χ^2 566	473, 475–476, 479, 487, 489, 496, 498, 515, 521, 525,
	528
A	affine reconstruction by alternation 440
absolute conic 5–6, 9, 16–18, 78, 80–84, 195, 209–210, 224,	affine transformation 39
272–277, 340, 458, 461, 464, 471, 475, 485, 487, 500	algebraic distance 93–94, 96–97, 186, 279, 308
relation to orthogonality 83	algebraic distance
absolute dual quadric 83–85, 458, 462, 466–467, 469,	comparison with geometric distance 95
472–473, 475, 477	algebraic error
absolute dual quadric 83–84, 463	minimizing 186
absolute dual quadric	algebraic minimization 107, 289, 400
extracting the rectifying transform 463	algebraic solution
properties 462	limitations 468
simple properties 462	ambiguities
adjoint matrix 31, 581	auto-calibration 478
affine camera 14, 166, 169, 172–174, 176, 184–185, 271, 344,	ambiguity 480
347, 355, 413, 425, 432, 436–437, 440–441, 520	ambiguity
affine camera	affine 438–439, 442, 444
	auto-calibration 473
counting arguments 425	
decomposition 169	bas-relief 356–359, 633
definition 166	examples 543
definition 166	for 2D cameras 535
error in employing 168	for 3D cameras 536
estimation of 184	for three views 554
hierarchy of 170	Necker reversal 356
more properties 172	of auto-calibration 473, 479–480
affine fundamental matrix 298, 308, 345, 347–349, 351–353,	of auto-calibration
360–361, 390, 413, 439	for a sequence 480
affine fundamental matrix	projective 265, 387
algebraic derivation 347	single view 549
derivation 345	two views 552
geometric derivation 345	angle
geometric interpretation 349	between two lines in image 215
Gold Standard algorithm 349	between two planes 83, 85, 218, 236
linear algorithm 348	between two rays 9, 195, 209–210, 213, 215, 223, 265
minimal configuration 352	between two scene lines 215
properties 347	of rotation 204–205, 628
singularity constraint 349	angle-axis parametrization 584–585, 624–625
affine geometry. 3	augmentation 601
affine imaging 169	auto-calibration – see also reconstruction metric, 18, 58, 86,
affine imaging conditions 346	205, 210, 253, 340, 439, 453, 456, 458–459, 461–465,
affine imaging model 169	469, 473–474, 476–479, 481, 483, 485–486, 490,
affine matrix 40, 98, 347	496–500
affine matrix 62	auto-calibration 274
affine multiple view tensors	auto-calibration
computation 439	ambiguities 478
affine properties 43, 49–50, 55, 62, 79–81, 220, 223	critical motion sequences 497
affine properties of reconstruction 81	finding plane at infinity 473
affine properties	from planar motion 496
recovery from image 49	implementation 485
affine reconstruction 10, 261, 266, 268–272, 274, 277, 339,	iterative methods 467
351, 355–356, 360, 434, 436–437, 439–440, 456, 459,	limitations of absolute dual quadric method 468

metric from affine 475	camera motion
numbers of views needed 467	recovering it 444
of stereo rig 494	camera orientation 156, 205, 210, 623
problems if \mathbb{Q}_{∞}^* not positive-definite 469	finding it 163
removing ambiguity 479 removing the ambiguity 479	camera parameters 147, 156, 164, 170, 182, 185–188, 193, 232, 399, 435, 444, 458, 467, 602, 610–611, 627
solving for \mathbb{Q}_{∞}^*	camera resectioning
linear 464	covariance 188
non-linear 466	degenerate configurations 179
solving for \mathbb{Q}_{∞}^*	from five points 549
non-linear 466	minimal solution 179
typical ambiguities 480 using \mathbb{Q}_{∞}^* 463	over-determined solution 179 camera rotation 155
varying parameters 477	camera translation 204, 249–250
auto-epipolar 249, 260	camera translation 155
axis planes of camera 160, 199	camera
	affine – see affine camera
B	affine 172
back-projection	at infinity 173
of conics 199 of lines 197	basic pinhole model 153 calibrated 193, 209, 231, 234
of points to rays 161	CCD 156
banded data 614	centre 158
bas-relief ambiguity 356	finite 170
bias 109, 150, 184, 302, 321, 568, 570–577	finite projective 157
dependency on parametrization 571	general projective 157
lessons 572	known orientation 448
bundle adjustment 14, 397, 434–435, 444, 452–453, 461, 467, 498, 611	line 175 pinhole model 153
bundle adjustment 434	projective 7, 153, 157–159, 161, 165–166, 173–176,
bundle adjustment	184–185, 193, 208, 213, 253, 361, 459, 509, 518
banded structure 614	projective
incremental 453	action on points 161
initial solution 435	pushbroom 174
sparse methods 435 with missing data 611	resection ambiguity 550 rotation 195, 204, 207, 215, 250, 489
with missing data of i	rotation and translation 155
C	cameras
calibrating conic 195	as points 533
orthogonality 231	Carlsson–Weinshall duality 505, 513, 546
calibration constraints 477	Carlsson–Weinshall map 546–547, 549
calibration constraints	Carlsson–Weinshall map definition 546
known internal parameters 273 same camera in all images 273	caution 227
calibration matrix 157, 163–165, 167–168, 170, 190, 204, 209,	central projection 6–7, 34, 37, 153–154, 165, 175, 200, 632
212, 215, 224, 226, 231, 257, 264, 273, 275, 459–460,	central projection 154
463–464, 469, 485, 489	change of coordinates 2, 106, 137, 299, 472, 566, 577
calibration	change of coordinates 566
internal 176, 185, 210, 220, 233, 239, 355, 486, 489–490	Chasles' theorem 535
what does it give? 208 camera anatomy 158	cheiral inequalities solving 526
camera calibration 6, 17, 21, 155, 185, 191, 195, 208, 212,	Cholesky factorization 211, 225–226, 272–273, 275, 277, 469,
216, 219, 222, 224, 228–230, 233, 235, 262, 268, 278,	582
293, 340, 355, 444, 458–459, 473, 482, 511, 595	choosing the depths 445
camera centre 163	circular points 5–6, 18, 25, 44, 48, 52–57, 61–63, 79, 82, 85,
camera centre	211, 226, 229, 235, 341, 485–491, 495, 500–501, 628
finding it 163 moving 207	circular points 52 cofactor matrix 581
camera matrices	collineation – see also projective transformation, 32–33, 65,
compatible with two fundamental matrices 386	631
computation from F 263	column vector 26, 143, 154, 158, 448, 578, 581, 603
computed from three fundamental matrices 386	column vector 159
defined by three fundamental matrices	compatibility conditions 385
uniqueness 385 camera matrix	computing a plane from point and line correspondence 332
canonical form 254	from three point correspondences 330
computation 263	computing vanishing lines 218
decomposition 163	concurrent lines 45–46
in projective space 165	concurrent lines 45
reduced – see reduced camera matrix	condition number 108, 439

conic 30	covariance
conic fitting 127, 229, 297	backward propagation 141
conic	backward propagation
affine classification 60	over-parametrized case 142
analog for fundamental matrix 97	estimation 188
classification 59	forward propagation 139
defined by 5 points 30	matrix 103, 111, 129, 137, 139–146, 148, 150, 188–189,
degenerate 32	282, 298–301, 565–566, 573, 576–577, 598, 603–607
dual – see also dual conic	609–611, 623
dual 31	of epipolar lines 301
dual to circular points 53 projective normal form 59	use in point transfer 148 Cramér-Rao lower bound 573
projective normal form of 59	critical configurations 11, 179, 533–534, 538, 544, 554, 559
tangent lines 31	examples 544
transformations of 36	critical motion sequences 497
conjugacy 59, 83, 212–213, 228–229, 494, 628	critical set 537
conjugacy relation 494	for 2d camera
conjugate configurations – definition 540	definition 536
consistency conditions 331	for 2D cameras 535
constraints	critical surface
from internal parameters 273	for three views 553
from same amera 273	cross product 581
from scene orthogonality 273	cross ratio 42, 44–46, 49, 51, 63, 534–535, 629–631
contour 200–201, 234, 300, 322	cross ratio 44
contour generator 200–202, 233–234, 295	D.
contour generator – definition 200	D
contour apparent 200, 202, 233, 234, 236	deficient-rank systems. 589
apparent 200–202, 233–234, 236 occluding 200	degeneracy 92, 226, 228, 293, 295–296, 323, 342, 381–383, 499, 546, 559
convex hull 515	degeneracy 225, 234, 295–296, 329–330, 352, 456, 498
coordinate orientation 164	degeneracy
coordinates. 2	of triangulation 323
coplanarity constraint 276, 422	transfer 383
correlation 59, 124, 148, 242, 246, 388, 447, 455, 486	degenerate configuration
correlation – definition 59	for resectioning 179
correspondence	for transfer 382
of curves and surfaces 295	degenerate configurations – see also camera resectioning,
of lines 294	transfer, homography 2D estimation
correspondences	degenerate configurations 127, 179, 341, 352, 443, 468, 545,
determining 124	559
corridor scene 289	degenerate configurations
corridor scene 302 cosine formula 209	2D homography 91
cost function 88, 90, 93–95, 98–99, 101–104, 110–114,	degenerate homographies 334 degrees of freedom (dof) 27
121–123, 125, 129, 134, 187, 191, 284, 287–289, 291,	degrees of freedom (dof)
308, 310, 312, 314–315, 318–319, 349–351, 386,	of trifocal tensor 368
397–399, 404, 435, 462, 467, 485, 496, 498, 513, 597,	degrees of freedom
599–602, 607, 616–624, 626	trifocal 368
cost function 88, 102, 110, 112, 279, 285, 602, 619, 621	depth of points 162
cost function	derivative matrix
heuristic 618	computation 145
Huber 617, 619–622	determining the correct convergence of an algorithm 138
least squares 621	determining the intersection 27
non-convex 619	DIAC – see dual image of the absolute conic
performance 620	direct metric reconstruction using ω 275
properties 619	direct motion estimation 450
robust 122 squared error 619	direct solution for structure and translation 448 distance ratio 270
statistically based 618	distance ratios
cost functions	on a line 270
asymptotically linear 619	distortion correction 191
linear 100	distortion function 191
robust 122	choice 191
summary 620	computing 191
counting argument 18, 43, 63, 255, 383, 387, 411, 425,	distortion
427–428, 451, 461	correction 191
counting argument 427	DLT - see also homography computation, transformation
covariance estimation 608	invariance, triangulation
covariance estimation	DLT 90–91, 93, 96, 104–110, 116, 127, 150, 179–184, 187,
camera resectioning 188	193–194, 276, 312, 424, 510–511, 573, 587, 595

in this images 101, 103, 134, 137, 147 in one image 34, 102, 112–113, 133, 136, 145 minimizing ageometric 106–107, 130, 181, 200, 400 reproduction 112 reproduc		
using line correspondences 180 dual absolute quadric computing assuming zero skew 466 limitations 408 with constrained parameters 466 equivalence to calibration 463 limitations 408 myth constrained parameters 466 equivalence to calibration 463 limitations 408 myth constrained parameters 466 equivalence to calibration 463 limitations 408 mythous 464 septing limited 40 mythous 464 septing 18 my	DLT algorithm	in both images 101, 103, 134, 137, 147
