Intro to 3D + Camera Calibration

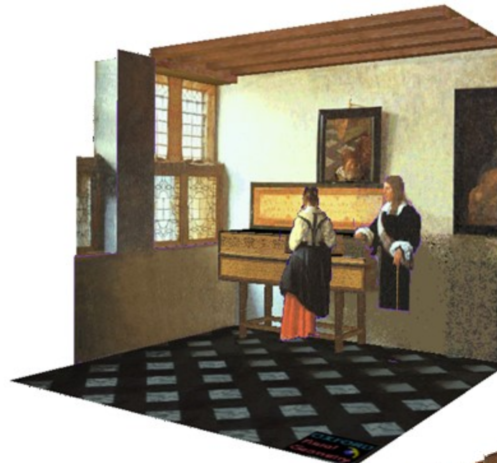
EECS 442 – David Fouhey

Fall 2019, University of Michigan

http://web.eecs.umich.edu/~fouhey/teaching/EECS442_F19/

Our goal: Recovery of 3D structure

J. Vermeer, *Music Lesson*, 1662

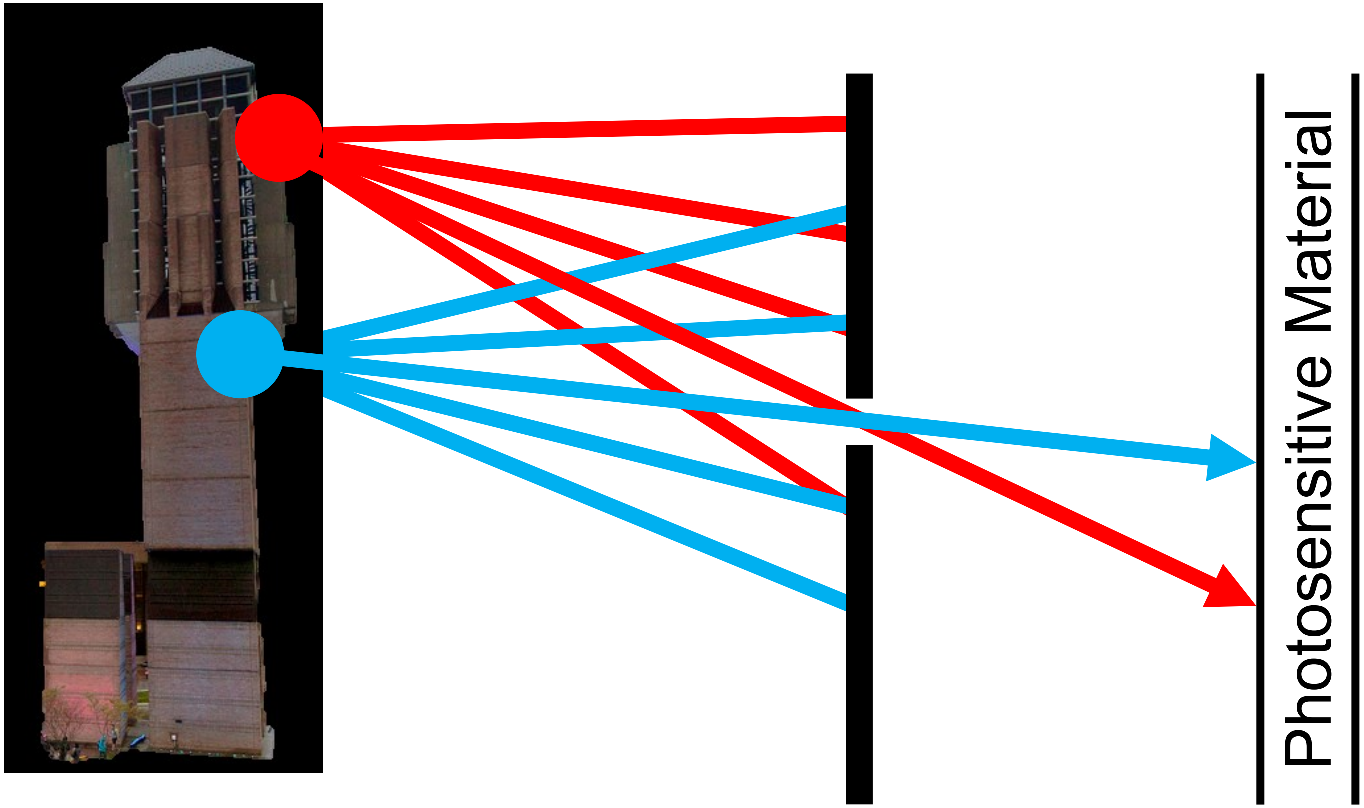


A. Criminisi, M. Kemp, and A. Zisserman,[Bringing Pictorial Space to Life: computer techniques for the analysis of paintings](), *Proc. Computers and the History of Art*, 2002

Next few classes

- First: some intuitions and examples from biological vision about 3D perception
- But first, a brief review

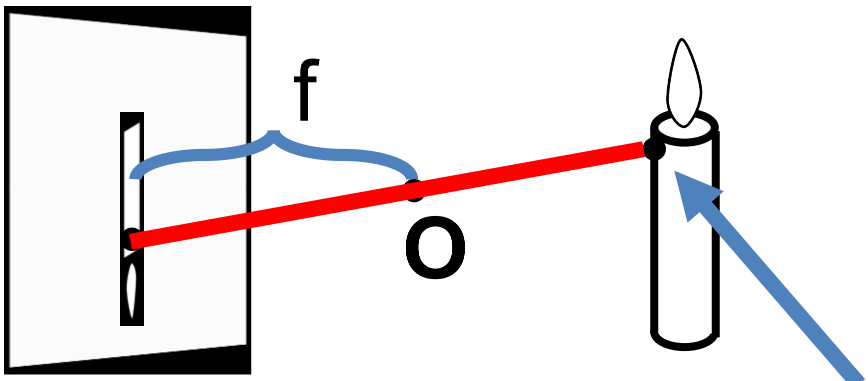
Let’s Take a Picture!



Slide inspired by S. Seitz; image from Michigan Engineering

Projection Matrix

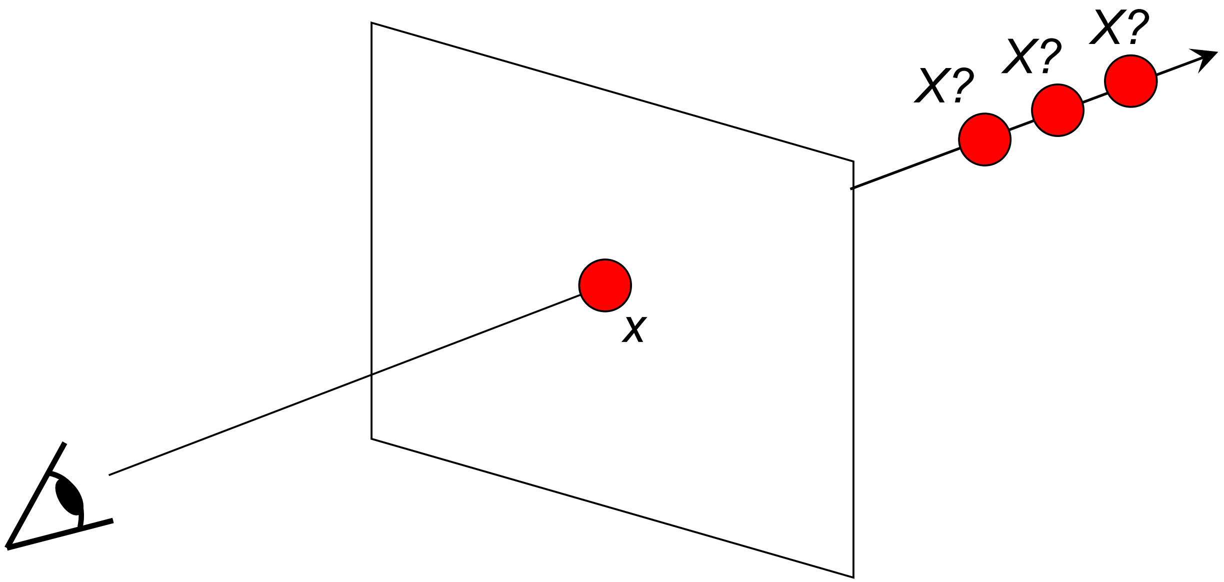
Projection (fx/z, fy/z) is matrix multiplication



$$\begin{bmatrix} fx \\ fy \\ z \end{bmatrix} \equiv \begin{bmatrix} f & 0 & 0 & 0 \\ 0 & f & 0 & 0 \\ 0 & 0 & 1 & 0 \end{bmatrix} \begin{bmatrix} x \\ y \\ z \\ 1 \end{bmatrix} \rightarrow \begin{bmatrix} fx/z \\ fy/z \end{bmatrix}$$

Slide inspired from L. Lazebnik

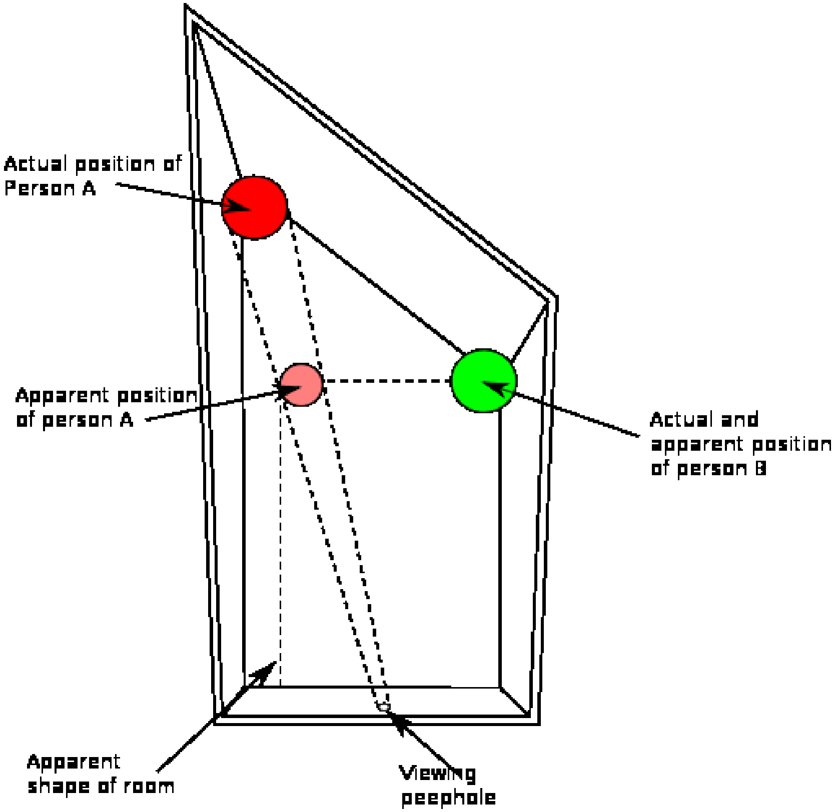
Single-view Ambiguity



- Given a *calibrated camera* and an image, we only know the ray corresponding to each pixel.
- Nowhere near enough constraints for X

Diagram credit: S. Lazebnik

Single-view Ambiguity



http://en.wikipedia.org/wiki/Ames_room

Slide Credit: J. Hays

Single-view Ambiguity

Diagram credit: J. Hays

Single-view Ambiguity

[Rashad Alakbarov shadow sculptures]

