

---

# **Advances in Computer Vision and Pattern Recognition**

## **Founding editor**

Sameer Singh, Rail Vision, Castle Donington, UK

## **Series editor**

Sing Bing Kang, Microsoft Research, Redmond, WA, USA

## **Advisory Board**

Horst Bischof, Graz University of Technology, Austria

Richard Bowden, University of Surrey, Guildford, UK

Sven Dickinson, University of Toronto, ON, Canada

Jiaya Jia, The Chinese University of Hong Kong, Hong Kong

Kyoung Mu Lee, Seoul National University, South Korea

Yoichi Sato, The University of Tokyo, Japan

Bernt Schiele, Max Planck Institute for Computer Science, Saarbrücken, Germany

Stan Sclaroff, Boston University, MA, USA

More information about this series at <http://www.springer.com/series/4205>

---

Kenichi Kanatani · Yasuyuki Sugaya  
Yasushi Kanazawa

# Guide to 3D Vision Computation

Geometric Analysis  
and Implementation

Kenichi Kanatani  
Okayama University  
Okayama  
Japan

Yasushi Kanazawa  
Toyohashi University of Technology  
Toyohashi, Aichi  
Japan

Yasuyuki Sugaya  
Toyohashi University of Technology  
Toyohashi, Aichi  
Japan

ISSN 2191-6586 ISSN 2191-6594 (electronic)  
Advances in Computer Vision and Pattern Recognition  
ISBN 978-3-319-48492-1 ISBN 978-3-319-48493-8 (eBook)  
DOI 10.1007/978-3-319-48493-8

Library of Congress Control Number: 2016955063

© Springer International Publishing AG 2016

This work is subject to copyright. All rights are reserved by the Publisher, whether the whole or part of the material is concerned, specifically the rights of translation, reprinting, reuse of illustrations, recitation, broadcasting, reproduction on microfilms or in any other physical way, and transmission or information storage and retrieval, electronic adaptation, computer software, or by similar or dissimilar methodology now known or hereafter developed.

The use of general descriptive names, registered names, trademarks, service marks, etc. in this publication does not imply, even in the absence of a specific statement, that such names are exempt from the relevant protective laws and regulations and therefore free for general use.

The publisher, the authors and the editors are safe to assume that the advice and information in this book are believed to be true and accurate at the date of publication. Neither the publisher nor the authors or the editors give a warranty, express or implied, with respect to the material contained herein or for any errors or omissions that may have been made.

Printed on acid-free paper

This Springer imprint is published by Springer Nature  
The registered company is Springer International Publishing AG  
The registered company address is: Gewerbestrasse 11, 6330 Cham, Switzerland

---

## Preface

Today, computer vision techniques are used for various purposes, and there exist many textbooks and references that describe principles of programming and system organization. At the same time, ever new research is going on all over the world, and the achievements are offered in the form of open source code on the Web. It appears, therefore, that sufficient environments already exist for students and researchers for embarking on computer vision research.

However, although executing a public source code may be easy, improving or modifying it for other applications is rather difficult, because the intent of the code author is difficult to discern simply by reading the code. On the other hand, many computer vision textbooks focus on theoretical principles coupled with application demos. As a result, one is often at a loss as to how to write a program oneself. Actual implementation of algorithms requires many small details that must be carefully taken into consideration, which a ready-to-use code does not provide. This book intends to fill that gap, describing in detail the computational procedures for programming 3D geometric tasks. The algorithms presented in this book are based on today's state of the art, yet arranged in a form simple and easy enough to understand. The authors also believe that they are the most appropriate form for practical use in real situations.

In this book, the mathematical background of the presented algorithms is mostly omitted for the ease of reading, but for theoretically minded readers detailed derivations and justifications are given in the form of Problems in each chapter; their Solutions are given at the end of the volume. Also, historical notes and related references are discussed in the Supplemental Note at the end of each chapter. In this sense, this book can also serve as a theoretical reference of computer vision research. To help readers implement the algorithms in this book, sample codes of typical procedures are placed on the publisher's Web page.<sup>1</sup>

This book is based on the teaching materials that the authors used for student projects at Okayama University and Toyohashi University of Technology, Japan. Every year, new students with little background knowledge come to our labs to do computer vision work. According to our experience, the most effective way for them to learn is to let them implement basic algorithms such as those given here.

---

<sup>1</sup><http://www.springer.com/book/9783319484921>

Through this process, they learn the basic know-how of programming and at the same time gradually understand the theoretical background as their interest deepens. Thus we are hoping that this book can serve not only as a reference of the latest computer vision techniques but also as useful material for introductory courses of computer vision.

The authors thank Takayuki Okatani of Tohoku University, Japan, Mike Brooks and Wojciech Chojnacki of the University of Adelaide, Australia, Peter Meer of Rutgers University, the United States, Wolfgang Förstner, of the University of Bonn, Germany, Michael Felsberg of Linköping University, Sweden, Rudolf Mester of the University of Frankfurt, Germany, Prasanna Rangarajan of Southern Methodist University, the United States, Ali Al-Sharadqah of California State University, Northridge, the United States, Alexander Kukush of the University of Kiev, Ukraine, and Chikara Matsunaga of For-A, Co. Ltd., Japan. Special thanks go to (the late) Prof. Nikolai Chernov of the University of Alabama at Birmingham, the United States, without whose inspiration and assistance this work would not have been possible. Parts of this work are used with permission from the authors' work *Ellipse Fitting for Computer Vision: Implementation and Applications*, ©Morgan & Claypool,<sup>2</sup> 2016.