onal absolute quadric computing assuming zero skew 466 limitations 468 with constrained parameters 466 equivalence to calibration 463 linear solution 463 linear solution 463 all conic 31–32, 37, 33–55, 64, 475 dual conic 31–32, 37, 33–55, 64, 475 dual conic 31–32, 37, 33–55, 64, 475 dual timege of the absolute conic 464–466, 477 dual limage of the absolute conic 464–466, 477 dual limage of the absolute conic 464–466, 477 dual quadric 73 dual reconstruction algorithm 503 dual reconstruction algorithm 504 possible conic – see absolute dual quadric of circular points 53 duality 29–31, 66, 207, 456, 503, 507, 514, 546, 548–550, 552 duality 29–31, 66, 207, 456, 503, 507, 514, 546, 548–550, 552 duality 29–31, 66, 207, 456, 503, 307, 514, 546, 548–550, 552 duality 29–31, 68, 207, 436, 503, 307, 514, 546, 548–550, 552 duality 29–31, 68, 207, 436, 503, 307, 514, 546, 548–550, 552 duality 29–31, 68, 207, 436, 503, 307, 514, 546, 548–550, 552 duality 29–31, 68, 207, 436, 503, 307, 514, 546, 548–550, 552 duality 29–31, 68, 207, 436, 503, 307, 514, 546, 548–550, 552 duality 29–31, 68, 207, 436, 503, 307, 514, 546, 548–550, 552 duality 29–31, 68, 207, 436, 503, 307, 514, 546, 548–550, 552 duality 29 general revelope 301–303 eliptic quartic 556–558, 560 epipolar line - see also epipolar lines, 46, 208, 240–249, 241, 631–633 eliptic quartic 526–538, 560 epipolar line - see also epipolar lines, 46, 208, 240–249, 241, 631–633 eliptic quartic 526–538, 560 epipolar line - see also epipolar lines, 46, 208, 240–249, 241, 631–633 eliptic quartic 58, 560 epipolar line correspondence 251 epipolar line correspondence 251 epipolar line correspondence 251 epipolar line correspondence 251 epipolar line correspondence 261 epipolar line correspondence 27 epipolar line correspondence 28 epipolar see also epip	non-invariance 105	in one image 94, 102, 112–113, 133, 136, 145
computing assuming zero skew 466 limitations 408 with constrained parameters 466 equivalence to calibration 403 linear solution 465 specifying linear constraints 464 dual circular points 52 dual conic 31–32, 37, 33–55, 64, 475 dual conic 30 dual image of the absolute conic 464–466, 477 dual linear of the absolute conic definition 210 definition 210 definition 210 definition 210 definition 210 dual reconstruction algorithm 504–506 dual reconstruction algorithm 503 dual eroconstruction algorithm 503 dual reconstruction algorithm 503 dual reconstruction algorithm 503 dual reconstruction algorithm 503 dual reconstruction algorithm 504 dual reconstruction algorithm 503 dual reconstruction algorithm 504 dual reconstruction algorithm 503 dual reconstruction algorithm 504 dual reconstruction algorithm 505 dual reconstruction algorithm 504 dual reconstruction algorithm 505 dual reconstruction algorithm 504 dual reconstruction algorithm 504 dual reconstruction algorithm 505 dual reconstruction algorithm 505 dual reconstruction algorithm 505 dual reconstruction algorithm 505 dual reconstruction algorithm 506 dual reconstruction algorithm 506 dual reconstruction algorithm 507 duality 50–31, 12, 12, 13, 13, 13, 13, 13, 13, 13, 13, 13, 13	using line correspondences 180	minimizing algebraic 129, 186, 288, 290
assuming zero skow 466 with constrained parameters 466 equivalence to calibration 463 linear solution 465 specifying linear constraints 464 dual circular points 52 dual conic 30 - 32, 37, 53–55, 64, 475 dual image of the absolute conic - 464–466, 477 dual image of the absolute conic - 464–466, 477 dual image of the absolute conic - 464–466, 477 dual image of the absolute conic - 464–466, 477 dual image of the absolute conic - 464–466, 477 dual image of the absolute conic - 464–466, 477 dual image of the absolute conic - 464–466, 477 dual image of the absolute conic - 464–466, 477 dual image of the absolute conic - 464–466, 477 dual image of the absolute conic - 464–466, 477 dual image of the absolute conic - 464–466, 477 dual image of the absolute dual quadric of circular points 53 dual reconstruction algorithm 504–506 dual reconstruction 507 dual mage of the absolute conic declaration 507 dual mage of the absolute conic declaration 507 dual mage of th	dual absolute quadric	minimizing geometric 106-107, 130, 181, 290, 400
imitations 468 with constrained parameters 466 equivalence to calibration 463 linear solution 455 specifying linear constraints 464 dual circular points 52 dual conic 31–32, 37, 35–35, 64, 475 dual roin 30 dual image of the absolute conic 464–466, 477 dual image of the absolute conic definition 210 dual quadric; 73 dual reconstruction algorithm 503 dual reconstruction algorithm 504 dual tonic 30 of absolute conic – see absolute dual quadric of circular points 53 duality 29–31, 66, 207, 456, 503, 507, 514, 546, 548–550, 552 duality 29 duality 29–31, 66, 207, 456, 503, 507, 514, 546, 548–550, 552 duality 19–31, 66, 207, 456, 503, 507, 514, 546, 548–550, 552 duality 19–31, 506, 207, 456, 503, 507, 514, 546, 548–550, 552 duality 19–31, 52, 53, 538–538, 500 eipipolar distance 288 eipipolar masce 288 eipipolar masce 288 export enemption 201–303 eipipolar line correspondence 251 exploration correspondence 251 exploration in correspondence 251 explorat	computing	reproduction 112
with constrained parameters 466 equivalence to calibration 463 linear solution 465 specifying linear constraints 464 dual circular points 52 dual conic 31–32, 37, 53–55, 64, 475 dual conic 30 dual image of the absolute conic 464–466, 477 dual incompartion algorithm 504–506 dual reconstruction algorithm 704–706 dual reconstruction 305 dual reconstruction 306	assuming zero skew 466	reprojection 95–97, 103, 112–113, 130, 291, 312, 314, 343,
incar solution 465 specifying linear constraints 464 dual circular points 52 dual conic 31–32, 37, 35–35, 64, 475 dual conic 30 dual image of the absolute conic 464–466, 477 dual quadric 73 dual reconstruction algorithm 503 dual reconstruction algorithm 504 dual of circular points 53 duality 29–31, 66, 207, 456, 503, 507, 514, 546, 548–550, 552 duality 29 E eigenvalue extraction Jacobi's method 581 elation 43, 62, 341, 631–633 eliptic quarte 556–538, 560 epipolar distance 288 epipolar remole 901–303 epipolar line – see also epipolar lines, 46, 208, 240–249, 251–253, 253–353, 358–360, 372–374, 380–385, 340, 4443, 37 epipolar line sourcespondence 251 epipolar line correspondence 251 epipolar line sourcespondence 251 epipolar line fourcespondence 251 epipolar line sourcespondence 251 epipolar line sourcespondence 251 epipolar line fourcespondence 251 epipolar line correspondence 251 epipolar line fourcespondence 251 epipolar line correspondence 251 ep	limitations 468	355, 401, 406, 434–435, 437
linear solution 465 specifying linear constraints 464 dual circular points 52 dual conic 30 dual conic 31–32, 37, 53–55, 64, 475 dual image of the absolute conic 464–466, 477 dual incorrection algorithm 503 dual reconstruction algorithm 903 dual reconstruction algorithm 904 dual conic sea absolute dual quadric of circular points 33 duality 29–31, 66, 207, 456, 503, 507, 514, 546, 548–550, 552 duality 29–31, 66, 207, 456, 503, 507, 514, 546, 548–550, 552 duality 29–31, 66, 207, 456, 503, 507, 514, 546, 548–550, 552 duality principle 548 E E E E E E E E E C cignraluc extraction Jacobi's method 581 elation 43, 62, 234, 631–633 ellipite quartic 556–558, 560 epipolar line, 588 epipolar envelope 301–303 epipolar line, 588 epipolar envelope 301–303 epipolar line, 588 epipolar renvelope 301–303 epipolar line, 588 epipolar renvelope 301–303 epipolar line 347 epipolar line 64 epipolar line 347 epipolar line 64 e	with constrained parameters 466	residual 115–116, 133–139, 150, 188, 288, 290, 400, 513
specifying linear constraints 464 dual circular points 52 dual conic 31–32, 37, 53–55, 64, 475 dual conic 30 dual image of the absolute conic 464–466, 477 dual image of the absolute conic 464–466, 477 dual image of the absolute conic 464–466, 477 dual quadric 73 dual reconstruction algorithm 504–506 dual quadric 73 dual reconstruction algorithm 503 dual reconstruction algorithm 503 dual reconstruction algorithm 503 dual reconstruction algorithm 503 dual reconstruction algorithm 504 duality 29–31, 66, 207, 456, 503, 507, 514, 546, 548–550, 552 duality 29–31, 66, 207, 456, 503, 507, 514, 546, 548–550, 552 duality 29–31, 66, 207, 456, 503, 507, 514, 546, 548–550, 552 duality 29–31, 66, 207, 456, 503, 507, 514, 546, 548–550, 552 duality 29–31, 68, 207, 456, 503, 507, 514, 546, 548–550, 552 duality 29–31, 68, 207, 456, 503, 507, 514, 546, 548–550, 552 duality 29–31, 68, 207, 456, 503, 507, 514, 546, 548–550, 552 duality 29–31, 68, 207, 456, 503, 507, 514, 546, 548–550, 552 duality 29–31, 68, 207, 456, 503, 507, 514, 546, 548–550, 552 duality 29–31, 68, 207, 456, 503, 507, 514, 546, 548–550, 552 duality 29–31, 68, 207, 456, 503, 507, 514, 546, 548–550, 552 duality 29–31, 68, 207, 456, 503, 507, 514, 546, 548–550, 552 duality 29–31, 68, 207, 456, 503, 507, 514, 546, 548–550, 552 duality 29–31, 68, 207, 456, 503, 507, 514, 546, 548–550, 552 duality 29–31, 68, 207, 456, 503, 507, 514, 546, 548–550, 552 duality 29–31, 68, 207, 456, 503, 507, 514, 546, 548–550, 552 duality 29–31, 68, 207, 456, 503, 507, 514, 546, 548–550, 552 duality 29–31, 68, 207, 456, 503, 507, 514, 546, 548–550, 552 duality 29–31, 68, 207, 456, 503, 507, 514, 546, 548–550, 552 duality 29–31, 68, 207, 456, 207, 456, 207, 457, 459, 449, 449, 456, 453, 579, 583, 585, 615 morning 402 defination 257 dual reconstruction algorithm results and file interpretations 165 exclidean transformation of camera 187 extending the fundamental matrics 374 dual reconstruction of camera 187 extending the fundamental matrics 374 dual reconstruction 187 definition 246 expend	•	
dual criterular points \$2 dual conic 30 dual conic 30 dual conic 30 dual conic 30 dual mage of the absolute conic 464-466, 477 dual image of the absolute conic 464-466, 477 dual image of the absolute conic definition 210 dual quadric 73 dual reconstruction algorithm 504 dual reconstruction algorithm 503 duality 29-31, 66, 207, 456, 503, 507, 514, 546, 548-550, 552 duality 29-31, 66, 207, 456, 503, 507, 514, 546, 548-550, 552 duality 29-31, 66, 207, 456, 503, 507, 514, 546, 548-550, 552 duality 29-31, 60, 207, 456, 503, 507, 514, 546, 548-550, 552 duality principle 548 E E E E E E E C 231-233, 263, 269, 288, 201, 295, 298-299, 301-306, 308, 311, 313-318, 324, 234-333, 340, 344-348, 352-353, 358-360, 372-374, 380-385, 400, 406, 443, 470 epipolar inc are see calso epipolar lines, 46, 208, 240-249, 251-253, 263, 269, 288, 291, 295, 298-299, 301-306, 308, 311, 313-318, 324, 283, 382, 334-334-335, 340, 344-348, 352-353, 358-360, 372-374, 380-385, 400, 406, 443, 470 epipolar line are see also epipolar lines, 46, 208, 240-249, 261-263, 261, 261, 261, 261, 261, 261, 261, 261		
dual conic 31–32, 37, 33–55, 64, 475 dual conic 30 dual image of the absolute conic 464–466, 477 dual image of the absolute conic definition 210 dual quadric 73 dual reconstruction algorithm 503 dual reconstruction 405 duality 29–31, 66, 207, 456, 503, 507, 514, 546, 548–550, 552 duality 29 duality principle 548 E E eigenvalue extraction Jacobi's method 581 elation 43, 62, 241, 631–633 elliptic quartic 556–558, 560 epipolar envelope 301–203 epipolar line 58, 523, 538, 538, 538, 538, 538, 538, 538, 53	1 , 0	1