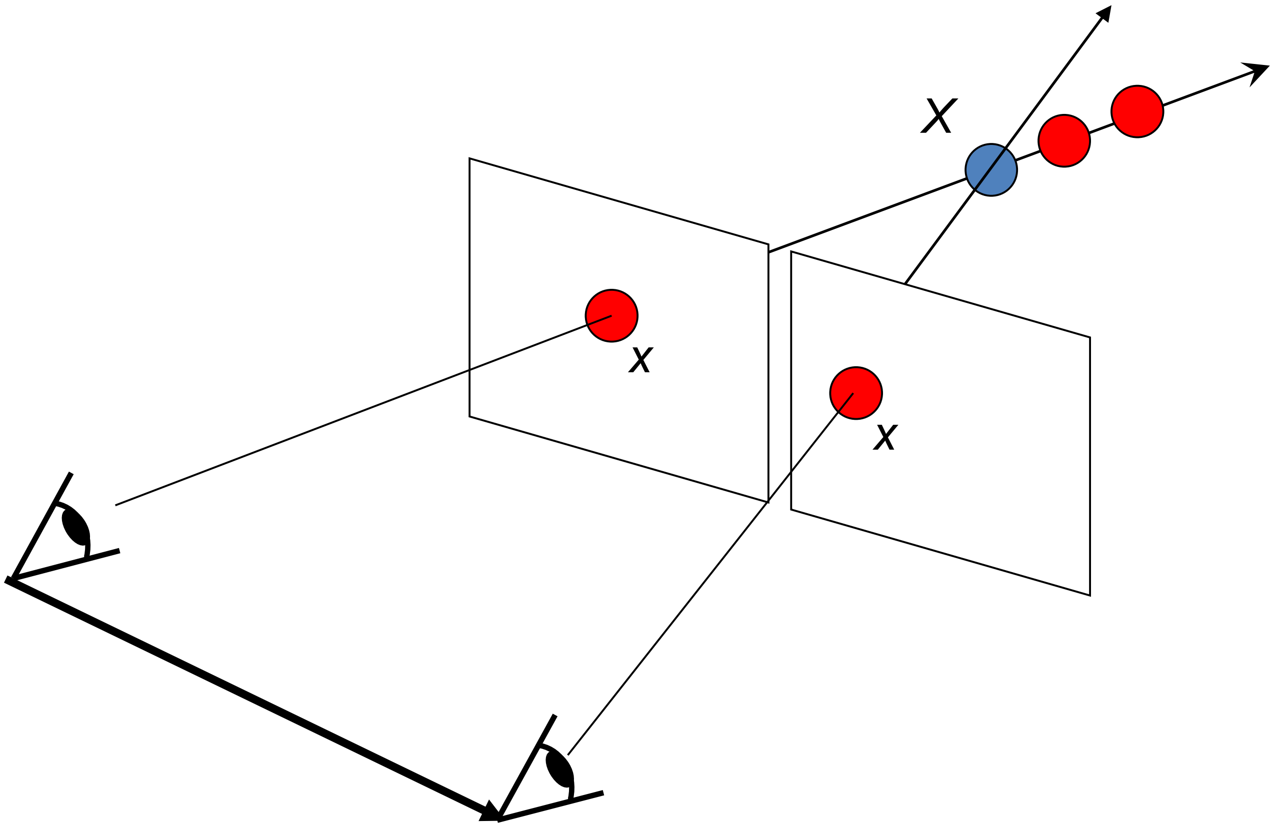
Resolving Single-view Ambiguity

- Shoot light (lasers etc.) out of your eyes!
- Con: not so biologically plausible, dangerous?

Resolving Single-view Ambiguity

- Shoot light (lasers etc.) out of your eyes!
- Con: not so biologically plausible, dangerous?

Resolving Single-view Ambiguity

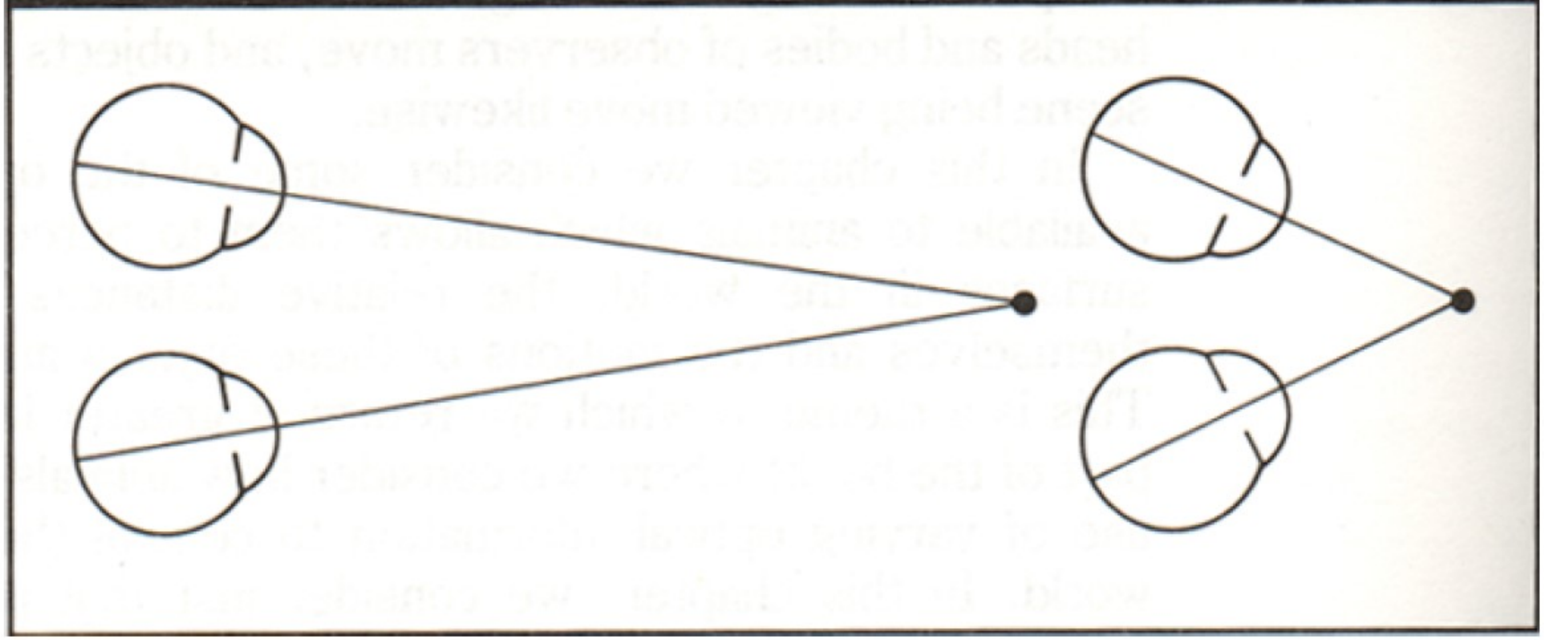


- Stereo: given 2 calibrated cameras in different views and correspondences, can solve for X

Original diagram credit: S. Lazebnik

Human stereopsis: disparity

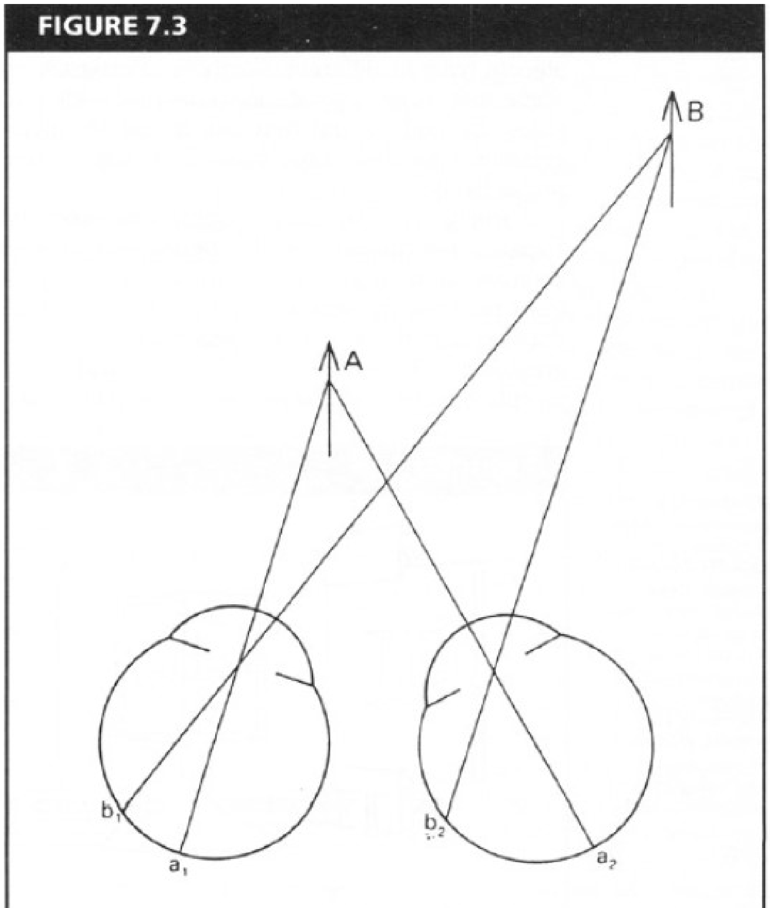
FIGURE 7.1



From Bruce and Green, Visual Perception, Physiology, Psychology and Ecology

Human eyes **fixate** on point in space – rotate so that corresponding images form in centers of fovea.

Human stereopsis: disparity



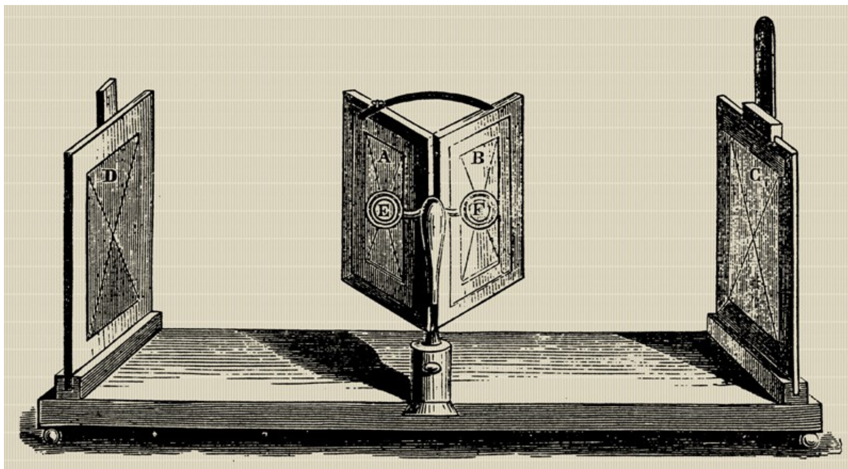
From Bruce and Green, Visual Perception, Physiology, Psychology and Ecology

Disparity occurs when eyes fixate on one object; others appear at different visual angles

Adapted from David Forsyth, UC Berkeley

Stereo photography and stereo viewers

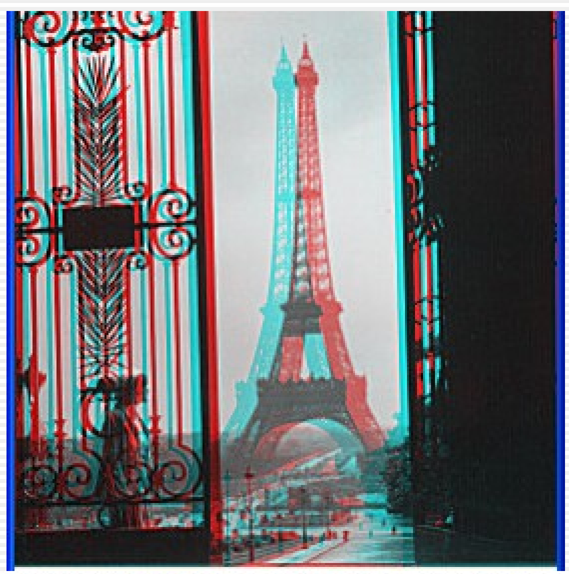
Take two pictures of the same subject from two slightly different viewpoints and display so that each eye sees only one of the images.



