CONTENTS

1 Introduction 1

1.1 The Background of Machine Vision 1

1.2 The Aim of This Book 4

1.3 The Organization of This Book 6
- 1.3.1 Computational projective geometry 6
- 1.3.2 Translational motion, stereo and 3-D rotation 7
- 1.3.3 Analysis of 3-D motion and optical flow 9
- 1.3.4 Analysis of conics 11
- 1.3.5 Statistical analysis of geometric computation 12

1.4 Bibliographical Notes 13

2 Computational Projective Geometry, 1 15

2.1 Geometry of Perspective Projection 15
- 2.1.1 Interpretation of N-vectors 15
- 2.1.2 Vanishing points and vanishing lines 19

2.2 Computation of Points and Lines 20
- 2.2.1 Fundamental duality of N-vectors 20
- 2.2.2 Collinearity of points and concurrency of lines 21

2.3 Geometry of 2-D Projective Space 25
- 2.3.1 Collineations and camera rotation transformations 25
- 2.3.2 Correlations, polarities, conjugacy, and conics 28

2.4 Cross Ratio and Projective Coordinates 30
- 2.4.1 Perspective invariance of cross ratio 30
- 2.4.2 Projective invariance of cross ratio 35
- 2.4.3 Harmonic Range of Points 40

2.5 Bibliographical Notes 42

Exercises 43

3 Computational Projective Geometry, 2 51

3.1 Geometry of Standard Polarity 51
- 3.1.1 The absolute conic and its polarity 51
- 3.1.2 Conjugacy and orthogonality 54

3.2 Camera Calibration 56

3.2.1 Determination of the focal length 56
3.2.2 Pose parameters and motion parameters 60
3.2.3 Constraints on rectangles and squares 63

3.3 3-D Road Shape Reconstruction 65
3.3.1 Modelling ideal roads 65
3.3.2 Local-flatness approximation 67
3.3.3 3-D reconstruction by curve fitting 69

3.4 Bibliographical Notes 72

Exercises 74

4 Translational Motion and Stereo 77

4.1 Analysis of Translational Motion 77
4.1.1 N-velocities and trajectories 77
4.1.2 Focus of expansion 78
4.1.3 Constant velocity motion 80
4.1.4 Vanishing points and line orientations 82

4.2 Motion Parallax 84
4.2.1 Motion parallax of a point 84
4.2.2 Representation of a space line 86
4.2.3 Motion parallax of a line 89
4.2.4 Motion parallax for general motion 91

4.3 Analysis of Stereo 92
4.3.1 Epipolars and epipole 92
4.3.2 Disparity maps and depth maps 94
4.3.3 Converging stereo 95

4.4 Bibliographical Notes 96

Exercises 98

5 Computation of 3-D Rotation 100

5.1 Representation of 3-D Rotation 100
5.1.1 Rotation matrices 100
5.1.2 Axis and angle of rotation 102

5.2 Optimal Estimation of 3-D Rotation 105
5.2.1 Least-squares estimation of 3-D rotation 105
5.2.2 Singular value decomposition 109
5.2.3 Polar decomposition 112
5.2.4 Quaternion representation 114

5.3 Orthogonality Recovery 117
5.3.1 Orthogonality fitting 117
5.3.2 Orthogonal frame reconstruction 118

5.3.3 Optimal resolution 121
5.4 Spherical Optimization Search 123
5.4.1 Optimization of pose and orientation 123
5.4.2 Quadratic search 124
5.4.3 Model update search 128
5.5 Bibliographical Notes 130
Exercises 132

6 Analysis of 3-D Rigid Motion 143

6.1 Representation of Planar Surface Motion 143
6.1.1 Planar surface motion 143
6.1.2 Collineation of planar surface motion 146
6.2 3-D Interpretation of Planar Surface Motion 148
6.2.1 Analytical solution 148
6.2.2 Ambiguity of planar surface motion 151
6.3 Determination of Collineation 153
6.4 3-D Interpretation from Point Correspondence 156
6.4.1 General formulation 156
6.4.2 Optimization search 158
6.5 Least-Squares Point Correspondence Algorithm 160
6.5.1 Essential matrix and eight-point algorithm 160
6.5.2 Robust analytical solution 161
6.5.3 Decomposability and uniqueness 165
6.6 3-D Interpretation from Line Correspondence 166
6.6.1 General formulation 166
6.6.2 Optimization search 168
6.7 Least-Squares Line Correspondence Algorithm 170
6.7.1 Essential parameters and thirteen-line algorithm 170
6.7.2 Robust analytical solution 171
6.7.3 Uniqueness of the solution 177
6.8 Ambiguity of 3-D Interpretation 178
6.8.1 Critical surface for point correspondence 178
6.8.2 Degeneracy into two planar surfaces 183
6.8.3 Critical line congruence for line correspondence 185
6.9 Bibliographical Notes 188
Exercises 191

