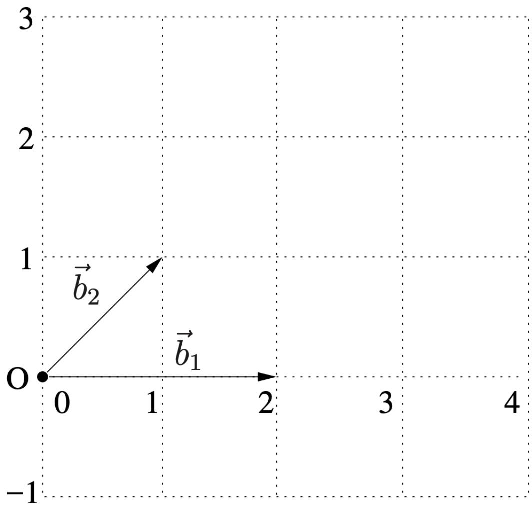
GVG Lab-05 Solution

Task 1. *The following picture shows a coordinate system* $\sigma = (O, \beta)$ *and a basis* $\beta = (\vec{b}_1, \vec{b}_2)$.



1. *Find a coordinate system* $\sigma' = (O', \beta')$, $\beta' = (\vec{b}_1', \vec{b}_2')$, *whose basis vector* $\vec{b}_1'$ *has in basis* β *coordinates*
$$\vec{b}'_{1\beta} = \begin{bmatrix} 1 \\ -1 \end{bmatrix}$$
and its origin O' *is in the coordinate system* σ *described by vector*
$$\vec{O}'_\beta = \begin{bmatrix} 1/2 \\ 1 \end{bmatrix}$$
and there exists point X *described by vector* $\vec{X}$ *in* σ *and vector* $\vec{X}'$ *in* σ' *with coordinates*
$$\vec{X}_\beta = \begin{bmatrix} 3/2 \\ 1 \end{bmatrix}, \quad \vec{X}'_{\beta'} = \begin{bmatrix} 1 \\ 1 \end{bmatrix}$$
and draw it on the picture.
2. *Write the coordinates of the point* O *in coordinate system* σ'.

Solution: By applying the same ideas as in the solution of Task 5 from Test-α we can write
$$\vec{X} = \vec{X}' + \vec{O}'$$
After passing to the coordinates of the above vectors in basis β we get
$$\vec{X}_\beta = \vec{X}'_\beta + \vec{O}'_\beta$$
$$\vec{X}_\beta = \mathtt{A}_{\beta' \to \beta} \vec{X}'_{\beta'} + \vec{O}'_\beta$$
$$\vec{X}_\beta = \begin{bmatrix} \vec{b}'_{1\beta} & \vec{b}'_{2\beta} \end{bmatrix} \vec{X}'_{\beta'} + \vec{O}'_\beta$$
$$\begin{bmatrix} 3/2 \\ 1 \end{bmatrix} = \begin{bmatrix} 1 & a \\ -1 & b \end{bmatrix} \begin{bmatrix} 1 \\ 1 \end{bmatrix} + \begin{bmatrix} 1/2 \\ 1 \end{bmatrix}$$
Rewriting the above matricial equation in terms of individual equations we obtain
$$\frac{3}{2} = 1 + a + \frac{1}{2}, \quad 1 = -1 + b + 1$$

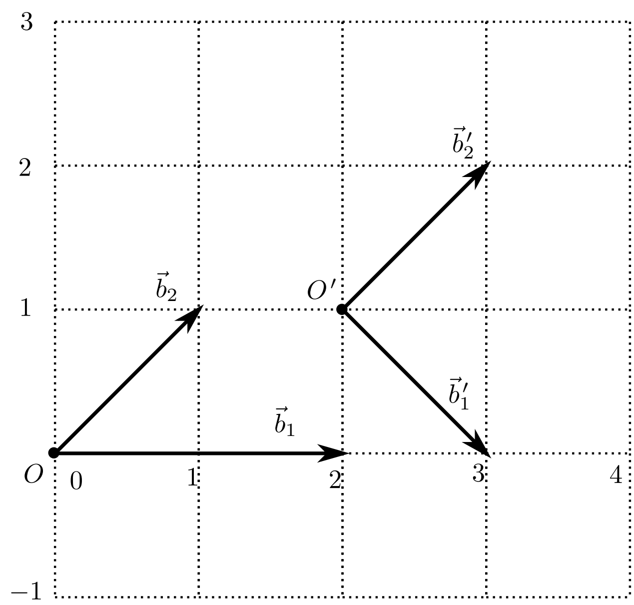
and hence

$$a = 0, \quad b = 1$$

which means that

$$\vec{b}'_{2\beta} = \begin{bmatrix} 0 \\ 1 \end{bmatrix}$$

In the picture the desired coordinate system σ' looks as follows:



□

Task 2. *Find coordinates of the image point which is the projection of point* $[1, 1, 1]^\top$ *by the camera with the following camera projection matrix*

$$\mathtt{P} = \begin{bmatrix} 1 & 0 & 0 & 0 \\ 1 & 0 & 1 & 0 \\ 0 & 1 & 0 & 1 \end{bmatrix}$$

Solution: See the methodology in the solution to Lab 02, Task 1. □

Answer: $[u, v] = \begin{bmatrix} \frac{1}{2} & 1 \end{bmatrix}^\top$.

Task 3. *Find the camera calibration matrix* K*, rotation* R*, and the projection center* $\vec{C}_\delta$ *of a camera with the camera projection matrix*

$$\mathtt{P} = \begin{bmatrix} 0 & 1 & 0 & 1 \\ 1 & 0 & 1 & 0 \\ 1 & 0 & 0 & 0 \end{bmatrix}$$

Solution: See the methodology in the solution to Lab 03, Task 3. The only difference is that in this task $\mathtt{KR} = \mathtt{P}_{1:3,1:3}$. □

Answer:

$$\mathtt{K} = \begin{bmatrix} 1 & 0 & 0 \\ 0 & 1 & 1 \\ 0 & 0 & 1 \end{bmatrix}, \quad \mathtt{R} = \begin{bmatrix} 0 & 1 & 0 \\ 0 & 0 & 1 \\ 1 & 0 & 0 \end{bmatrix}, \quad \vec{C}_\delta = \begin{bmatrix} 0 \\ -1 \\ 0 \end{bmatrix}$$

Task 4. *Denote the image coordinates by* $[u, v]^\top$. *Write down coordinates of all points in the three-dimensional space that projects on the line* $v = 0$ *by a camera with the following camera projection matrix*

$$\mathtt{P} = \begin{bmatrix} 1 & 0 & 0 & 0 \\ 1 & 1 & 0 & 0 \\ 0 & 0 & 1 & 2 \end{bmatrix}$$

Solution: See the solution to Lab 02, Task 4. □