Invented by Sir Charles Wheatstone, 1838


Image from fisher-price.com

Slide credit: J. Hays



http://www.johnsonshawmuseum.org

Slide credit: J. Hays

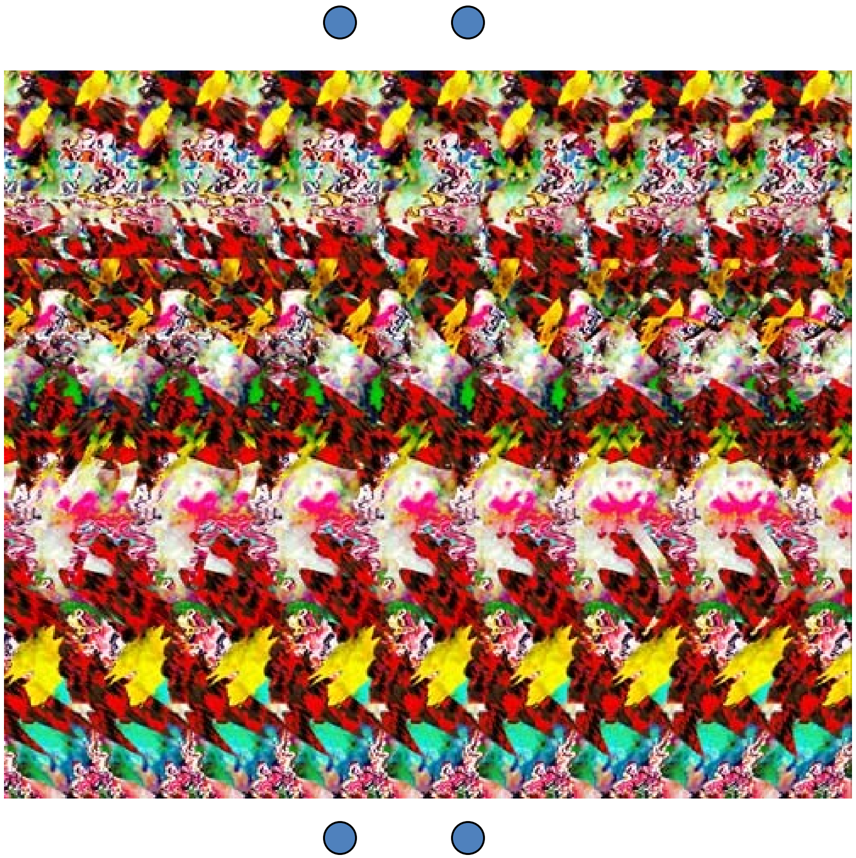
http://www.well.com/~jimg/stereo/stereo_list.html

Slide credit: J. Hays

http://www.well.com/~jimg/stereo/stereo_list.html

Slide credit: J. Hays

Autostereograms



Exploit disparity as depth cue using single image.

(Single image random dot stereogram, Single image stereogram)

Slide credit: J. Hays, Images from magiceye.com

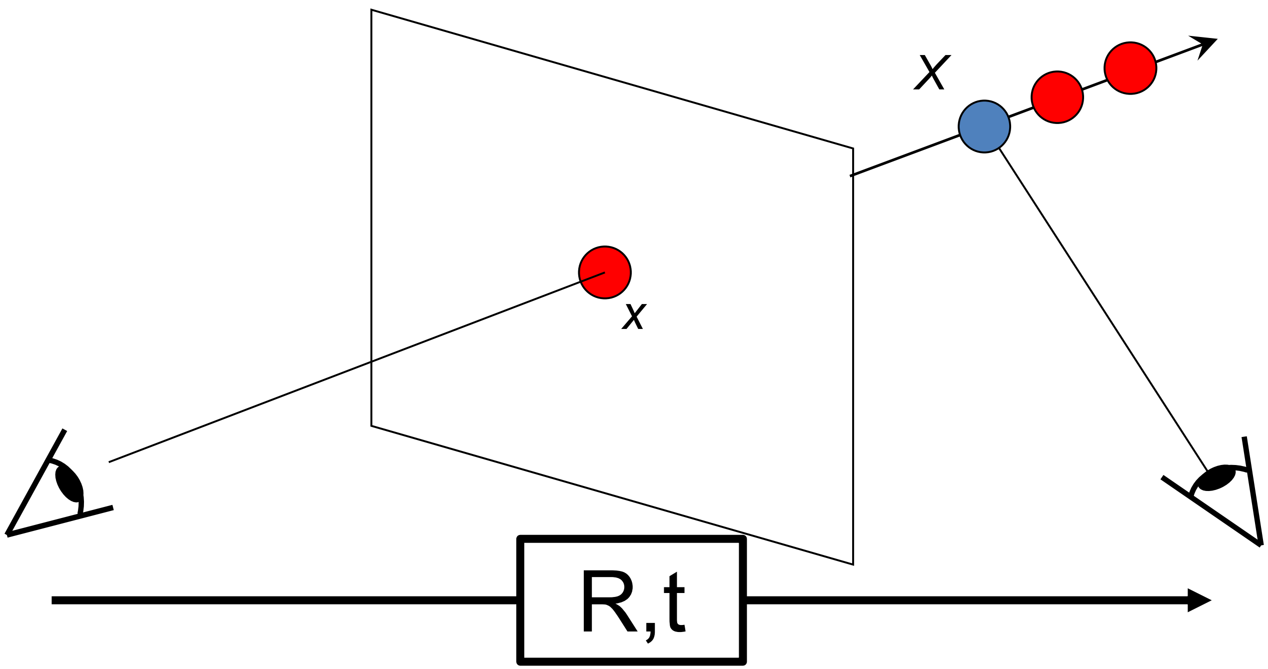
Autostereograms

Slide credit: J. Hays, Images from magiceye.com

Yeah, yeah, but…

Not all animals see stereo:
Prey animals (large field of view to spot predators)
Stereoblind people

Resolving Single-view Ambiguity

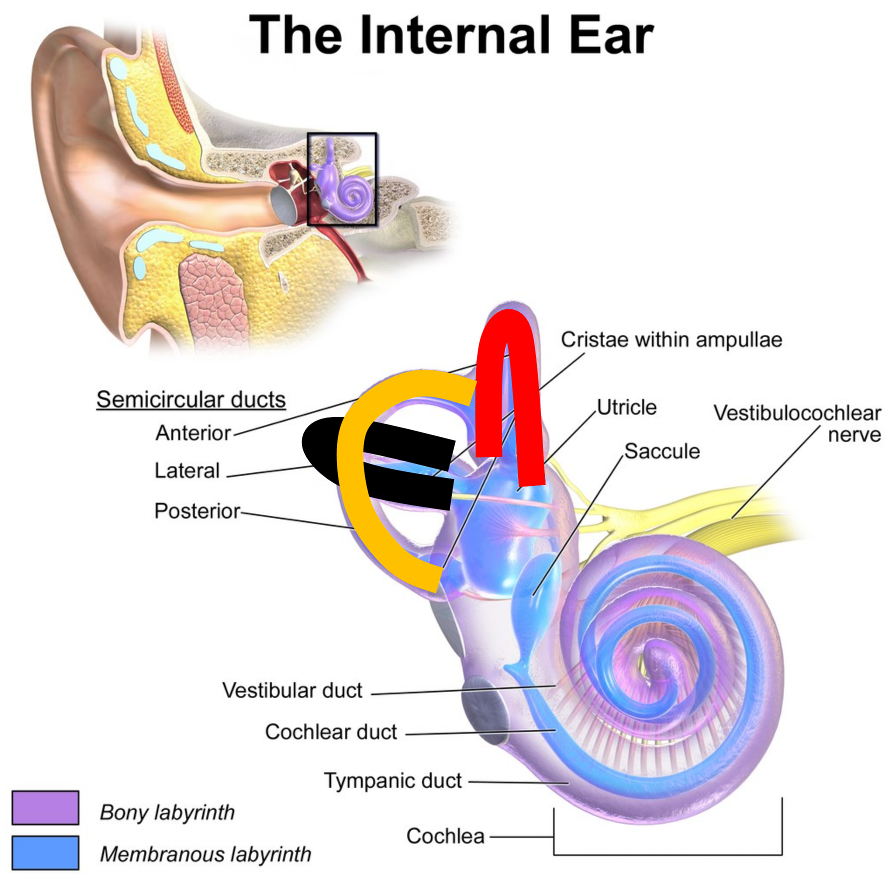


- One option: move, find correspondence.
- If you know how you moved and have a calibrated camera, can solve for X

Original diagram credit: S. Lazebnik

Knowing R,t

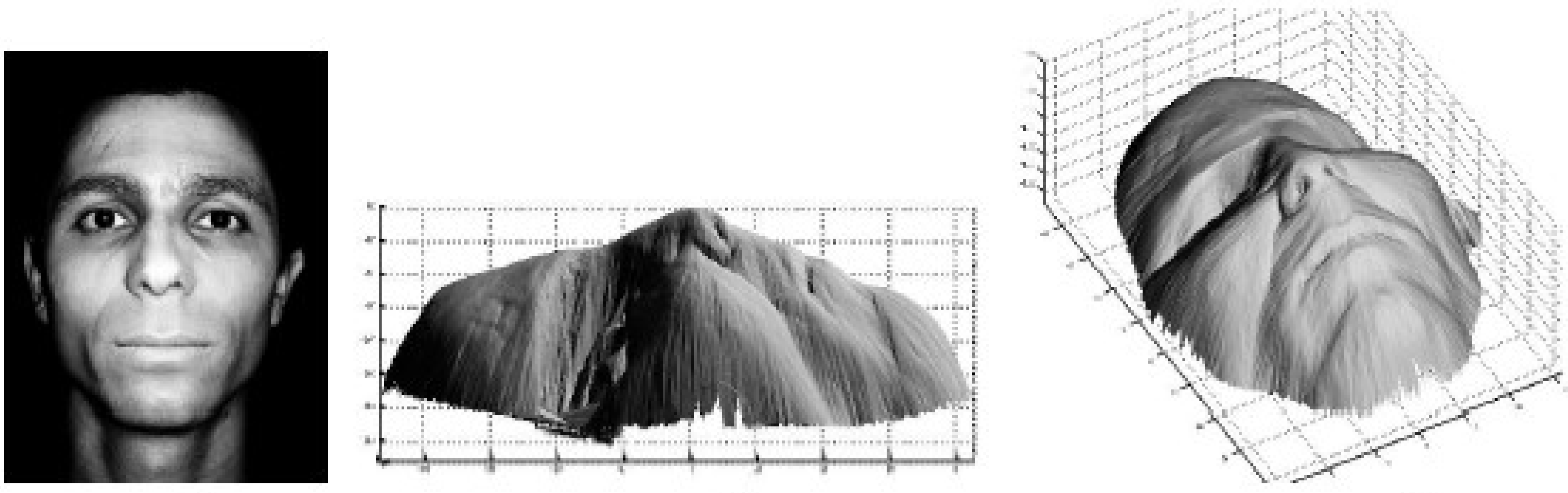
- How do you know how far you moved?
- Can solve via vision
- Can solve via ears
- **Why does your inner ear have 3 ducts?**
- Can solve via signals sent to muscles



Yeah, yeah, but…

You haven't been here before, yet you probably have a fairly good understanding of this scene.

