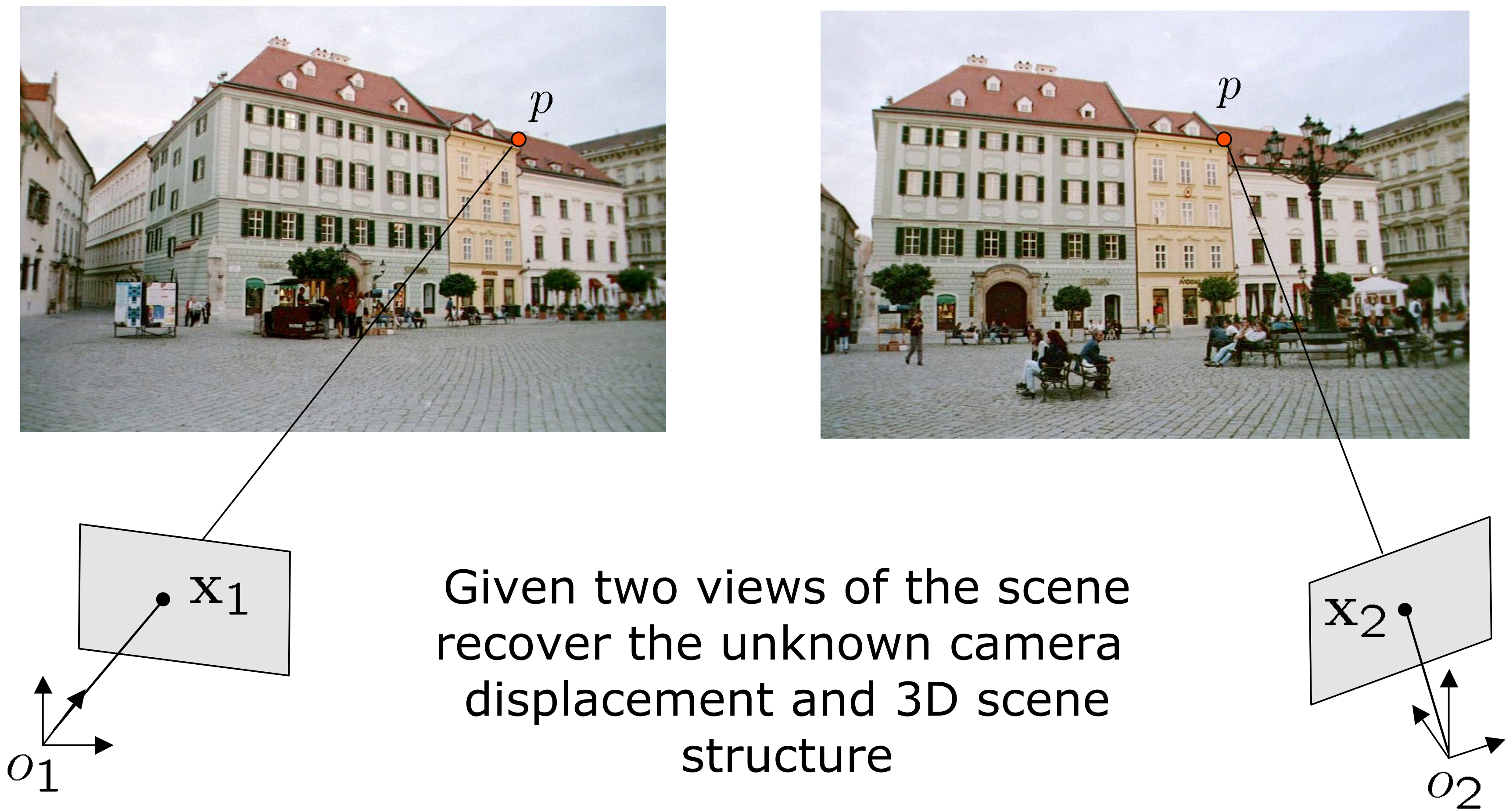
# Reconstruction from 2 views

Epipolar geometry
Essential matrix
Eight-point algorithm

# General Formulation




Given two views of the scene recover the unknown camera displacement and 3D scene structure

