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Part VI

3D Structure and Camera Motion

- 1 Introduction
- 2 Reconstructing Camera Systems
- 3 Bundle Adjustment

covered by

- [1] [H&Z] Secs: 9.5.3, 10.1, 10.2, 10.3, 12.1, 12.2, 12.4, 12.5, 18.1
- [2] Triggs, B. et al. Bundle Adjustment—A Modern Synthesis. In *Proc ICCV Workshop on Vision Algorithms*. Springer-Verlag. pp. 298–372, 1999.

► Constructing Cameras from the Fundamental Matrix

Given \mathbf{F} , construct some cameras $\mathbf{P}_1, \mathbf{P}_2$ such that \mathbf{F} is their fundamental matrix.

Solution

See [H&Z, p. 256]

$$\mathbf{P}_1 = [\mathbf{I} \quad \mathbf{0}] \quad v = e_1$$

$$\mathbf{P}_2 = [[e_2]_{\times} \mathbf{F} + e_2 \underline{v}^T \quad \lambda e_2]$$

where

$$([e_2]_{\times} \mathbf{F} + e_2 e_1^T) e_1 = \cancel{v} = 0 = e_2 \|e_1\|^2$$

- \underline{v} is any 3-vector, e.g. $\underline{v} = e_1$ to make the camera finite
- $\lambda \neq 0$ is a scalar,
- $e_2 = \text{null}(\mathbf{F}^T)$, i.e. $e_2^T \mathbf{F} = 0$

Proof

1. \mathbf{S} is antisymmetric iff $\mathbf{x}^T \mathbf{S} \mathbf{x} = 0$ for all \mathbf{x}
2. we have $\underline{x} \simeq \mathbf{P} \underline{X}$
3. a non-zero \mathbf{F} is a f.m. iff $\mathbf{P}_2^T \mathbf{F} \mathbf{P}_1$ is antisymmetric
4. if $\mathbf{P}_1 = [\mathbf{I} \quad \mathbf{0}]$ and $\mathbf{P}_2 = [\mathbf{S} \mathbf{F} \quad e_2]$ then \mathbf{F} corresponds to $(\mathbf{P}_1, \mathbf{P}_2)$ by Step 3
5. we can write $\mathbf{S} = [\mathbf{s}]_{\times}$
6. a suitable choice is $\mathbf{s} = e_2$
7. for the full the class including \underline{v} , see [H&Z, Sec. 9.5]

look-up the proof!

[Luong96]

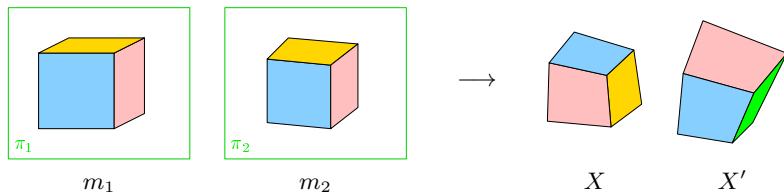
► The Projective Reconstruction Theorem

Observation: Unless \mathbf{P}_i are constrained, then for any number of cameras $i = 1, \dots, k$

$$\underline{m}_i = \mathbf{P}_i \underline{\mathbf{X}} = \underbrace{\mathbf{P}_i \mathbf{H}^{-1}}_{\mathbf{P}'_i} \underbrace{\mathbf{H} \underline{\mathbf{X}}}_{\underline{\mathbf{X}}'} = \mathbf{P}'_i \underline{\mathbf{X}}'$$

motion → \mathbf{P}_i *structure* → $\underline{\mathbf{X}}$

- when \mathbf{P}_i and $\underline{\mathbf{X}}$ are both determined from correspondences (including calibrations \mathbf{K}_i), they are given up to a common 3D homography \mathbf{H}
(translation, rotation, scale, shear, pure perspectivity)

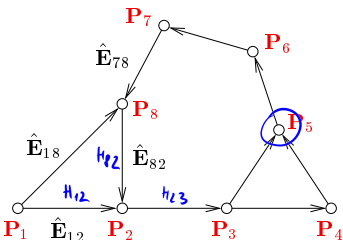


- when cameras are internally calibrated (\mathbf{K}_i known) then \mathbf{H} is restricted to a similarity since it must preserve the calibrations \mathbf{K}_i [H&Z, Secs. 10.2, 10.3], [Longuet & Higgins 81]
(translation, rotation, scale)

