

AA 274

Principles of Robotic Autonomy

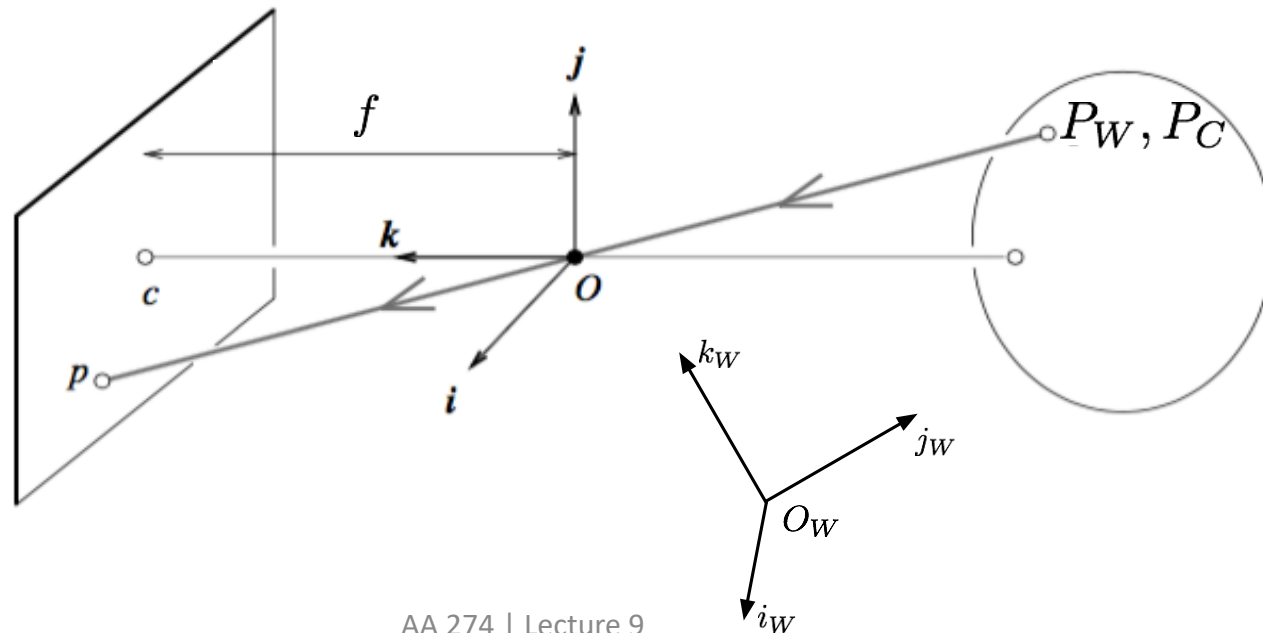
Camera models and camera calibration

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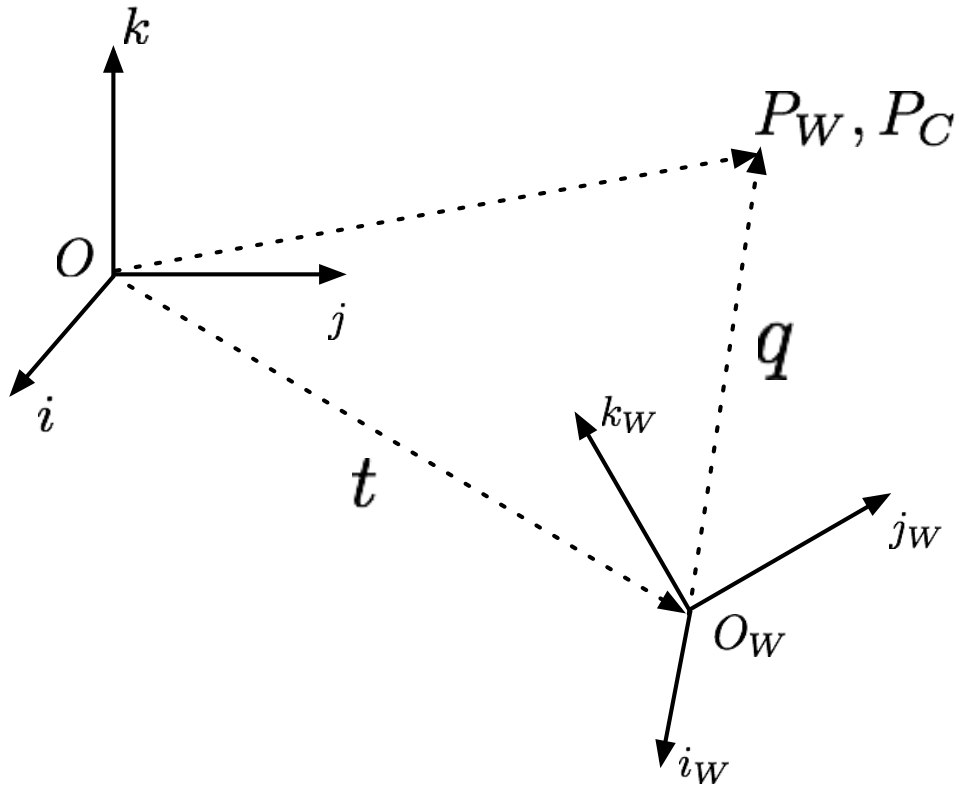
- Aim
 - Learn how to calibrate a camera
 - Learn about 3D reconstruction
- Readings
 - SNS: 4.2.3
 - D. A. Forsyth and J. Ponce [FP]. Computer Vision: A Modern Approach (2nd Edition). Prentice Hall, 2011. Chapter 1.
 - R. Hartley and A. Zisserman [HZ]. Multiple View Geometry in Computer Vision. Academic Press, 2002. Chapter 6.1.
 - Z. Zhang. A Flexible New Technique for Camera Calibration. IEEE Transactions on Pattern Analysis and Machine Intelligence, 2000.