four solutions 259 that all mage of the absolute conic 464–466, 477 dual image of the absolute conic 464–466, 477 dual image of the absolute conic 464–466, 477 dual image of the absolute conic 464–466, 477 dual quadric 73 dual reconstruction algorithm 503 dual reconstruction stop of the absolute dual quadric of absolute conic – see absolute dual quadric of absolute conic – see absolute dual quadric of circular points 53 duality 29–31, 166, 207, 456, 503, 507, 514, 546, 548–550, 552 duality 29 duality principle 548 E eigenvalue extraction Jacobi's method 581 elation 43, 62, 341, 631–633 elliptic quaries 556–558, 560 epipolar distance 288 epipolar evelope 301–303 epipolar line – see also epipolar lines, 46, 208, 240–249, 251–253, 263, 269, 288, 291, 295, 298–299, 301–306, 308, 311, 315–318, 324, 328, 332, 334–335, 340, 400, 443, 470 epipolar line 347 epipolar line ad47 epipolar line ad47 epipolar line ad7 epipolar line ad47 epipolar line ad47 epipolar lines 440–243, 244, 245–247, 249, 280, 298, 309–303, 305, 307, 315–316, 238, 342, 345–347, 358–360, 371, 373–374, 380, 384–385, 392, 470 affine cameras 344 epipolar transfer degeneracies 380 epipoles 240–242, 244, 251–252, 260, 264–266, 280, 286–287, 289, 307, 317–318, 320, 322, 328, 347, 354, 366, 371, 373, 375, 380–382, 384–385, 395–396, 404, 400 epipolar transfer degeneracies 380 epipoles 240–242, 244, 251–252, 260, 264–266, 280, 286–287, 289, 307, 317–318, 320, 322, 328, 347, 354, 366, 371, 373, 375, 380–382, 384–385, 395–396, 404, 400 epipolar transfer degeneracies 380 epipoles 240–242, 244, 251–252, 260, 264–266, 280, 286–287, 289, 307, 317–318, 320, 322, 328, 347, 354, 364, 365, 371, 373, 375, 380–382, 384–385, 395–396, 404, 400 epipolar transfer degeneracies 380 epipoles 240–242, 244, 251–252, 260, 264–266, 280, 286–287, 289, 307, 317–318, 320, 322, 328, 347, 354, 364, 365, 371, 373, 375, 3	1	
dual image of the absolute conic 464–466, 477 dual and image of the absolute conic definition 210 dual quadric 73 dual reconstruction algorithm 504–506 dual reconstruction algorithm 504–506 dual reconstruction algorithm 503 dual reconstruction algorithm 504 dual reconstruction algorithm 503 dual reconstruction algorithm 503 dual reconstruction algorithm 503 duality 29–31, 66, 207, 456, 503, 507, 514, 546, 548–550, 552 duality 29–31, 66, 207, 456, 503, 507, 514, 546, 548–550, 552 duality 29–31, 66, 207, 456, 503, 507, 514, 546, 548–550, 552 duality principle 548 E E E E E E E E E E E E E		
dual mage of the absolute conic definition 210 dual quadric 73 dual reconstruction algorithm 504–506 dual reconstruction algorithm 503 dual reconstruction algorithm 503 dual reconstruction stopportion 503 dual reconstruction stopportion 503 dual reconstruction stopportion 503 dual reconstruction 507 dual algorithm 504–506 dual reconstruction 507 dual algorithm 505 duality 29–31, 66, 207, 456, 503, 507, 514, 546, 548–550, 552 duality 29–31, 66, 207, 456, 503, 507, 514, 548–550, 507, 514, 548–550, 507, 514, 548–550, 507, 514, 548–550, 507, 514, 548–550,		
dual quadric 73 dual reconstruction algorithm 504-506 dual reconstruction algorithm 503 dual reconstruction algorithm 503 dual reconstruction algorithm justification 507 dual reconstruction algorithm justification 507 dual reconstruction algorithm justification 507 dual reconstruction algorithm justification 508 duality 29-31, 66, 207, 456, 503, 507, 514, 546, 548-550, 552 duality 29-31, 66, 207, 456, 503, 507, 514, 546, 548-550, 552 duality 29-duality principle 548 E E E E E E E E C S S S S S S S S S S S S		• •
estimator 109, 117, 122, 135–136, 145, 303, 310, 568–575, dual reconstruction algorithm 503 dual reconstruction 305 duality 29-31, 160, 207, 450, 503, 507, 514, 546, 548–550, 552 duality 29 duality principle 548 E eigenvalue extraction 1 3 cobis method 581 elation 43, 62, 341, 631–633 elliptic quartic 556–558, 560 epipolar sitine – see also epipolar line – see also epipolar line – see also epipolar line – see also epipolar sine – see also epipolar sine – see also epipolar line affine 344 epipolar line affine 344 epipolar line 547 epipolar line affine 349 epipolar line 240–243, 245–247, 249, 280, 298, 300–303, 305, 307, 315–316, 328, 342, 345–347, 358–360, 371, 373–374, 380, 384–385, 392, 470 affine cameras 344 epipolar transfer degeneracies 80 epipoles area resectioning 186 geometric seems 344 retrieval from trifocal tensor 395 retrieving 395 error algebraic earner seetioning 186 geometric interpretation 188 geometric 98, 100–101, 103, 105, 107, 114, 130, 134, 400 edition of the seems of the	•	
dual reconstruction algorithm 503 dual reconstruction algorithm justification 507 duality 29–31, 66, 207, 456, 503, 507, 514, 546, 548–550, 552 duality 29–31, 66, 207, 456, 503, 507, 514, 546, 548–550, 552 duality 29–31, 66, 207, 456, 503, 507, 514, 546, 548–550, 552 duality 29–31, 66, 207, 456, 503, 507, 514, 546, 548–550, 552 duality principle 548 E E E E elation 43, 62, 341, 631–633 elliptic quartic 556–558, 560 epipolar distance 288 epipolar envelope 301–303 epipolar line – see also epipolar lines, 46, 208, 240–249, 251–253, 260, 288, 291, 295, 298–299, 301–306, 308, 311, 315–318, 324, 328, 332, 334–335, 340, 446, 443, 470 epipolar line addressed and affine interpretations 165 euclidean ransformation fixed points 445 exterior orientation of camera 187 extracting the fundamental matrices 374 Exclidean transformation fixed points 495 extending the baseline 452 exterior orientation of camera 187 extracting the fundamental matrices 374 exterior orientation of camera 187 extracting the fundamental matrices 374 exterior orientation of camera 187 extracting the fundamental matrices 374 extending the baseline 452 exterior orientation of camera 187 extracting the fundamental matrices 374 extension and 4, 21, 258–259, 351, 355, 406, 434–437, 439–446, 449, 456, 463, 579, 583, 585, 615 non-rigid 442–443, 456 feature detection 192 Fisher information matrix 573, 577 fixed points 478, 491 fixed points 47 explored and addressed an		•
dual reconstruction algorithm 503 dual reconstruction algorithm justification 507 dual of absolute conic – see absolute dual quadric of circular points 53 duality 29 duality 30	•	
dualir varietion algorithm justification 507 dual of absolute conic – see absolute dual quadric of circular points 53 duality 29–31, 66, 207, 456, 503, 507, 514, 546, 548–550, 552 duality 29—31, 66, 207, 456, 503, 507, 514, 546, 548–550, 552 duality 29—31, 66, 207, 456, 503, 507, 514, 546, 548–550, 552 duality yrinciple 548 E E E E E E E E E E E E E	•	
justification 507 dual of absolute conic - see absolute dual quadric of circular points 53 duality 29 duality 29 duality 29 duality 29 duality 29 duality principle 548 E E eigenvalue extraction Jacobi's method 581 elation 43, 62, 341, 631–633 ellipite quartic 556–558, 560 epipolar distance 288 epipolar envelope 301–303 epipolar inne - see also epipolar lines accessed as exposed affine ameras 344 epipolar lines 240–243, 245–247, 249, 280, 298, 300–303, 303, 311, 315–318, 324, 342, 345–347, 358–360, 371, 373–374, 380, 384–385, 392, 470 affine cameras 344 epipolar lines 240–243, 245–247, 249, 280, 298, 300–303, 303, 303, 313, 315, 318, 324, 345–347, 358–360, 371, 373–374, 380, 384–385, 392, 470 affine 344 epipolar lines 240–243, 244, 251–252, 260, 264–266, 280, 286–287, 289, 307, 317–318, 320, 322, 328, 347, 361, 366, 371, 373, 375, 380–382, 384–385, 395–396, 404, 413, 471, 487–490 epipoles are proposed as a parameters 286 as tensors 413 for affine cameras 344 retrieval from trifocal tensor 395 error algebraic cameras 344 retrieval from trifocal tensor 395 error algebraic cameras 344 retrieval from trifocal tensor 395 error algebraic accessed as 391, 395–396, 309–400, 467 algebraic camera resectioning 186 geometric interpretation 183 geometric 98, 100–101, 103, 105, 107, 114, 130, 134, 400, 401, 103, 105, 107, 114, 130, 134, 400, 401, 103, 105, 107, 114, 130, 134, 400, 401, 401, 401, 402, 403, 403, 404, 449, 450, 463, 579, 583, 585, 615 non-rigid 442–443, 456, 463, 579, 583, 585, 615 non-rigid 442–443, 456, 463, 579, 583, 585, 615 non-rigid 442–443, 456, 460, 450, 450, 450, 450, 450, 450, 450, 45		•
of absolute conic – see absolute dual quadric of circular points 53 duality 29–31, 66, 207, 456, 503, 507, 514, 546, 548–550, 552 duality 29–31, 66, 207, 456, 503, 507, 514, 546, 548–550, 552 duality 29–31, 66, 207, 456, 503, 507, 514, 546, 548–550, 552 duality 29–31, 66, 207, 456, 503, 507, 514, 546, 548–550, 552 duality 29–31, 66, 207, 456, 503, 507, 514, 546, 548–550, 552 duality 29–31, 66, 207, 456, 503, 507, 514, 546, 548–550, 552 duality 29–31, 66, 207, 456, 503, 507, 514, 546, 548–550, 552 duality 29–31, 66, 207, 456, 503, 507, 514, 546, 548–550, 552 duality 29–31, 66, 207, 440, 443, 456, 463, 579, 583, 585, 615 and 140, 404, 444, 456, 463, 459, 585, 561 son-rigid 442–443, 456 feature detection 192 fixed points 487, 491 fixed point	justification 507	
of circular points 53 duality 29–31, 66, 207, 456, 503, 507, 514, 546, 548–550, 552 duality 29–31, 66, 207, 456, 503, 507, 514, 546, 548–550, 552 duality principle 548 E E E cigenvalue extraction Jacobi's method 581 clation 43, 62, 341, 631–633 clipitic quartic 556–558, 560 epipolar distance 288 epipolar envelope 301–303 epipolar line – see also epipolar lines, 46, 208, 240–249, 251–253, 263, 269, 269, 288, 291, 295, 208–299, 301–306, 308, 311, 315–318, 324, 328, 332, 334–335, 340, 344–348, 352–353, 358–360, 372–374, 380–385, 400, 443, 470 epipolar line correspondence 251 epipolar line correspondence 251 epipolar lines 240–243, 245–247, 249, 280, 298, 300–303, 305, 307, 315–316, 328, 342, 345–347, 358–360, 371, 373–374, 380, 384–385, 392, 470 affine cameras 344 epipolar transfer degeneracies 380 epipoles 240–242, 244, 251–252, 260, 264–266, 280, 286–287, 289, 307, 317–318, 320, 322, 328, 347, 361, 360, 371, 373, 375, 380–382, 384–385, 395–396, 404, 413, 471, 487–490 epipoles a form of the complete of th	dual	fixed points 495
duality 29–31, 66, 207, 456, 503, 507, 514, 546, 548–550, 552 duality principle 548 E E eigenvalue extraction Jacobi's method 581 elation 43, 62, 341, 631–633 elipite quartic 556–558, 560 epipolar distance 288 epipolar envelope 301–303 epipolar ine - see also epipolar lines, 46, 208, 240–249, 251–253, 263, 269, 288, 291, 295, 298–299, 301–306, 308, 311, 315–318, 324, 328, 332, 334–335, 340, 344–348, 352–353, 358–360, 372–374, 380–385, 400, 406, 443, 470 epipolar line correspondence 251 epipolar line affine 344 epipolar line as 440–243, 245–247, 249, 280, 298, 300, 303, 305, 307, 315–316, 328, 342, 345–347, 358–360, 371, 373–374, 380, 384–385, 392, 470 affine cameras 344 epipolar transfer degeneracies 380 epipoles 240–242, 244, 251–252, 260, 264–266, 280, 286–287, 289, 307, 317–318, 320, 322, 328, 347, 361, 366, 371, 373, 375, 380–382, 384–385, 395–396, 404, 413, 471, 487–490 epipoles epipoles epipoles 240–242, 244, 251–252, 260, 264–266, 280, 286–287, 289, 307, 317–318, 320, 322, 328, 347, 361, 366, 371, 373, 375, 380–382, 384–385, 395–396, 404, 413, 471, 487–490 epipoles epipoles error algebraic 88, 93–95, 98, 100, 106, 134, 179, 183–187, 229, 283–284, 288, 391, 395–396, 399–400, 467 algebraic camera resectioning 186 geometric interpretation 183 geometric 98, 100–101, 103, 105, 107, 114, 130, 134,	of absolute conic – see absolute dual quadric	extending the baseline 452