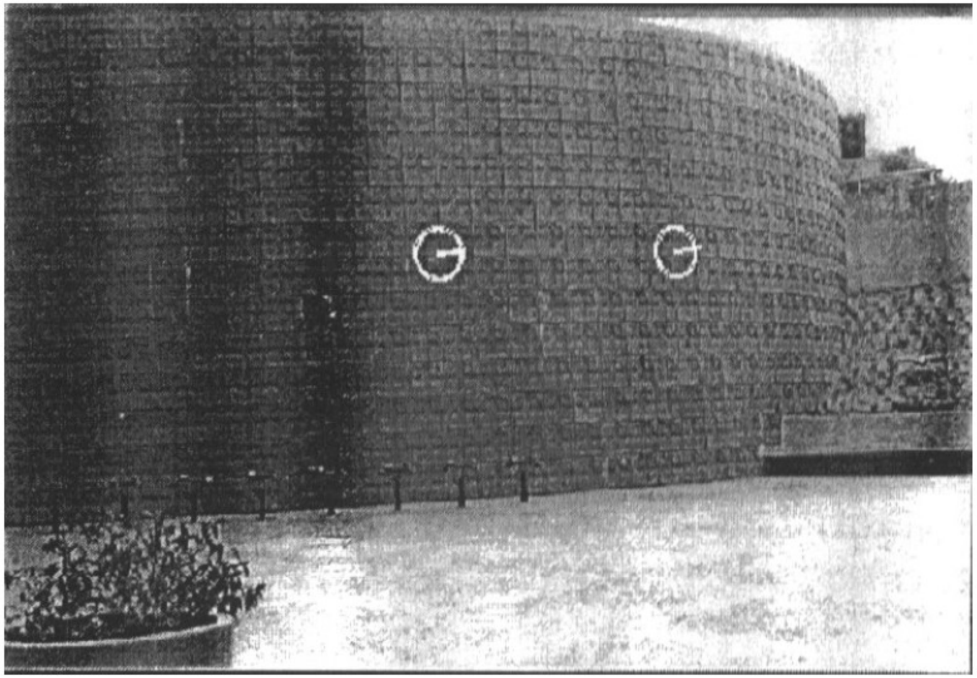
Pictorial Cues – Shading

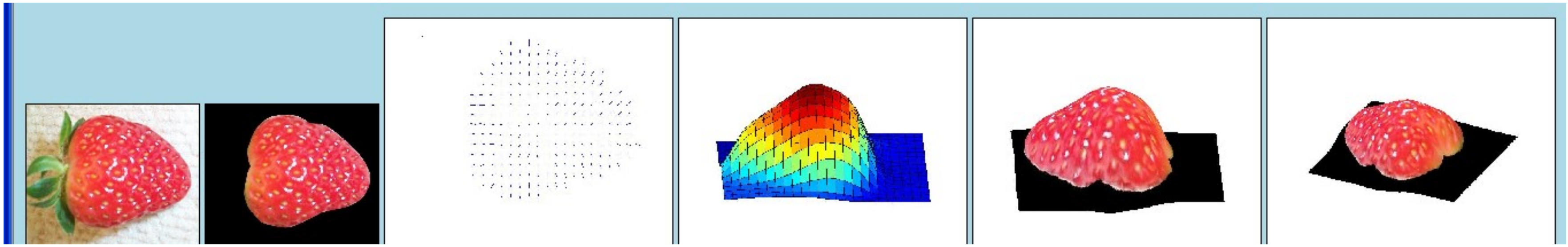


a) b) c)

[Figure from Prados & Faugeras 2006]

Pictorial Cues – Texture





[From A.M. Loh. The recovery of 3-D structure using visual texture patterns. PhD thesis]

Pictorial Cues – Perspective effects

Image credit: S. Seitz

Pictorial Cues – Familiar Objects

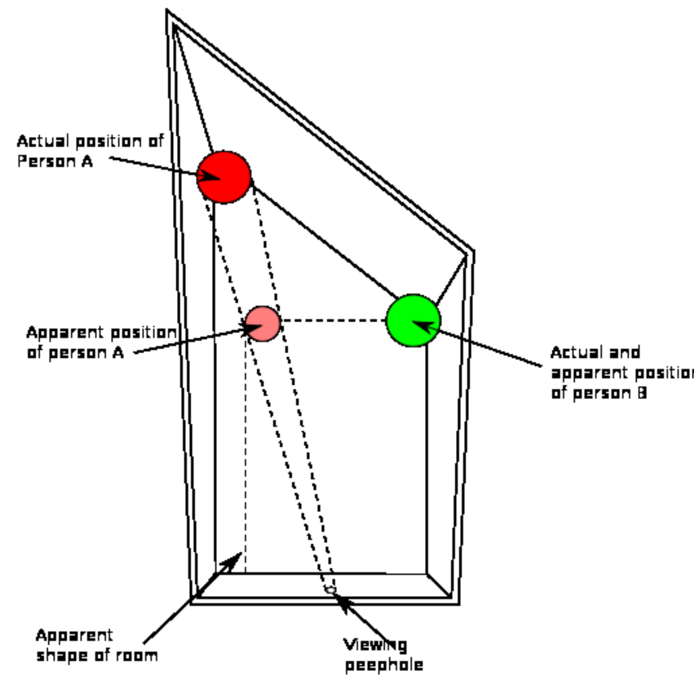
Reality of 3D Perception

- 3D perception is absurdly complex and involves integration of many cues:
  - Learned cues for 3D
  - Stereo between eyes
  - Stereo via motion
  - Integration of known motion signals to muscles (efferent copy), acceleration sensed via ears
  - Past experience of touching objects
- All connect: learned cues from 3D probably come from stereo/motion cues in large part

Really fantastic article on cues for 3D from Cutting and Vishton, 1995: https://pmvish.people.wm.edu/cutting%26vishton1995.pdf

How are Cues Combined?

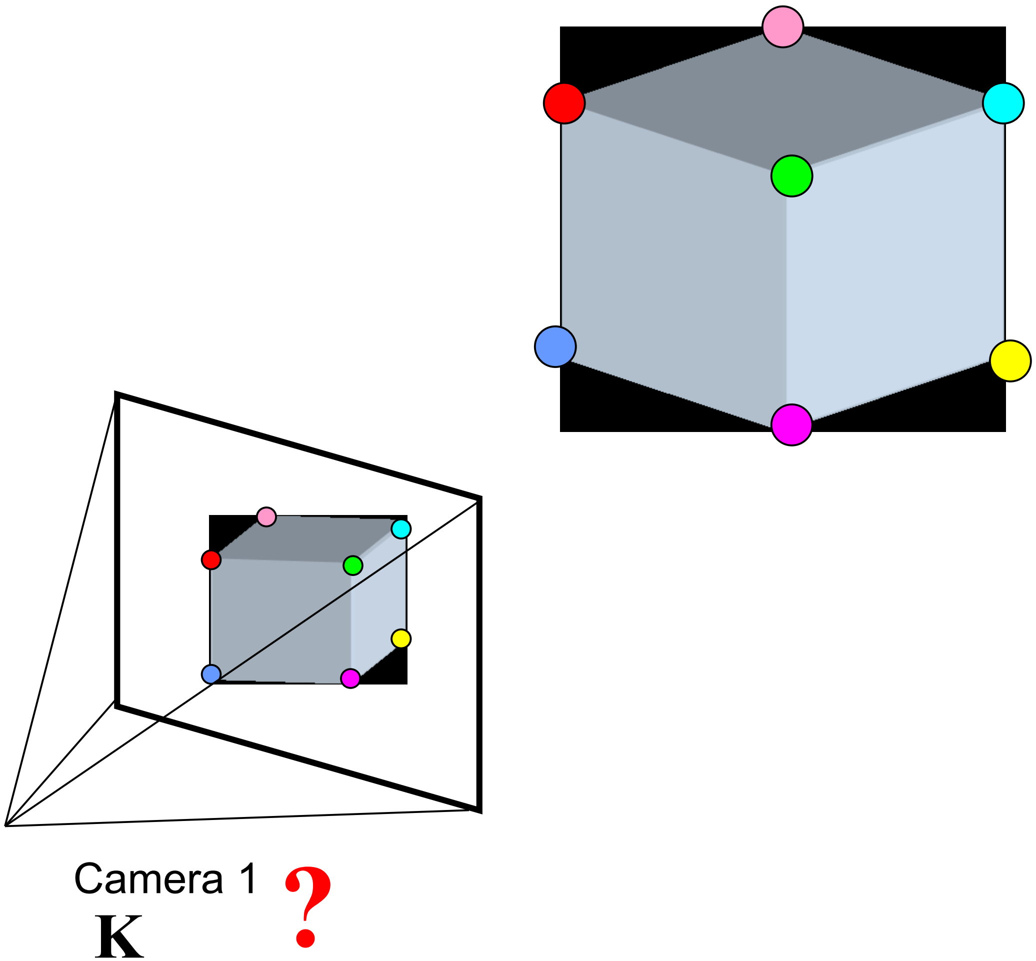
Ames illusion persists (in a weaker form) even if you have stereo vision –gussing the texture is rectilinear is usually incredibly reliable



Gehringer and Engel, Journal of Experimental Psychology: Human Perception and Performance, 1986

More Formally

Multi-view geometry problems

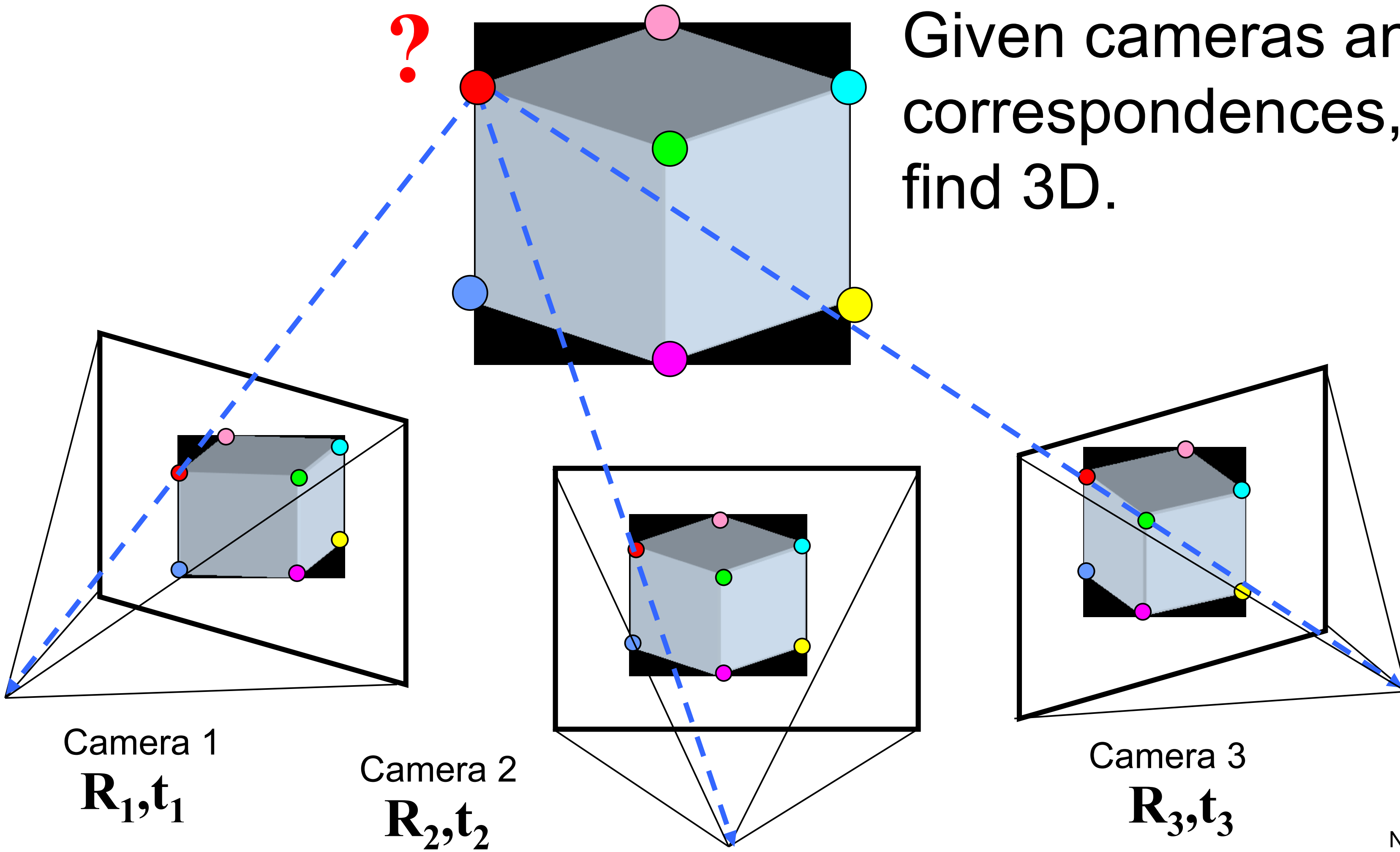


Calibration:
We need camera intrinsics / K in order to figure out where the rays are