Step 3

- In previous lecture, we have derived a mapping between a point P in the 3D camera reference frame to a point p in the 2D image plane
- Last step is to include in our mapping an additional transformation to account for the difference between the world frame and the 3D camera reference frame



Rigid transformations



$$P_C = t + q$$

$$q = R P_W$$

where R is the rotation matrix relating camera and world frames

$$R = \begin{bmatrix} i_W \cdot i & j_W \cdot i & k_W \cdot i \\ i_W \cdot j & j_W \cdot j & k_W \cdot j \\ i_W \cdot k & j_W \cdot k & k_W \cdot k \end{bmatrix}$$

$$\Rightarrow P_C = t + R P_W$$

Rigid transformations in homogeneous coordinates

$$\begin{pmatrix} P_C \\ 1 \end{pmatrix} = \begin{bmatrix} R & t \\ 0_{1 \times 3} & 1 \end{bmatrix} \begin{pmatrix} P_W \\ 1 \end{pmatrix}$$

Point P_C in homogeneous coordinates

Point P_W in homogeneous coordinates

Perspective projection equation

- Collecting all results

$$p^h = [K \quad 0_{3 \times 1}] P_C^h = K [I_{3 \times 3} \quad 0_{3 \times 1}] \begin{bmatrix} R & t \\ 0_{1 \times 3} & 1 \end{bmatrix} P_W^h$$

