Single-view Metrology and Cameras

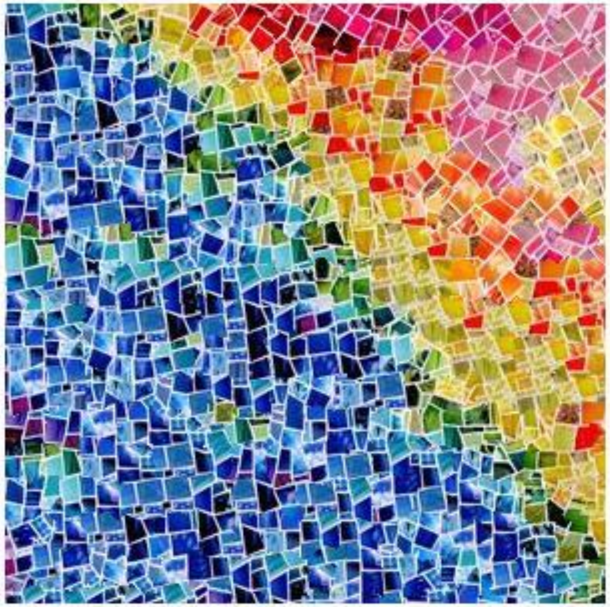
Computational Photography

Derek Hoiem, University of Illinois

Project 2 Results

- Incomplete list of great project pages
  - Haohang Huang: Best presented project; nice iterative results and demonstration, animations for hole filling
  - Xiaotian Le: Runner Up Project: Cool Sliding Window to demonstrate difference in textures (most liked)
  - Xiaoyan Wang: Runner Up Project: Cool QR Code Texture Transfer and Toast results
  - Kartik Agarwal: Overall nice project
  - Ho Yin Au: Nice seam finding results
  - Yuanzhe Rijn Bian: Nice Einstein Toast Result
  - Yundi Fei: Nice seam finding results
  - Zih Siou Hung: Nice Van Gogh texture transfer onto a cat
  - Brendan Wilson (synthesized pattern): Very unique texture patterns that were explored
  - Zexuan Zhong: Best hole filling exploration