# Pinhole Camera Model

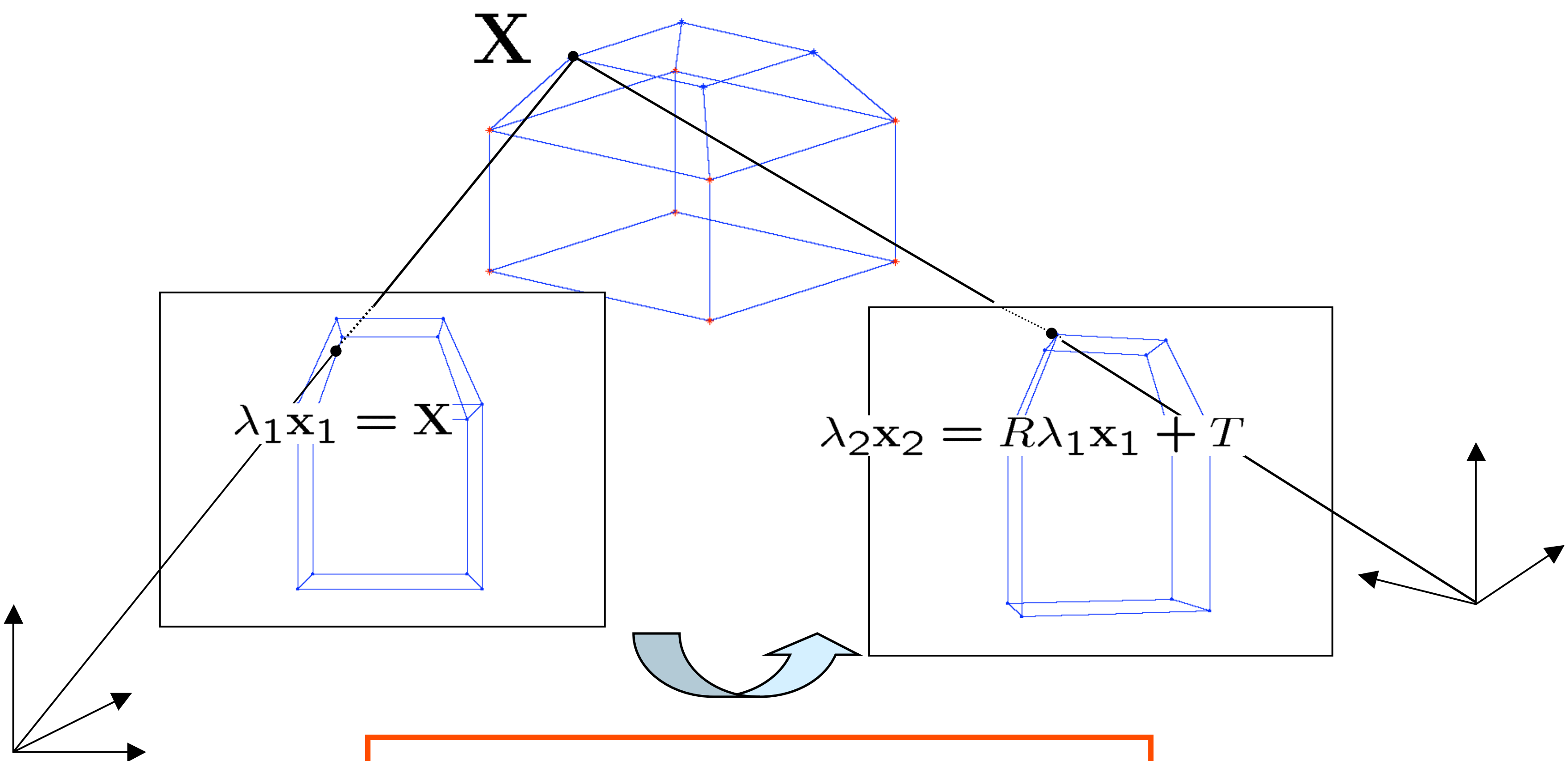
- 3D points $\mathbf{X} = [X, Y, Z, W]^T \in \Re^4, \quad (W = 1)$
- Image points $\mathbf{x} = [x, y, z]^T \in \Re^3, \quad (z = 1)$
- Perspective Projection $\lambda \mathbf{x} = \mathbf{X}$

$$\lambda = Z \quad x = \frac{X}{Z} \quad y = \frac{Y}{Z}$$

- Rigid Body Motion $\Pi = [R, T] \in \Re^{3 \times 4}$
- Rigid Body Motion + Projective projection

$$\lambda \mathbf{x} = \Pi \mathbf{X} = [R, T] \mathbf{X}$$

# Rigid Body Motion – Two views




$$\lambda_2 \mathbf{x}_2 = R\lambda_1 \mathbf{x}_1 + T$$

# 3D Structure and Motion Recovery

Euclidean transformation

$$\lambda_2 \mathbf{x}_2 = R \lambda_1 \mathbf{x}_1 + T$$

measurements unknowns

$$\sum_{j=1}^{n} \|\mathbf{x}_1^j - \pi(R_1, T_1, \mathbf{X})\|^2 + \|\mathbf{x}_2^j - \pi(R_2, T_2, \mathbf{X})\|^2$$