7 Analysis of Optical Flow 196

7.1 Representation of Planar Surface Optical Flow 196
7.1.1 Infinitesimal surface motion 196
7.1.2 Optical flow and flow matrix 197
7.1.3 Optical flow of lines and dual flow 199

7.2 3-D Interpretation of Planar Surface Optical Flow 200
7.2.1 Optical flow and motion parameters 200
7.2.2 Analytical solution 201

7.3 Determination of the Flow Matrix 203
7.3.1 Flow-based approach 203
7.3.2 Contour-based approach 206

7.4 Representation of General Optical Flow 208
7.4.1 General optical flow equation 208
7.4.2 Twisted flow and the epipolar equation 210

7.5 3-D Interpretation of General Optical Flow 212
7.5.1 Least-squares algorithm 212
7.5.2 Optimization search 215

7.6 Critical Surface of Optical Flow 217
7.6.1 Critical surface equation 217
7.6.2 Degeneracy into two planes 220

7.7 Bibliographical Notes 221

Exercises 223

8 Analysis of Conics 228

8.1 Conics and Their Canonical Forms 228
8.1.1 Representation of a conic 228
8.1.2 Canonical form of a conic 229

8.2 Polarity of a Conic 231
8.2.1 Poles, polars, and tangents 231
8.2.2 Conjugacy of points and lines 234

8.3 Intersections and Orthogonality 235
8.3.1 Intersections of a conic with a line 235
8.3.2 Interpretation of rectangular corners 237

8.4 Conic Fitting 240
8.4.1 Existence and uniqueness 240
8.4.2 Least-squares fitting 240

8.5 3-D Interpretation of a Conic 242
8.5.1 The supporting plane and the true shape 242
8.5.2 3-D interpretation of a circle 246

8.5.3 3-D interpretation of an ellipse 251
8.6 Mapping of Conics and Invisible Motions 258
8.6.1 Group of invisible motions 258
8.6.2 Mapping of conics 260
8.6.3 Standard circle 262
8.7 Invisible Optical Flows 263
8.7.1 Representation of invisible flows 263
8.7.2 Adjoint transformation of invisible flows 266
8.8 Deformation of a Conic 268
8.8.1 Linear space of conic deformations 268
8.8.2 Normal flow along a conic 271
8.9 3-D Interpretation of a Moving Conic 271
8.9.1 Finite motion of a conic 271
8.9.2 Infinitesimal motion of a conic 273
8.10 Bibliographical Notes 275
Exercises 277
9 Statistical Analysis of Geometric Computation, 1 280
9.1 Statistical Model of Noise 280
9.1.1 Covariance matrix of an N-vector 280
9.1.2 Model of noise 282
9.1.3 Effective focal length 283
9.2 Covariance Matrices of Joins and Intersections 284
9.3 Optimal Least-Squares Estimation 287
9.3.1 Optimal weights and optimal estimation 287
9.3.2 Covariance matrix of optimal estimation 289
9.3.3 Statistical bias of optimal estimation 292
9.4 Edge Fitting, Vanishing Points, and Focuses of Expansion 294
9.4.1 Error in edge fitting 294
9.4.2 Error in vanishing points 297
9.4.3 Error in focuses of expansion 300
9.5 Statistics of Rotation Fitting 305
9.5.1 Covariance matrix of 3-D rotation 305
9.5.2 Covariance matrix of the best fitting rotation 305
9.6 Statistics of Depth from Stereo 309
9.6.1 Sources of error 309
9.6.2 Error due to image noise 310

9.6.3 Error due to uncertainty of camera orientation 311
9.6.4 Error due to uncertainty of base-line 312
9.7 Bibliographical Notes 314
Exercises 315

10 Statistical Analysis of Geometric Computation, 2 318

10.1 Statistics of Focal Length Calibration 318
10.1.1 Reliability of focal length estimation 318
10.1.2 Optimal estimation of focal length 322
10.2 Statistical Analysis of 3-D Motion Estimation 326
10.2.1 Statistical bias of motion parameters 326
10.2.2 Small object approximation 330
10.2.3 Unbiased motion parameter estimation 333
10.3 Statistics of Conic Fitting 336
10.3.1 Optimal conic fitting 336
10.3.2 Covariance tensor of conic fitting 337
10.3.3 Statistical bias of conic fitting 340
10.3.4 Unbiased conic fitting 346
10.4 Hypothesizing and Testing Geometric Configurations 349
10.4.1 Gaussian approximation 349
10.4.2 Testing edge groupings 350
10.4.3 Testing vanishing points 352
10.4.4 Testing focuses of expansion 354
10.4.5 Testing vanishing lines 355
10.5 Bibliographical Notes 357
Exercises 360

References 364

Answers 381

Index 468