► Reconstructing Camera Systems

Problem: Given a set of p decomposed pairwise essential matrices $\hat{\mathbf{E}}_{ij} = [\hat{\mathbf{t}}_{ij}]_{\times} \hat{\mathbf{R}}_{ij}$ and calibration matrices \mathbf{K}_i reconstruct the camera system $\mathbf{P}_i, i = 1, \dots, k$

→ Slides 78 and 138 on representing \mathbf{E}



We construct camera pairs $\hat{\mathbf{P}}_{ij} \in \mathbb{R}^{6,4}$ → Slide 123

$$\hat{\mathbf{P}}_{ij} = \begin{bmatrix} \hat{\mathbf{P}}_i \\ \hat{\mathbf{P}}_j \end{bmatrix} = \begin{bmatrix} \hat{\mathbf{K}}_i [\mathbf{I} & \mathbf{0}] \\ \hat{\mathbf{K}}_j [\hat{\mathbf{R}}_{ij} & \hat{\mathbf{t}}_{ij}] \end{bmatrix} \in \mathbb{R}^{6,4}$$

- singletons i, j correspond to vertices V k vertices
- pairs ij correspond to graph edges E p edges

$\hat{\mathbf{P}}_{ij}$ are in different coordinate systems but these are related by similarities $\hat{\mathbf{P}}_{ij} \mathbf{H}_{ij} = \mathbf{P}_{ij}$

$$\begin{array}{c} \mathbf{R}_{ij} \quad | \quad \mathbf{t}_{ij} \\ \hline \hat{\mathbf{R}}_{ij} \quad \mathbf{R}_{ij} \quad | \quad \hat{\mathbf{R}}_{ij} \mathbf{t}_{ij} + \mathbf{s}_{ij} \quad \mathbf{t}_{ij} \end{array} \underbrace{\begin{bmatrix} \mathbf{I} & \mathbf{0} \\ \hat{\mathbf{R}}_{ij} & \hat{\mathbf{t}}_{ij} \end{bmatrix}}_{\mathbb{R}^{6,4}} \underbrace{\begin{bmatrix} \mathbf{R}_{ij} & \mathbf{t}_{ij} \\ \mathbf{0}^T & \mathbf{s}_{ij} \end{bmatrix}}_{\mathbf{H}_{ij} \in \mathbb{R}^{4,4}} \stackrel{!}{=} \underbrace{\begin{bmatrix} \mathbf{R}_i & \mathbf{t}_i \\ \mathbf{R}_j & \mathbf{t}_j \end{bmatrix}}_{\mathbb{R}^{6,4}} \quad (24)$$

- \mathbf{K}_i removed on both sides of eq. (24)
- (24) is a linear system of $24p$ eqs. in $7p + 6k$ unknowns $7p \sim (\mathbf{t}_{ij}, \mathbf{R}_{ij}, \mathbf{s}_{ij}), 6k \sim (\mathbf{R}_i, \mathbf{t}_i)$
- each \mathbf{P}_i appears on the right side as many times as is the degree of vertex \mathbf{P}_i eg. \mathbf{P}_5 3-times

Eq. (24) implies
$$\begin{bmatrix} \mathbf{R}_{ij} \\ \hat{\mathbf{R}}_{ij} \mathbf{R}_{ij} \end{bmatrix} = \begin{bmatrix} \mathbf{R}_i \\ \mathbf{R}_j \end{bmatrix} \quad \begin{bmatrix} \mathbf{t}_{ij} \\ \hat{\mathbf{R}}_{ij} \mathbf{t}_{ij} + s_{ij} \hat{\mathbf{t}}_{ij} \end{bmatrix} = \begin{bmatrix} \mathbf{t}_i \\ \mathbf{t}_j \end{bmatrix}$$