Slide credit: Noah Snavely

Multi-view geometry problems

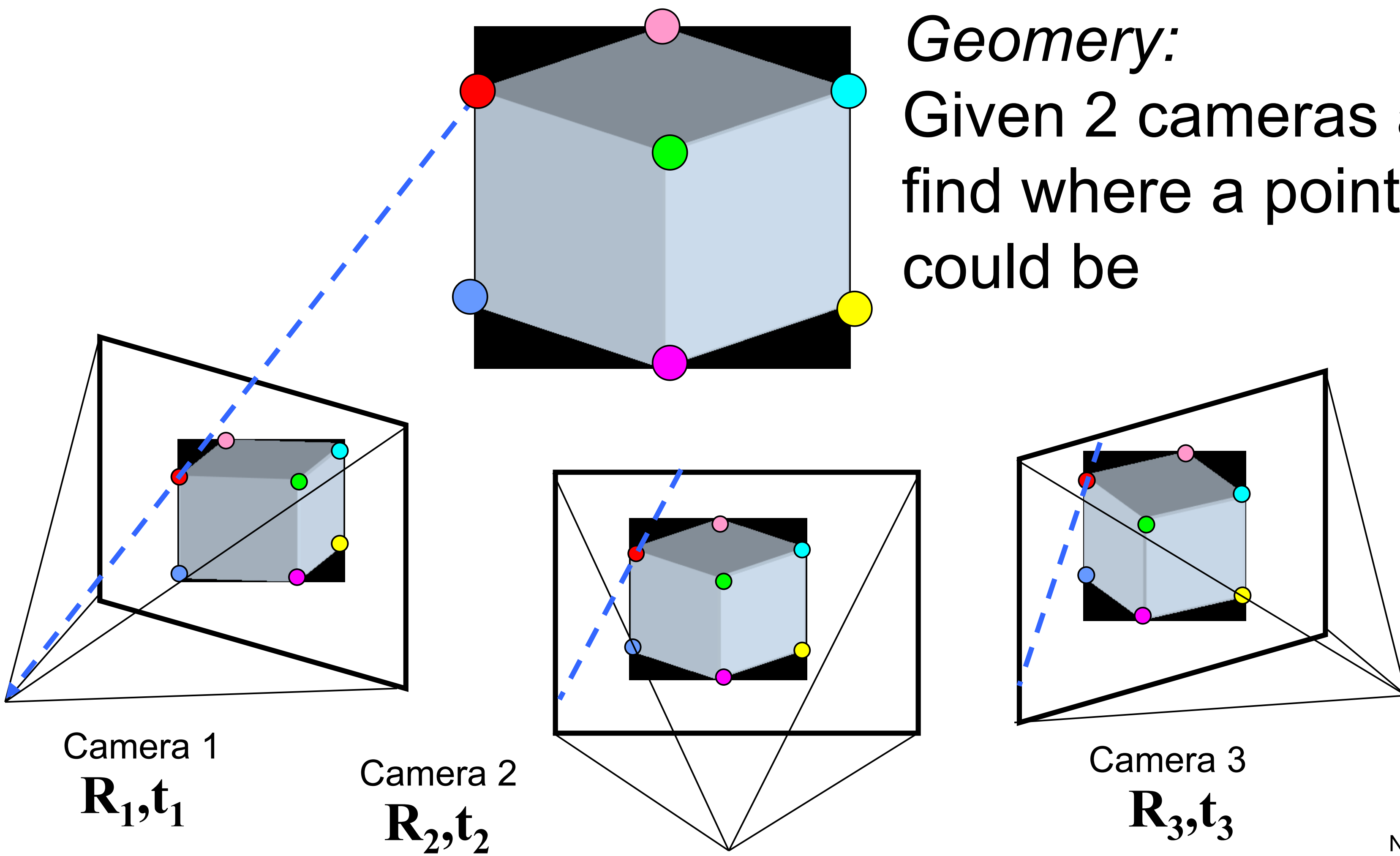
Recovering structure: Given cameras and correspondences, find 3D.



Slide credit: Noah Snavely

Multi-view geometry problems

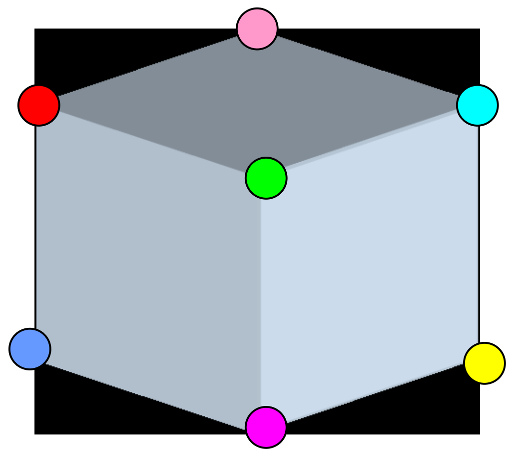
Stereo/Epipolar Geomery:
Given 2 cameras and find where a point could be

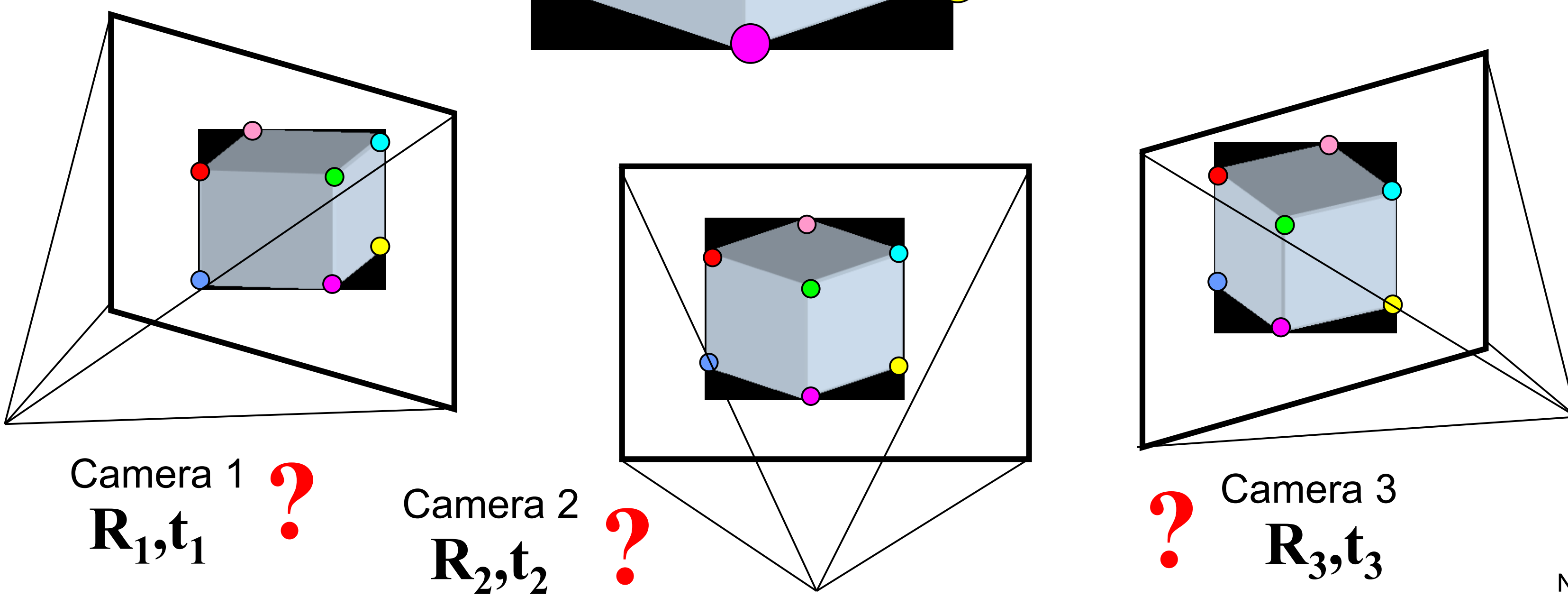


Slide credit: Noah Snavely

Multi-view geometry problems

Motion:
Figure out R, t for a set of cameras given correspondences





Slide credit:
Noah Snavely

Outline

- (Today) Calibration:
  - Getting intrinsic matrix/K
- Single view geometry:
  - measurements with 1 image
- Stereo/Epipolar geometry:
  - 2 pictures → depthmap
- Structure from motion (SfM):
  - 2+ pictures → cameras, pointcloud

Typical Perspective Model

principal point (image coords of camera origin on retina)
Just moves camera origin

focal length

rotation translation

$$\boldsymbol{p} \equiv \begin{bmatrix} f & 0 & u_0 \\ 0 & f & v_0 \\ 0 & 0 & 1 \end{bmatrix} [\boldsymbol{R}_{3x3} \quad \boldsymbol{t}_{3x1}] \quad \boldsymbol{X}_{4x1}$$

2D Projection of X

3D point

Camera Calibration

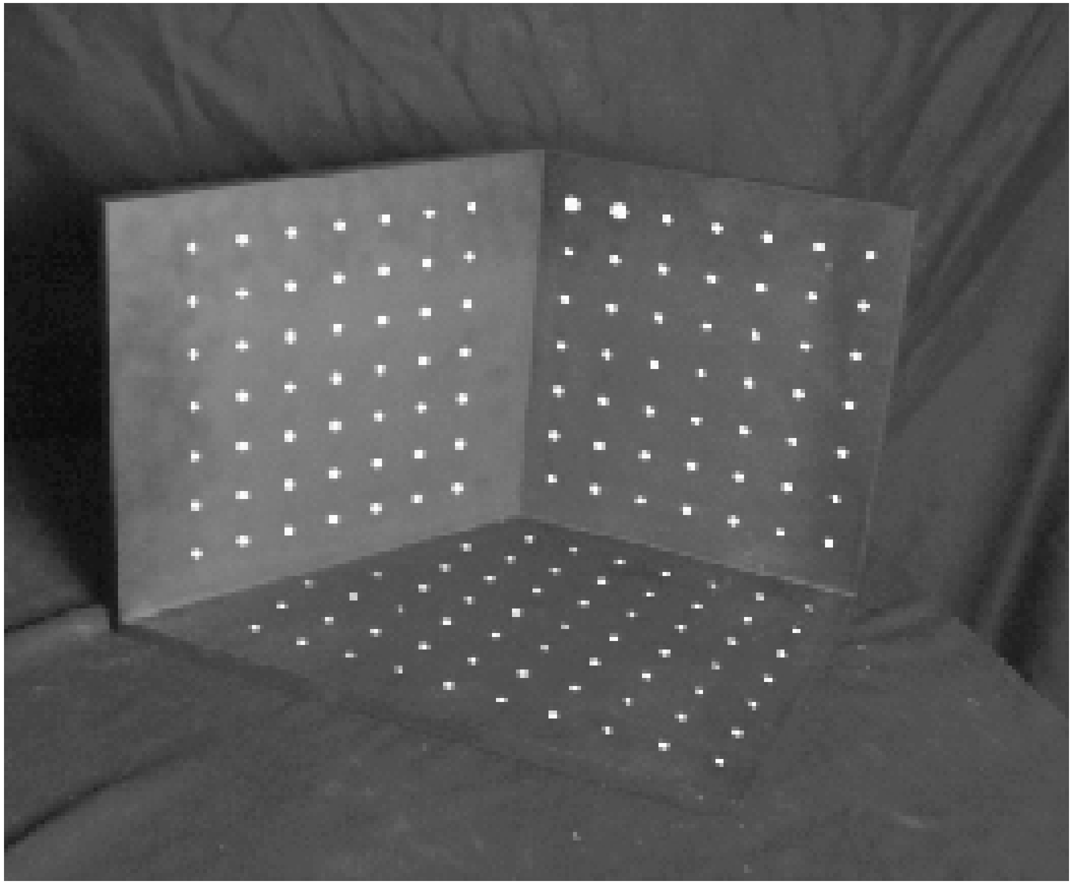
$$\boldsymbol{p} \equiv \begin{bmatrix} f & 0 & u_0 \\ 0 & f & v_0 \\ 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} \boldsymbol{R}_{3x3} & \boldsymbol{t}_{3x1} \end{bmatrix} \boldsymbol{X}_{4x1}$$

$$\begin{bmatrix} u \\ v \\ 1 \end{bmatrix} \equiv \boldsymbol{M}_{3x4} \begin{bmatrix} X \\ Y \\ Z \\ 1 \end{bmatrix}$$