duality 29 duality principle 548 E E Gigenvalue extraction Jacobi's method 581 elliptic quartic 556-558, 560 epipolar distance 288 epipolar envelope 301-303 epipolar line - see also epipolar lines, 46, 208, 240-249, 251-253, 263, 269, 288, 291, 295, 298-299, 301-306, 308, 311, 315-318, 324, 328, 332, 334-335, 340, 406, 443, 470 epipolar line correspondence 251 epipolar line affine 344 epipolar lines 240-243, 245-247, 249, 280, 298, 300-303, 305, 307, 315-316, 328, 342, 345-347, 358-360, 371, 373-374, 380, 384-385, 392, 470 affine cameras 344 epipolar transfer degeneracies 380 epipoles 240-242, 244, 251-252, 260, 264-266, 280, 286-287, 289, 307, 317-318, 320, 322, 328, 347, 361, 366, 371, 373, 375, 380-382, 384-385, 395-396, 404, 413, 471, 487-490 epipolar from trifocal tensor 395 error algebraic 88, 93-95, 98, 100, 106, 134, 179, 183-187, 229, 283-284, 288, 391, 395-396, 399-400, 467 algebraic camera resectioning 186 geometric interpretation 183 geometric 98, 100-101, 103, 105, 107, 114, 130, 134, 46reation 245 degeneracies camera resectioning 186 geometric interpretation 183 geometric 98, 100-101, 103, 105, 107, 114, 130, 134, 46reation 245 degeneracies no tarabation 247 points on a plane 533 fixed points 487, 491 fixed points 47 fixed points 487, 491 fixed points 47 fixed points 487, 491 fixed points 49, 456, 463, 379, 583, 585, 615 non-rigid 442-443, 456 feature detection 192 Fisher information matrix 573, 577 fixed points 487, 491 fixed points 49, 496, 449, 449, 45	of circular points 53	exterior orientation 187
E eigenvalue extraction Jacobi's method 581 elation 43, 62, 341, 631–633 elliptic quartic 556–558, 560 epipolar distance 288 epipolar envelope 301–303 308, 311, 315–318, 324, 328, 332, 334–335, 340, 344–348, 352–353, 358–360, 372–374, 380–385, 400, 443, 470 epipolar line 347 epipolar line correspondence 251 epipolar line ine momography 246 epipolar line shomography 246	duality 29–31, 66, 207, 456, 503, 507, 514, 546, 548–550, 552	exterior orientation of camera 187
E eigenvalue extraction Jacobi's method 581 elation 43, 62, 341, 631–633 elliptic quartic 556–558, 560 epipolar distance 288 epipolar envelope 301–303 epipolar line – see also epipolar lines, 46, 208, 240–249, 251–253, 263, 269, 288, 291, 295, 298–299, 301–306, 308, 311, 315–318, 324, 328, 332, 334–335, 340, 344–348, 352–353, 358–360, 372–374, 380–385, 400, 406, 443, 470 epipolar line correspondence 251 epipolar line bomography 246 epipolar lines 240–243, 245–247, 249, 280, 298, 300–303, 305, 307, 315–316, 328, 342, 345–347, 358–360, 371, 373, 373–374, 380, 384–385, 392, 470 affine cameras 344 epipolar transfer degeneracies 380 epipoles 240–242, 244, 251–252, 260, 264–266, 280, 286–287, 289, 307, 317–318, 320, 322, 328, 347, 361, 366, 371, 373, 375, 380–382, 384–385, 395–396, 404, 413, 471, 487–400 epipoles as parameters 286 as tensors 413 for affine cameras 344 retrieval from trifocal tensor 395 retrieving 395 error algebraic 88, 93–95, 98, 100, 106, 134, 179, 183–187, 229, 283–284, 288, 391, 395–396, 399–400, 467 algebraic camera resectioning 186 geometric 98, 100–101, 103, 105, 107, 114, 130, 134, 56 factorization 14, 211, 258–259, 351, 355, 406, 434–447, 436, 449, 456, 463, 579, 583, 585, 615 non-rigid 442–443, 456 fixed points 487, 491 fixed points 48	•	extracting the fundamental matrices 374
E eigenvalue extraction Jacobi's method 581 elation 43, 62, 341, 631–633 elpitic quartic 556–558, 560 epipolar distance 288 epipolar envelope 301–303 epipolar line - see also epipolar lines, 46, 208, 240–249, 251–253, 263, 269, 288, 291, 295, 298–299, 301–306, 308, 311, 315–318, 324, 328, 332, 334–335, 340, 446, 443, 470 epipolar line 347 epipolar line correspondence 251 epipolar line homography 246 epipolar line suppolar lines 240–243, 245–247, 249, 280, 298, 309, 301, 305, 307, 315–316, 328, 342, 345–347, 358–360, 371, 373–374, 380, 384–385, 392, 470 affine cameras 344 epipolar transfer degeneracies 380 epipoles 240–242, 244, 251–252, 260, 264–266, 280, 286–287, 289, 307, 317–318, 320, 322, 328, 347, 361, 366, 371, 373, 375, 380–382, 384–385, 395–396, 404, 413, 471, 487–490 epipolar line cameras 344 retrieval from trifocal tensor 395 retrieving 395 error algebraic 88, 93–95, 98, 100, 106, 134, 179, 183–187, 229, 283–284, 288, 391, 395–396, 399–400, 467 algebraic camera resectioning 186 geometric interpretation 183 geometrie 98, 100–101, 103, 105, 107, 114, 130, 134, 470, 410, 410, 410, 410, 410, 410, 410, 41	duality principle 548	_
eigenvalue extraction Jacobi's method 581 elation 43, 62, 341, 631–633 ellipite quartic 556–558, 560 epipolar distance 288 epipolar envelope 301–303 epipolar line – see also epipolar lines, 46, 208, 240–249, 251–253, 263, 269, 288, 291, 295, 298–299, 301–306, 308, 311, 315–318, 324, 328, 332, 334–335, 340, 344–348, 352–353, 358–360, 372–374, 380–385, 400, 406, 443, 470 epipolar line correspondence 251 epipolar line bomography 246 epipolar line bomography 246 epipolar line s440–243, 245–247, 249, 280, 298, 300–303, 305, 307, 315–316, 328, 342, 345–347, 358–360, 371, 373–374, 380, 384–385, 392, 470 affine cameras 344 epipolar transfer degeneracies 380 epipoles 240–242, 244, 251–252, 260, 264–266, 280, 286–287, 289, 307, 317–318, 320, 322, 328, 347, 361, 366, 371, 373, 375, 380–382, 384–385, 395–396, 404, 413, 471, 487–490 epipoles as parameters 286 as tensors 413 for affine cameras 344 retrieval from trifocal tensor 395 retrieving 395 error algebraic 88, 93–95, 98, 100, 106, 134, 179, 183–187, 229, 283–284, 288, 391, 395–396, 399–400, 467 algebraic camera resectioning 186 geometric interpretation 183 geometric on a lagebraic camera 422	T.	
Jacobi's method 581 clation 43, 62, 341, 631–633 eliptic quartic 556–558, 560 epipolar distance 288 epipolar envelope 301–303 epipolar envelope 301–303 epipolar line – see also epipolar lines, 46, 208, 240–249, 251–253, 263, 269, 288, 291, 295, 298–299, 301–306, 308, 311, 315–318, 324, 328, 332, 334–335, 340, 344–348, 352–353, 358–360, 372–374, 380–385, 400, 443, 470 epipolar line orrespondence 251 epipolar line bomography 246 epipolar line bomography 246 epipolar line saffine 344 epipolar line saffine 347 epipolar line saffine 344 epipolar line saffine 344 epipolar transfer degeneracies 380 epipolar search 240–242, 244, 251–252, 260, 264–266, 280, 286–287, 289, 307, 317–318, 320, 322, 328, 347, 361, 366, 371, 373, 375, 380–382, 384–385, 395–396, 404, 413, 471, 487–490 epipoles as parameters 286 as tensors 413 for affine cameras 344 retrieval from trifocal tensor 395 retrieving 395 error algebraic 88, 93–95, 98, 100, 106, 134, 179, 183–187, 229, 283–284, 288, 391, 395–396, 399–400, 467 algebraic camera resectioning 186 geometric interpretation 183 geometric 98, 100–101, 103, 105, 107, 114, 130, 134,		
elation 43, 62, 341, 631–633 elliptic quartic 556–558, 560 epipolar distance 288 epipolar line – see also epipolar lines, 46, 208, 240–249, 251–253, 263, 269, 288, 291, 295, 298–299, 301–306, 308, 311, 315–318, 324, 328, 332, 334–335, 340, 46, 443, 470 epipolar line correspondence 251 epipolar line homography 246 epipolar line bomography 246 epipolar line sa47 epipolar line correspondence 251 epipolar line sa49 epipolar line as47 epipolar line correspondence 251 epipolar line sa49 epipolar line sa49, 345–347, 249, 280, 298, 300–303, 305, 307, 315–316, 328, 342, 345–347, 358–360, 371, 373–374, 380, 384–385, 392, 470 affine cameras 344 epipolar transfer degeneracies 380 epipoles 240–242, 244, 251–252, 260, 264–266, 280, 286–287, 289, 307, 317–318, 320, 322, 328, 347, 361, 366, 371, 373, 375, 380–382, 384–385, 395–396, 404, 413, 471, 487–490 epipoles as parameters 286 as tensors 413 for affine cameras 344 retrieval from trifocal tensor 395 retrieving 395 cerror algebraic 88, 93–95, 98, 100, 106, 134, 179, 183–187, 229, 283–284, 288, 391, 395–396, 399–400, 467 algebraic camera sectioning 186 geometric interpretation 183 geometric of the distribution of the points of a Euclidean transformation 495 fixed points of a Euclidean transforma	•	
elliptic quartic 556–558, 560 epipolar distance 288 epipolar envelope 301–303 epipolar line – see also epipolar lines, 46, 208, 240–249, 251–253, 263, 269, 288, 291, 295, 298–299, 301–306, 308, 311, 315–318, 324, 328, 332, 334–335, 340, 344–348, 352–353, 358–360, 372–374, 380–385, 400, 406, 443, 470 epipolar line bomography 246 epipolar line bomography 246 epipolar line bomography 246 epipolar line saffine 344 epipolar lines 240–243, 245–247, 249, 280, 298, 300–303, 305, 307, 315–316, 328, 342, 345–347, 358–360, 371, 373–374, 380, 384–385, 392, 470 affine cameras 344 epipolar transfer degeneracies 380 epipoles 240–242, 244, 251–252, 260, 264–266, 280, 286–287, 289, 307, 317–318, 320, 322, 328, 347, 361, 366, 371, 373, 375, 380–382, 384–385, 395–396, 404, 413, 471, 487–490 epipoles as parameters 286 as tensors 413 for affine cameras 344 retrieval from trifocal tensor 395 retrieving 395 error algebraic x 88, 93–95, 98, 100, 106, 134, 179, 183–187, 229, 283–284, 288, 391, 395–396, 399–400, 467 algebraic camera resectioning 186 geometric interpretation 183 geometric interpretation 184 (2012) definition 245 degeneracies 340 derivation from four planes 422		
epipolar distance 288 epipolar envelope 301–303 epipolar line – see also epipolar lines, 46, 208, 240–249, 251–253, 263, 269, 288, 291, 295, 298–299, 301–306, 308, 311, 315–318, 324, 328, 332, 334–335, 340, 406, 443, 470 epipolar line adverse epipolar line correspondence 251 epipolar line correspondence 251 epipolar line bnomography 246 epipolar line s240–243, 245–247, 249, 280, 298, 300–303, 305, 307, 315–316, 328, 342, 345–347, 358–360, 371, 373–374, 380, 384–385, 392, 470 affine cameras 344 epipolar transfer degeneracies 380 epipoles 240–242, 244, 251–252, 260, 264–266, 280, 286–287, 289, 307, 317–318, 320, 332, 322, 328, 347, 361, 366, 371, 373, 375, 380–382, 384–385, 395–396, 404, 413, 471, 487–490 epipoles as parameters 286 as tensors 413 for affine cameras 344 retrieval from trifocal tensor 395 retrieving 395 error algebraic examera esectioning 186 geometric interpretation 183 geometric interpretation 249, 201–249, 211, 240, 251, 294, 265, 466–469, 472, 484, 486, 497, 499–500, 568 forward projection 197 forwar		