- \mathbf{R}_{ij} and \mathbf{t}_{ij} can be eliminated:

$$\hat{\mathbf{R}}_{ij} \mathbf{R}_i = \mathbf{R}_j, \quad \hat{\mathbf{R}}_{ij} \mathbf{t}_i + s_{ij} \hat{\mathbf{t}}_{ij} = \mathbf{t}_j, \quad s_{ij} > 0 \quad (25)$$

- note transformations that do not change these equations assuming no error in $\hat{\mathbf{R}}_{ij}$

1. $\mathbf{R}_i \mapsto \mathbf{R}_i \mathbf{R}$,
2. $\mathbf{t}_i \mapsto \sigma \mathbf{t}_i$ and $s_{ij} \mapsto \sigma s_{ij}$,
3. $\mathbf{t}_i \mapsto \mathbf{t}_i + \mathbf{R}_i \mathbf{t}$

- the global frame is fixed by e.g. selecting

$$\mathbf{R}_1 = \mathbf{I}, \quad \sum_{i=1}^k \mathbf{t}_i = \mathbf{0}, \quad \frac{1}{p} \sum_{i,j} s_{ij} = 1 \quad (26)$$

- rotation equations are decoupled from translation equations
- in principle, s_{ij} could correct the sign of $\hat{\mathbf{t}}_{ij}$ from essential matrix decomposition Slide 78
but \mathbf{R}_i cannot correct the α sign in $\hat{\mathbf{R}}_{ij}$

→ therefore make sure all points are in front of cameras and constrain $s_{ij} > 0$; see Slide 80

+ pairwise correspondences are sufficient

– suitable for well-located cameras only (dome-like configurations)

otherwise intractable or numerically unstable

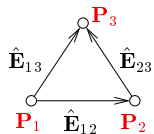
Finding The Rotation Component in Eq. (25)

Task: Solve $\hat{\mathbf{R}}_{ij}\mathbf{R}_i = \mathbf{R}_j$, $i, j \in V$, $(i, j) \in E$ where \mathbf{R} are a 3×3 rotation matrix each. Per columns $c = 1, 2, 3$ of \mathbf{R}_j :

$$\hat{\mathbf{R}}_{ij}\mathbf{r}_i^c - \mathbf{r}_j^c = \mathbf{0}, \quad \text{for all } i, j \quad (27)$$

- fix c and denote $\mathbf{r}^c = [\mathbf{r}_1^c, \mathbf{r}_2^c, \dots, \mathbf{r}_k^c]^\top$ c -th columns of all rotation matrices stacked; $\mathbf{r}^c \in \mathbb{R}^{3k}$
- then (27) becomes $\mathbf{D}\mathbf{r}^c = \mathbf{0}$ $\mathbf{D} \in \mathbb{R}^{3p, 3k}$
- $3p$ equations for $3k$ unknowns $\rightarrow p \geq k$ in a 1-connected graph we have to fix $\mathbf{r}_1^c = [1, 0, 0]$

Ex: ($k = p = 3$)



$$\begin{aligned} &\hat{\mathbf{R}}_{12}\mathbf{r}_1^c - \mathbf{r}_2^c = \mathbf{0} \\ &\hat{\mathbf{R}}_{23}\mathbf{r}_2^c - \mathbf{r}_3^c = \mathbf{0} \\ &\hat{\mathbf{R}}_{13}\mathbf{r}_1^c - \mathbf{r}_3^c = \mathbf{0} \end{aligned} \quad \rightarrow \quad \mathbf{D}\mathbf{r}^c = \begin{bmatrix} \hat{\mathbf{R}}_{12} & -\mathbf{I} & \mathbf{0} \\ \mathbf{0} & \hat{\mathbf{R}}_{23} & -\mathbf{I} \\ \hat{\mathbf{R}}_{13} & \mathbf{0} & -\mathbf{I} \end{bmatrix} \begin{bmatrix} \mathbf{r}_1^c \\ \mathbf{r}_2^c \\ \mathbf{r}_3^c \end{bmatrix} = \mathbf{0}$$

- must hold for any c

Idea: [Martinec & Pajdla CVPR 2007]