Texture synthesis

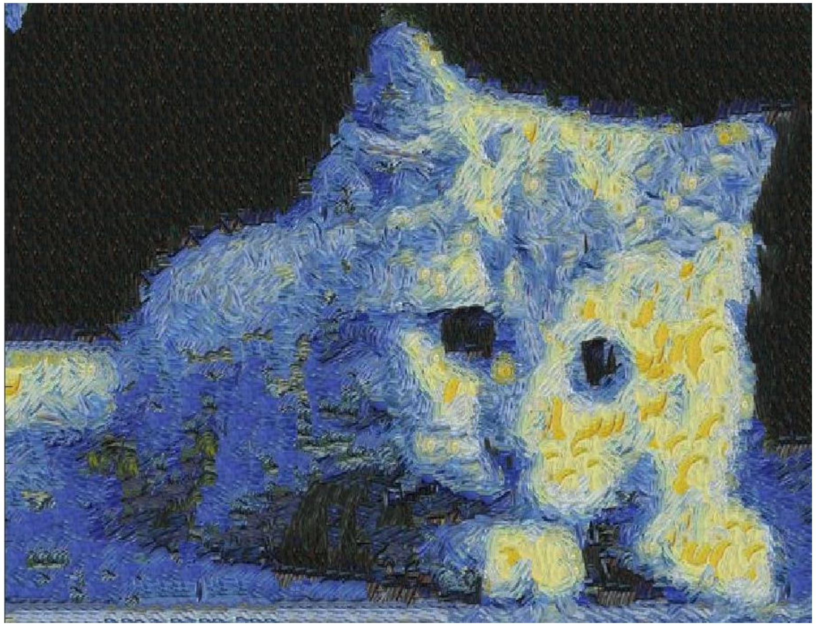


Brendan Wilson

Texture synthesis

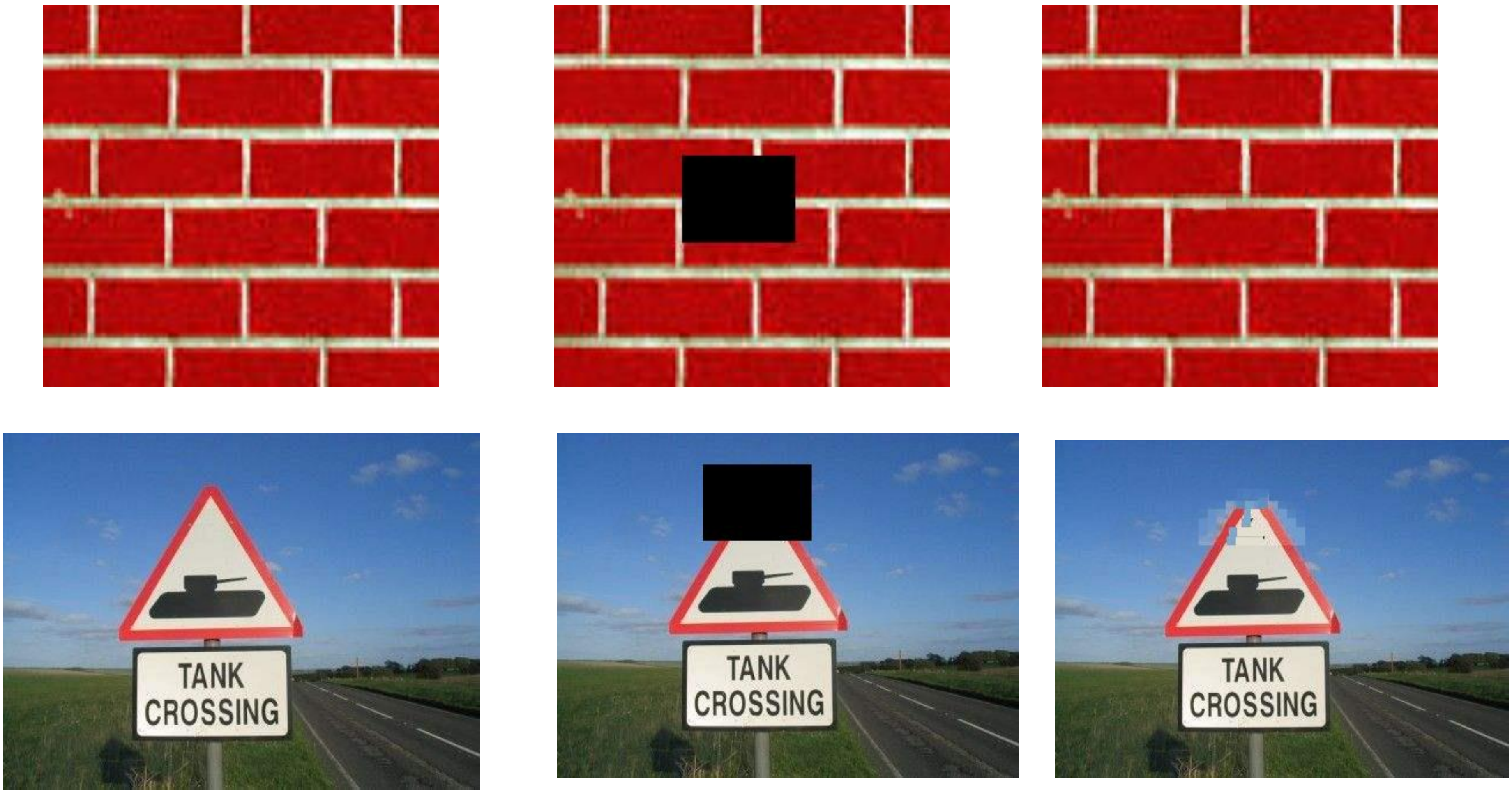
Brendan Wilson

Texture transfer



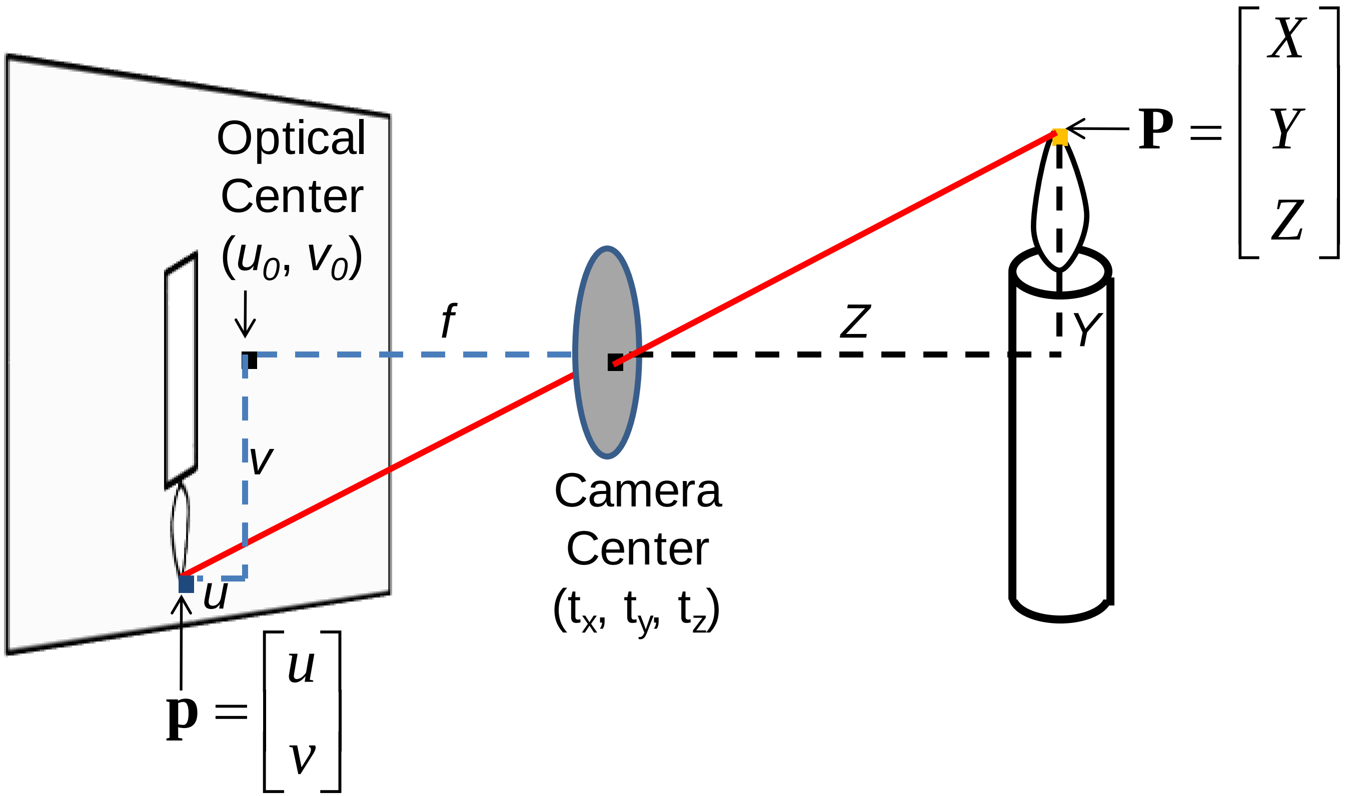
Zih Siou Hung

Hole filling

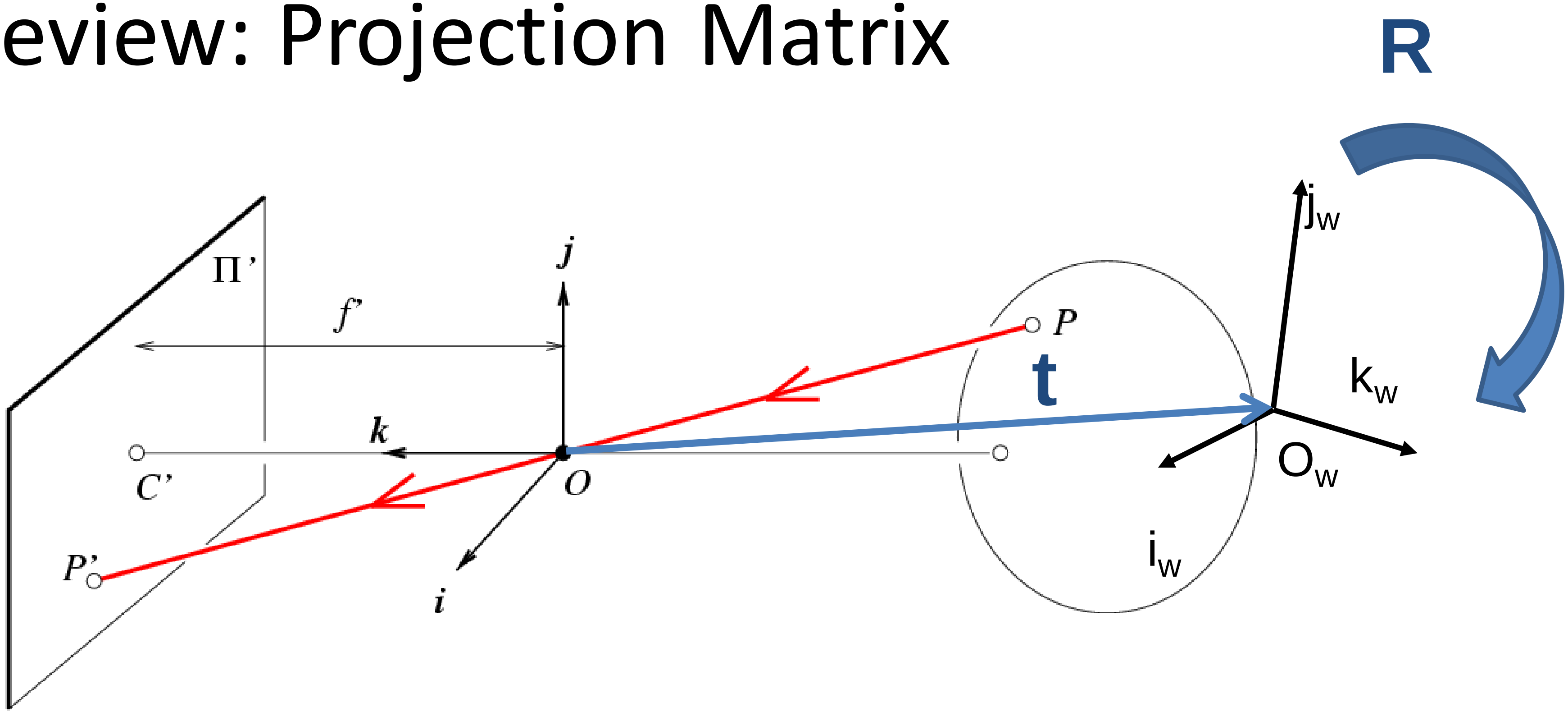


Zexuan Zhong

Review: Pinhole Camera



Review: Projection Matrix



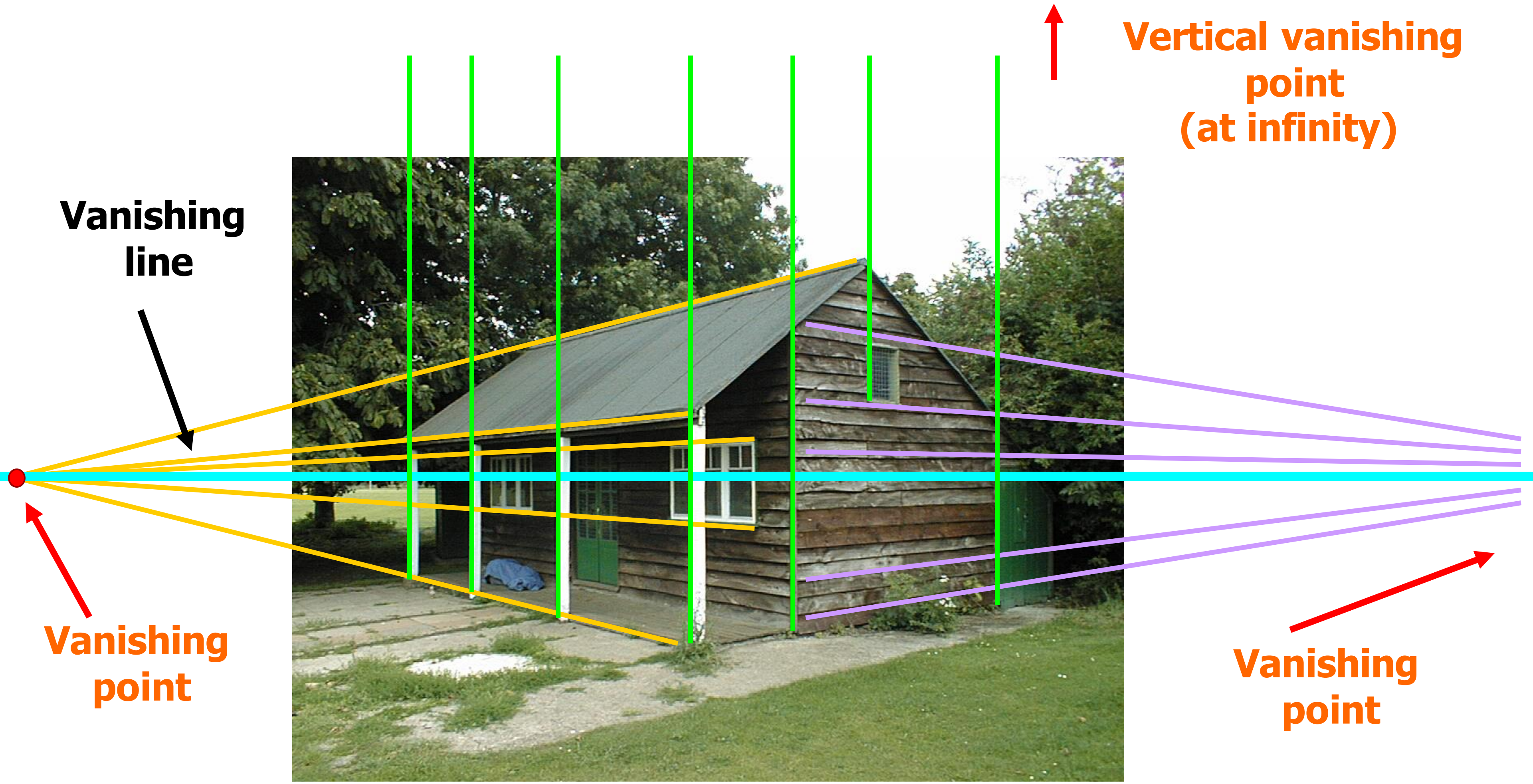
$$\mathbf{x} = \mathbf{K}\begin{bmatrix}\mathbf{R} & \mathbf{t}\end{bmatrix}\mathbf{X} \Rightarrow w\begin{bmatrix} u \\ v \\ 1 \end{bmatrix} = \begin{bmatrix} f & s & u_0 \\ 0 & \alpha f & v_0 \\ 0 & 0 & 1 \end{bmatrix}\begin{bmatrix} r_{11} & r_{12} & r_{13} & t_x \\ r_{21} & r_{22} & r_{23} & t_y \\ r_{31} & r_{32} & r_{33} & t_z \end{bmatrix}\begin{bmatrix} X \\ Y \\ Z \\ 1 \end{bmatrix}$$

Take-home questions from last week

- Suppose the camera axis is in the direction of (x=0, y=0, z=1) in its own coordinate system. What is the camera axis in world coordinates given the extrinsic parameters ***R***, ***t***

- Suppose a camera at height y=*h* *(x=0,z=0)* observes a point at *(u,v)* known to be on the ground (*y*=0). Assume *R* is identity. What is the 3D position of the point in terms of f, u_0, v_0?

Review: Vanishing Points



Slide from Efros, Photo from Criminisi

Perspective and weak perspective

Photo credit: GazetteLive.co.uk

This class

- How can we calibrate the camera?
- How can we measure the size of objects in the world from an image?
- What about other camera properties: focal length, field of view, depth of field, aperture, f-number?
- How to do “focus stacking” to get a sharp picture of a nearby object
- How the “vertigo effect” works

How to calibrate the camera?

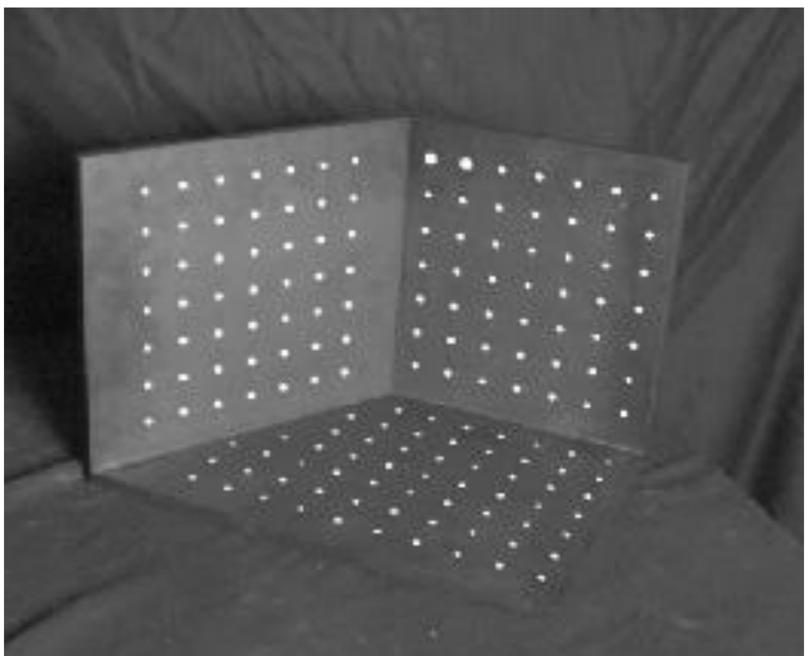
$$\mathbf{x} = \mathbf{K}\begin{bmatrix}\mathbf{R} & \mathbf{t}\end{bmatrix}\mathbf{X}$$

$$\begin{bmatrix} wu \\ wv \\ w \end{bmatrix} = \begin{bmatrix} * & * & * & * \\ * & * & * & * \\ * & * & * & * \end{bmatrix} \begin{bmatrix} X \\ Y \\ Z \\ 1 \end{bmatrix}$$

Calibrating the Camera

Method 1: Use an object (calibration grid) with known geometry

- Correspond image points to 3d points
- Get least squares solution (or non-linear solution)