- Hence

Projection matrix M

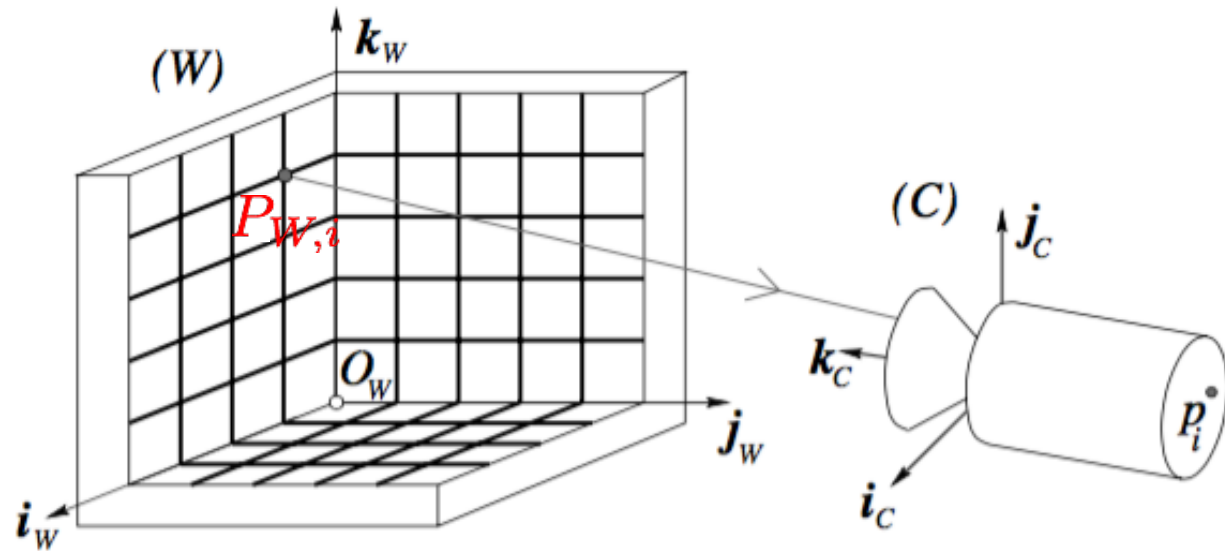
$$p^h = K [R \quad t] P_W^h$$

Intrinsic parameters Extrinsic parameters

- Degrees of freedom: 4 for K (or 5 if we also include skewness), 3 for R , and 3 for t . Total is 10 (or 11 if we include skewness)

Camera calibration: direct linear transformation method

- **Goal:** find the intrinsic and extrinsic parameters of the camera



Strategy: given known correspondences $p_i \leftrightarrow P_{W,i}$, compute unknown parameters K, R, t by applying perspective projection


$P_{W,1}, P_{W,2}, \dots, P_{W,n}$ with **known** positions in world frame

p_1, p_2, \dots, p_n with **known** positions in image frame

Step 1

- First consider **combined** parameters

$$p_i^h = M P_{W,i}^h, \quad i = 1, \dots, n, \quad \text{where} \quad M = K[R \quad t] = \begin{bmatrix} m_1 \\ m_2 \\ m_3 \end{bmatrix}$$

1×4 vector


- This gives rise to $2n$ component-wise equations, for $i = 1, \dots, n$

$$\begin{aligned} u_i &= \frac{m_1 \cdot P_{W,i}^h}{m_3 \cdot P_{W,i}^h} & \text{or} & & u_i (m_3 \cdot P_{W,i}^h) - m_1 \cdot P_{W,i}^h &= 0 \\ v_i &= \frac{m_2 \cdot P_{W,i}^h}{m_3 \cdot P_{W,i}^h} & & & v_i (m_3 \cdot P_{W,i}^h) - m_2 \cdot P_{W,i}^h &= 0 \end{aligned}$$

Calibration problem

- Stacking all equations together

$$\tilde{P}m = 0, \quad \text{where } m = \begin{bmatrix} m_1^T \\ m_2^T \\ m_3^T \end{bmatrix}$$

$2n \times 12$ matrix of known coefficients 12×1 vector of unknown coefficients 12×1

- \tilde{P} contains in block form the known coefficients stemming from the given correspondences
- To estimate 11 coefficients, we need **at least 6** correspondences

Solution

- To find non-zero solution

$$\begin{aligned} & \min_{m \in \mathbb{R}^{12}} \|\tilde{P}m\|^2 \\ & \text{subject to } \|m\|^2 = 1 \end{aligned}$$

- Solution: select eigenvector of $\tilde{P}^T \tilde{P}$ with the smallest eigenvalue
- Readily computed via SVD decomposition

Step 2

- Next, we need to extract the camera parameters, i.e., we want to factorize M as

$$M = [KR \quad Kt]$$

- This can be done efficiently (indeed, explicitly) by using RQ factorization, whereby the submatrix $M_{11:33}$ is decomposed into the product of an upper triangular matrix K and a rotation matrix R
- Calibration will be investigated in **Problem 1 in pset**

Radial distortion

- So far, we have assumed that a linear model is an accurate model of the imaging process
- For real (non-pinhole) lenses this assumption will not hold