1. find the space of all $\mathbf{r}^c \in \mathbb{R}^{3k}$ that solve (27) \mathbf{D} is sparse, use $[V, E] = \text{eigs}(\mathbf{D}^* \mathbf{D}, 3, 0)$; (Matlab)
 2. choose 3 unit orthogonal vectors in this space 3 smallest eigenvectors
 3. find closest rotation matrices per cam. using SVD because $\|\mathbf{r}^c\| = 1$ is necessary but insufficient
 $\mathbf{R}_i^* = \mathbf{U}\mathbf{V}^\top$, where $\mathbf{R}_i = \mathbf{U}\mathbf{D}\mathbf{V}^\top$
- global world rotation is arbitrary

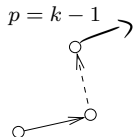
Finding The Translation Component in Eq. (25)

From eqs. (25) and (26): d – rank of camera center set p – No. of pairs, k – No. of cameras

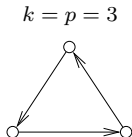
$$\hat{\mathbf{R}}_{ij} \mathbf{t}_i + s_{ij} \hat{\mathbf{t}}_{ij} - \mathbf{t}_j = \mathbf{0}, \quad \sum_{i=1}^k \mathbf{t}_i = \mathbf{0}, \quad \sum_{i,j} s_{ij} = p, \quad s_{ij} > 0, \quad \mathbf{t}_i \in \mathbb{R}^d$$

- in rank d : $d \cdot p + d + 1$ equations for $d \cdot k + p$ unknowns $\rightarrow p \geq \frac{d(k-1)-d}{d-1}$

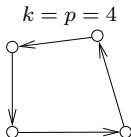
Ex: Chains and circuits construction from sticks of known orientation and unknown length?



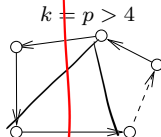
$k \leq 2$ for any d



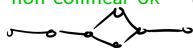
$d \geq 2$: non-collinear ok



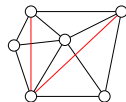
$d \geq 3$: non-planar ok



$d \geq k - 1$: not possible without chords



- rank is not sufficient for chains, trees, or when $d = 1$ (collinear cameras)
- 3-connectivity gives a sufficient rank for $d = 3$ (cams. in general pos. in 3D)
 - s -connected graph has $p \geq \lceil \frac{sk}{2} \rceil$ edges for $s \geq 2$, hence $p \geq \lceil \frac{3k}{2} \rceil \geq \frac{3k}{2} - 2$
- 4-connectivity gives a sufficient rank for any k for $d = 2$ (coplanar cams)
 - since $p \geq \lceil 2k \rceil \geq 2k - 3$
 - maximal planar (triangulated) graphs have $p = 3k - 6$ and give the rank for $k \geq 3$



Linear equations in (25) and (26) can be rewritten to

$$\mathbf{D}\mathbf{t} = \mathbf{0}, \quad \mathbf{t} = [\mathbf{t}_1^\top, \mathbf{t}_2^\top, \dots, \mathbf{t}_k^\top, s_{12}, \dots, s_{ij}, \dots]^\top$$

for $d = 3$: $\mathbf{t} \in \mathbb{R}^{3k+p}$, $\mathbf{D} \in \mathbb{R}^{3p, 3k+p}$ is sparse

$$\mathbf{t}^* = \arg \min_{\mathbf{t}, s_{ij} > 0} \mathbf{t}^\top \mathbf{D}^\top \mathbf{D} \mathbf{t}$$

- this is a quadratic programming problem (constraints!)

```
z = zeros(3*k+p,1);
t = quadprog(D'*D, z, diag([zeros(3*k,1); -ones(p,1)]), z);
```

- but check the rank first!

► Solving Eq. (25) by Stepwise Gluing

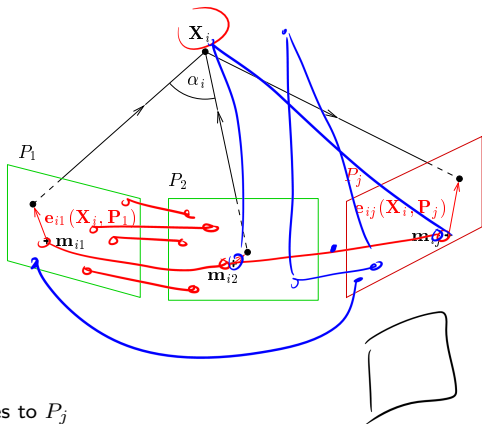
Given: Calibration matrices \mathbf{K}_j and tentative correspondences per camera triples.