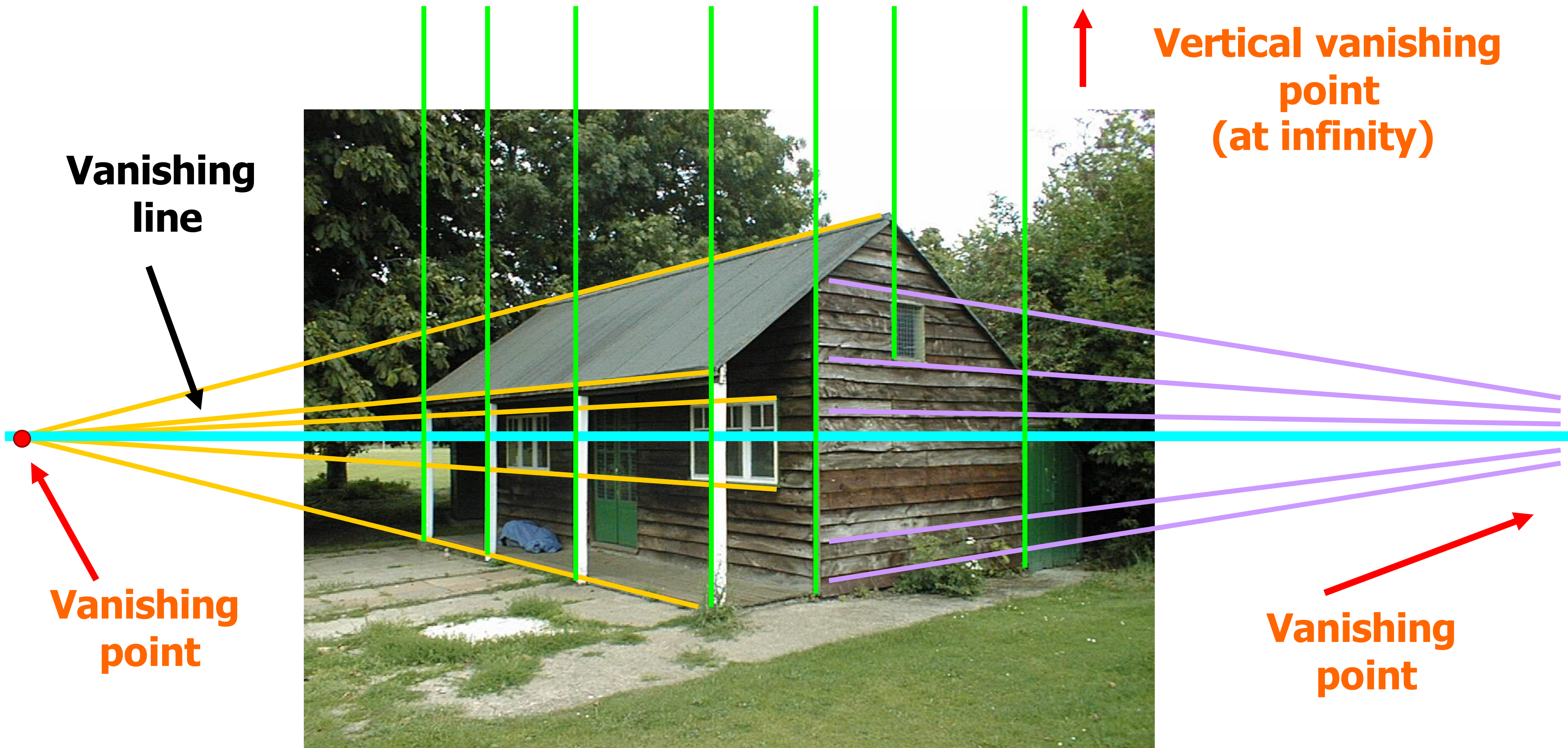


$$\begin{bmatrix} wu \\ wv \\ w \end{bmatrix} = \begin{bmatrix} m_{11} & m_{12} & m_{13} & m_{14} \\ m_{21} & m_{22} & m_{23} & m_{24} \\ m_{31} & m_{32} & m_{33} & m_{34} \end{bmatrix} \begin{bmatrix} X \\ Y \\ Z \\ 1 \end{bmatrix}$$

Calibrating the Camera

Method 2: Use vanishing points

– Find vanishing points corresponding to orthogonal directions



Take-home question (for later)

Suppose you have estimated finite three vanishing points corresponding to orthogonal directions:

1) How to solve for intrinsic matrix? (assume K has three parameters)
   - The transpose of the rotation matrix is its inverse
   - Use the fact that the 3D directions are orthogonal
2) How to recover the rotation matrix that is aligned with the 3D axes defined by these points?
   - In homogeneous coordinates, 3d point at infinity is (X, Y, Z, 0)

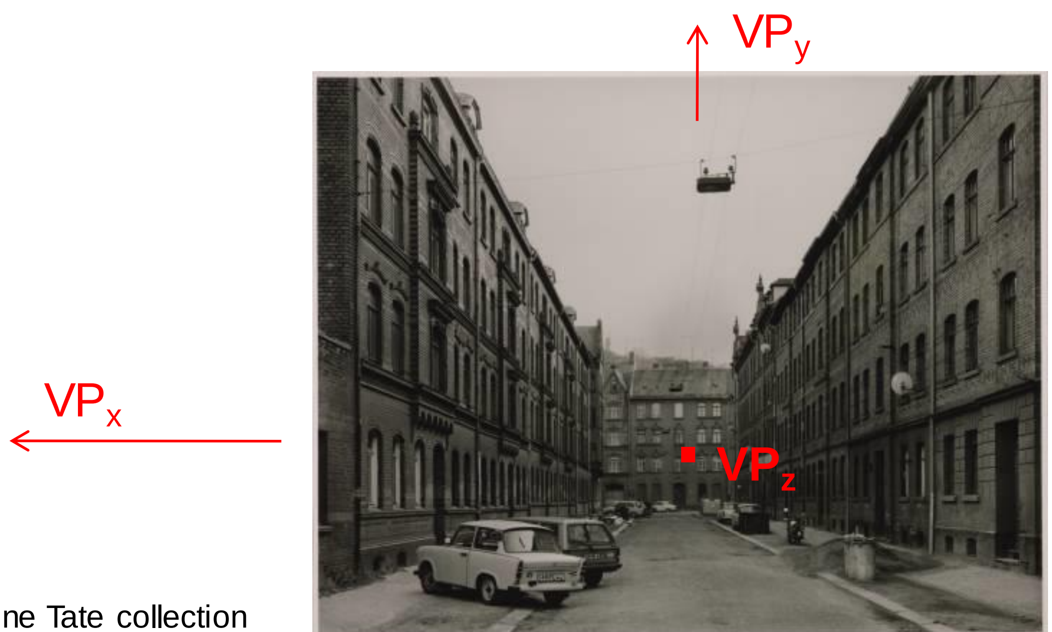
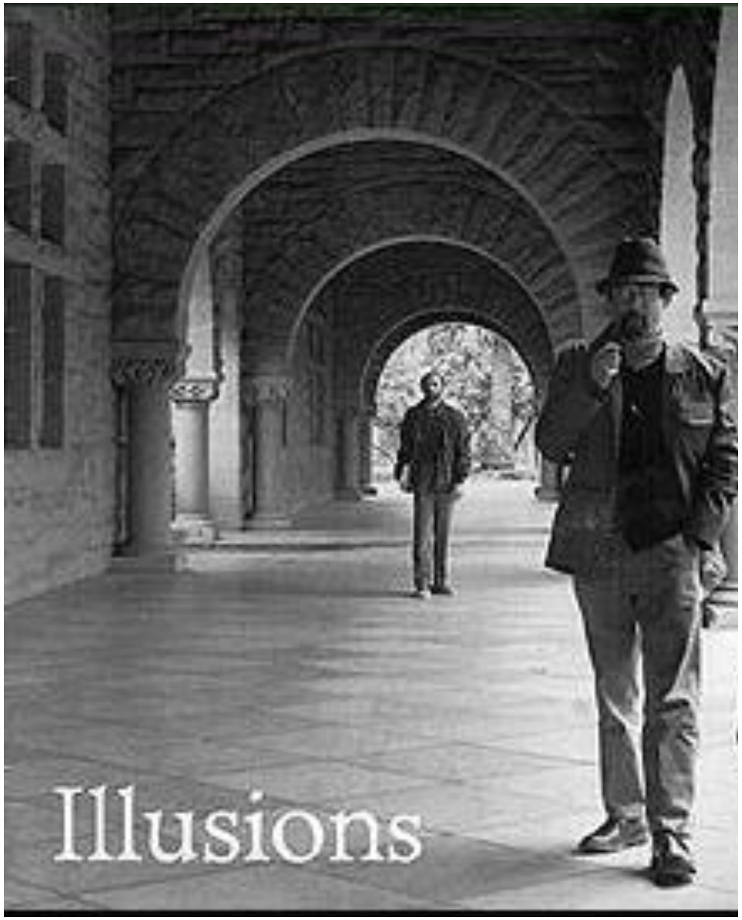


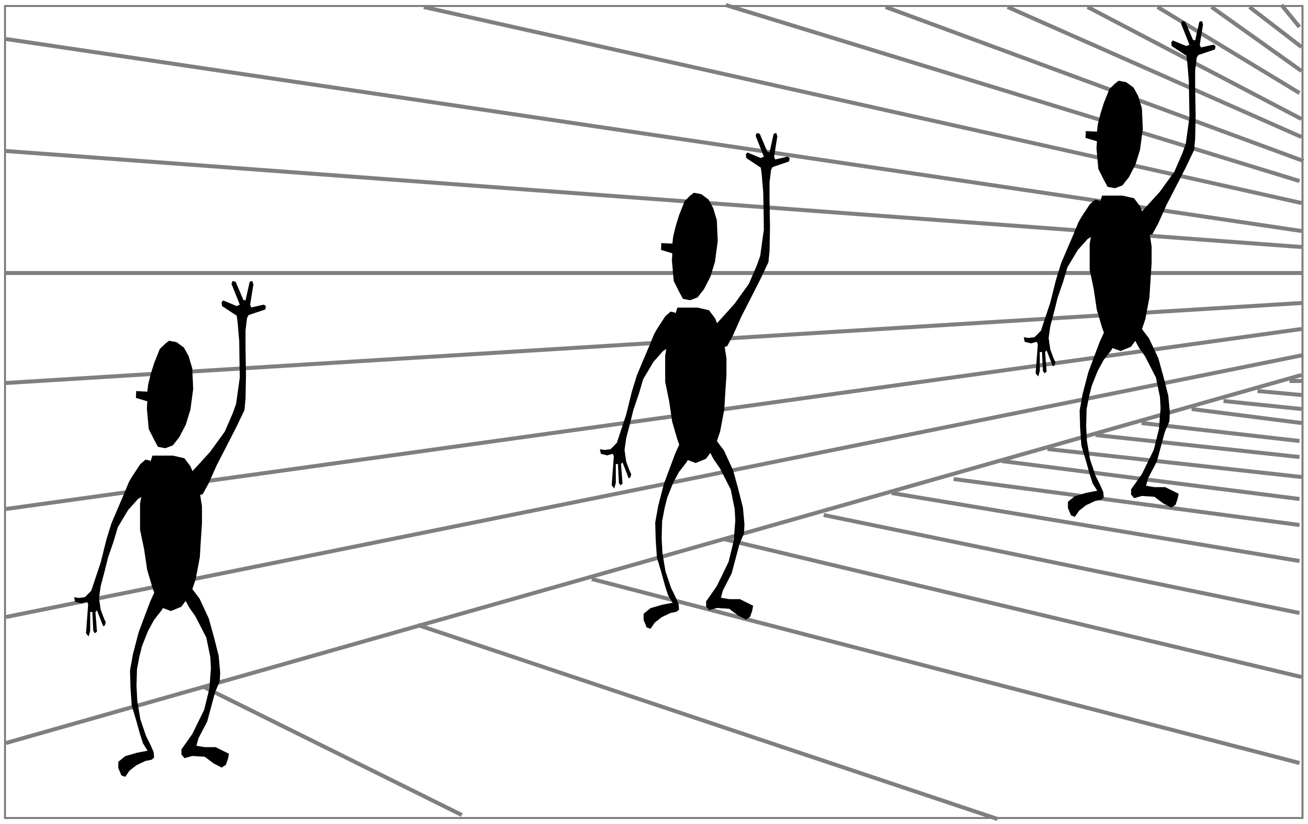
Photo from online Tate collection

How can we measure the size of 3D objects from an image?