epipolar envelope 301–303 epipolar line - see also epipolar lines, 46, 208, 240–249, 251–253, 263, 269, 288, 291, 295, 298–299, 301–306, 308, 311, 315–318, 324, 328, 332, 334–335, 340, 344–348, 352–353, 358–360, 372–374, 380–385, 400, 443, 470 epipolar line a47 epipolar line homography 246 epipolar line be morgraphy 246 epipolar line supplear lines 240–243, 245–247, 249, 280, 298, 300–303, 305, 307, 315–316, 328, 342, 345–347, 358–360, 371, 373–374, 380, 384–385, 392, 470 affine cameras 344 epipolar transfer degeneracies 380 epipoles 240–242, 244, 251–252, 260, 264–266, 280, 286–287, 289, 307, 317–318, 320, 322, 328, 347, 361, 366, 371, 373, 375, 380–382, 384–385, 395–396, 404, 413, 471, 487–490 epipoles as parameters 286 as tensors 413 for affine cameras 344 retrieval from trifocal tensor 395 retrieving 395 error algebraic 88, 93–95, 98, 100, 106, 134, 179, 183–187, 229, 283–284, 288, 391, 395–396, 399–400, 467 algebraic camera resectioning 186 geometric interpretation 183 geometric interpretation 1495 focal length 16, 21, 36, 157, 166–167, 169, 183–184, 188–190, 192–194, 203, 621, 524, 484, 486, 497, 499–500, 568 forward projection 167 forward projection 161 forward projection 197 forward pr	• •	
epipolar line – see also epipolar lines, 46, 208, 240–249, 251–253, 263, 269, 288, 291, 295, 298–299, 301–306, 308, 311, 315–318, 324, 328, 332, 334–335, 340, 344–348, 352–353, 358–360, 372–374, 380–385, 400, 443, 470 epipolar line correspondence 251 epipolar line homography 246 epipolar line momography 246 epipolar line affine 344 epipolar line save 240–243, 245–247, 249, 280, 298, 300–303, 305, 307, 315–316, 328, 342, 345–347, 358–360, 371, 373–374, 380, 384–385, 392, 470 affine cameras 344 epipolar transfer degeneracies 380 epipoles 240–242, 244, 251–252, 260, 264–266, 280, 286–287, 289, 307, 317–318, 320, 322, 328, 347, 361, 366, 371, 373, 375, 380–382, 384–385, 395–396, 404, 413, 471, 487–490 epipoles as parameters 286 as tensors 413 for affine cameras 344 retrieval from trifocal tensor 395 retrieving 395 error algebraic 88, 93–95, 98, 100, 106, 134, 179, 183–187, 229, 283–284, 288, 391, 395–396, 399–400, 467 algebraic camera resectioning 186 geometric interpretation 183 geometric interpretation 245 defended and additional formation and 1840 derivation from four planes 422	• •	•
of Euclidean transformation 495 308, 311, 315-318, 324, 328, 332, 334-335, 340, 344-348, 352-353, 358-360, 372-374, 380-385, 400, 406, 443, 470 epipolar line 347 epipolar line correspondence 251 epipolar line homography 246 epipolar lines 240-243, 245-247, 249, 280, 298, 300-303, 305, 307, 315-316, 328, 342, 345-347, 358-360, 371, 373-374, 380, 384-385, 392, 470 affine cameras 344 epipolar transfer degeneracies 380 epipoles 240-242, 244, 251-252, 260, 264-266, 280, 286-287, 289, 307, 317-318, 320, 322, 328, 347, 361, 366, 371, 373, 375, 380-382, 384-385, 395-396, 404, 413, 471, 487-490 epipoles as parameters 286 as tensors 413 for affine cameras 344 retrieval from trifocal tensor 395 error algebraic camera resectioning 186 geometric interpretation 183 geometric interpretation 183 geometric interpretation 183 geometric interpretation 183 geometric plant interpretation 183 geometric interpretation 197 forward projection 197 forward proje	• • •	•
344–348, 352–353, 358–360, 372–374, 380–385, 400, 406, 443, 470 epipolar line 347 epipolar line correspondence 251 epipolar line homography 246 epipolar lines 240–243, 245–247, 249, 280, 298, 300–303, 305, 307, 315–316, 328, 342, 345–347, 358–360, 371, 373–374, 380, 384–385, 392, 470 affine cameras 344 epipolar transfer degeneracies 380 epipoles 240–242, 244, 251–252, 260, 264–266, 280, 286–287, 289, 307, 317–318, 320, 322, 328, 347, 361, 366, 371, 373, 375, 380–382, 384–385, 395–396, 404, 413, 471, 487–490 epipoles as parameters 286 as tensors 413 for affine cameras 344 retrieval from trifocal tensor 395 error algebraic R8, 93–95, 98, 100, 106, 134, 179, 183–187, 229, 283–284, 288, 391, 395–396, 399–400, 467 algebraic camera resectioning 186 geometric interpretation 183 geometric 98, 100–101, 103, 105, 107, 114, 130, 134, 466–469, 472, 484, 486, 497, 499–500, 568 forward projection 197 forward projection 161 forward projection 161 forward projection 161 forward projection 107 forward projection 101 forward projection 101 forward projection 104 ines 196 of quadrics 201 Frobenius norm 108, 259, 280–281, 294, 467 fundamental matrix algebraic derivation 243 algorithm results and recommendations 400 both epipoles as parameters 286 computation 263 computation from seven points connection to quadrics 545 computation from seven points or connection to quadrics 545 computation 263 computation 264 decrivation 243 algorithm results and recommendations 400 both epipoles as parameters 286 compu	251–253, 263, 269, 288, 291, 295, 298–299, 301–306,	of Euclidean transformation 495
406, 443, 470 epipolar line 347 epipolar line correspondence 251 epipolar line homography 246 epipolar line homography 246 epipolar line sature projection 161 forward projection 162 for quadrics 20 foredation 243 algorithm results and recommendations 4	308, 311, 315–318, 324, 328, 332, 334–335, 340,	focal length 16, 21, 36, 157, 166–167, 169, 183–184,
epipolar line 347 epipolar line correspondence 251 epipolar line homography 246 epipolar line affine 344 epipolar lines 240–243, 245–247, 249, 280, 298, 300–303, 305, 307, 315–316, 328, 342, 345–347, 358–360, 371, 373–374, 380, 384–385, 392, 470 affine cameras 344 epipolar transfer degeneracies 380 epipoles 240–242, 244, 251–252, 260, 264–266, 280, 286–287, 289, 307, 317–318, 320, 322, 328, 347, 361, 366, 371, 373, 375, 380–382, 384–385, 395–396, 404, 413, 471, 487–490 epipoles as parameters 286 as tensors 413 for affine cameras 344 retrieval from trifocal tensor 395 retror algebraic 88, 93–95, 98, 100, 106, 134, 179, 183–187, 229, 283–284, 288, 391, 395–396, 399–400, 467 algebraic camera resectioning 186 geometric interpretation 183 geometric 98, 100–101, 103, 105, 107, 114, 130, 134, for from two planes 37 Gold Standard algorithm 284 Maximum likelihood 284 condition for point correspondence 245 consistency conditions 331 covariance 610 definition 245 degeneracies no translation 297 points on a plane 553 points on a ruled quadric 296 derivation from four planes 422	344–348, 352–353, 358–360, 372–374, 380–385, 400,	189–190, 192–194, 203, 227–228, 231, 234, 265,
pipolar line correspondence 251 epipolar line homography 246 epipolar line affine 344 epipolar lines 240–243, 245–247, 249, 280, 298, 300–303, 305, 307, 315–316, 328, 342, 345–347, 358–360, 371, 373–374, 380, 384–385, 392, 470 affine cameras 344 epipolar transfer degeneracies 380 epipoles 240–242, 244, 251–252, 260, 264–266, 280, 286–287, 289, 307, 317–318, 320, 322, 328, 347, 361, 366, 371, 373, 375, 380–382, 384–385, 395–396, 404, 413, 471, 487–490 epipoles as parameters 286 as tensors 413 for affine cameras 344 retrieval from trifocal tensor 395 retrieving 395 error algebraic 88, 93–95, 98, 100, 106, 134, 179, 183–187, 229, 283–284, 288, 391, 395–396, 399–400, 467 algebraic camera resectioning 186 geometric interpretation 183 geometric 98, 100–101, 103, 105, 107, 114, 130, 134, for affine correspondence 251 forward projection 161 forward projection of lines 196 of juadrics 201 Frobenius norn 108, 259, 280–281, 294, 467 fundamental matrix algebraic 826 computation 243 algorithm results and recommendations 400 both epipoles as parameters 286 computation 263 computation 264 computation 264 computation 264 computation 264 computation 264 computation		
pipolar line homography 246 pipolar lines 240–243, 245–247, 249, 280, 298, 300–303, 305, 307, 315–316, 328, 342, 345–347, 358–360, 371, 373–374, 380, 384–385, 392, 470 affine cameras 344 pipolar transfer degeneracies 380 pipoles 240–242, 244, 251–252, 260, 264–266, 280, 266–287, 289, 307, 317–318, 320, 322, 328, 347, 361, 366, 371, 373, 375, 380–382, 384–385, 395–396, 404, 413, 471, 487–490 pipoles as parameters 286 as tensors 413 for affine cameras 344 retrieval from trifocal tensor 395 retrieving 395 error algebraic 88, 93–95, 98, 100, 106, 134, 179, 183–187, 229, 283–284, 288, 391, 395–396, 399–400, 467 algebraic camera resectioning 186 geometric interpretation 183 geometric 98, 100–101, 103, 105, 107, 114, 130, 134, 450 pipolar line fomography 246 of quadrics 201 Frobenius norm 108, 259, 280–281, 294, 467 fundamental matrix affine – see affine fundamental matrix algebraic derivation 243 algorithm results and recommendations 400 both epipoles as parameters 286 computation 263 computation from seven points 261 from two planes 337 Gold Standard algorithm 284 Maximum likelihood 284 condition for point correspondence 245 consistency conditions 331 covariance 610 definition 245 degeneracies no translation 297 points on a plane 553 points on a ruled quadric 296 derivation from four planes 422	• •	
repipolar line affine 344 epipolar lines 240–243, 245–247, 249, 280, 298, 300–303, 305, 307, 315–316, 328, 342, 345–347, 358–360, 371, 373–374, 380, 384–385, 392, 470 affine cameras 344 epipolar transfer degeneracies 380 epipoles 240–242, 244, 251–252, 260, 264–266, 280, 286–287, 289, 307, 317–318, 320, 322, 328, 347, 361, 366, 371, 373, 375, 380–382, 384–385, 395–396, 404, 413, 471, 487–490 epipoles as parameters 286 as tensors 413 for affine cameras 344 retrieval from trifocal tensor 395 retrieving 395 error algebraic 88, 93–95, 98, 100, 106, 134, 179, 183–187, 229, 283–284, 288, 391, 395–396, 399–400, 467 algebraic rasectioning 186 geometric interpretation 183 geometric 98, 100–101, 103, 105, 107, 114, 130, 134, and of quadrics 201 for quadrics 201 frobenius norm 108, 259, 280–281, 294, 467 fundamental matrix affine – see affine fundamental matrix algebraic algebraic sanguage derivation 243 algorithm results and recommendations 400 both epipoles as parameters 286 computation from seven points connection to quadrics 545 computation from seven points 281 from two planes 337 Gold Standard algorithm 284 Maximum likelihood 284 condition for point correspondence 245 consistency conditions 331 covariance 610 definition 245 degeneracies no translation 297 points on a plane 553 points on a plane 553 points on a ruled quadric 296 derivation from four planes 422	• •	