If I can get pairs of [X,Y,Z] and [u,v]
→ equations to constrain **M**
How do I get [X,Y,Z], [u,v]

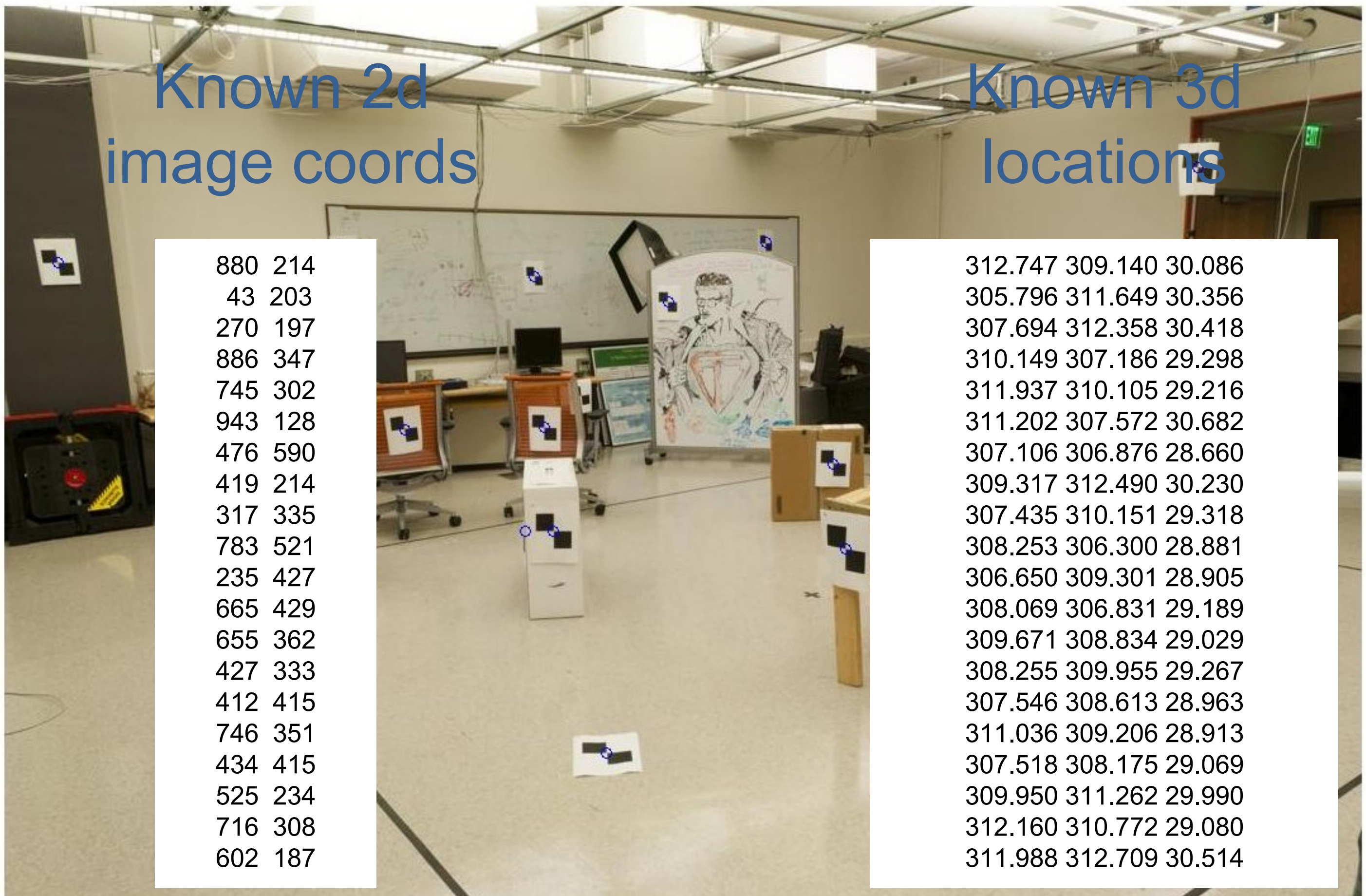
Camera Calibration

A funny object with multiple planes.



Camera Calibration Targets

Using a tape measure



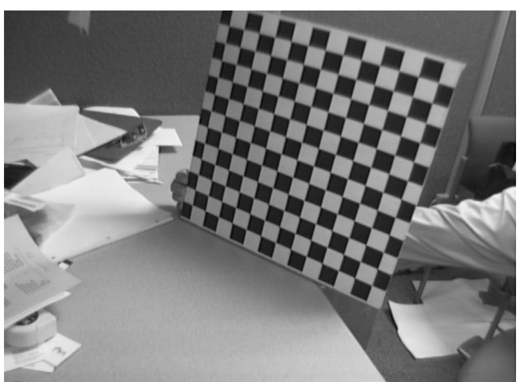
Known 2d image coords		Known 3d locations		
880	214	312.747	309.140	30.086
43	203	305.796	311.649	30.356
270	197	307.694	312.358	30.418
886	347	310.149	307.186	29.298
745	302	311.937	310.105	29.216
943	128	311.202	307.572	30.682
476	590	307.106	306.876	28.660
419	214	309.317	312.490	30.230
317	335	307.435	310.151	29.318
783	521	308.253	306.300	28.881
235	427	306.650	309.301	28.905
665	429	308.069	306.831	29.189
655	362	309.671	308.834	29.029
427	333	308.255	309.955	29.267
412	415	307.546	308.613	28.963
746	351	311.036	309.206	28.913
434	415	307.518	308.175	29.069
525	234	309.950	311.262	29.990
716	308	312.160	310.772	29.080
602	187	311.988	312.709	30.514

Image credit: J. Hays

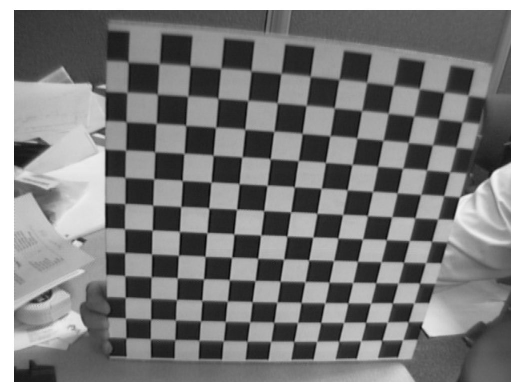
Camera Calibration Targets

A set of views of a plane (not covered today)



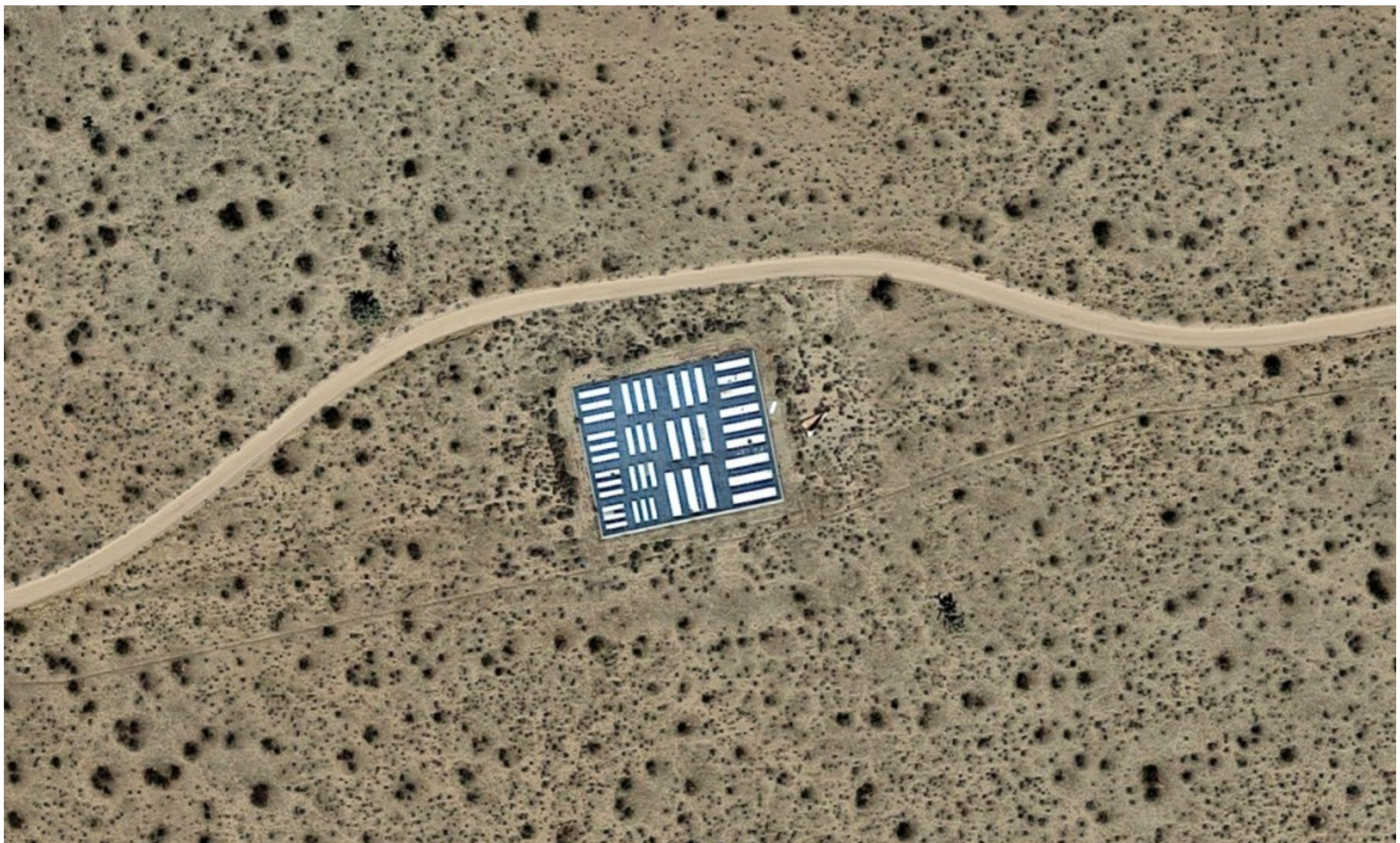


. . .



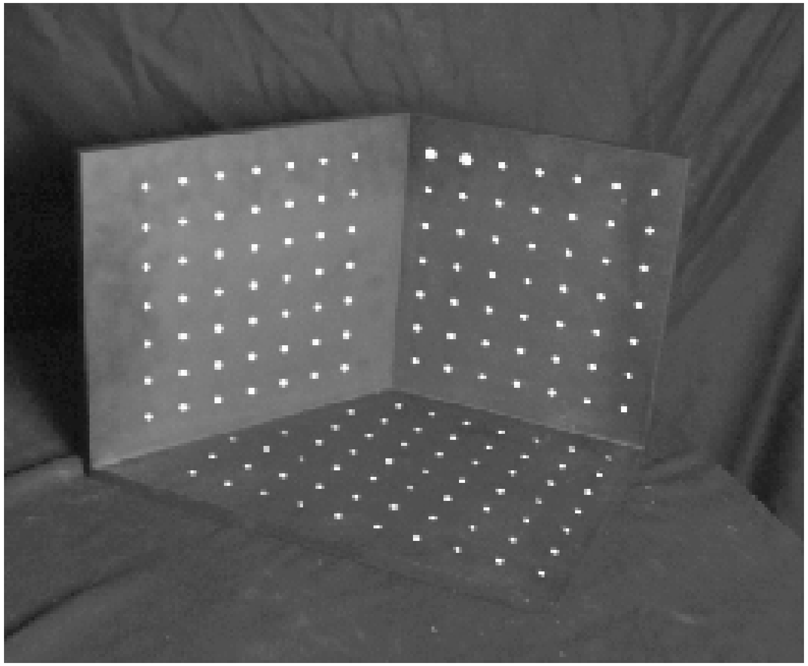
Camera Calibration Targets

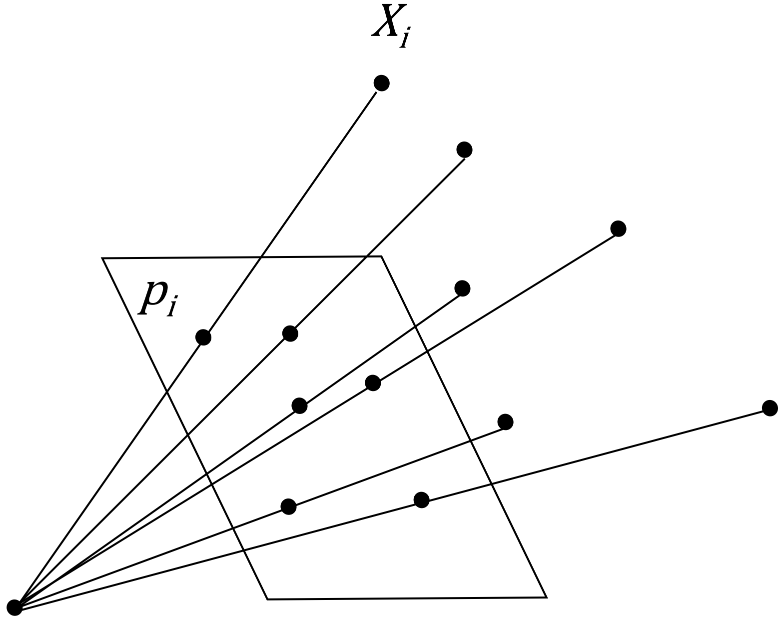
A single, huge plane. **What's this for?**