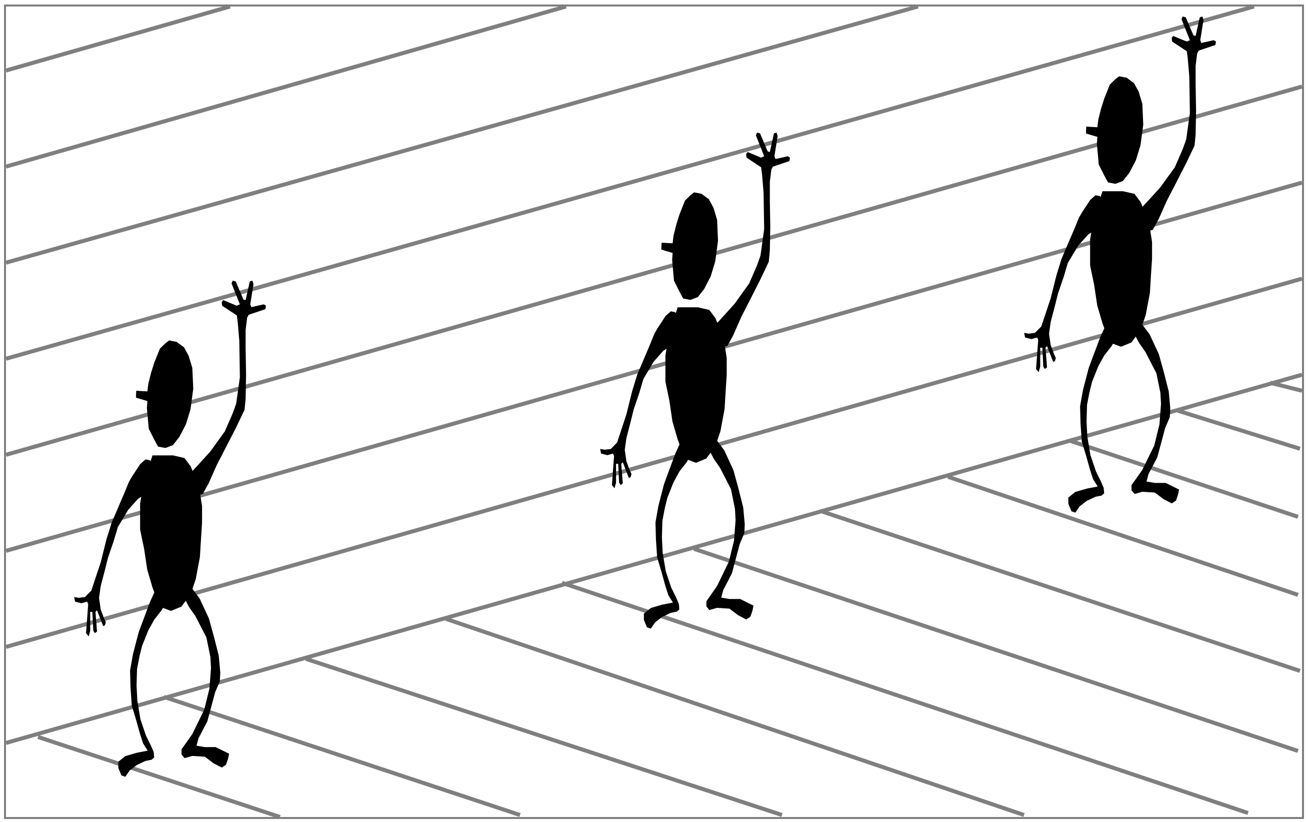
Slide by Steve Seitz

Perspective cues

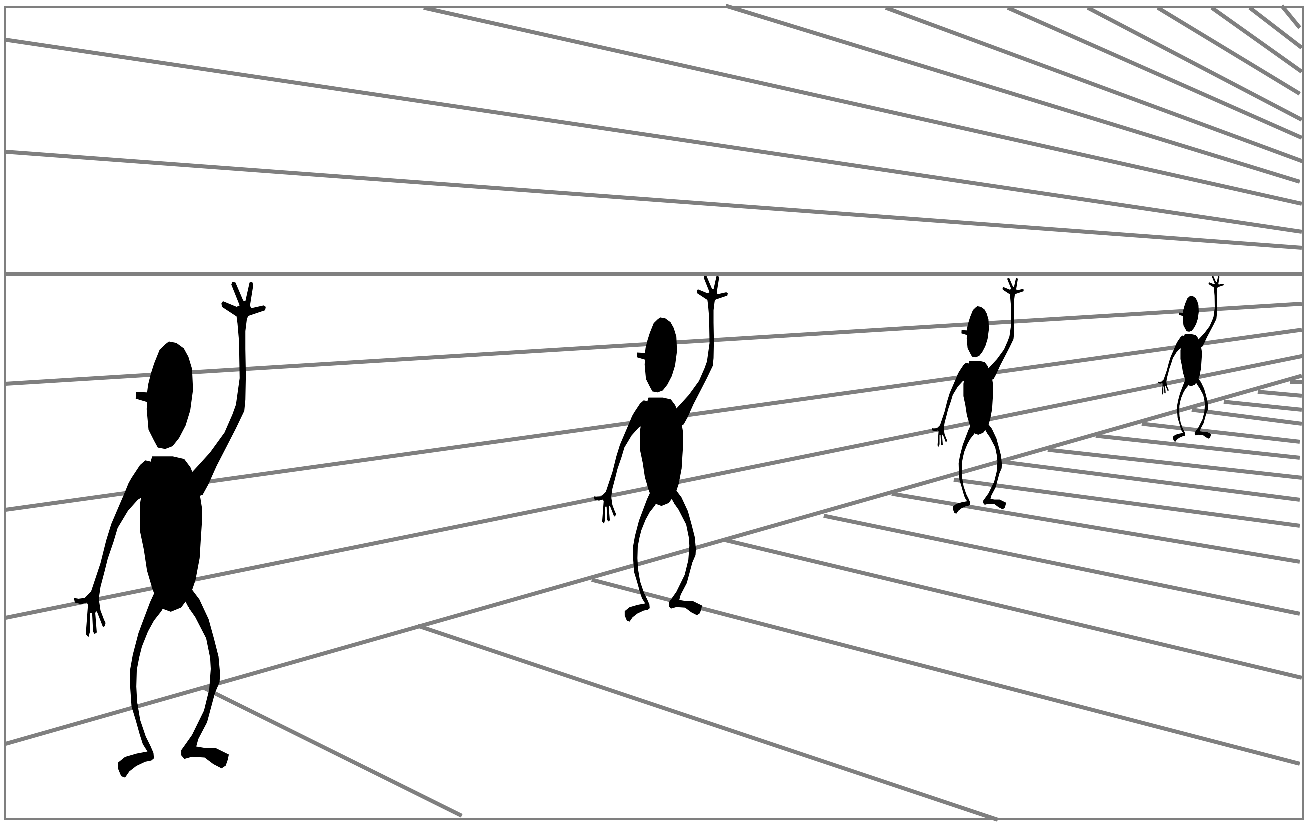


Slide by Steve Seitz

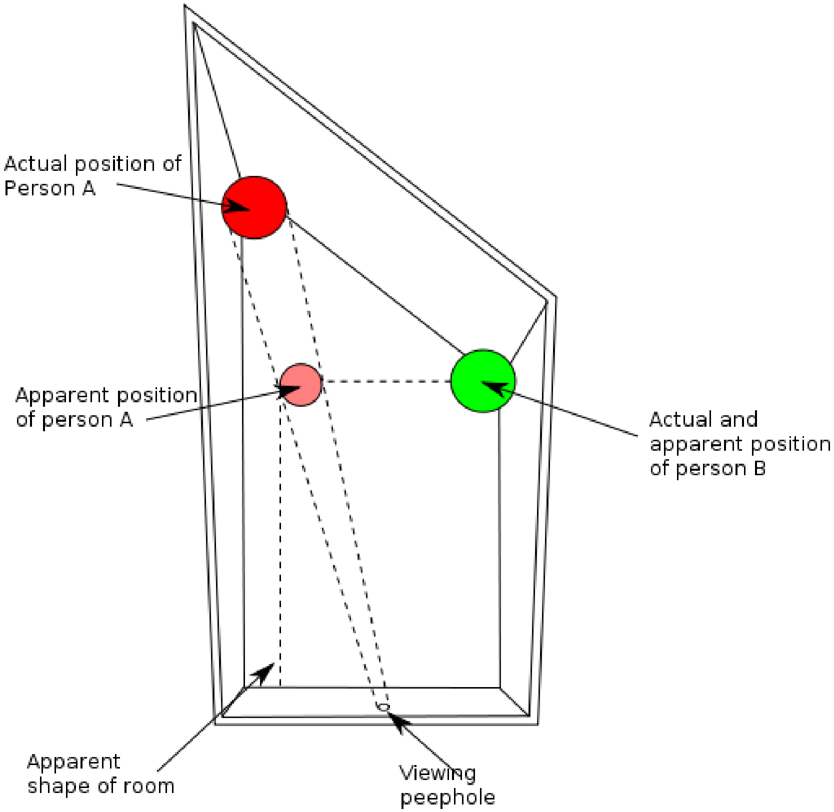
Perspective cues



Perspective cues

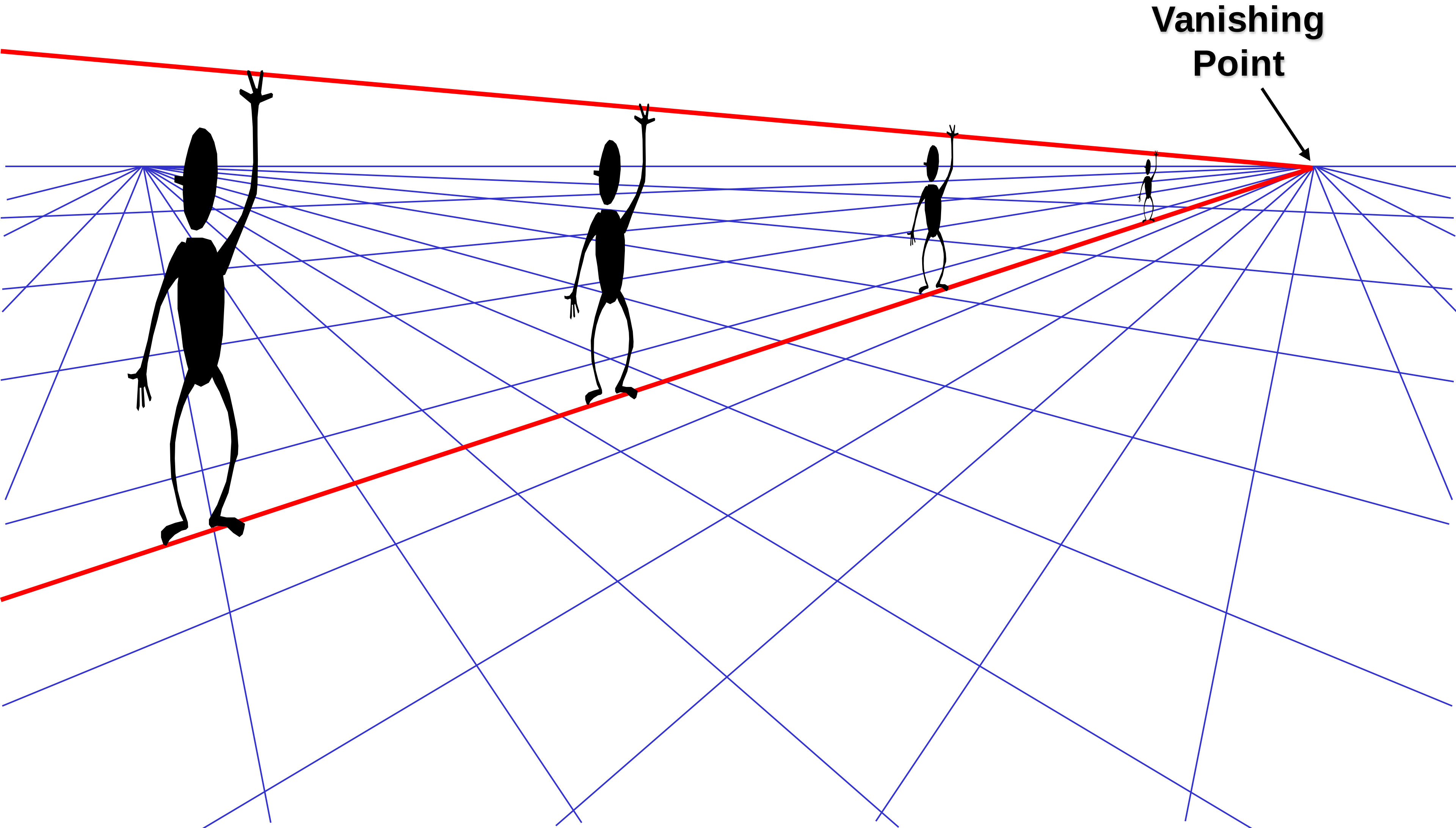


Ames Room


Actual position of
Person A
Apparent position
of person A
Actual and