affine 344 epipolar lines 240–243, 245–247, 249, 280, 298, 300–303, 305, 307, 315–316, 328, 342, 345–347, 358–360, 371, 373–374, 380, 384–385, 392, 470 affine cameras 344 epipolar transfer degeneracies 380 epipoles 240–242, 244, 251–252, 260, 264–266, 280, 286–287, 289, 307, 317–318, 320, 322, 328, 347, 361, 366, 371, 373, 375, 380–382, 384–385, 395–396, 404, 413, 471, 487–490 epipoles as parameters 286 as tensors 413 for affine cameras 344 retrieval from trifocal tensor 395 retrieving 395 error algebraic 88, 93–95, 98, 100, 106, 134, 179, 183–187, 229, 283–284, 288, 391, 395–396, 399–400, 467 algebraic camera resectioning 186 geometric interpretation 183 geometric 98, 100–101, 103, 105, 107, 114, 130, 134, of quadrics 201 Frobenius norm 108, 259, 280–281, 294, 467 fundamental matrix affine – see affine fundamental matrix algebraic derivation 243 algorithm results and recommendations 400 both epipoles as parameters 286 computation from seven points connection to quadrics 545 computation from seven points 281 from two planes 337 Gold Standard algorithm 284 Maximum likelihood 284 condition for point correspondence 245 consistency conditions 331 covariance 610 definition 245 degeneracies no translation 297 points on a plane 553 points on a plane 553 points on a ruled quadric 296 derivation from four planes 422		1 3
epipolar lines 240–243, 245–247, 249, 280, 298, 300–303, 305, 307, 315–316, 328, 342, 345–347, 358–360, 371, 373–374, 380, 384–385, 392, 470 affine cameras 344 epipolar transfer degeneracies 380 epipoles 240–242, 244, 251–252, 260, 264–266, 280, 286–287, 289, 307, 317–318, 320, 322, 328, 347, 361, 366, 371, 373, 375, 380–382, 384–385, 395–396, 404, 413, 471, 487–490 epipoles as parameters 286 as tensors 413 for affine cameras 344 retrieval from trifocal tensor 395 retrieving 395 error algebraic 88, 93–95, 98, 100, 106, 134, 179, 183–187, 229, 283–284, 288, 391, 395–396, 399–400, 467 algebraic camera resectioning 186 geometric 98, 100–101, 103, 105, 107, 114, 130, 134, 560, 371, 373, 375, 380–382, 384–385, 395–396, 404, 413, 471, 487–490 epipoles as parameters 286 as tensors 413 for affine cameras 344 retrieval from trifocal tensor 395 retrieving 395 error algebraic 88, 93–95, 98, 100, 106, 134, 179, 183–187, 229, 283–284, 288, 391, 395–396, 399–400, 467 algebraic camera resectioning 186 geometric interpretation 183 geometric 98, 100–101, 103, 105, 107, 114, 130, 134, 570–300, 371, 373, 375, 380–382, 384–385, 395–396, 404, 413, 471, 487–490 epipoles as parameters 286 computation from seven points 281 from two planes 337 Gold Standard algorithm 284 Maximum likelihood 284 condition for point correspondence 245 consistency conditions 331 covariance 610 definition 245 degeneracies no translation 297 points on a plane 553 points on a plane 553 points on a ruled quadric 296 derivation from four planes 422	1 1	
305, 307, 315–316, 328, 342, 345–347, 358–360, 371, 373–374, 380, 384–385, 392, 470 affine cameras 344 epipolar transfer degeneracies 380 epipoles 240–242, 244, 251–252, 260, 264–266, 280, 286–287, 289, 307, 317–318, 320, 322, 328, 347, 361, 366, 371, 373, 375, 380–382, 384–385, 395–396, 404, 413, 471, 487–490 epipoles as parameters 286 as tensors 413 for affine cameras 344 retrieval from trifocal tensor 395 retrieving 395 error algebraic 88, 93–95, 98, 100, 106, 134, 179, 183–187, 229, 283–284, 288, 391, 395–396, 399–400, 467 algebraic camera resectioning 186 geometric 98, 100–101, 103, 105, 107, 114, 130, 134, fundamental matrix affine – see affine fundamental matrix algebraic derivation 243 algebraic derivation 263 computation from seven points connection to quadrics 545 computation from seven points 281 from two planes 337 Gold Standard algorithm 284 Maximum likelihood 284 condition for point correspondence 245 consistency conditions 331 covariance 610 definition 245 degeneracies no translation 297 points on a plane 553 points on a ruled quadric 296 derivation from four planes 422		•
affine – see affine fundamental matrix affine cameras 344 epipolar transfer degeneracies 380 epipoles 240–242, 244, 251–252, 260, 264–266, 280, 286–287, 289, 307, 317–318, 320, 322, 328, 347, 361, 366, 371, 373, 375, 380–382, 384–385, 395–396, 404, 413, 471, 487–490 epipoles as parameters 286 as tensors 413 for affine cameras 344 retrieval from trifocal tensor 395 retrieving 395 error algebraic 88, 93–95, 98, 100, 106, 134, 179, 183–187, 229, 283–284, 288, 391, 395–396, 399–400, 467 algebraic camera resectioning 186 geometric 198, 100–101, 103, 105, 107, 114, 130, 134, affine – see affine fundamental matrix algebraic caterivation 243 algorithm results and recommendations 400 both epipoles as parameters 286 computation from seven points connection to quadrics 545 computation from seven points 281 from two planes 337 Gold Standard algorithm 284 Maximum likelihood 284 condition for point correspondence 245 consistency conditions 331 covariance 610 definition 245 degeneracies no translation 297 points on a plane 553 points on a plane 553 points on a ruled quadric 296 derivation 243 algorithm results and recommendations 400 both epipoles as parameters 286 computation 263 computation 263 computation 263 computation 263 computation 263 computation 263 computation from seven points connection to quadrics 545 computation from seven points 281 from two planes 337 Gold Standard algorithm 284 Maximum likelihood 284 condition for point correspondence 245 consistency conditions 331 covariance 610 definition 245 degeneracies no translation 297 points on a plane 553 points on a plane 553 points on a ruled quadric 296 derivation from four planes 422	11	
affine cameras 344 epipolar transfer		
epipolar transfer degeneracies 380 epipoles 240–242, 244, 251–252, 260, 264–266, 280, 286–287, 289, 307, 317–318, 320, 322, 328, 347, 361, 366, 371, 373, 375, 380–382, 384–385, 395–396, 404, 413, 471, 487–490 epipoles as parameters 286 as parameters 286 as tensors 413 for affine cameras 344 retrieval from trifocal tensor 395 retrieving 395 error algebraic 88, 93–95, 98, 100, 106, 134, 179, 183–187, 229, 283–284, 288, 391, 395–396, 399–400, 467 algebraic camera resectioning 186 geometric interpretation 183 geometric 98, 100–101, 103, 105, 107, 114, 130, 134, algorithm results and recommendations 400 both epipoles as parameters 286 computation 263 computation from seven points connection to quadrics 545 connection to planters 341 for affine cameras 344 Maximum likelihood 284 condition for point correspondence 245 consistency conditions 331 covariance 610 definition 245 degeneracies no translation 297 points on a plane 553 points on a ruled quadric 296 derivation from four planes 422		
epipoles 240–242, 244, 251–252, 260, 264–266, 280,		
286–287, 289, 307, 317–318, 320, 322, 328, 347, 361, 366, 371, 373, 375, 380–382, 384–385, 395–396, 404, 413, 471, 487–490 epipoles computation from seven points connection to quadrics 545 computation from seven points 281 from seven points 281 from two planes 337 good Standard algorithm 284 maximum likelihood 284 condition for point correspondence 245 consistency conditions 331 covariance 610 definition 245 degeneracies algebraic camera resectioning 186 geometric 98, 100–101, 103, 105, 107, 114, 130, 134, derivation from seven points connection to quadrics 545 computation from seven points 281 from two planes 337 Gold Standard algorithm 284 maximum likelihood 284 condition for point correspondence 245 consistency conditions 331 covariance 610 definition 245 degeneracies no translation 297 points on a plane 553 points on a ruled quadric 296 derivation from four planes 422	degeneracies 380	both epipoles as parameters 286
366, 371, 373, 375, 380–382, 384–385, 395–396, 404, 413, 471, 487–490 epipoles as parameters 286 as tensors 413 for affine cameras 344 retrieval from trifocal tensor 395 retrieving 395 error algebraic 88, 93–95, 98, 100, 106, 134, 179, 183–187, 229, 283–284, 288, 391, 395–396, 399–400, 467 algebraic camera resectioning 186 geometric 98, 100–101, 103, 105, 107, 114, 130, 134, connection to quadrics 545 computation from seven points 281 from two planes 337 Gold Standard algorithm 284 Maximum likelihood 284 condition for point correspondence 245 consistency conditions 331 covariance 610 definition 245 degeneracies no translation 297 points on a plane 553 points on a ruled quadric 296 derivation from four planes 422		
413, 471, 487–490 epipoles as parameters 286 as tensors 413 for affine cameras 344 retrieval from trifocal tensor 395 retrieving 395 error algebraic 88, 93–95, 98, 100, 106, 134, 179, 183–187, 229, 283–284, 288, 391, 395–396, 399–400, 467 algebraic camera resectioning 186 geometric 98, 100–101, 103, 105, 107, 114, 130, 134, computation from seven points 281 from two planes 337 Gold Standard algorithm 284 Maximum likelihood 284 condition for point correspondence 245 consistency conditions 331 covariance 610 definition 245 degeneracies no translation 297 points on a plane 553 points on a ruled quadric 296 derivation from four planes 422		
epipoles as parameters 286 as tensors 413 for affine cameras 344 retrieval from trifocal tensor 395 retrieving 395 error algebraic 88, 93–95, 98, 100, 106, 134, 179, 183–187, 229, 283–284, 288, 391, 395–396, 399–400, 467 algebraic camera resectioning 186 geometric interpretation 183 geometric 98, 100–101, 103, 105, 107, 114, 130, 134, from two planes 337 Gold Standard algorithm 284 Maximum likelihood 284 condition for point correspondence 245 consistency conditions 331 consistency conditions 331 definition 245 degeneracies no translation 297 points on a plane 553 points on a ruled quadric 296 derivation from four planes 422		. •
as parameters 286 as tensors 413 for affine cameras 344 retrieval from trifocal tensor 395 retrieving 395 error algebraic 88, 93–95, 98, 100, 106, 134, 179, 183–187, 229, 283–284, 288, 391, 395–396, 399–400, 467 algebraic camera resectioning 186 geometric interpretation 183 geometric 98, 100–101, 103, 105, 107, 114, 130, 134, from two planes 337 Gold Standard algorithm 284 Maximum likelihood 284 condition for point correspondence 245 consistency conditions 331 covariance 610 definition 245 degeneracies no translation 297 points on a plane 553 points on a ruled quadric 296 derivation from four planes 422		•
as tensors 413 for affine cameras 344 retrieval from trifocal tensor 395 retrieving 395 error algebraic 88, 93–95, 98, 100, 106, 134, 179, 183–187, 229, 283–284, 288, 391, 395–396, 399–400, 467 algebraic camera resectioning 186 geometric interpretation 183 geometric 98, 100–101, 103, 105, 107, 114, 130, 134, Gold Standard algorithm 284 Maximum likelihood 284 condition for point correspondence 245 consistency conditions 331 covariance 610 definition 245 degeneracies no translation 297 points on a plane 553 points on a ruled quadric 296 derivation from four planes 422	1 1	*
for affine cameras 344 retrieval from trifocal tensor 395 retrieving 395 error algebraic 88, 93–95, 98, 100, 106, 134, 179, 183–187, 229, 283–284, 288, 391, 395–396, 399–400, 467 algebraic camera resectioning 186 geometric interpretation 183 geometric 98, 100–101, 103, 105, 107, 114, 130, 134, Maximum likelihood 284 condition for point correspondence 245 consistency conditions 331 covariance 610 definition 245 degeneracies no translation 297 points on a plane 553 points on a ruled quadric 296 derivation from four planes 422	1	•