Okayama, Japan  
Toyohashi, Japan  
Toyohashi, Japan  
October 2016

Kenichi Kanatani  
Yasuyuki Sugaya  
Yasushi Kanazawa

---

<sup>2</sup><http://www.morganclaypool.com>.

---

# Contents

<b>1</b>	<b>Introduction</b>	<b>1</b>
1.1	Background	1
1.2	Organization	2
1.3	Features	7
 <b>Part I Fundamental Algorithms for Computer Vision</b>		
<b>2</b>	<b>Ellipse Fitting</b>	<b>11</b>
2.1	Representation of Ellipses	11
2.2	Least-Squares Approach	12
2.3	Noise and Covariance Matrices	13
2.4	Algebraic Methods	15
2.4.1	Iterative Reweight	15
2.4.2	Renormalization and the Taubin Method	16
2.4.3	Hyper-Renormalization and HyperLS	17
2.4.4	Summary of Algebraic Methods	18
2.5	Geometric Methods	19
2.5.1	Geometric Distance and Sampson Error	19
2.5.2	FNS	19
2.5.3	Geometric Distance Minimization	20
2.5.4	Hyper-Accurate Correction	22
2.6	Ellipse-Specific Methods	23
2.6.1	Ellipse Condition	23
2.6.2	Method of Fitzgibbon et al.	23
2.6.3	Method of Random Sampling	24
2.7	Outlier Removal	25
2.8	Examples	26
2.9	Supplemental Note	27
	Problems	29
	References	31
<b>3</b>	<b>Fundamental Matrix Computation</b>	<b>33</b>
3.1	Fundamental Matrices	33
3.2	Covariance Matrices and Algebraic Methods	34

3.3	Geometric Distance and Sampson Error . . . . .	37
3.4	Rank Constraint . . . . .	38
3.5	A Posteriori Correction . . . . .	39
3.6	Hidden Variables Approach . . . . .	41
3.7	Extended FNS . . . . .	45
3.8	Geometric Distance Minimization . . . . .	46
3.9	Outlier Removal . . . . .	48
3.10	Examples . . . . .	49
3.11	Supplemental Note . . . . .	50
	Problems . . . . .	53
	References . . . . .	56
<b>4</b>	<b>Triangulation . . . . .</b>	<b>59</b>
4.1	Perspective Projection . . . . .	59
4.2	Camera Matrix and Triangulation . . . . .	60
4.3	Triangulation from Noisy Correspondence . . . . .	62
4.4	Optimal Correction of Correspondences . . . . .	63
4.5	Examples . . . . .	65
4.6	Supplemental Note . . . . .	66
	Problems . . . . .	66
	References . . . . .	68
<b>5</b>	<b>3D Reconstruction from Two Views . . . . .</b>	<b>69</b>
5.1	Camera Modeling and Self-calibration . . . . .	69
5.2	Expression of the Fundamental Matrix . . . . .	72
5.3	Focal Length Computation . . . . .	73
5.4	Motion Parameter Computation . . . . .	75
5.5	3D Shape Computation . . . . .	76
5.6	Examples . . . . .	77
5.7	Supplemental Note . . . . .	78
	Problems . . . . .	79
	References . . . . .	80
<b>6</b>	<b>Homography Computation . . . . .</b>	<b>81</b>
6.1	Homographies . . . . .	81
6.2	Noise and Covariance Matrices . . . . .	83
6.3	Algebraic Methods . . . . .	85
6.4	Geometric Distance and Sampson Error . . . . .	88
6.5	FNS . . . . .	89
6.6	Geometric Distance Minimization . . . . .	90
6.7	Hyperaccurate Correction . . . . .	92
6.8	Outlier Removal . . . . .	93
6.9	Examples . . . . .	94
6.10	Supplemental Note . . . . .	95
	Problems . . . . .	96
	References . . . . .	97



<b>7</b>	<b>Planar Triangulation</b> . . . . .	99
7.1	Perspective Projection of a Plane . . . . .	99
7.2	Planar Triangulation . . . . .	101
7.3	Procedure of Planar Triangulation. . . . .	101
7.4	Examples . . . . .	103
7.5	Supplemental Note . . . . .	104
	Problems. . . . .	105
	References. . . . .	105
<b>8</b>	<b>3D Reconstruction of a Plane</b> . . . . .	107
8.1	Self-calibration with a Plane . . . . .	107
8.2	Computation of Surface Parameters and Motion Parameters . . . . .	108
8.3	Selection of the Solution. . . . .	109
8.4	Examples . . . . .	112
8.5	Supplemental Note . . . . .	113
	Problems. . . . .	113
	References. . . . .	115
<b>9</b>	<b>Ellipse Analysis and 3D Computation of Circles</b> . . . . .	117
9.1	Intersections of Ellipses . . . . .	117
9.2	Ellipse Centers, Tangents, and Perpendiculars . . . . .	119
9.3	Projection of Circles and 3D Reconstruction . . . . .	120
9.4	Center of Circle . . . . .	123
9.5	Front Image of the Circle . . . . .	124
9.6	Examples . . . . .	125
9.7	Supplemental Note . . . . .	126
	Problems. . . . .	128
	References. . . . .	129