apparent position
of person B
Apparent
shape of room
Viewing
peephole

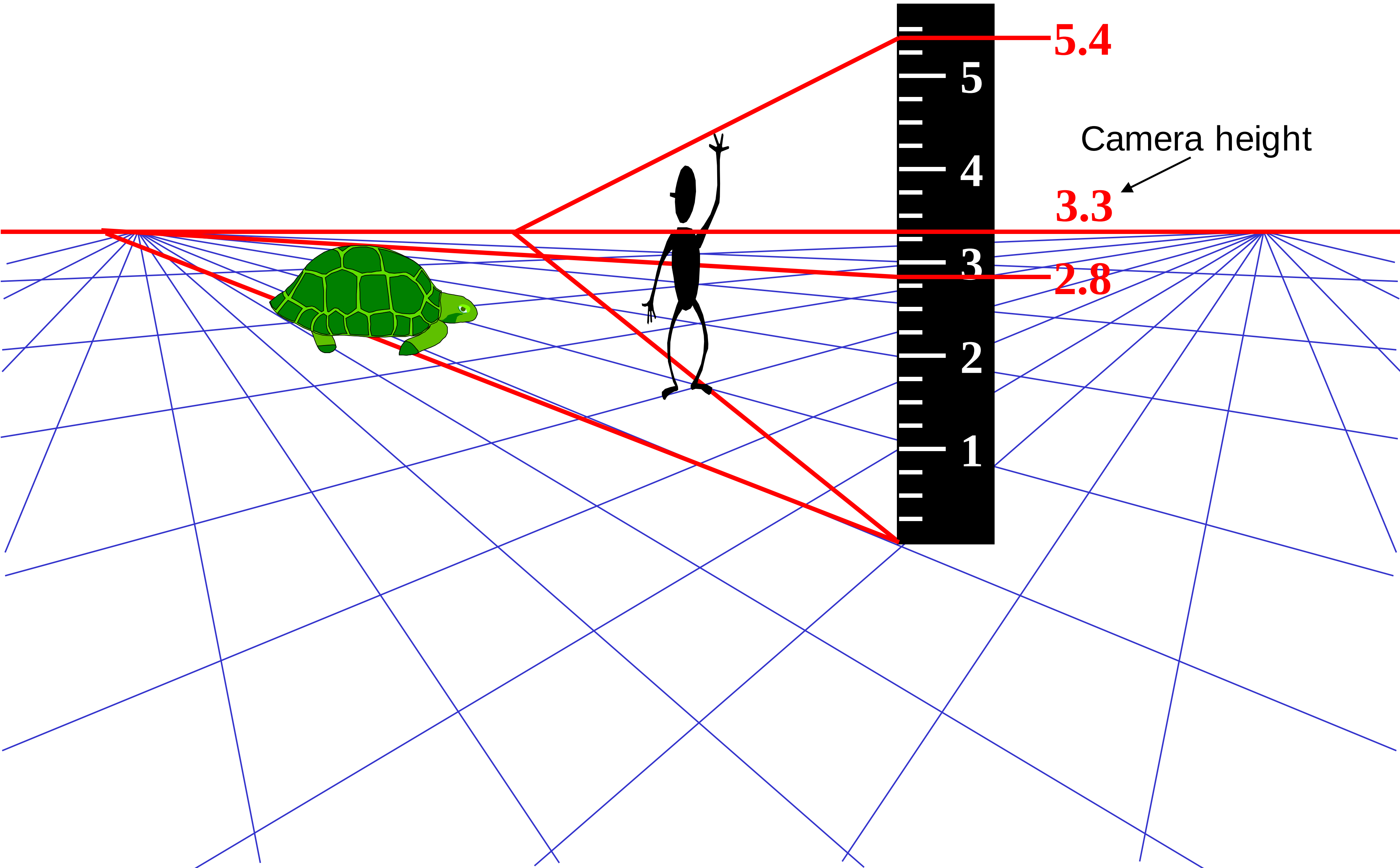
Slide by Steve Seitz

Comparing heights

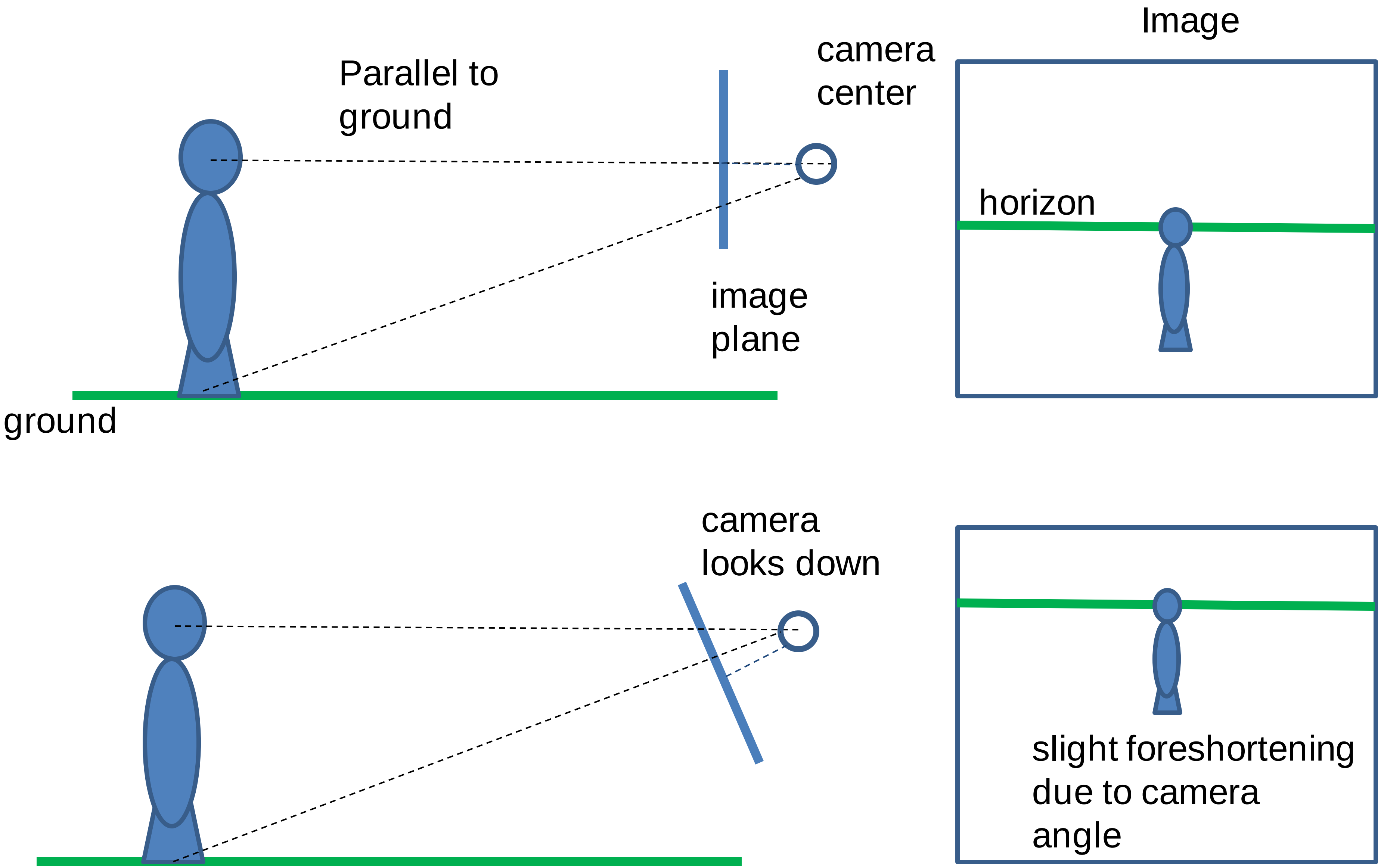


Slide by Steve Seitz

Measuring height

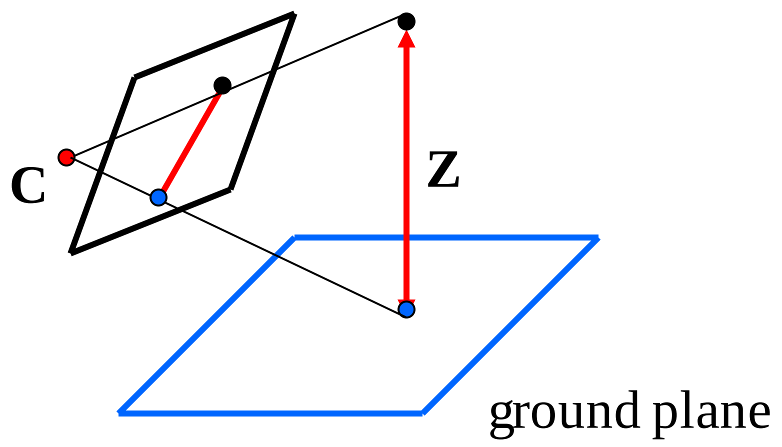


Two views of a scene



Which is higher – the camera or the parachute?

