

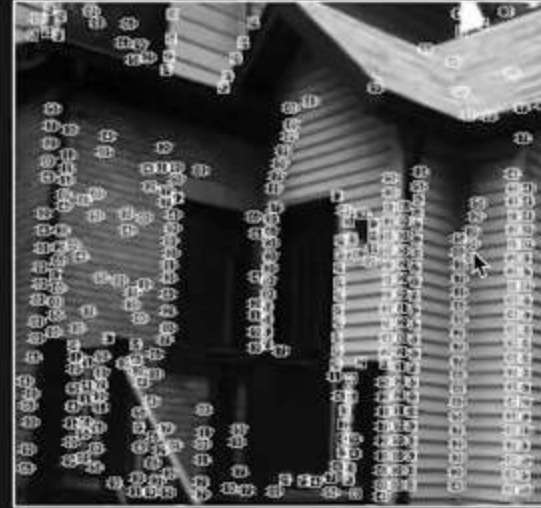




# Results



Input Image Sequence



Tracked Features



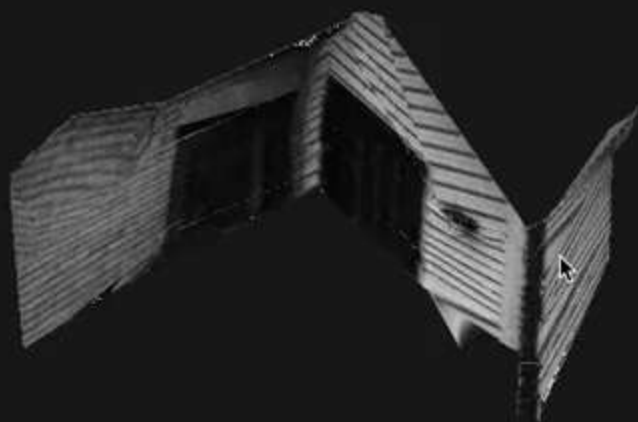
# Results



Input Image Sequence



Tracked Features



3D Reconstruction



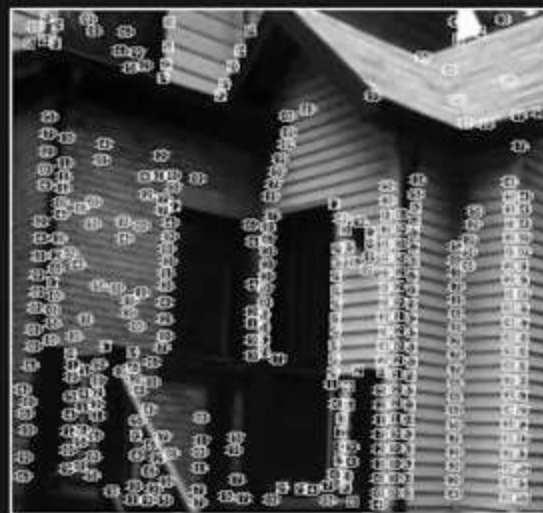
3D Reconstruction



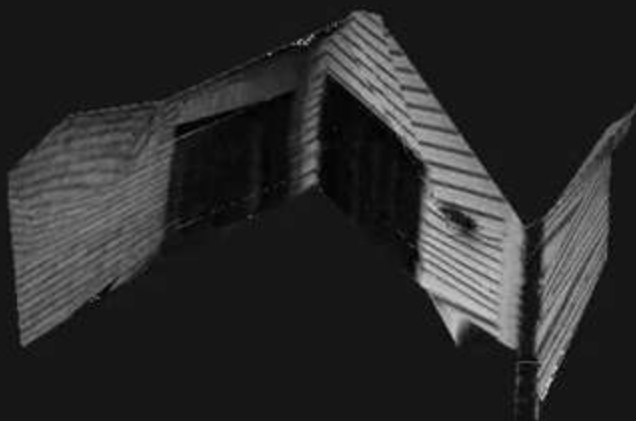
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3D Reconstruction