Camera calibration

- Given n points with known 3D coordinates $\boldsymbol{X}_i$ and known image projections $\mathbf{p}_i$, estimate the camera parameters





Slide credit: S. Lazebnik

Camera Calibration: Linear Method

$$\boldsymbol{p_i} \equiv \boldsymbol{MX_i}$$

Remember (from geometry): this implies $\mathbf{MX_i}$ $\mathbf{p_i}$ are scaled copies of each other

$$\boldsymbol{p_i} = \lambda \boldsymbol{MX_i}, \lambda \neq 0$$

Remember (from homography fitting): this implies their cross product is **0**

$$\boldsymbol{p_i} \times \boldsymbol{MX_i} = \mathbf{0}$$

Camera Calibration: Linear Method

$$\boldsymbol{p_i} \times \boldsymbol{M X_i} = \boldsymbol{0}$$

$$\begin{bmatrix} u_i \\ v_i \\ 1 \end{bmatrix} \times \begin{bmatrix} \boldsymbol{M_1 X_i} \\ \boldsymbol{M_2 X_i} \\ \boldsymbol{M_3 X_i} \end{bmatrix} = \begin{bmatrix} 0 \\ 0 \\ 0 \end{bmatrix}$$

…Some tedious math occurs…

(see Homography deriviation)

$$\begin{bmatrix} \boldsymbol{0}^T & -\boldsymbol{X_i^T} & \boldsymbol{v_i X_i^T} \\ \boldsymbol{X_i^T} & \boldsymbol{0}^T & -\boldsymbol{u_i X_i^T} \\ -\boldsymbol{v_i X_i^T} & \boldsymbol{u_i X_i^T} & \boldsymbol{0}^T \end{bmatrix} \begin{bmatrix} \boldsymbol{M_1^T} \\ \boldsymbol{M_2^T} \\ \boldsymbol{M_3^T} \end{bmatrix} = \begin{bmatrix} 0 \\ 0 \\ 0 \end{bmatrix}$$

Camera Calibration: Linear Method

$$\begin{bmatrix} \mathbf{0}^T & -\boldsymbol{X}_i^T & v_i\boldsymbol{X}_i^T \\ \boldsymbol{X}_i^T & \mathbf{0}^T & -u_i\boldsymbol{X}_i^T \\ -v_i\boldsymbol{X}_i^T & u_i\boldsymbol{X}_i^T & \mathbf{0}^T \end{bmatrix} \begin{bmatrix} \boldsymbol{M}_1^T \\ \boldsymbol{M}_2^T \\ \boldsymbol{M}_3^T \end{bmatrix} = \begin{bmatrix} 0 \\ 0 \\ 0 \end{bmatrix}$$

How many linearly independent equations?

2

How many equations per [u,v] + [X,Y,Z] pair?

2

If M is 3x4, how many degrees of freedom?

11

Camera Calibration: Linear Method

$$\begin{bmatrix} \mathbf{0}^T & \boldsymbol{X}_i^T & -v_1 \boldsymbol{X}_i^T \\ \boldsymbol{X}_1^T & \mathbf{0}^T & -u_1 \boldsymbol{X}_i^T \\ \cdots & \cdots & \cdots \\ \mathbf{0}^T & \boldsymbol{X}_n^T & -v_1 \boldsymbol{X}_n^T \\ \boldsymbol{X}_n^T & \mathbf{0}^T & -u_n \boldsymbol{X}_n^T \end{bmatrix} \begin{bmatrix} \boldsymbol{M}_1^T \\ \boldsymbol{M}_2^T \\ \boldsymbol{M}_3^T \end{bmatrix} = \begin{bmatrix} 0 \\ 0 \\ 0 \end{bmatrix}$$

How do we solve problems of the form

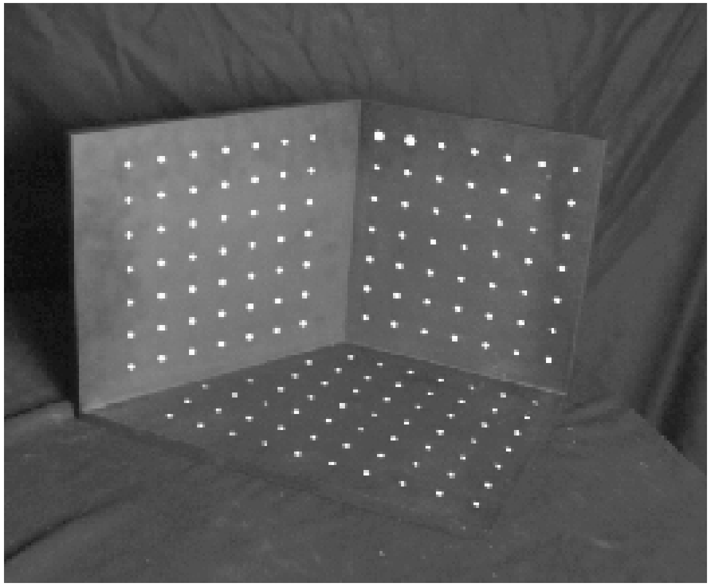
$\arg\min \|\boldsymbol{A}\boldsymbol{n}\|_2^2 , \|\boldsymbol{n}\|_2^2 = 1$ **?**

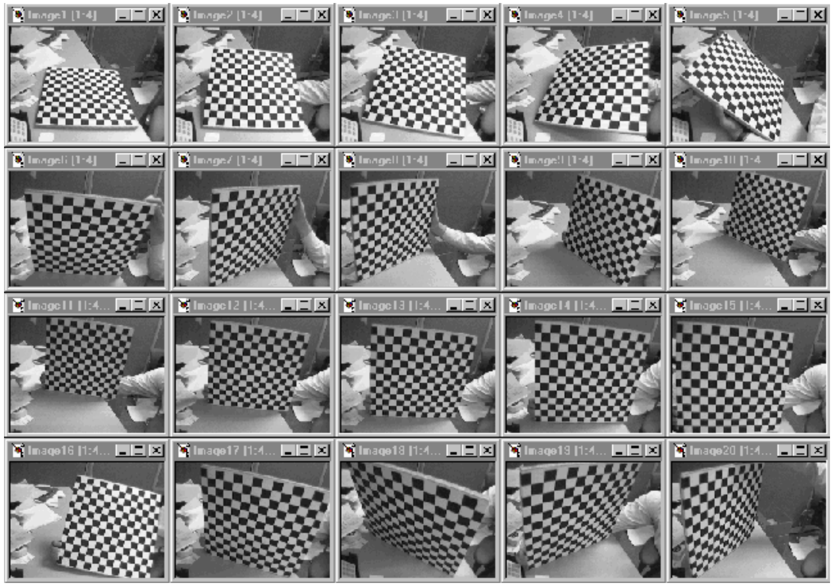
Eigenvector of $\mathbf{A}^\mathbf{T}\mathbf{A}$ with smallest eigenvalue

Derivation from L. Lazebnik; note we negate one of the equations from the cross product

In Practice

Degenerate configurations (e.g., all points on one plane) an issue. Usually need multiplane targets.





In Practice

I pulled a fast one.

We want: $$\boldsymbol{p} \equiv \boldsymbol{K}_{3x3}[\boldsymbol{R}_{3x3}, \boldsymbol{t}_{3x1}] \quad \boldsymbol{X}_{4x1}$$

We get: $$\boldsymbol{p} \equiv \boldsymbol{M}_{3x4}\boldsymbol{X}_{4x1}$$

What's the difference between K[R,t] and M?

Solution: QR-decomposition on left-most 3x3 matrix
→ finite options of a upper triangular matrix * rotation

In Practice

If $\mathbf{p}_i = \mathbf{M}\mathbf{x}_i$ is overconstrained, the objective function isn't actually the one you care about.

Instead:

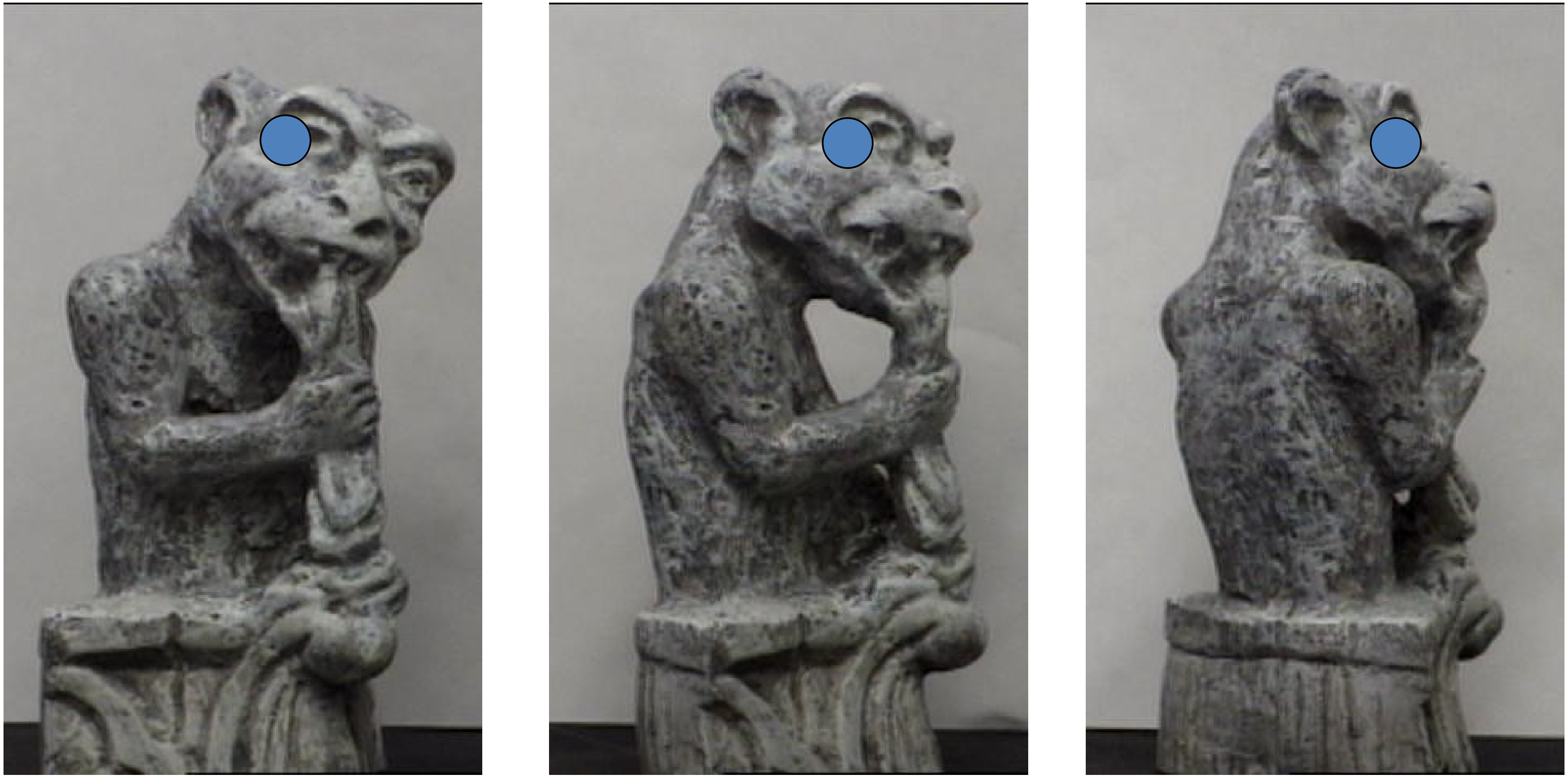
1) initialize parameters with linear model
2) Apply off-the-shelf non-linear optimizer to:

$$\sum \|\mathrm{proj}(\boldsymbol{M}\boldsymbol{X}_{\boldsymbol{i}}) - [u_i, v_i]^T\|_2^2$$

Advantage: can also add radial distortion, not optimize over known variables, add constraints

What Does This Get You?