Measuring height without a giant ruler



Compute Z from image measurements

- Need a reference object

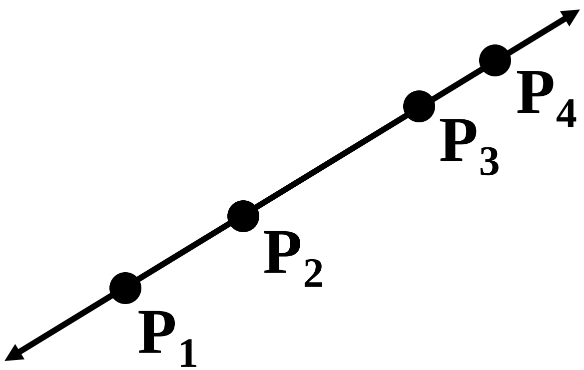
Slide by Steve Seitz

The cross ratio

A Projective Invariant

- Something that does not change under projective transformations (including perspective projection)

The cross-ratio of 4 collinear points



$$\frac{\|\mathbf{P}_3 - \mathbf{P}_1\| \, \|\mathbf{P}_4 - \mathbf{P}_2\|}{\|\mathbf{P}_3 - \mathbf{P}_2\| \, \|\mathbf{P}_4 - \mathbf{P}_1\|}$$

$$\mathbf{P}_i = \begin{bmatrix} X_i \\ Y_i \\ Z_i \\ 1 \end{bmatrix}$$

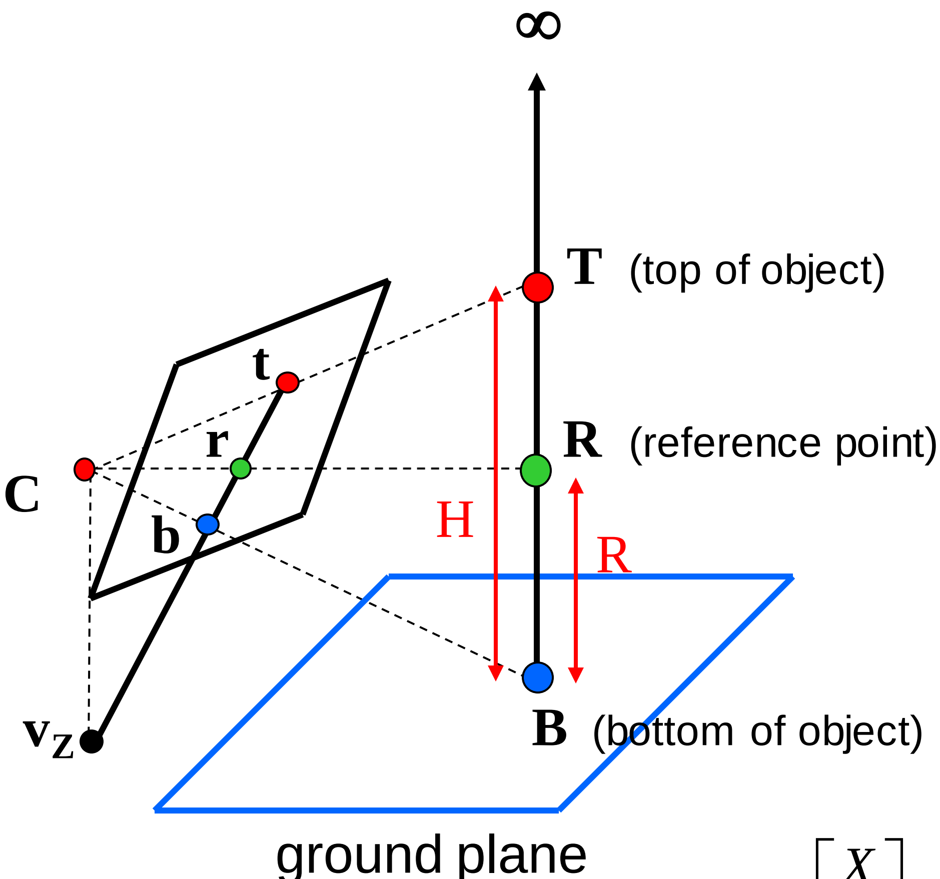
Can permute the point ordering

$$\frac{\|\mathbf{P}_1 - \mathbf{P}_3\| \, \|\mathbf{P}_4 - \mathbf{P}_2\|}{\|\mathbf{P}_1 - \mathbf{P}_2\| \, \|\mathbf{P}_4 - \mathbf{P}_3\|}$$

- 4! = 24 different orders (but only 6 distinct values)

This is the fundamental invariant of projective geometry

Measuring height



$$\frac{\|\mathbf{B}-\mathbf{T}\|\,\|\infty-\mathbf{R}\|}{\|\mathbf{B}-\mathbf{R}\|\,\|\infty-\mathbf{T}\|} = \frac{H}{R}$$

scene cross ratio

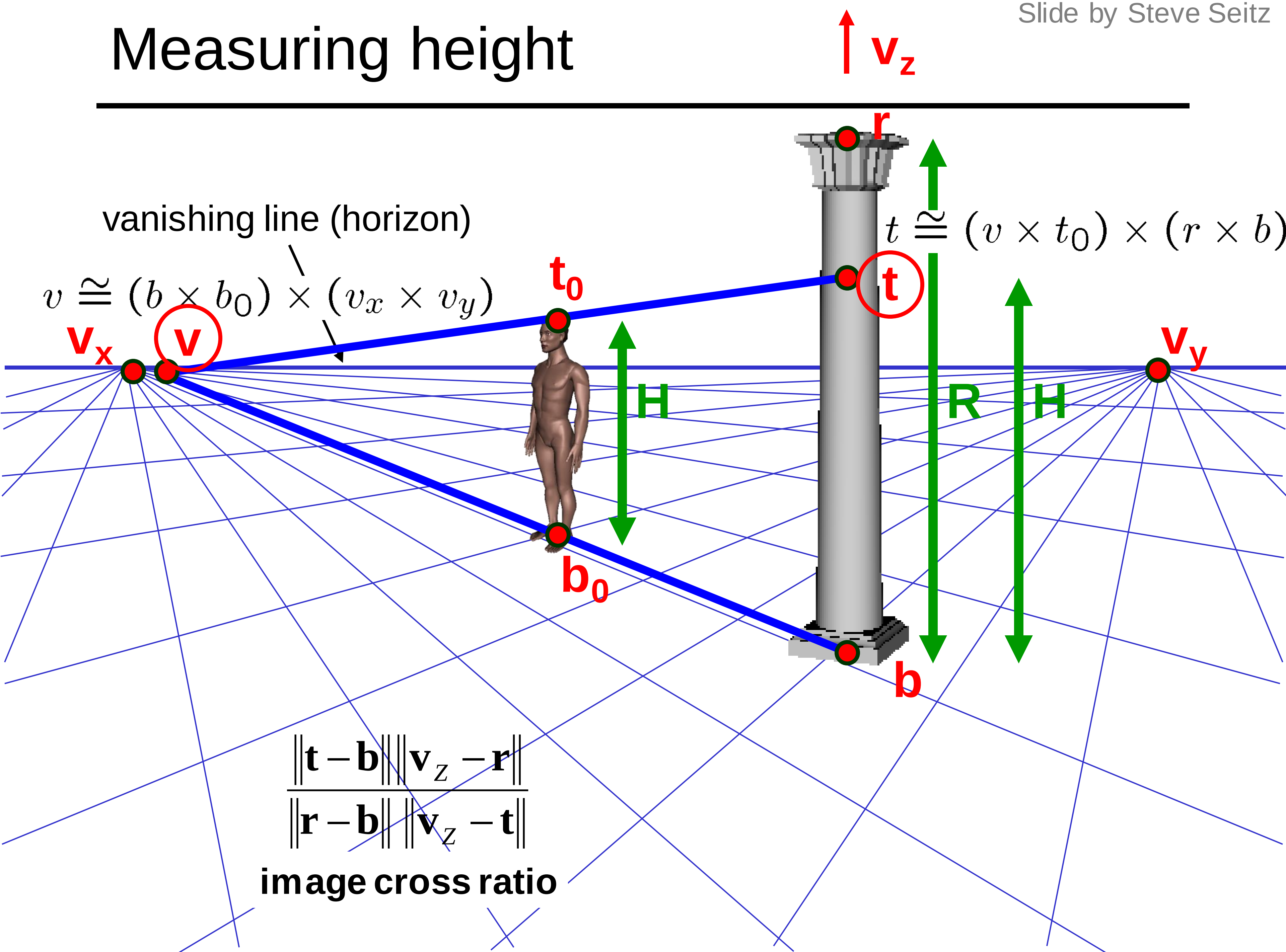
$$\frac{\|\mathbf{b}-\mathbf{t}\|\,\|\mathbf{v}_Z-\mathbf{r}\|}{\|\mathbf{b}-\mathbf{r}\|\,\|\mathbf{v}_Z-\mathbf{t}\|} = \frac{H}{R}$$

image cross ratio

scene points represented as $\mathbf{P} = \begin{bmatrix} X \\ Y \\ Z \\ 1 \end{bmatrix}$ image points as $\mathbf{p} = \begin{bmatrix} x \\ y \\ 1 \end{bmatrix}$