3D Reconstruction





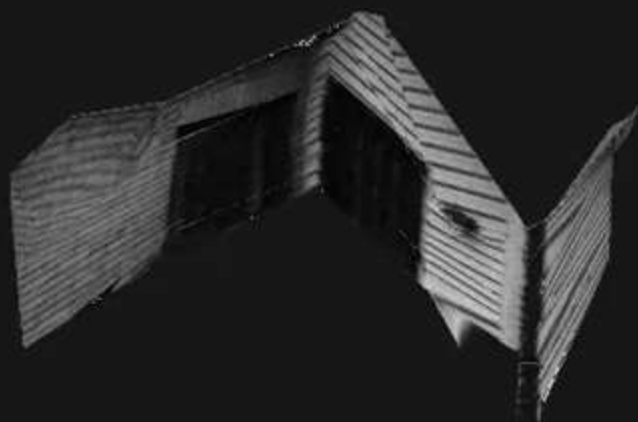
# Results



Input Image Sequence



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3D Reconstruction



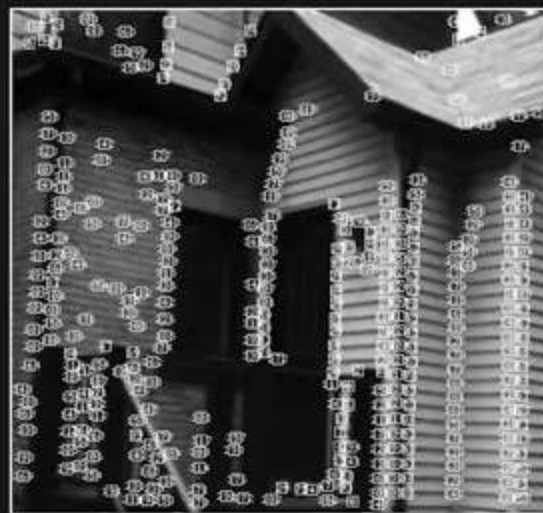
3D Reconstruction



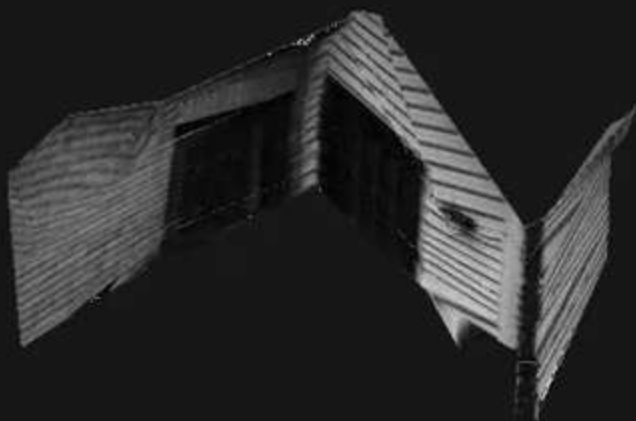
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Input Image Sequence