Initialization

1. initialize camera cluster \mathcal{C} with P_1, P_2 ,
2. find essential matrix \mathbf{E}_{12} and matches M_{12} by the 5-point algorithm [Slide 84](#)
3. construct camera pair

$$\mathbf{P}_1 = \mathbf{K}_1 [\mathbf{I} \quad \mathbf{0}], \quad \mathbf{P}_2 = \mathbf{K}_2 [\mathbf{R} \quad \mathbf{t}]$$

4. compute 3D reconstruction $\{X_i\}$ per match from M_{12} [Slide 90](#)
5. initialize point cloud \mathcal{X} with $\{X_i\}$ satisfying chirality constraint $z_i > 0$ and apical angle constraint $|\alpha_i| > \alpha_T$



Attaching camera $P_j \notin \mathcal{C}$

1. select points \mathcal{X}_j from \mathcal{X} that have matches to P_j
2. estimate \mathbf{P}_j using \mathcal{X}_j , RANSAC with the 3-pt alg. (P3P), projection errors e_{ij} in \mathcal{X}_j [Slide 69](#)
3. reconstruct 3D points from all tentative matches from P_j to all $P_l, l \neq k$ that are not in \mathcal{X}
4. filter them by the chirality and apical angle constraints and add them to \mathcal{X}
5. add P_j to \mathcal{C}
6. perform bundle adjustment on \mathcal{X} and \mathcal{C}

coming next

► Bundle Adjustment

Given:

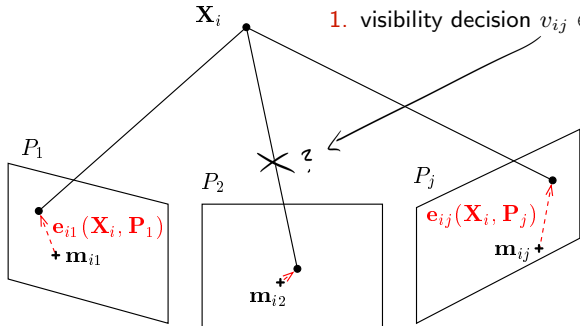
1. set of 3D points $\{\mathbf{X}_i\}_{i=1}^P$
2. set of cameras $\{\mathbf{P}_j\}_{j=1}^C$
3. fixed tentative projections \mathbf{m}_{ij}

Required:

1. corrected 3D points $\{\mathbf{X}'_i\}_{i=1}^P$
2. corrected cameras $\{\mathbf{P}'_j\}_{j=1}^C$

Latent:

1. visibility decision $v_{ij} \in \{0, 1\}$ per \mathbf{m}_{ij}



- for simplicity, \mathbf{X} , \mathbf{m} are considered direct (not homogeneous)
- we have projection error $\mathbf{e}_{ij}(\mathbf{X}_i, \mathbf{P}_j) = \mathbf{x}_i - \mathbf{m}_i$ per image feature, where $\mathbf{x}_i = \mathbf{P}_j \mathbf{X}_i$
- for simplicity, we will work with scalar error $e_{ij} = \|\mathbf{e}_{ij}\|$

Robust Objective Function for Bundle Adjustment

Data likelihood is

constructed by marginalization, as in Robust Matching Model, Slide 107

$$p(\{\mathbf{m}\} | \{\mathbf{P}\}) = \prod_{\text{pts: } i=1}^p \prod_{\text{cams: } j=1}^c \left((1 - \alpha_0) p_1(e_{ij} | \mathbf{X}_i, \mathbf{P}_j) + \alpha_0 p_0(e_{ij} | \mathbf{X}_i, \mathbf{P}_j) \right)$$

the simplified log-likelihood is (as on Slide 108)

$$V(\{\mathbf{m}\} | \{\mathbf{P}\}) = -\log p(\{\mathbf{m}\} | \{\mathbf{P}\}) = \sum_i \sum_j \underbrace{-\log \left(e^{-\frac{e_{ij}^2(\mathbf{X}_i, \mathbf{P}_j)}{2\sigma_1^2}} + t \right)}_{\rho(e_{ij}^2(\mathbf{X}_i, \mathbf{P}_j)) = \nu_{ij}^2(\mathbf{X}_i, \mathbf{P}_j)} \stackrel{\text{def}}{=} \sum_i \sum_j \nu_{ij}^2(\mathbf{X}_i, \mathbf{P}_j)$$