Measuring height

Slide by Steve Seitz

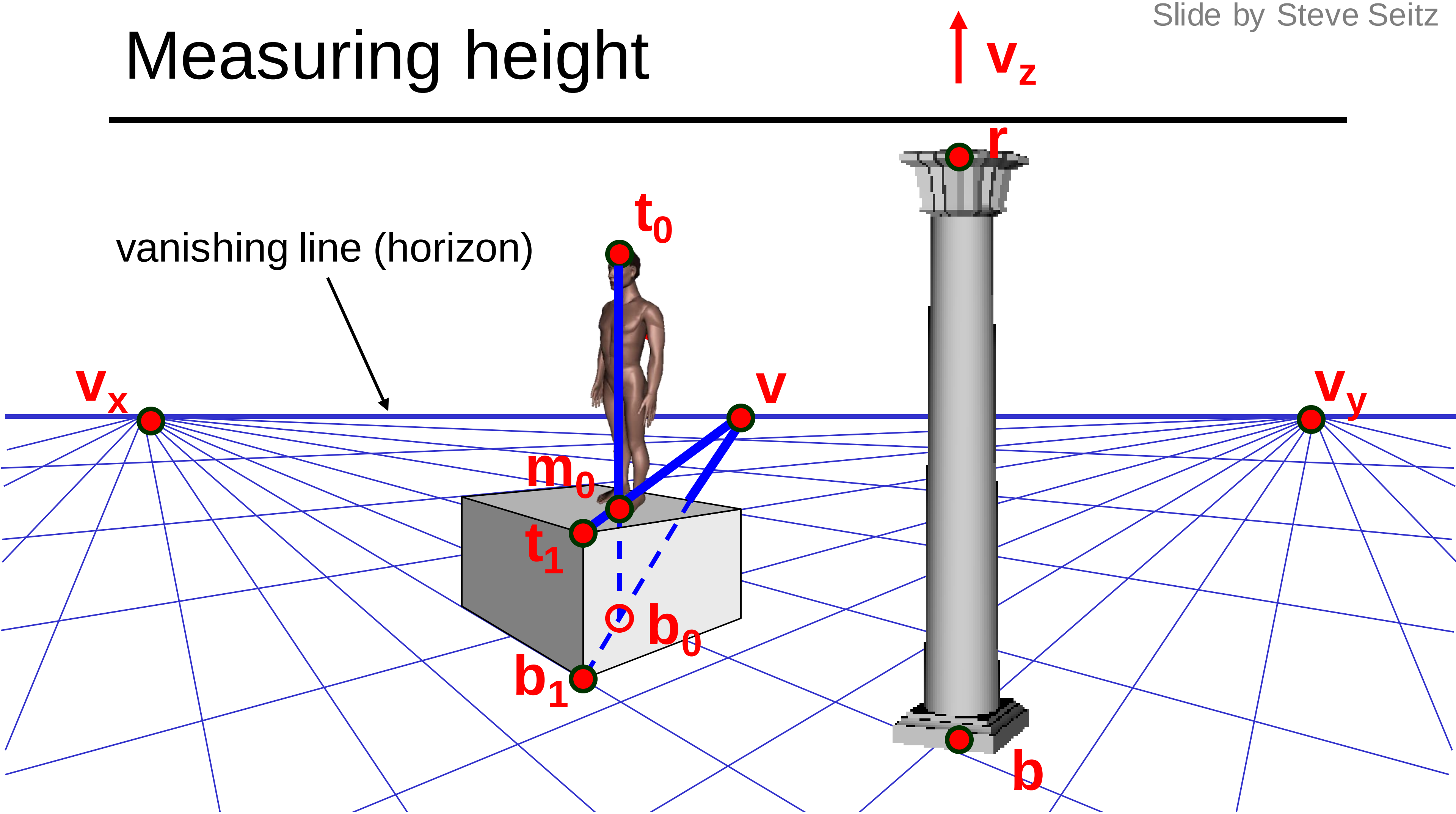


$$\frac{\|\mathbf{t}-\mathbf{b}\| \|\mathbf{v}_Z-\mathbf{r}\|}{\|\mathbf{r}-\mathbf{b}\| \|\mathbf{v}_Z-\mathbf{t}\|}$$

image cross ratio

Slide by Steve Seitz

Measuring height



What if the point on the ground plane $\mathbf{b_0}$ is not known?

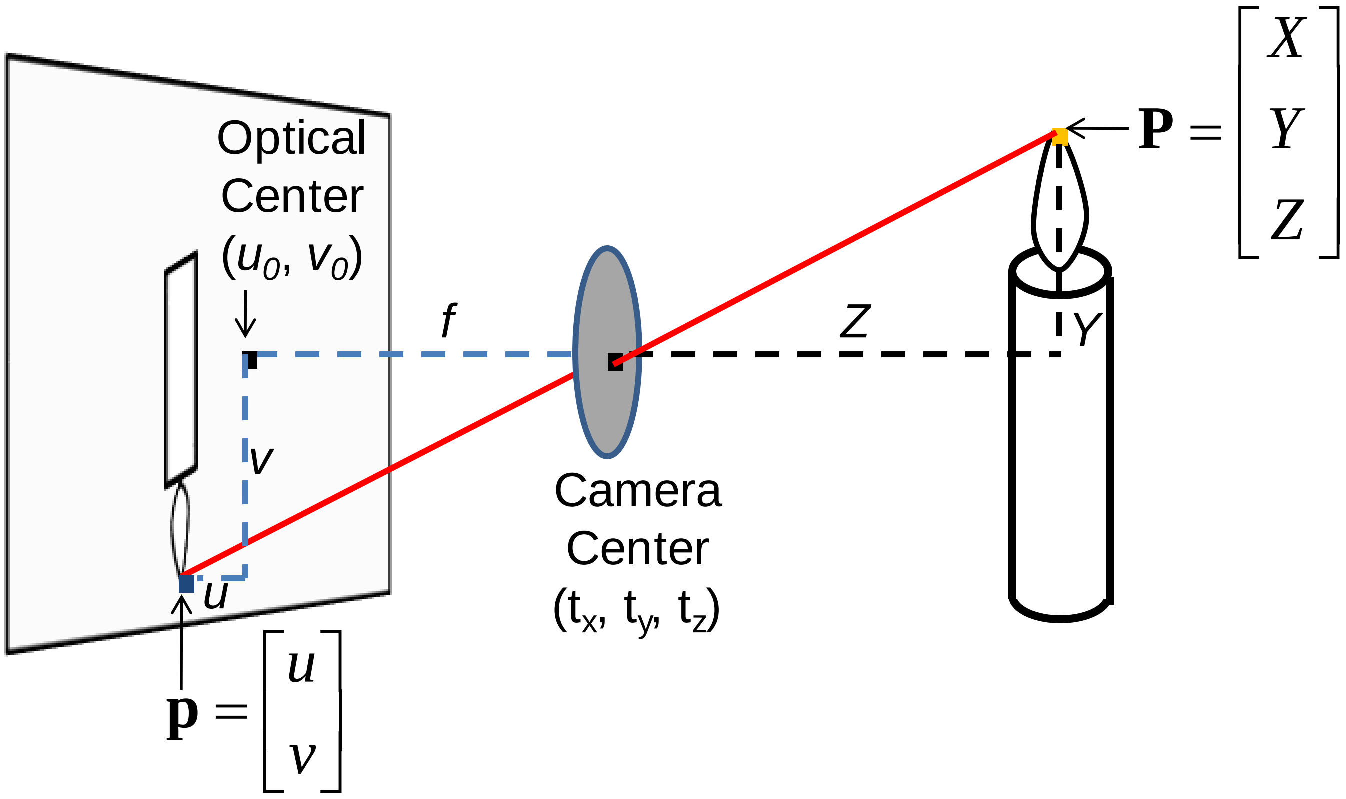
- Here the guy is standing on the box, height of box is known
- Use one side of the box to help find $\mathbf{b_0}$ as shown above

Take-home question

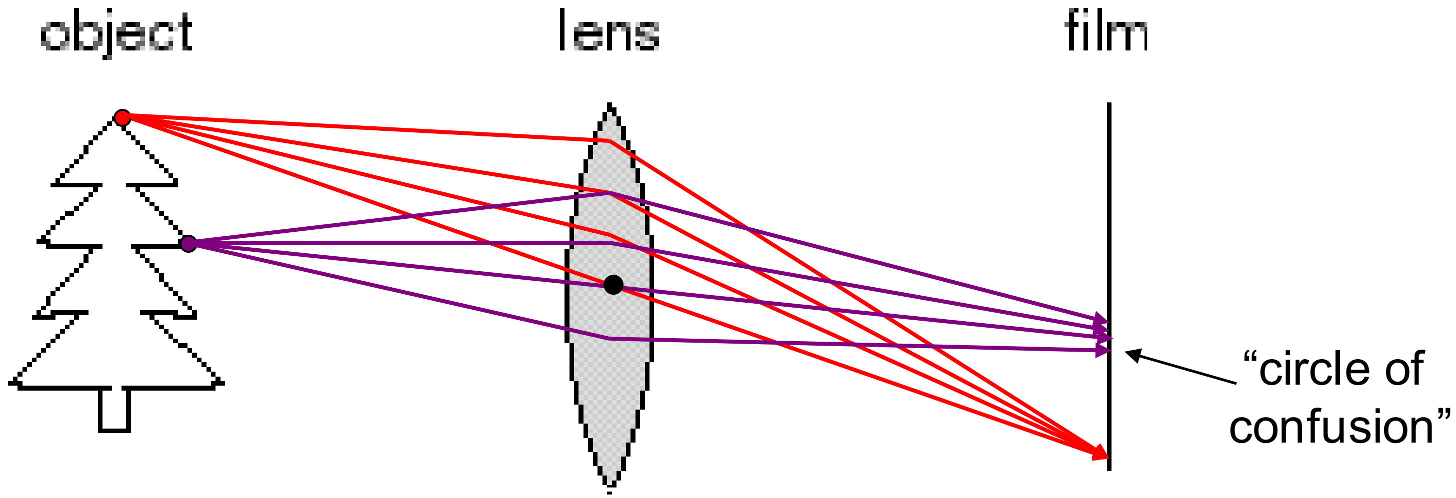
Assume that the man is 6 ft tall

- What is the height of the front of the building?
- What is the height of the camera?

Beyond the pinhole: What about focus, aperture, DOF, FOV, etc?

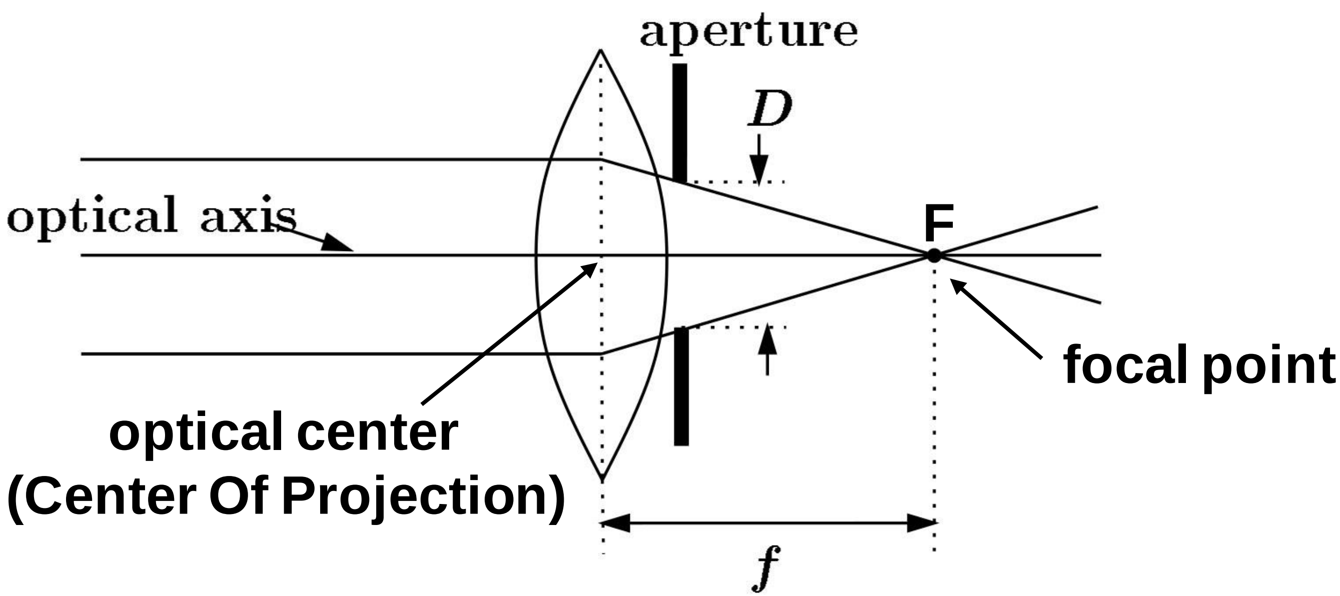


Adding a lens



- A lens focuses light onto the film
  - There is a specific distance at which objects are "in focus"
    - other points project to a "circle of confusion" in the image
  - Changing the shape of the lens changes this distance