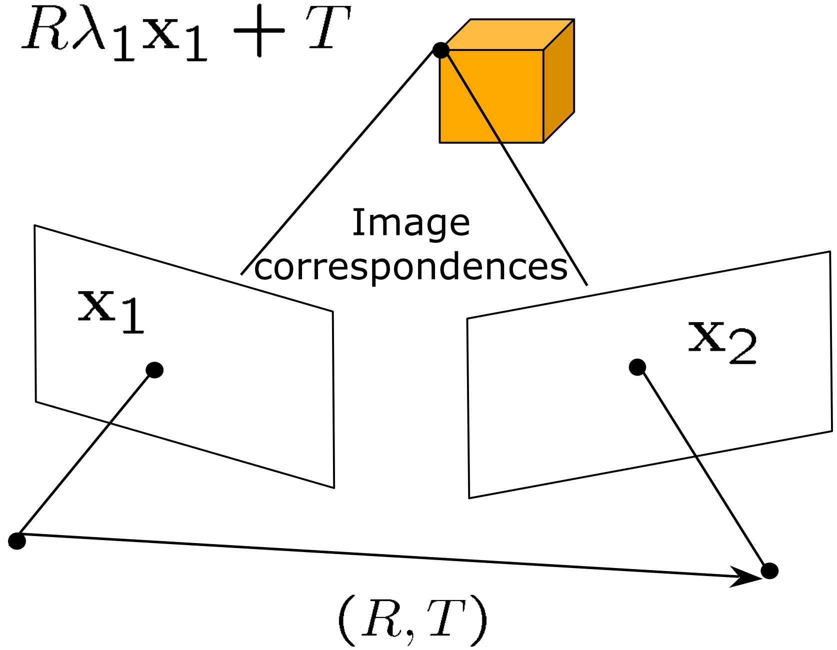
Find such Rotation and Translation and Depth that the reprojection error is minimized

Two views ~ 200 points
6 unknowns – Motion 3 Rotation, 3 Translation
- Structure 200x3 coordinates
- (-) universal scale