No distortion



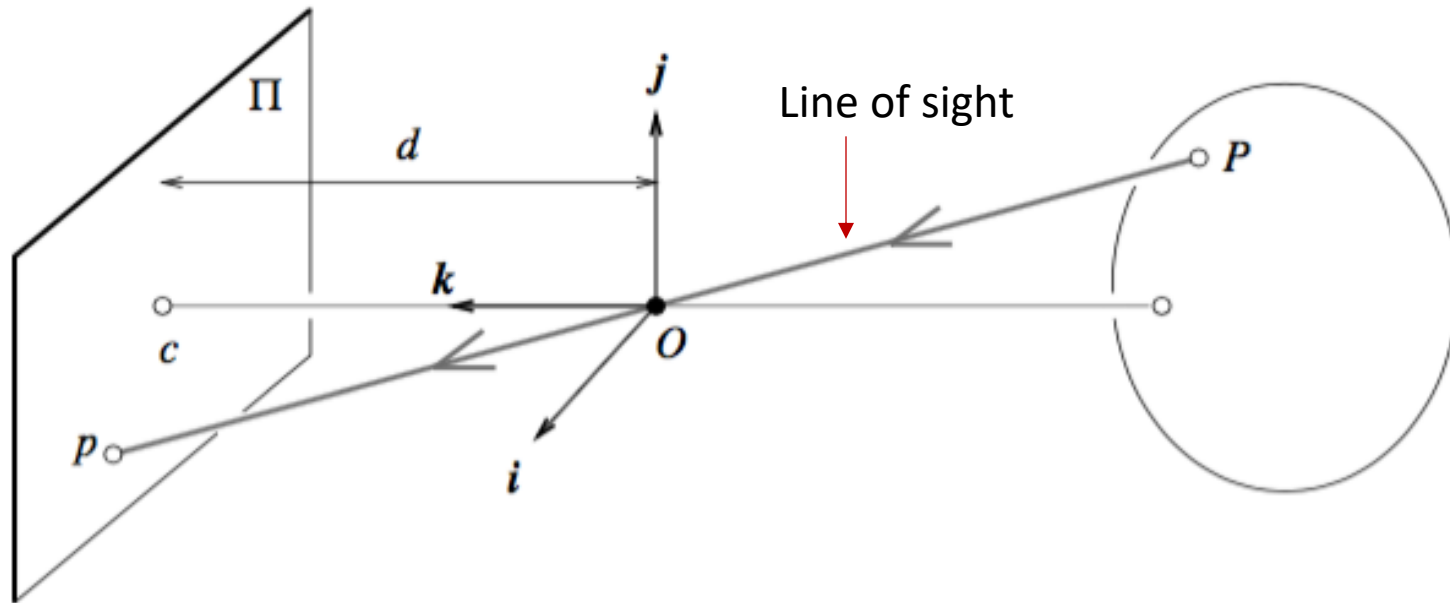
Barrel distortion



Pincushion distortion

Credit: SNS

Measuring depth



$$p^h = K[R \quad t]P_W^h$$

Homogeneous coordinates

Once the camera is calibrated, can we measure the location of a point P in 3D given its known observation p ?

- **No**: one can only say that P is located *somewhere* along the line joining p and O !

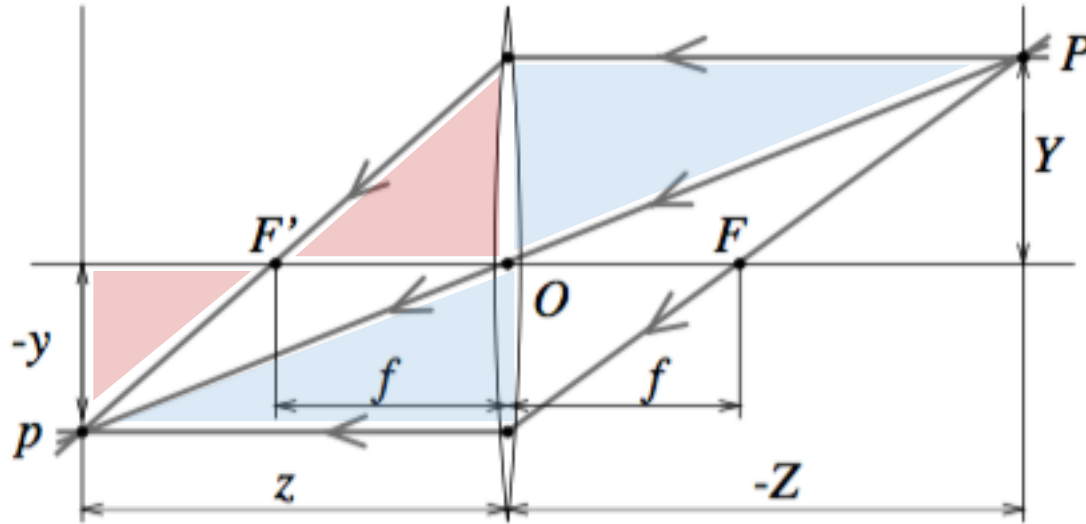
Issues with recovering structure



Recovering structure

- **Structure:** 3D scene to be reconstructed by having access to 2D images
- Common methods
 1. Through recognition of landmarks (e.g., orthogonal walls)
 2. Depth from focus: determines distance to one point by taking multiple images with better and better focus
 3. Stereo vision: processes two distinct images taken at the *same time* and assumes that the relative pose between the two cameras is *known*
 4. Structure from motion: processes two images taken with the same or different cameras at *different times* and from different *unknown* positions