retrieval from trifocal tensor 395 retrieving 395 error algebraic 88, 93–95, 98, 100, 106, 134, 179, 183–187, 229, 283–284, 288, 391, 395–396, 399–400, 467 algebraic camera resectioning 186 geometric interpretation 183 geometric 98, 100–101, 103, 105, 107, 114, 130, 134, condition for point correspondence 245 consistency conditions 331 covariance 610 definition 245 degeneracies no translation 297 points on a plane 553 points on a ruled quadric 296 derivation from four planes 422		•
retrieving 395 error algebraic 88, 93–95, 98, 100, 106, 134, 179, 183–187, 229, 283–284, 288, 391, 395–396, 399–400, 467 algebraic camera resectioning 186 geometric interpretation 183 geometric 98, 100–101, 103, 105, 107, 114, 130, 134, consistency conditions 331 covariance 610 definition 245 degeneracies no translation 297 points on a plane 553 points on a ruled quadric 296 derivation from four planes 422		
error covariance 610 algebraic 88, 93–95, 98, 100, 106, 134, 179, 183–187, 229,		
283–284, 288, 391, 395–396, 399–400, 467 algebraic no translation 297 camera resectioning 186 points on a plane 553 geometric interpretation 183 points on a ruled quadric 296 geometric 98, 100–101, 103, 105, 107, 114, 130, 134, derivation from four planes 422	_	
283–284, 288, 391, 395–396, 399–400, 467 algebraic no translation 297 camera resectioning 186 points on a plane 553 geometric interpretation 183 points on a ruled quadric 296 geometric 98, 100–101, 103, 105, 107, 114, 130, 134, derivation from four planes 422	algebraic 88, 93-95, 98, 100, 106, 134, 179, 183-187, 229,	definition 245
camera resectioning 186 points on a plane 553 points on a ruled quadric 296 geometric 98, 100–101, 103, 105, 107, 114, 130, 134, derivation from four planes 422	· ·	degeneracies
geometric interpretation 183 points on a ruled quadric 296 geometric 98, 100–101, 103, 105, 107, 114, 130, 134, derivation from four planes 422	algebraic	no translation 297
geometric 98, 100–101, 103, 105, 107, 114, 130, 134, derivation from four planes 422	•	• •
· ·	• .	•
101–102, 104, 180, 287, 318, 391, 398–399, 430, 438 epipolar parametrization 286	•	*
	101–102, 104, 100, 207, 310, 391, 398–399, 430, 438	срірогаі раганісптийнні 200

extraction of canonical cameras 255	Hessian 599–600
for planar motion	hierarchical merging 453
computation of 14, 78, 86, 247, 250, 252–253, 260–261,	homogeneity. 2
293, 341, 389, 457–458, 486–490, 495, 497, 499	homogeneous representation 27, 30, 33, 65–66, 159, 163, 175
form of 250, 252	446, 516, 518
for translation	of lines 26
computation of 247	of points 27
form of 247	homogeneous scaling 115, 224
geometric derivation 242–243 geometric derivation 242	homogeneous vector 2, 27–28, 51, 65, 88, 90, 144, 154, 249, 317, 447, 623, 625
iterative estimation 283	homographies
over-parametrization 286	what do they say about the camera matrices? 448
parametrization of 285	homography estimation
parametrization of	approximate solution 88
over-parametrization 286	conic analogue 97
projective ambiguity given F 254	degenerate configurations 91
projective invariance of 253	DLT 90
properties 245	error in both images 134, 147
reduced 433, 508–512	error in one image 94, 102, 112–113, 133, 145
reduced	errors in world points 182
computation of 509	experimental evaluation 187
Sampson method for estimation 287, 398 singularity constraint 280	from noisy points 332 function specification 111
symmetric part 251	Gold Standard algorithm 88
symmetric part 251	inhomogeneous solution 90
G	initialization 14, 110, 113–114, 400, 435, 621
gauge freedom 623	iterative methods 114
Gaussian	linear cost function 100
distribution 102-103, 135, 137, 143-144, 299-301, 565,	over-determined solution 90
569–570, 572, 598, 618	parametrization 110
distribution	symmetric transfer error 94, 112
isotropic 134–136	using RANSAC 124
error 100, 102, 111, 116, 122, 150, 314	homography
noise 109, 132–133, 136, 145, 289, 301, 303, 315,	2D 91, 93, 99–101, 105, 109, 114, 123, 129, 133, 142, 145
320–321, 399–400, 436, 571, 575, 616	148, 180–181, 183, 188, 243, 270, 297, 602, 607,
general motion 204, 239, 249–250, 252–253, 293, 406, 467–469, 473, 491, 494, 496, 498–499	609–610 3D 423, 508
general position 31–32, 35, 44, 63, 66–67, 73, 76, 92–93, 131,	compatible with epipolar geometry 327
296, 326, 336, 341, 349, 352, 384, 393, 406, 411, 425,	degenerate 334
533, 539, 545	induced by a plane 368
general position 352	homology
generator	parametrization of 630
of quadric 75	planar harmonic 631
geometric distance 94	horopter 77, 251–253, 343, 487–488, 550–551
geometric error – see also error geometric	horopter 550
camera resectioning 186	Householder matrix 128, 147, 268, 431, 580, 625–626
invariance to coordinate transforms 106	Huber cost function 617, 619–622
geometric interpretation 63, 72, 98, 234, 461, 464, 476	hyperboloid – see quadric, 74–75, 86, 296, 543–545, 548,
geometric interpretation 334, 349	552–553, 559
geometric interpretation of estimation 101	I
geometric minimization 114, 187–188	IAC – see image of the absolute conic
geometric representation 80, 82–84, 213, 246, 250, 252–253,	IAC
463	advantage over DIAC 477
Givens rotation 579	ideal point 28
Gold Standard algorithm 88, 114–116, 130, 181–182, 185,	image of the absolute conic 9, 17–18, 210, 215, 231, 233, 236
284–285, 287–289, 293, 303, 310, 344, 349, 351, 397,	272–273, 275, 461, 469, 473, 475–479, 487
399–401	image of the absolute conic
Gold Standard algorithm	connection to calibration 209
for affine fundamental matrix 349	image plane
for affine homography 130	moving it 203
for fundamental matrix 284	image-equivalent configurations
for homography 114 for trifocal tensor 396	definition 535
gradient descent 599	incidence relations 66, 367, 370–372, 376–377, 379, 422 incidence relations
ground truth 223, 228, 320, 360	for lines 365
groups of projectivities 39	independently moving objects. 442
guided matching 125, 401	infinite homography 205, 250, 270–271, 274, 276, 325,
-	338–339, 341, 473, 475, 479–483, 496, 498, 500
H	infinite homography 270, 475

infinite homography constraint	line estimation 117, 233
relationship to Kruppa equations 481	line projection matrix
infinite homography	definition 198
definition 338 inhomogeneous method 313	line reconstruction 323 line transfer 377
initialization	line transfer 382
for camera resectioning 187	linear equations
interest points 123–125, 290–291, 400–401, 403, 452–453,	systems of unknown rank 589
468	linear solution 465
internal parameters 163, 167, 178, 187, 195, 204, 210, 228,	lines
239, 247–248, 250, 264, 269, 273–274, 276, 339, 365,	concurrent 45
439, 444, 458–459, 461–462, 464, 466, 468–469,	parallel 269
471–473, 475–479, 481–486, 489–490, 492–493,	representation 68, 393
495–500	transformations of 36
of camera	
finding them 163	M
intersection	Mahalanobis
of lines 27, 253, 269, 373 of parallel lines 28	distance 103, 112, 137, 141, 183, 282, 398, 565–566, 598,
invariance to image coordinate transformations 104	603 norm 100, 129, 143
invariants 38–39, 41, 43–44, 63, 77, 176, 266, 489–490, 532,	matching
628	using trifocal tensor 123, 126–127, 291–292, 401–403, 455
invariants 38–40, 42	matrix
invariants	Euclidean 62
of a transformation 38-40, 42	orthogonal
isometries 38	norm-preserving properties 578
iteration	skew-symmetric part 251
weighted 598	symmetric 590
iterative algorithms 533	symmetric part 251
iterative methods 114, 461, 485	Maximum likelihood estimate 114, 127, 134, 144, 181,
iterative minimization 110–113, 121–122, 128, 181, 186–187, 191, 193, 406, 462, 469	184–185, 216, 279, 284–285, 291, 312, 323, 332, 240, 251, 252, 207, 403, 427, 420, 456, 560, 616, 620
191, 193, 400, 402, 409	349–351, 353, 397, 403, 437, 439, 456, 569, 616, 620 Maximum likelihood estimate
J	robust 121, 125
Jacobi's method 581	Maxmimum likelihood estimate
Jacobian 132, 140, 142, 144–145, 147–148, 188, 299, 301,	robust 125
305, 315, 523, 598, 602–604, 606–607, 610–612, 626	measurement matrix
	reduced 186
K	metric calibration 495
Klein	metric properties 25, 48, 53, 55, 79, 82–84, 266, 458
Erlangen Program 32	metric properties of reconstruction 82
known principal point 467, 472, 477	metric properties
Kruppa equations 458, 469–474, 481, 498, 500 Kruppa equations	recovery from images 55 metric reconstruction
relationship to infinite homography 481	via the infinite homography 475
relationship to mininte nonlography 401	metric rectification 55–57, 236, 479
L	metric rectification 55
least squares 110	metric structure 39
least squares solution 589, 597	metric structure : structure
least-squares problems 592	metric 39
least-squares solution 589, 597	metric-calibration
least-squares solution	of a stereo rig 495
of constrained systems 594–595	minimal solution 91–92, 113, 181, 193–194, 279, 348, 352,
using normal equations 591	406 minimization
weighted 592 least-squares solutions	iterative 435
full rank case 588	MLE – see Maximum likelihood estimate
length ratios 6, 41, 43, 51, 54–56, 221–222, 270	modulus constraint 473–474, 499
Levenberg-Marquardt 111, 186, 285, 398, 600–604, 606–609,	modulus constraint 473
616, 621	multiview tensor
Levenberg-Marquardt	affine 439
covariance 604	
implementation 602	N
justification 601	Necker reversal 356
sparse 603, 606	Necker reversal ambiguity 356
line at infinity 2–6, 10, 25, 28–29, 43–44, 48–50, 62, 79, 81,	Newton iteration 111, 114, 597, 599–601, 616, 621
91, 160, 218, 518, 632 line at infinity 28, 48	newton's method and the hessian. 598
line at infinity 28, 48 line correspondences 92, 131, 180, 391–392, 394, 396, 398,	non-collinearity conditions 386 non-isotropic scaling – see scaling – non-isotropic
406, 411, 424, 428, 432, 447, 450, 532	non-isotropic scanng – see scanng – non-isotropic non-rigid factorization 442–443, 456
.00, 111, 121, 120, 102, 177, 730, 332	

non-zero skew 164	parametrization 630
norm	planar motion
in vector space 592	fixed image points 487
normal equations 440, 591, 598–604, 611–612, 614, 623	planar projective transformation
normalization 91, 94, 97, 107–110, 127, 129, 146, 179–181,	definition 33
185, 259, 281–282, 284, 313, 391–392, 394, 396, 446,	plane at infinity 2–4, 6, 9, 16–18, 78, 80, 82–85, 160–162,
513, 618, 624	166, 172–173, 175, 195, 209, 214, 268–272, 274–277,
for camera resectioning 180	313, 338, 347, 353, 425–426, 448–449, 458, 460–461,
for trifocal tensor 394	463, 471, 473–475, 481, 487, 489, 494–496, 500, 515,
why is it essential? 107	517, 519, 521–522, 527–528, 530
normalized coordinates 257	computation 495
normalized coordinates	methods of finding 474
for calibrated camera 257	plane induced parallax 335–336
normalizing transformation 105, 107, 282, 394	plane induced parallax 335
note. 574	plane plus parallax 404
null-space 67–70, 72, 76, 90, 144, 158, 175, 179, 198–199,	plane plus parallax reconstruction
234, 258, 280–281, 283, 296, 299, 309, 348, 367, 374,	counting arguments 425
405, 451, 471, 480, 538, 582, 591	plane