Difficult optimization problem

# Epipolar Geometry

$$\lambda_2 \mathbf{x}_2 = R\lambda_1 \mathbf{x}_1 + T$$



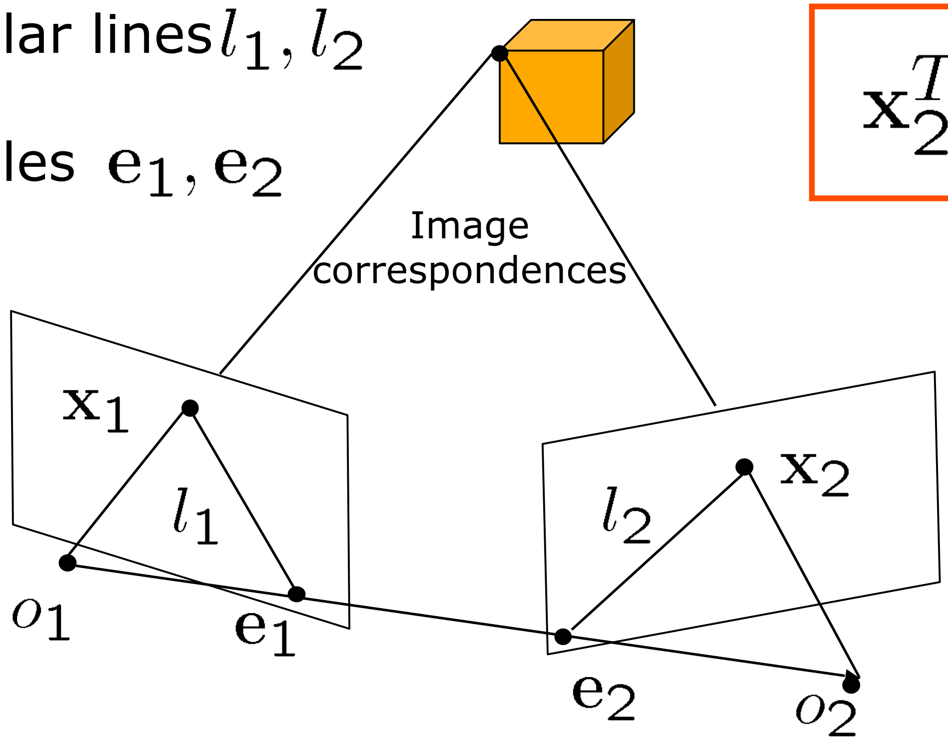

- Algebraic Elimination of Depth [Longuet-Higgins '81]:

$$\mathbf{x}_2^T \underbrace{\widehat{T} R}_{E} \mathbf{x}_1 = 0$$

- Essential matrix $E = \widehat{T} R$

# Epipolar Geometry

- Epipolar lines $l_1, l_2$
- Epipoles $\mathbf{e}_1, \mathbf{e}_2$




$$\mathbf{x}_2^T E \mathbf{x}_1 = 0$$

$$E = \hat{T} R$$

$$l_1 \sim E^T \mathbf{x}_2 \qquad l_i^T \mathbf{x}_i = 0 \qquad l_2 \sim E \mathbf{x}_1$$

$$E \mathbf{e}_1 = 0 \qquad l_i^T \mathbf{e}_i = 0 \qquad \mathbf{e}_2 E^T = 0$$

# Characterization of the Essential Matrix

$$\mathbf{x}_2^T \widehat{T} R \mathbf{x}_1 = 0$$

- Essential matrix $E = \widehat{T} R$  Special 3x3 matrix

$$\mathbf{x}_2^T \begin{bmatrix} e_1 & e_2 & e_2 \\ e_4 & e_5 & e_6 \\ e_7 & e_8 & e_9 \end{bmatrix} \mathbf{x}_1 = 0$$

**Theorem 1a** (Essential Matrix Characterization)
A non-zero matrix $E$ is an essential matrix iff its SVD: $E = U \Sigma V^T$ satisfies: $\Sigma = diag([\sigma_1, \sigma_2, \sigma_3])$ with $\sigma_1 = \sigma_2 \neq 0$ and $\sigma_3 = 0$ and $U, V \in SO(3)$

# Estimating the Essential Matrix

- Estimate Essential matrix $E = \hat{T}R$
- Decompose Essential matrix into $R, T$

$$\mathbf{x}_2^T \hat{T} R \mathbf{x}_1 = 0$$

- Given n pairs of image correspondences:
- Find such Rotation and Translation that the epipolar error is minimized

$$min_E \sum_{j=1}^{n} \mathbf{x}_2^{jT} E \mathbf{x}_1^j$$

- Space of all Essential Matrices is 5 dimensional
- 3 Degrees of Freedom – Rotation
- 2 Degrees of Freedom – Translation (up to scale !)

# Pose Recovery from the Essential Matrix

Essential matrix $E = \widehat{T}R$

**Theorem 1a** (Pose Recovery)
There are two relative poses $(R, T)$ with $T \in \mathcal{R}^3$ and $R \in SO(3)$ corresponding to a non-zero matrix essential matrix.

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

$$\begin{aligned} (\widehat{T}_1, R_1) &= (UR_Z(+\tfrac{\pi}{2})\Sigma U^T, UR_Z^T(+\tfrac{\pi}{2})V^T) \\ (\widehat{T}_2, R_2) &= (UR_Z(-\tfrac{\pi}{2})\Sigma U^T, UR_Z^T(-\tfrac{\pi}{2})V^T) \end{aligned}$$

$$\Sigma = diag([1, 1, 0]) \qquad R_z(+\tfrac{\pi}{2}) = \begin{bmatrix} 0 & -1 & 0 \\ 1 & 0 & 0 \\ 0 & 0 & 1 \end{bmatrix}$$