Depth from focus



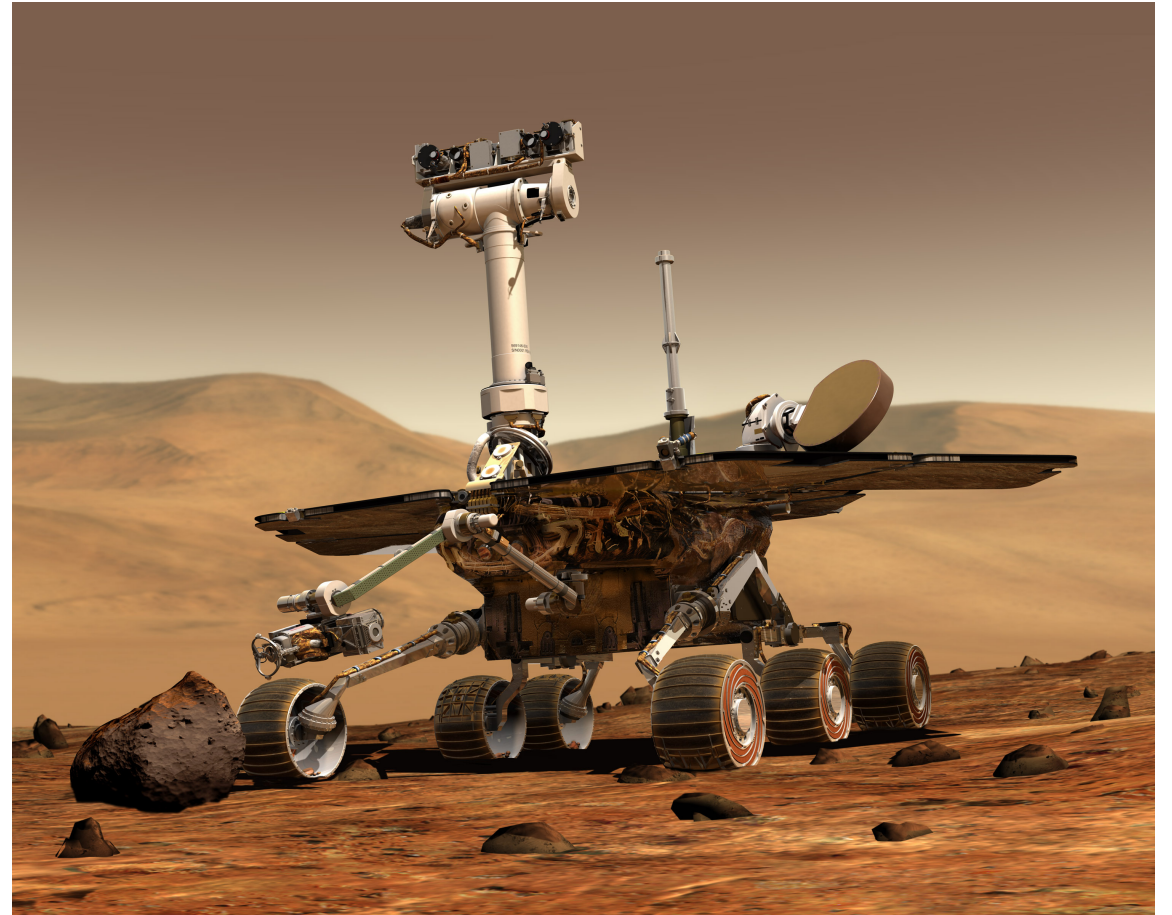
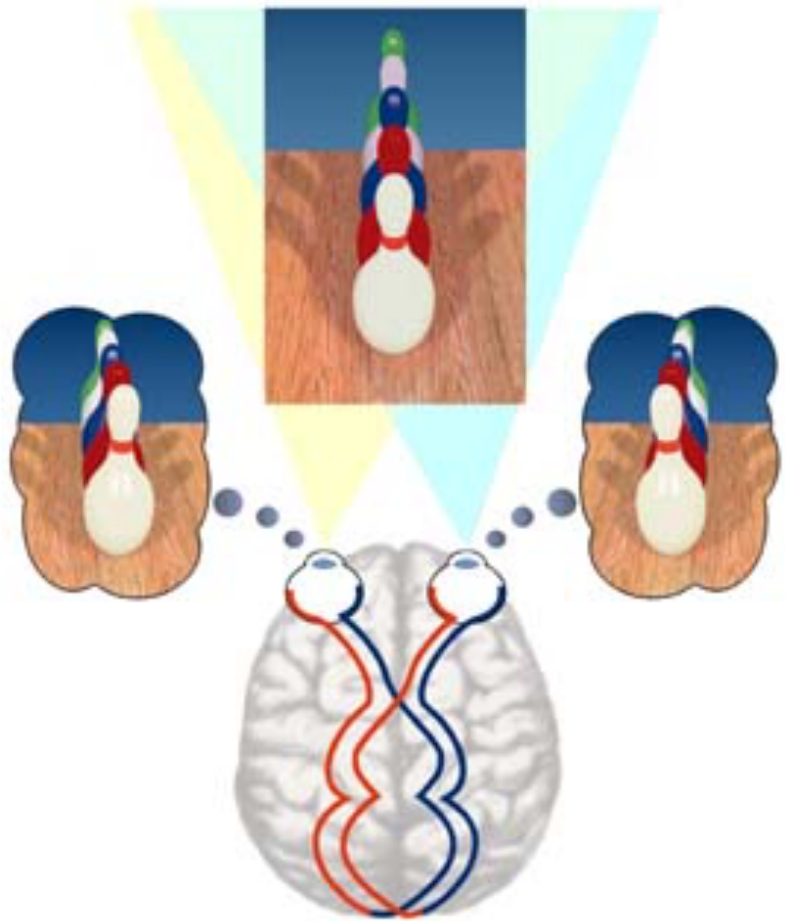
Credit: FP Chapter 1