numbers of equations generated. 451	defined by three points 66
	homogeneous vector representation 66
0	point equations
orientation – see also camera orientation	recommended method 431
orientation 11, 30, 37–39, 41–42, 47–48, 105, 156, 163–165,	point transfer
167, 174, 186–187, 193, 210, 215–216, 218, 230–231,	using fundamental matrix 380
262, 264, 273, 301–302, 358, 427, 448, 486, 490, 493,	using trifocal tensor 381
496, 523, 531	point
orthogonal matrices	defined by three planes 67
norm-preserving properties 578	points on a plane 296
orthogonal regression 351, 489	polarity 83
orthogonal regression 406	pole–polar relationship 58
orthogonality and ω 212	positive definite matrix 598
orthogonality in the image 213	positive-definite matrix
orthogonality relationships 219	symmetric 582
orthographic projection 170–172, 174, 177, 456	preserve the convex hull – definition 515
over-parametrization 142	principal axis vector 158
over-parametrization 70, 141–143, 177, 286, 435, 597, 605	principal axis vector 161
	principal plane 154, 158, 160–163, 165, 173, 183, 199, 215,
P	271, 323, 414, 418, 425, 456–457, 518–519, 530
parallax 204, 207–208, 325, 334–337, 339–340, 352–353,	principal plane 160
388, 404, 407	principal plane
induced by a plane 335	of camera 160
parallel lines 1–2, 4, 9, 25, 28–29, 34, 39, 41, 44, 49–50, 65,	principal point 16, 21, 154–155, 157–158, 160–161, 163, 168
86, 174, 176, 215, 217–219, 226, 247–248, 269–270,	170, 185, 191, 203–204, 226–228, 231–232, 235–236,
293–294, 496	260, 464–467, 469, 475, 477–478, 480, 484, 486, 492,
parallel projection 153, 170, 172–173, 200, 344, 346,	498–499
356–357, 361	principal point 160
parameter minimization 620	principal point offset 155
parameter space 113, 134, 141–143, 145, 475, 498, 568, 570,	probability density function 569 profile
572, 574, 577, 623–624	of a surface 200
parameters constant internal 466	programming hint 129, 399
limit range 570	projection
parametrization 76, 100, 110–111, 113–114, 127, 134, 141,	orthographic 171
164, 181, 186, 284–286, 293–294, 316, 392, 398, 406,	parallel 170
467, 491, 499, 512, 568–569, 572, 574, 576, 579, 597,	scaled orthographic 171
610, 623–626, 633	weak perspective 171
epipolar 286	projective ambiguity 265
of 3D rotations 624	projective camera
of homogeneous vectors 624	action on conics 199
of homology 630	action on lines 196
of the n -sphere 625	action on planes 196
what makes a good one? 623	definition 157
Plücker	projective depth 407, 444–447
coordinates 72–73, 86, 197	projective depth 336
line coordinates 72, 198–199, 233	projective factorization
line representation 197	normalizing image coordinates 446
matrix 70, 198	normalizing the weights 446
planar harmonic homology 64, 631	what is being minimized 446
planar harmonic homology 631	projective plane model 29, 47
nlanar homology	projective plane

model 29	affine 339
topology 47	affine properties 81
projective realization – see realization – projective	affine
projective reconstruction	from affine camera 271
dual algorithm 504	from scene constraints 269
from reduced cameras matrices 509	from translation 268
from seven points in n views 512	Euclidean 19, 266–267, 526
from six points 510 from six points in n views 511	metric – see also auto-calibration metric 268, 272–277, 339, 439, 454, 458–461, 463–464,
projective transformation 68	467–468, 473, 476, 479, 481, 488–490, 492, 497–499,
projective transformation	520, 532
decomposition of 42	metric properties 82
projectivity	projective 13, 16–18, 150, 239, 266–268, 270–271,
definition 32	275–277, 310–312, 320, 330, 339, 387, 398, 434,
pseudo-inverse 144–145, 147, 161, 185, 244, 246, 347–348,	445–446, 448, 453, 456, 458–464, 467, 475, 479, 485,
440, 566, 590–592, 595, 598, 605, 610, 626	489, 491, 495–496, 502–503, 506, 508, 511, 514–515,
	519–521, 525–531, 535, 539–540, 602, 627
Q OD decomposition 196 579 590	quasi-affine 475, 515, 517–521, 523, 525–528, 530, 532
QR decomposition 186, 578–580 quadric 6, 72–76, 83–85, 97, 176, 195, 199–202, 234, 267,	rectifying homography 463 reduced camera matrix 207
295–298, 309, 340, 462–464, 473, 499, 541–549,	reduced camera matrix
552–560	definition 502
dual – see dual quadric	reduced fundamental matrix – see fundamental matrix –
ruled 543, 549, 557	reduced
ruled	reduced measurement matrix 186
definition 75	reduced measurement matrix 186
quadrics 73	reduced trifocal tensor – see trifocal tensor – reduced
quadrics	relation
classification of 74	bilinear 419
quadrifocal tensor 13, 411, 421, 423, 426, 432–433, 450 quadrifocal tensor	quadrilinear 420 trilinear 391, 397, 414–417
derivation from four planes 421	reprojection error 401
quartic 97, 474, 559	reprojection error
quasi-affine mapping	both images 95
definition 517	geometric interpretation 96
two-dimensional 518	resection 276, 424, 435, 453, 533-534, 536-539, 549-550,
quasi-affine reconstruction	553, 558, 587
algorithm 527	resectioning – see camera resectioning, 77, 178, 453, 536–537,
bounds on π_{∞} 527	559
quaternions 585	covariance estimation 188
quaternions 585, 624–625	degenerate configuration 179 initialization 187
R	normalization 180
radial distortion 188–193, 223	residuals 187, 192, 194, 216, 298, 472
estimating 191	retrieving the camera matrices 374
RANSAC 88, 114, 117–118, 121–124, 126–128, 193,	robust algorithms 122
290–292, 352, 391, 400–403, 620	robust methods 88, 113, 117-118, 121-123, 125, 128, 281,
RANSAC	291, 352, 391, 393, 401, 455, 514, 597, 617, 619, 622
adaptive 120	Rodrigues formula 585
application domain 125	rotations in n dimensions 583
distance threshold 118 for 2D homography 124	in 3 dimensions 583
for homography 124	row vector 26, 521, 578
number of samples 119	row vector 159
run details 125	
size of consensus set 120	S
realizable points	Sampson approximation 99, 113-114, 287, 291, 308, 314,
definition 503	349, 391, 398, 401
realization 503	Sampson distance 287
realization	Sampson error 98
definition 503	scaled orthographic projection 171
strong 524 realizations	scaling isotropic 62, 107, 445
equivalent	non-isotropic 109
definition 540	with points near infinity 110
non-equivalent 541	scene constraints
oppositely oriented 526	distance ratios
recommendations 289	on a line 270
reconstruction	parallel lines 269
affine – see affine reconstruction	scene orthogonality 273

screw axis 78–79, 86, 253, 487–488, 490, 500	transformation invariance 129
screw decomposition of a rigid motion 77–79	transformation invariance 184
similarity matrix 62	transformation invariance
similarity transformation 39, 43, 53, 107, 184	of DLT 184
Singular Value Decomposition 40, 55, 70, 91, 108, 163, 186,	transformation rule 36–37, 53–54, 63, 231, 394, 406, 475,
225, 258, 280–282, 294, 308, 344, 430, 437–439, 442,	563–564
444–445, 469, 471, 585–590, 592–596	transformation
Singular Value Decomposition	of conic 36
computational complexity 586	of conics 36
implementation 439, 586	of lines 36
singular values	projective 1, 3–4, 7–9, 11–13, 16, 25, 30, 33–37, 41–49,
relation to eigenvalues 586	51–55, 57, 59, 61–65, 74, 76–77, 80–84, 86–88,
singularity constraint 281–282, 288, 349	91–92, 94, 101, 103–105, 115, 132–133, 137, 165,
singularity constraint 349	177–178, 195–196, 201–202, 204, 210, 222, 239,
skew-symmetric part 250–252	249–250, 253–255, 265–268, 271–272, 296, 303,
skyline structure 615–616 solution	305–308, 310, 313, 320, 366, 374–375, 387, 389, 404, 420, 423, 434, 445, 463, 475, 482, 491, 494, 502, 508,
over-determined 179	511, 513, 516–517, 519–522, 524, 527, 529, 531,
space curve 295	533–534, 539–540, 557, 559, 628–631
span representation 70, 322	similarity 39, 43, 53, 107, 184
sparse linear systems	translational motion 293
solution 615	triangulation 12, 263, 267, 276–277, 285, 291, 293, 310–315,
special points 5	318, 320, 323–324, 332, 344, 380, 385, 397, 406, 435,
stability 469	439–440, 442, 453–454, 456, 491, 568, 575
stereo correspondence 240	triangulation 263
stereo correspondence 340	triangulation
stereo rectification 47, 49–50, 228–230, 249, 279, 302–303,	DLT method 312
308–309, 339, 479	evaluation on real images 320
stereo rectification	for affine cameras 353
affine 308	for affine cameras 439–440, 442
algorithm outline 307	inhomogenous method 313
mapping the epipole to infinity 303	local minima 319
matching transforms 305	minimizing the cost function 316
stereo-rig metric calibration 495	problem formulation 315 trifocal tensor 12–13, 16, 87, 108, 119, 123, 164, 365,
stratification 276–277	367–378, 381–383, 386–407, 411, 414–419, 422–423,
stratification 57	426, 431, 439, 443, 446, 452, 456, 488–489, 508, 510,
stratified reconstruction	512, 514, 533, 563–564, 594, 611
affine 268	trifocal tensor
metric 272	affine 390, 406, 418
structure	algebraic properties 373
affine 9, 356, 481, 570, 573	computation from camera matrices 377
metric 233, 276, 461, 491, 611	computation
projective 19, 386, 423, 426, 448, 494, 535	from 6 points 393
subspaces and tensors 442	Gold Standard algorithm 396
SVD – see Singular Value Decomposition symmetric epipolar distance 287	iterative 396 reprojection error 401
symmetric linear equations 614	results and recommendations 400
symmetric linear equations	Sampson distance 287, 398
sparse 615	specifying lines 404
symmetric matrices 590	using algebraic minimization 395
symmetric part 250–252, 261, 293, 489, 541	constraints 392
symmetric transfer error 94, 112	definition 367
synthetic data 132, 138, 399, 572	definition 377
	derivation from four planes 421
T	geometrically valid 392
tangent line	line relations 416
to conic 31	parametrization 398
tensor notation 376	picture 564
tensor	point and line relations 369 point relations 414
pictorial representation 564 terminology 172, 240, 445	reduced 433, 512
topology of IP ¹ 47	relation to two views 418
total least squares 110	transformation rule 563
transfer 14, 16, 94–98, 109, 113, 123–124, 131, 143, 147–150,	trilinearities – see also relations – trilinear
221–222, 242–243, 270, 274, 299, 318, 325, 336, 338,	trilinearities 378
340, 346, 365, 368–369, 374, 377, 379–383, 385, 388,	twisted cubic 75–77, 179–180, 251, 253, 343, 487, 536–537,
392, 398, 462, 473, 476, 485	539–540, 547, 549–553, 558–559
transfer	properties 76
degenerate configurations 382–383	twisted pair 259, 275

```
vanishing lines 176, 213, 216, 218-219, 230, 236, 270
vanishing lines 339
vanishing points 9, 42, 51, 110, 158–159, 161, 176, 180, 195, 208, 212–213, 215, 217–219, 222–224, 226–230,
     232–233, 236, 269–271, 273, 278, 294, 339, 341, 448,
    458, 497
vanishing points 339
vanishing points
computing 215 variance 102, 109, 122, 132–137, 139–141, 143–145,
     147-148, 150, 188, 300-301, 321-322, 565, 568-569,
    573-574, 576-577, 605, 623, 627
vector geometry 67
vector space norms 592
weak perspective 170-172, 357
zero skew 164, 193, 224-226, 228-229, 231, 235, 273,
     465-466, 472, 477-479, 484, 497-499
zero skew 466
```