- Twisted pair ambiguity $(R_2, T_2) = (e^{\widehat{u}\pi}R_1, -T_1)$

# Estimating Essential Matrix

$$\mathbf{x}_2^T \hat{T} R \mathbf{x}_1 = 0$$

- Denote $\mathbf{a} = \mathbf{x}_1 \otimes \mathbf{x}_2$

$$\mathbf{a} = [x_1x_2, x_1y_2, x_1z_2, y_1x_2, y_1y_2, y_1z_2, z_1x_2, z_1y_2, z_1z_2]^T$$

$$E^s = [e_1, e_4, e_7, e_2, e_5, e_8, e_3, e_6, e_9]^T$$

- Rewrite $\mathbf{a}^T E^s = 0$

- Collect constraints from all points

$$\chi E^s = 0$$

$$min_E \sum_{j=1}^n \mathbf{x}_2^{jT} E \mathbf{x}_1^j \quad \Rightarrow \quad min_{E^s} \|\chi E^s\|^2$$

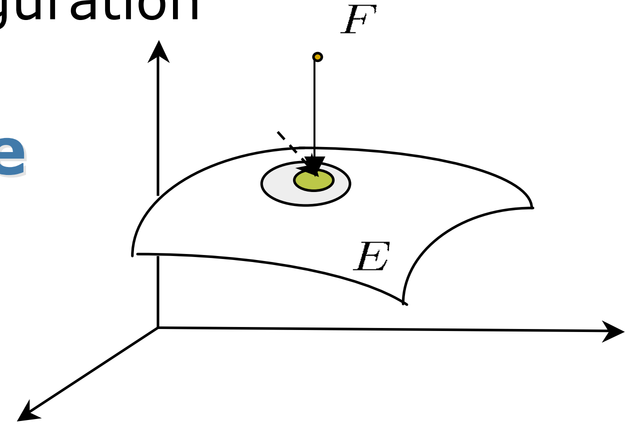
# Estimating Essential Matrix

$$min_E \sum_{j=1}^{n} \mathbf{x}_2^{jT} E \mathbf{x}_1^j \Rightarrow min_{E^s} \|\chi E^s\|^2$$

Solution

- Eigenvector associated with the smallest eigenvalue of $\chi^T \chi$
- if $rank(\chi^T \chi) < 8$ degenerate configuration

## Projection onto Essential Space




**Theorem 2a** (Project to Essential Manifold)
If the SVD of a matrix $F \in \mathcal{R}^{3\times 3}$ is given by $F = Udiag(\sigma_1, \sigma_2, \sigma_3)V^T$ then the essential matrix $E$ which minimizes the Frobenius distance $\|E - F\|_f^2$ is given by $E = Udiag(\sigma, \sigma, 0)V^T$ with $\sigma = \frac{\sigma_1 + \sigma_2}{2}$

# Two view linear algorithm

$$E = \{\hat{T}R | R \in SO(2), T \in S^2\}$$

- Solve the LLSE problem:

$$min_E \sum_{j=1}^n \mathbf{x}_2^{jT} E \mathbf{x}_1^j$$

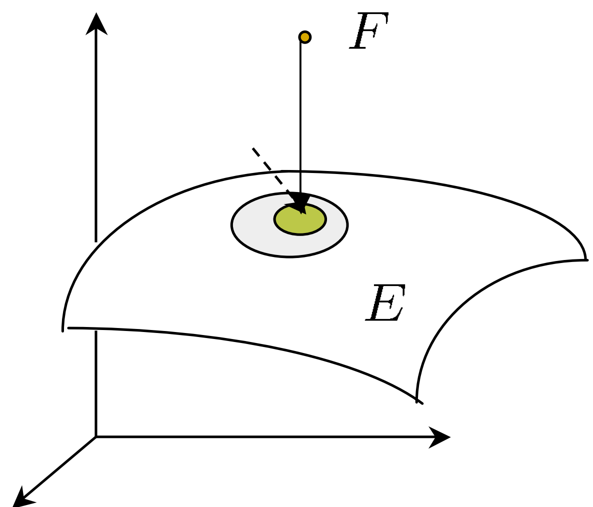
$\chi E^s = 0$ followed by projection

- Project onto the essential manifold:

SVD: $F = U \Sigma V^T$

$$\Sigma' = diag(1,1,0)$$

$$E = U \Sigma' V^T$$




**E** is 5 diml. sub. mnfld. in

- 8-point linear algorithm

- Recover the unknown pose:

$$(\hat{T}, R) = (U R_Z(\pm\tfrac{\pi}{2}) \Sigma U^T, U R_Z^T(\pm\tfrac{\pi}{2}) V^T)$$