## Part II Multiview 3D Reconstruction Techniques

<b>10</b>	<b>Multiview Triangulation</b> . . . . .	133
10.1	Trilinear Constraint. . . . .	133
10.2	Triangulation from Three Views. . . . .	134
10.2.1	Optimal Correspondence Correction . . . . .	134
10.2.2	Solving Linear Equations. . . . .	136
10.2.3	Efficiency of Computation . . . . .	138
10.2.4	3D Position Computation. . . . .	138
10.3	Triangulation from Multiple Views. . . . .	140
10.4	Examples . . . . .	144
10.5	Supplemental Note . . . . .	144
	Problems. . . . .	146
	References. . . . .	147

<b>11</b>	<b>Bundle Adjustment</b>	149
11.1	Principle of Bundle Adjustment	149
11.2	Bundle Adjustment Algorithm	151
11.3	Derivative Computation	153
11.3.1	Gauss-Newton Approximation	153
11.3.2	Derivatives with Respect to 3D Positions	154
11.3.3	Derivatives with Respect to Focal Lengths	154
11.3.4	Derivatives with Respect to Principal Points	154
11.3.5	Derivatives with Respect to Translations	154
11.3.6	Derivatives with Respect to Rotations	155
11.3.7	Efficient Computation and Memory Use	155
11.4	Efficient Linear Equation Solving	156
11.5	Examples	158
11.6	Supplemental Note	160
	Problems	160
	References	161
<b>12</b>	<b>Self-calibration of Affine Cameras</b>	163
12.1	Affine Cameras	163
12.2	Factorization and Affine Reconstruction	164
12.3	Metric Condition for Affine Cameras	167
12.4	Description in the Camera Coordinate System	168
12.5	Symmetric Affine Camera	169
12.6	Self-calibration of Symmetric Affine Cameras	172
12.7	Self-calibration of Simplified Affine Cameras	175
12.7.1	Paraperspective Projection Model	175
12.7.2	Weak Perspective Projection Model	177
12.7.3	Orthographic Projection Model	178
12.8	Examples	179
12.9	Supplemental Note	181
	Problems	182
	References	182
<b>13</b>	<b>Self-calibration of Perspective Cameras</b>	183
13.1	Homogeneous Coordinates and Projective Reconstruction	183
13.2	Projective Reconstruction by Factorization	185
13.2.1	Principle of Factorization	185
13.2.2	Primary Method	187
13.2.3	Dual Method	190
13.3	Euclidean Upgrading	192
13.3.1	Principle of Euclidean Upgrading	192
13.3.2	Computation of $\Omega$	194
13.3.3	Modification of $K_K$	196
13.3.4	Computation of $H$	198
13.3.5	Procedure for Euclidean Upgrading	198

13.4	3D Reconstruction Computation . . . . .	199
13.5	Examples . . . . .	201
13.6	Supplemental Notes . . . . .	202
	Problems . . . . .	207
	References . . . . .	210
<b>Part III Mathematical Foundation of Geometric Estimation</b>		
<b>14</b>	<b>Accuracy of Geometric Estimation. . . . .</b>	<b>213</b>
14.1	Constraint of the Problem . . . . .	213
14.2	Noise and Covariance Matrices . . . . .	214
14.3	Error Analysis . . . . .	214
14.4	Covariance and Bias . . . . .	216
14.5	Bias Elimination and Hyper-Renormalization . . . . .	218
14.6	Derivations . . . . .	219
14.7	Supplemental Note . . . . .	228
	Problems . . . . .	228
	References . . . . .	229
<b>15</b>	<b>Maximum Likelihood of Geometric Estimation . . . . .</b>	<b>231</b>
15.1	Maximum Likelihood . . . . .	231
15.2	Sampson Error . . . . .	232
15.3	Error Analysis . . . . .	233
15.4	Bias Analysis and Hyper-Accurate Correction . . . . .	235
15.5	Derivations . . . . .	236
15.6	Supplemental Note . . . . .	241
	Problems . . . . .	242
	References . . . . .	242
<b>16</b>	<b>Theoretical Accuracy Limit . . . . .</b>	<b>243</b>
16.1	Kanatani-Cramer-Rao (KCR) Lower Bound . . . . .	243
16.2	Structure of Constraints . . . . .	244
16.3	Derivation of the KCR Lower Bound . . . . .	246
16.4	Expression of the KCR Lower Bound . . . . .	249
16.5	Supplemental Note . . . . .	251
	Problems . . . . .	253
	References . . . . .	254
	<b>Solutions . . . . .</b>	<b>255</b>
	<b>Index . . . . .</b>	<b>319</b>