$$\Rightarrow \frac{1}{z} + \frac{1}{Z} = \frac{1}{f}$$

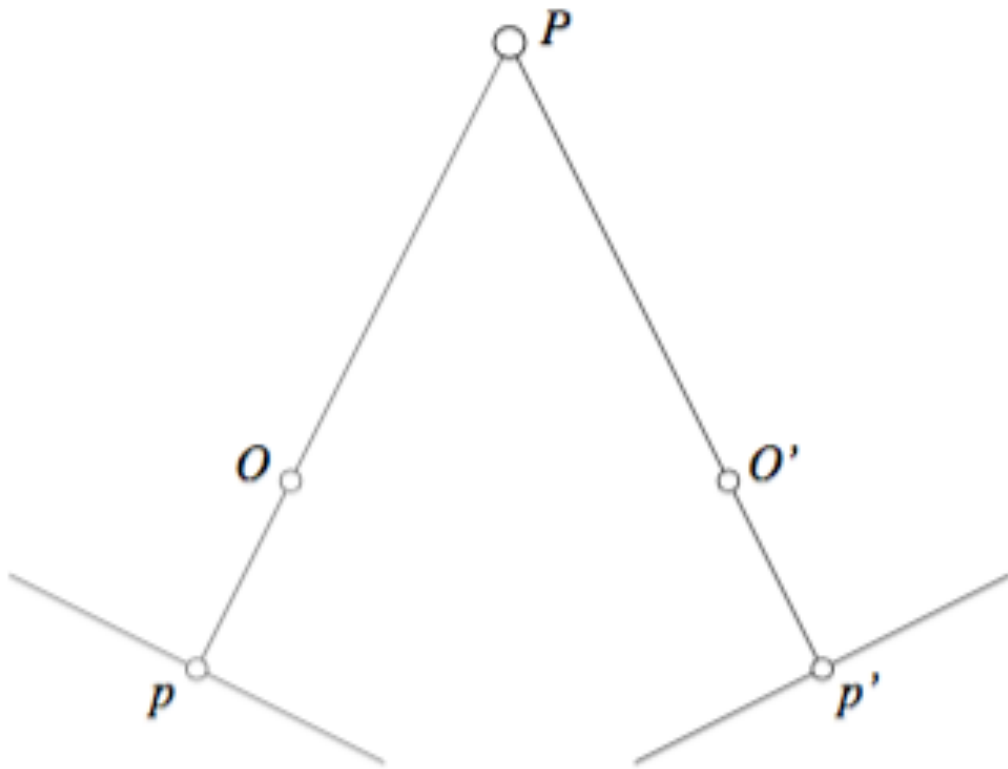
Thin lens
equation

- Take several images until the projection of point P is in focus; let z denote the distance at which the image is in focus
- Since we know z and f , through the thin lens equation we obtain Z