# Pose Recovery

- There are exactly two pairs $(R, T)$ corresponding to each essential matrix $E$ .
- There are also two pairs $(R, T)$ corresponding to each essential matrix $-E$ .
- Positive depth constraint - used to disambiguate the physically impossible solutions
- Translation has to be non-zero
- Points have to be in general position
  - degenerate configurations – planar points
  - quadratic surface
- Linear 8-point algorithm
- Nonlinear 5-point algorithms yield up to 10 solutions

# 3D structure recovery

$$\lambda_2 \mathbf{x}_2 = R\lambda_1 \mathbf{x}_1 + \gamma T$$

- Eliminate one of the scales

$$\lambda_1^j \widehat{\mathbf{x}_2^j} R \mathbf{x}_1^j + \gamma \widehat{\mathbf{x}_2^j} T = 0, \qquad j = 1, 2, \ldots, n$$

- Solve LLSE problem

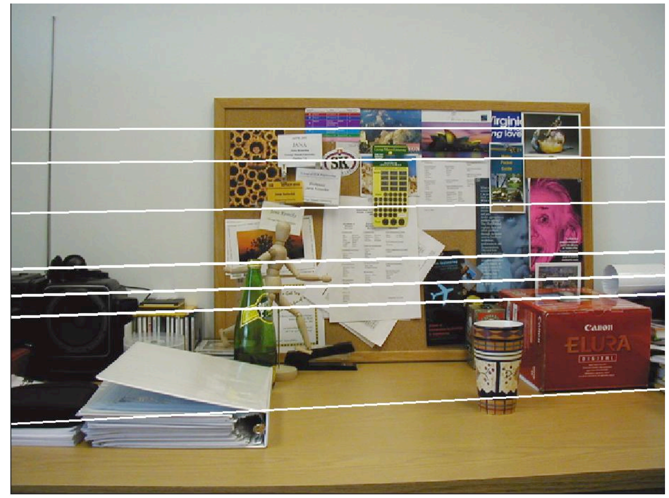
$$M^j \bar{\lambda}^j \doteq \left[ \widehat{\mathbf{x}_2^j} R \mathbf{x}_1^j, \; \widehat{\mathbf{x}_2^j} T \right] \begin{bmatrix} \lambda_1^j \\ \gamma \end{bmatrix} = 0$$

If the configuration is non-critical, the Euclidean structure of then points and motion of the camera can be reconstructed up to a universal scale.