Tracked Features



3D Reconstruction



3D Reconstruction





# Structure From Motion: Result

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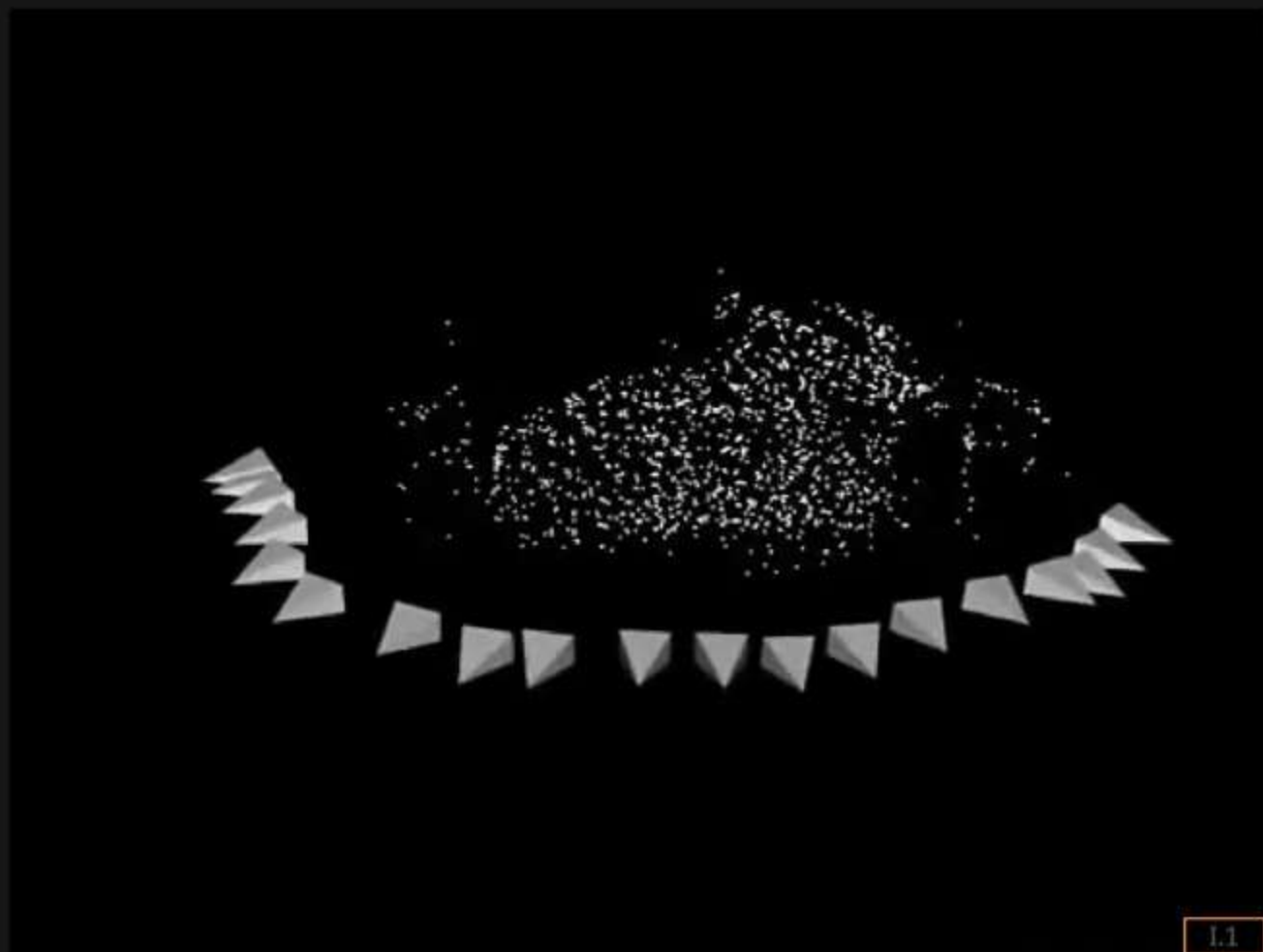
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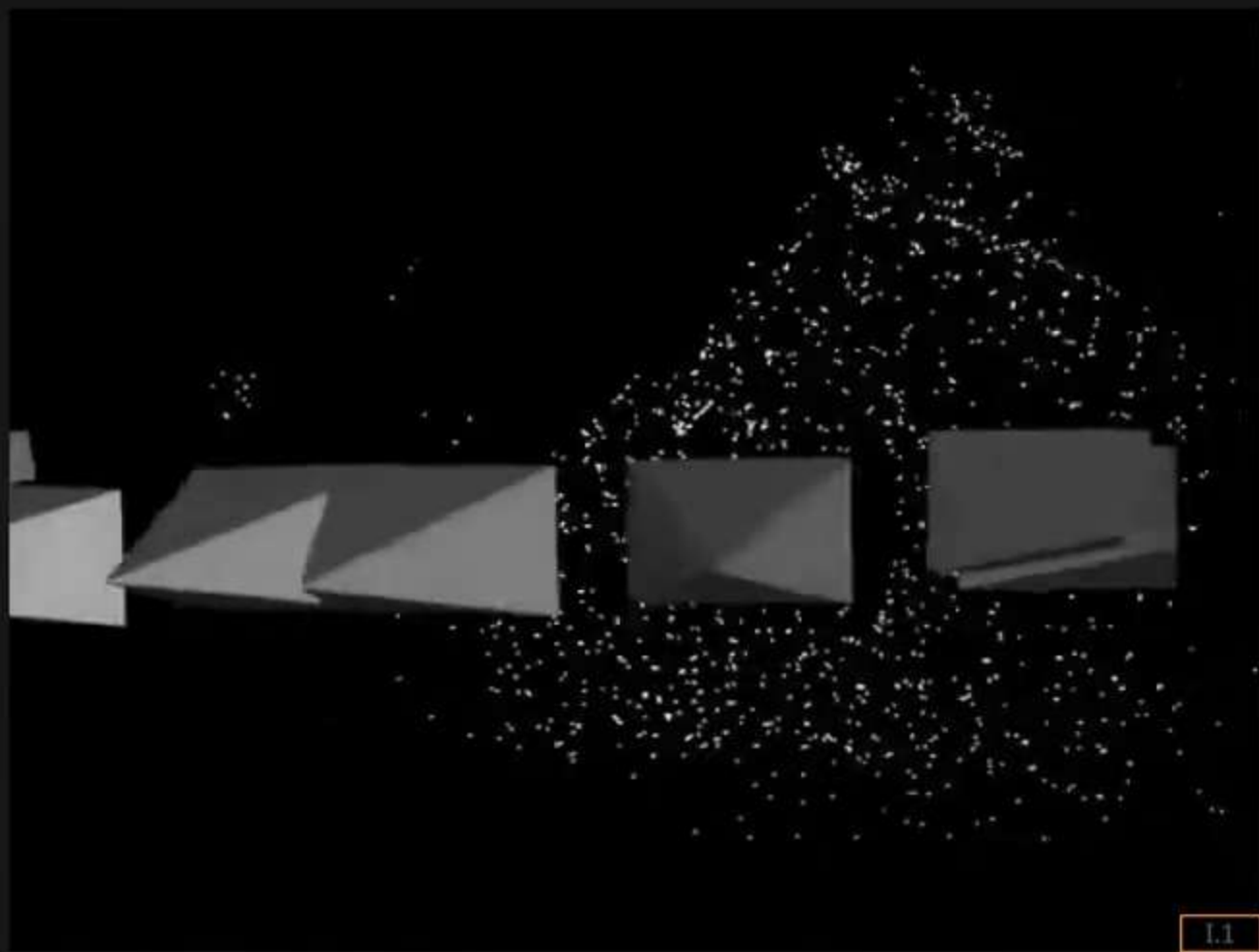
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# Structure From Motion: Result

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# Structure From Motion: Result

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1.1





# Structure From Motion: Result

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# References: Papers

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[Tomasi 1992] Tomasi, C. and Kanade, T. "Shape and Motion from Image Streams under Orthography: A Factorization Method" IJCV, 1992.

[Pollefeys 2002] M. Pollefeys and L. Van Gool. Visual modeling: from images to images, The Journal of Visualization and Computer Animation, 13: 199-209, 2002.