Stereopsis, or why we have two eyes

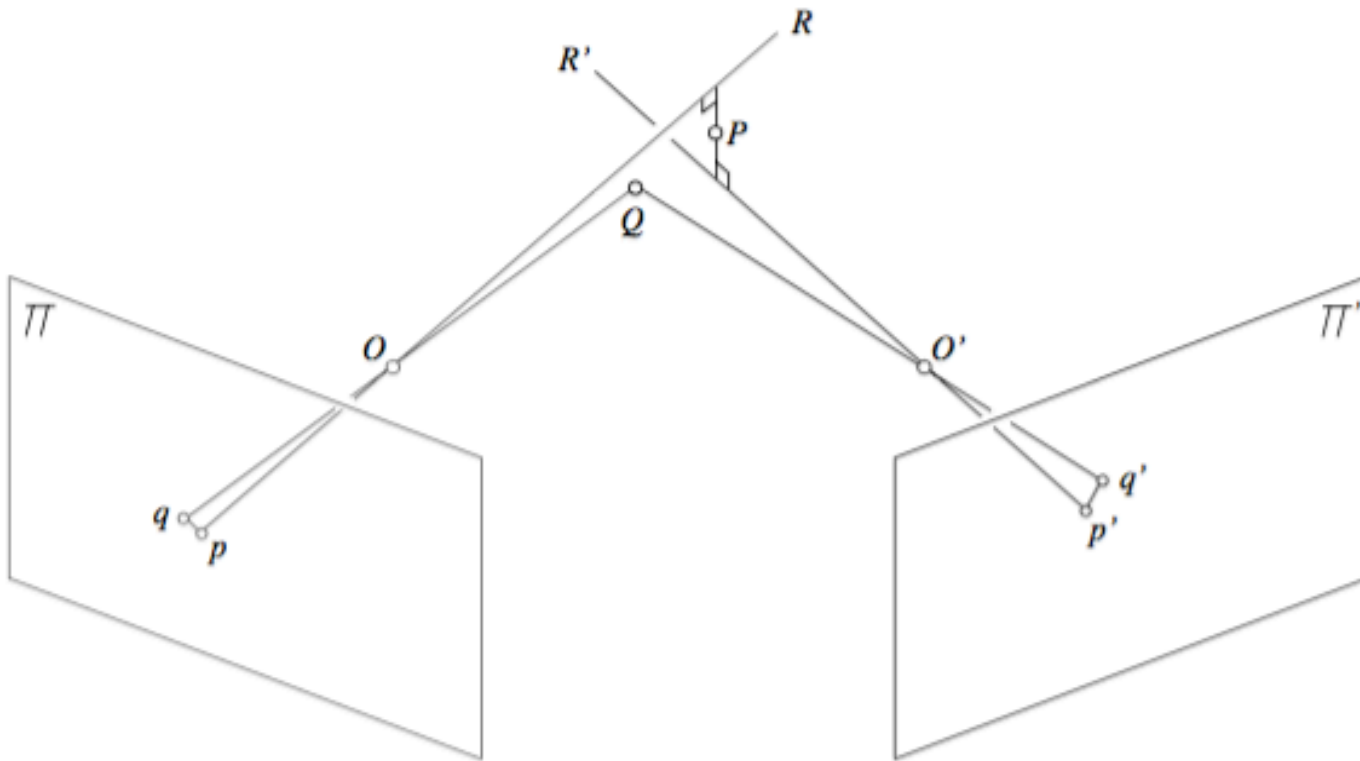


Binocular reconstruction



- **Given:** *calibrated* stereo rig and two image matching points p and p'
- **Find** corresponding scene point by intersecting the two rays \overline{Op} and $\overline{O'p'}$ (process known as **triangulation**)

Approximate triangulation



- Due to noise, triangulation problem is often solved as finding the point Q with images q and q' that minimizes

$$\underbrace{d^2(p, q) + d^2(p', q')}_{\text{Re-projection error}}$$

Next time: stereo