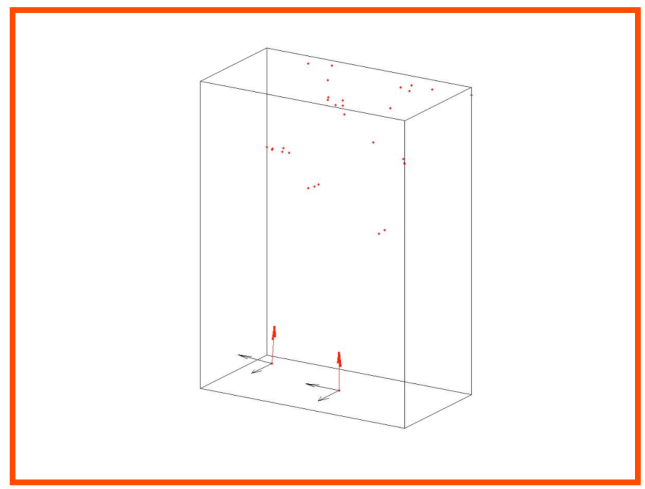
# Example- Two views


Point Feature Matching

# Example – Epipolar Geometry



Camera Pose
and
Sparse Structure Recovery



# Epipolar Geometry – Planar Case

- Plane in first camera coordinate frame

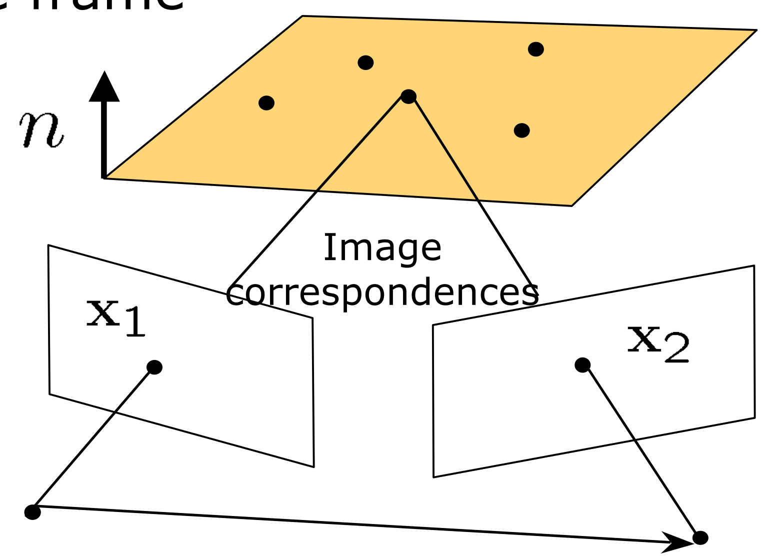
$$aX + bY + cZ + d = 0$$

$$\frac{1}{d}N^T\mathbf{X} = 1$$

$$\lambda_2\mathbf{x}_2 = R\lambda_1\mathbf{x}_1 + T$$

$$\lambda_2\mathbf{x}_2 = (R + \frac{1}{d}TN^T)\lambda_1\mathbf{x}_1$$

$$\mathbf{x}_2 \sim H\mathbf{x}_1$$




Planar homography

$$H = (R + \frac{1}{d}TN^T)$$

Linear mapping relating two corresponding planar points in two views

# Decomposition of H

- Algebraic elimination of depth $\widehat{\mathbf{x}_2} H \mathbf{x}_1 = 0$
- $H_L$ can be estimated linearly $H_L = \lambda H$
- Normalization of $H = H_L / \sigma_3$
- Decomposition of H into 4 solutions $H = (R + \frac{1}{d} T N^T)$

| | | | |
|---|---|---|---|
| $R_1 = W_1 U_1^T$<br>$N_1 = \widehat{v_2} u_1$<br>$\frac{1}{d} T_1 = (H - R_1) N_1$ | $R_3 = R_1$<br>$N_3 = -N_1$<br>$\frac{1}{d} T_3 = -\frac{1}{d} T_1$ | $R_2 = W_2 U_2^T$<br>$N_2 = \widehat{v_2} u_2$<br>$\frac{1}{d} T_2 = (H - R_2) N_2$ | $R_4 = R_2$<br>$N_4 = -N_2$<br>$\frac{1}{d} T_4 = -\frac{1}{d} T_2$ |

$$H^T H = V \Sigma V^T \quad V = [v_1, v_2, v_3] \quad \Sigma = diag(\sigma_1^2, \sigma_2^2, \sigma_3^2)$$

$$u_1 \doteq \frac{\sqrt{1-\sigma_3^2} v_1 + \sqrt{\sigma_1^2 - 1} v_3}{\sqrt{\sigma_1^2 - \sigma_3^2}} \quad u_2 \doteq \frac{\sqrt{1-\sigma_3^2} v_1 - \sqrt{\sigma_1^2 - 1} v_3}{\sqrt{\sigma_1^2 - \sigma_3^2}}$$

- $$U_1 = [v_2, u_1, \widehat{v_2} u_1], \quad W_1 = [H v_2, H u_1, \widehat{H v_2} H u_1];$$
  $$U_2 = [v_2, u_2, \widehat{v_2} u_2], \quad W_2 = [H v_2, H u_2, \widehat{H v_2} H u_2].$$

# Motion and pose recovery for planar scene

- Given at least 4 point correspondences $\widehat{\mathbf{x}_2^j} H \mathbf{x}_1^j = 0$
- Compute an approximation of the homography matrix $H_l^s$

as the nullspace of $\chi$

$\chi H_l^s = 0$ the rows of $\chi$ are $\mathbf{a} = \mathbf{x}_1^j \otimes \widehat{\mathbf{x}_2^j}$

- Normalize the homography matrix

$$H = H_L / \sigma_3$$

- Decompose the homography matrix

$$H^T H = V \Sigma V^T$$

- Select two physically possible solutions imposing positive depth constraint

# Example

# Special Rotation Case

- Two view related by rotation only $\lambda_2 \mathbf{x}_2 = R \lambda_1 \mathbf{x}_1$

$$\widehat{\mathbf{x}_2} R \mathbf{x}_1 = 0$$

- Mapping to a reference view

- Mapping to a cylindrical surface

# Motion and Structure Recovery – Two Views

- Two views – general motion, general structure

  1. Estimate essential matrix
  2. Decompose the essential matrix
  3. Impose positive depth constraint
  4. Recover 3D structure

- Two views – general motion, planar structure

  1. Estimate planar homography
  2. Normalize and decompose H
  3. Recover 3D structure and camera pose