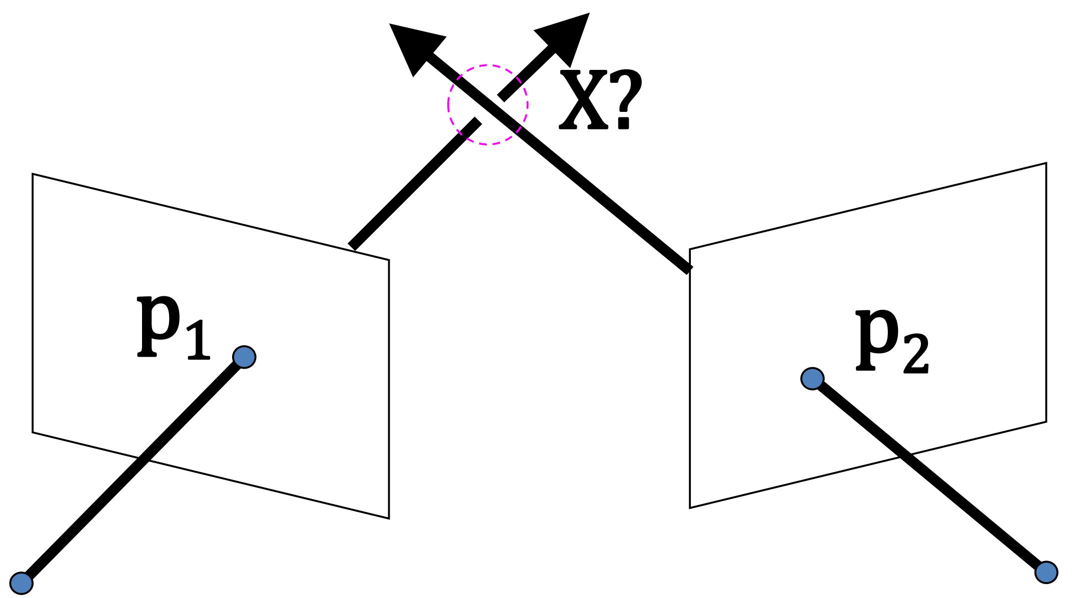
Given projection $\mathbf{p_i}$ of unknown 3D point $\mathbf{X}$ in two or more images (with known cameras $\mathbf{M_i}$), find $\mathbf{X}$



Triangulation

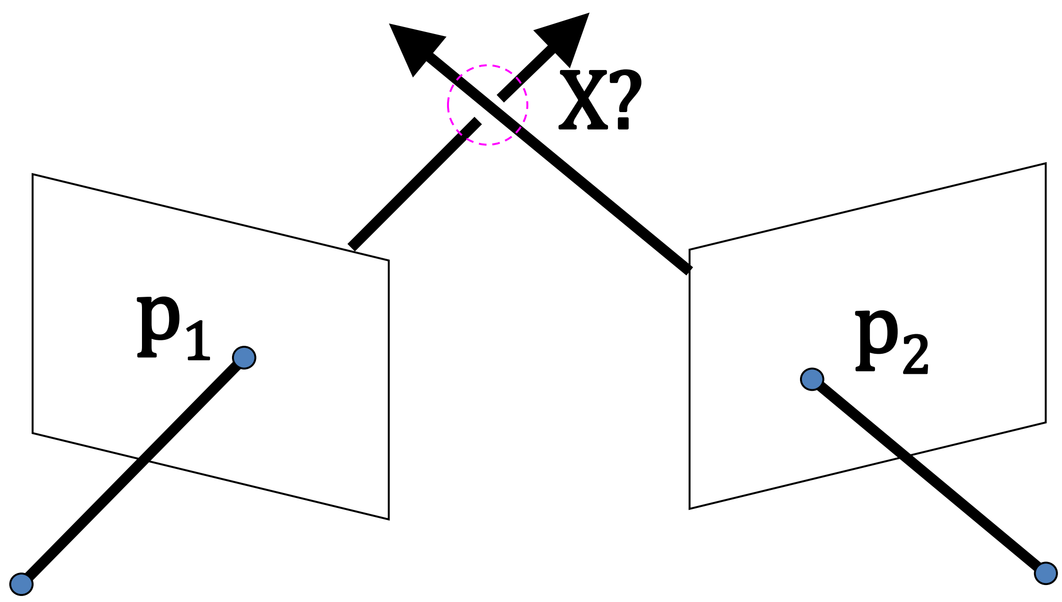
Given projection $\mathbf{p_i}$ of unknown 3D point $\mathbf{X}$ in two or more images (with known cameras $\mathbf{M}_i$), find $\mathbf{X}$

Why is the calibration here important?



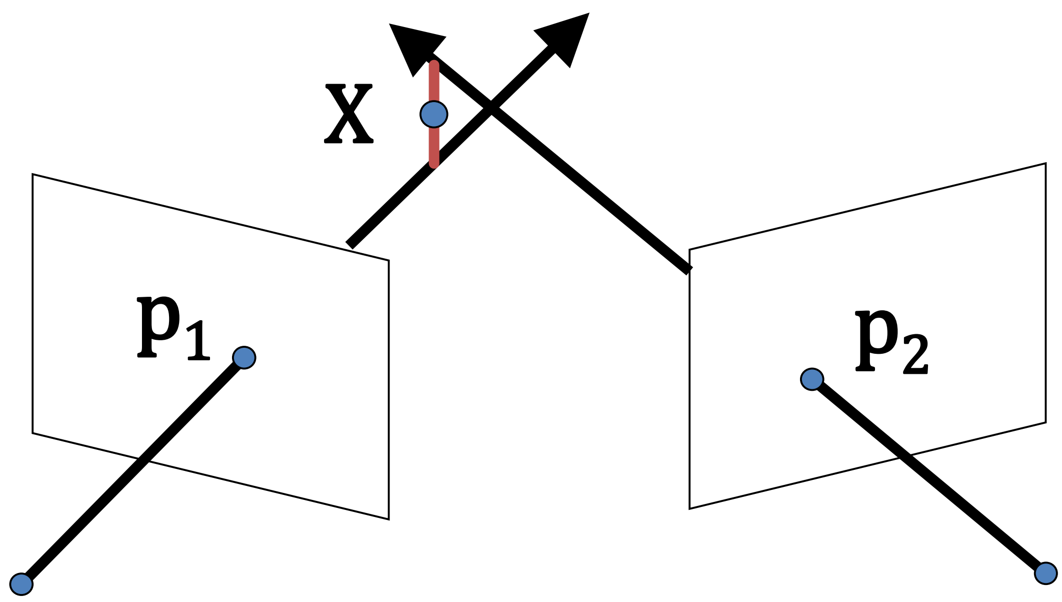
Triangulation

Rays in principle should intersect, but in practice usually don't exactly due to noise, numerical errors.



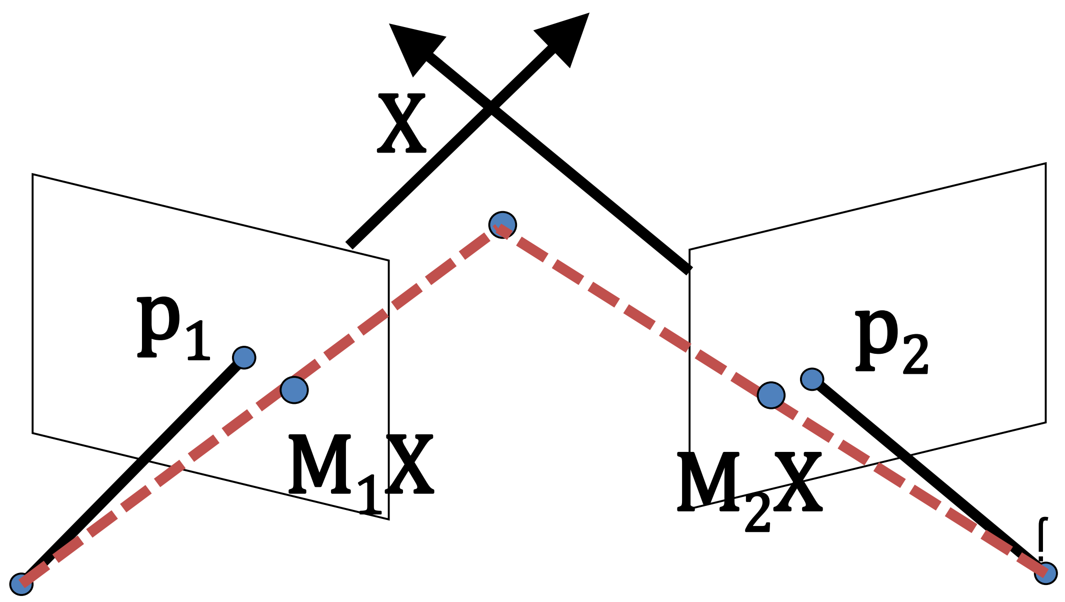
Triangulation – Geometry

Find shortest segment between viewing rays, set **X** to be the midpoint of the segment.



Triangulation – Non-linear Optim.

Find X minimizing $d(\boldsymbol{p}_1, \boldsymbol{M}_1\boldsymbol{X})^2 + d(\boldsymbol{p}_2, \boldsymbol{M}_2\boldsymbol{X})^2$



Triangulation – Linear Optimization

$$\boldsymbol{p_1} \equiv \boldsymbol{M_1 X} \quad \rightarrow \quad \boldsymbol{p_1} \times \boldsymbol{M_1 X} = \boldsymbol{0} \quad \rightarrow \quad [\boldsymbol{p_{1x}}]\boldsymbol{M_1 X} = \boldsymbol{0}$$

$$\boldsymbol{p_2} \equiv \boldsymbol{M_2 X} \qquad\quad \boldsymbol{p_2} \times \boldsymbol{M_2 X} = \boldsymbol{0} \qquad\quad [\boldsymbol{p_{2x}}]\boldsymbol{M_2 X} = \boldsymbol{0}$$

Cross Prod.
as matrix

$$\boldsymbol{a} \times \boldsymbol{b} = \begin{bmatrix} 0 & -a_3 & a_2 \\ a_3 & 0 & -a_1 \\ -a_2 & a_1 & 0 \end{bmatrix} \begin{bmatrix} b_1 \\ b_2 \\ b_3 \end{bmatrix} = [\boldsymbol{a}_x]\boldsymbol{b}$$

$$[\boldsymbol{p_{1x}}]\boldsymbol{M_1 X} = \boldsymbol{0} \quad \rightarrow \quad ([\boldsymbol{p_{1x}}]\boldsymbol{M_1})\boldsymbol{X} = \boldsymbol{0}$$

$$[\boldsymbol{p_{2x}}]\boldsymbol{M_2 X} = \boldsymbol{0} \qquad\quad ([\boldsymbol{p_{2x}}]\boldsymbol{M_2})\boldsymbol{X} = \boldsymbol{0}$$

→ Two eqns per camera for 3 unkn. in X