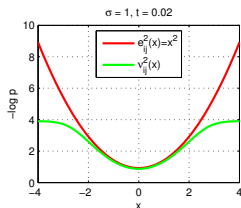
- ν_{ij} is a 'robust' error fcn.; it is non-robust ($\nu_{ij} = e_{ij}$) when $t = 0$
- $\rho(\cdot)$ is a 'robustification function' we often find in M-estimation
- the \mathbf{L}_{ij} in Levenberg-Marquardt changes to vector

$$(\mathbf{L}_{ij})_l = \frac{\partial \nu_{ij}}{\partial \theta_l} = \underbrace{\frac{1}{1 + t e^{\frac{e_{ij}^2(\theta)/(2\sigma_1^2)}}}}_{\text{small for big } e_{ij}} \cdot \frac{1}{\nu_{ij}(\theta)} \cdot \frac{1}{4\sigma_1^2} \cdot \frac{\partial e_{ij}^2(\theta)}{\partial \theta_l} \quad (28)$$

but the LM method stays the same as on Slides 101–102

- outliers have virtually no impact on \mathbf{d}_s in normal equations because of the red term in (28) that scales contributions to the sums down

$$-\sum_{i,j} \mathbf{L}_{ij}^\top \nu_{ij}(\theta^s) = \left(\sum_{i,j} \mathbf{L}_{ij}^\top \mathbf{L}_{ij} \right) \mathbf{d}_s$$

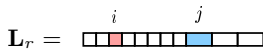


► Sparsity in Bundle Adjustment

We have $q = 3p + 11c$ parameters: $\theta = (\mathbf{X}_1, \mathbf{X}_2, \dots, \mathbf{X}_p; \mathbf{P}_1, \mathbf{P}_2, \dots, \mathbf{P}_c)$ points, cameras
 We will use a running index $r = 1, \dots, k$, $k = p \cdot c$. Then each r corresponds to some i, j

$$\theta^* = \arg \min_{\theta} \sum_{r=1}^k \nu_r^2(\theta), \quad \theta^{s+1} := \theta^s + \mathbf{d}_s, \quad - \sum_{r=1}^k \mathbf{L}_r^\top \nu_r(\theta^s) = \left(\sum_{r=1}^k \mathbf{L}_r^\top \mathbf{L}_r + \lambda \text{diag} \mathbf{L}_r^\top \mathbf{L}_r \right) \mathbf{d}_s$$

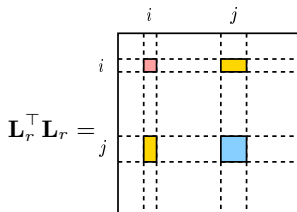
The block form of \mathbf{L}_r in Levenberg-Marquardt (Slide 101) is zero except in columns i and j :
 r -th error term is $\nu_r^2 = \rho(e_{ij}^2(\mathbf{X}_i, \mathbf{P}_j))$



blocks:

: $\mathbf{X}_i, 1 \times 3$

: $\mathbf{P}_j, 1 \times 11$

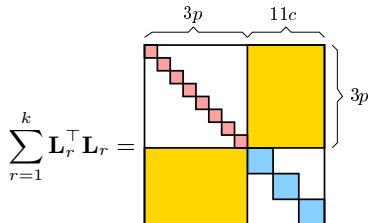


blocks:

: $\mathbf{X}_i \sim \mathbf{X}_i, 3 \times 3$

: $\mathbf{X}_i \sim \mathbf{P}_j, 3 \times 11$

: $\mathbf{P}_j \sim \mathbf{P}_j, 11 \times 11$



- “points first, then cameras” scheme
- standard bundle adjustment eliminates points and solves cameras, then back-substitutes



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