Focal length, aperture, depth of field

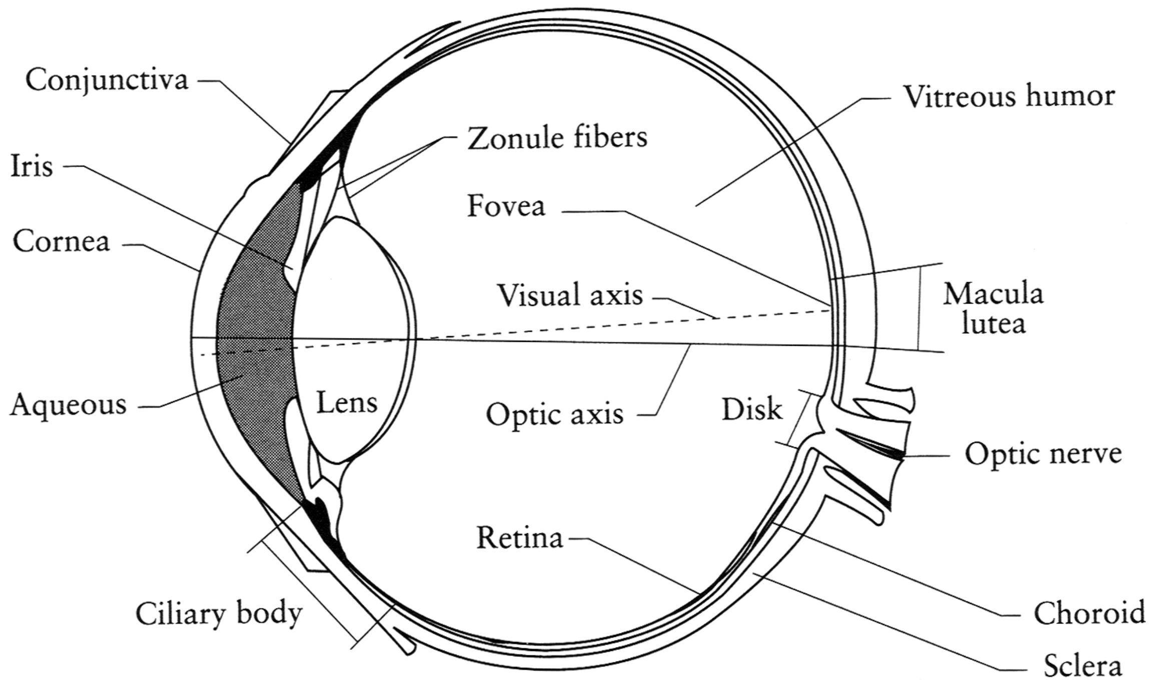


A lens focuses parallel rays onto a single focal point

- focal point at a distance *f* beyond the plane of the lens
- Aperture of diameter D restricts the range of rays

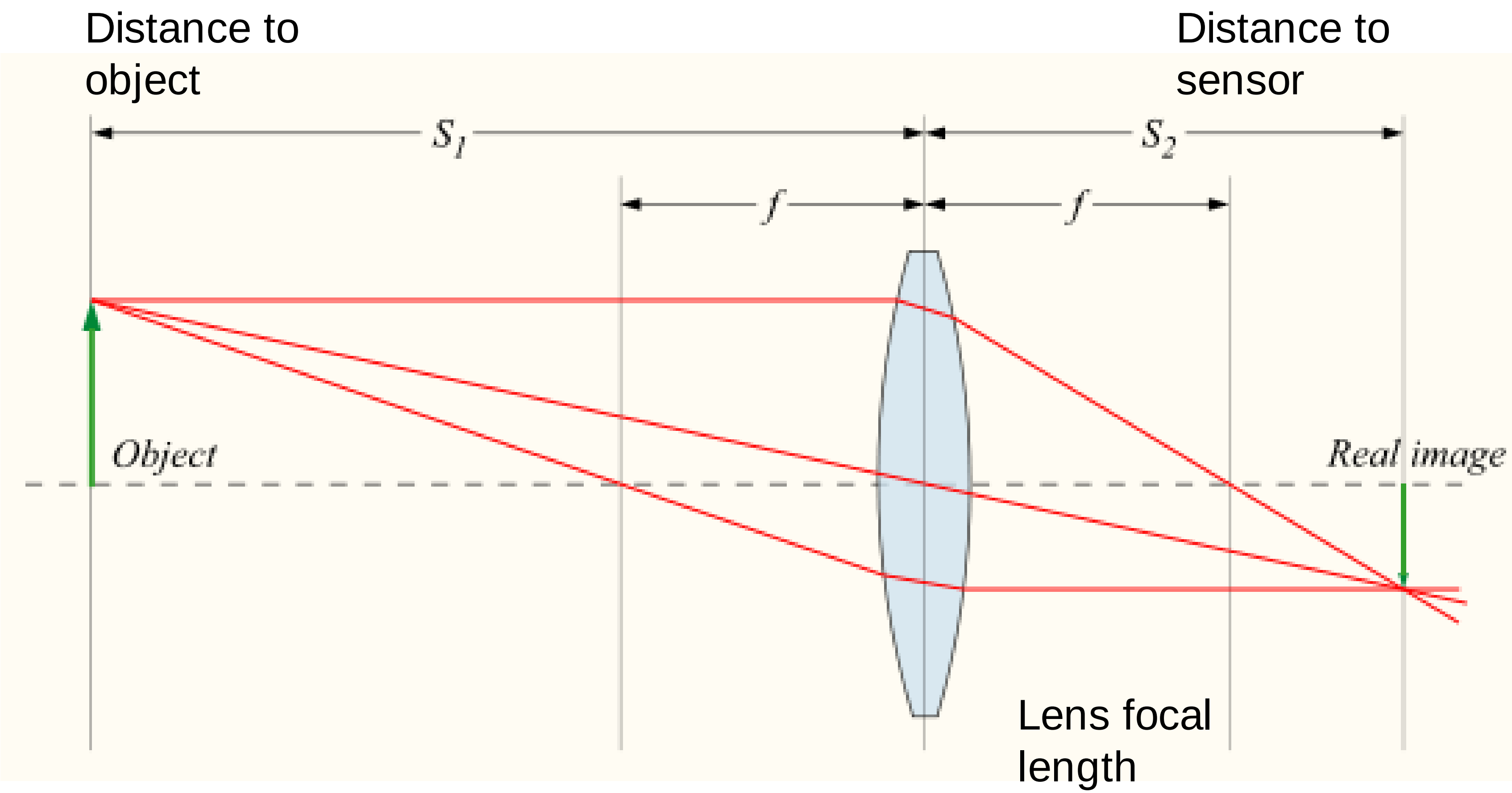
Slide source: Seitz

The eye



- The human eye is a camera
  - **Iris** - colored annulus with radial muscles
  - **Pupil** - the hole (aperture) whose size is controlled by the iris

Focus with lenses

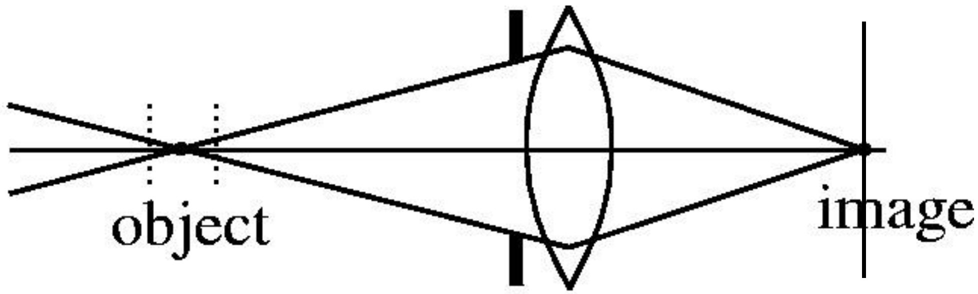


Equation for objects in focus

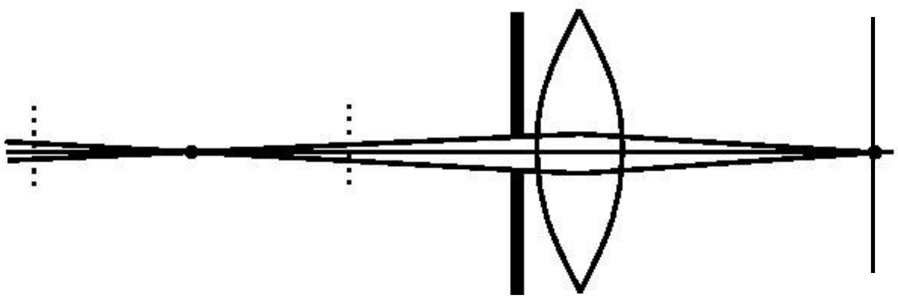
$$\frac{1}{S_1} + \frac{1}{S_2} = \frac{1}{f}$$

Source: http://en.wikipedia.org/wiki/File:Lens3.svg

The aperture and depth of field



f / 5.6



f / 32

Changing the aperture size or focusing distance affects depth of field

- f-number (f/#) =focal_length / aperture_diameter (e.g., f/16 means that the focal length is 16 times the diameter)
- When you change the f-number, you are changing the aperture

Flower images from Wikipedia http://en.wikipedia.org/wiki/Depth_of_field

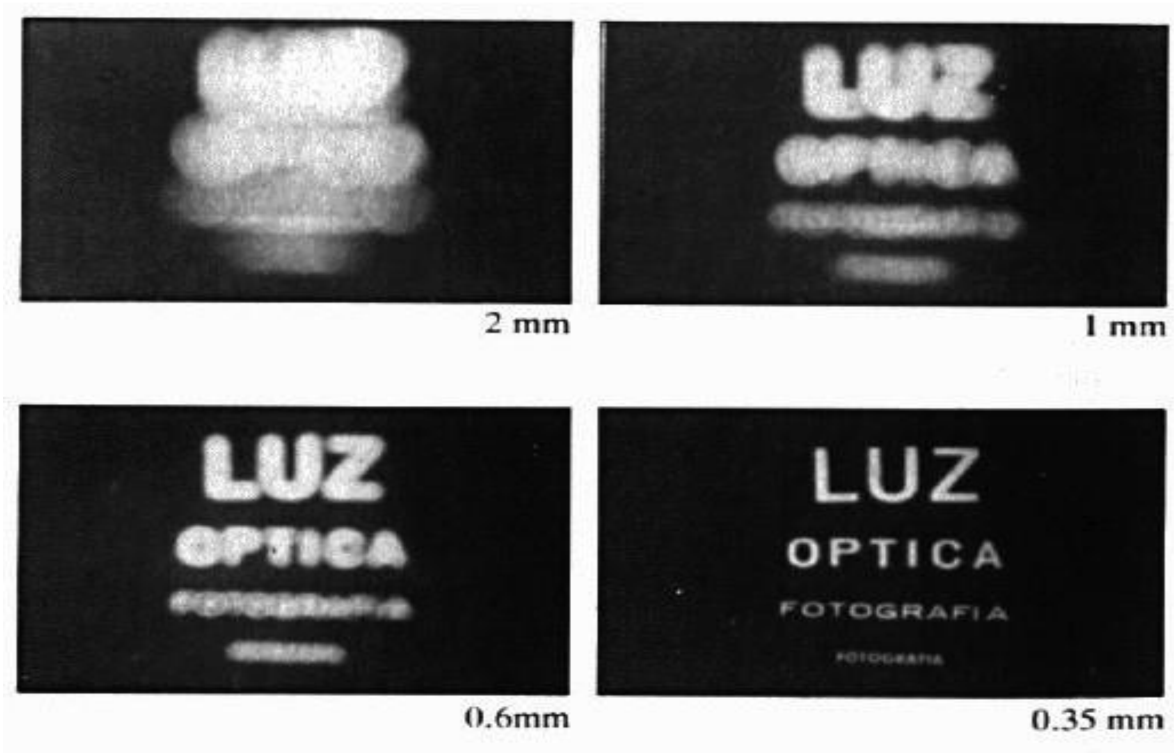
Slide from Efros

Varying the aperture

Large aperture = small DOF

Small aperture = large DOF

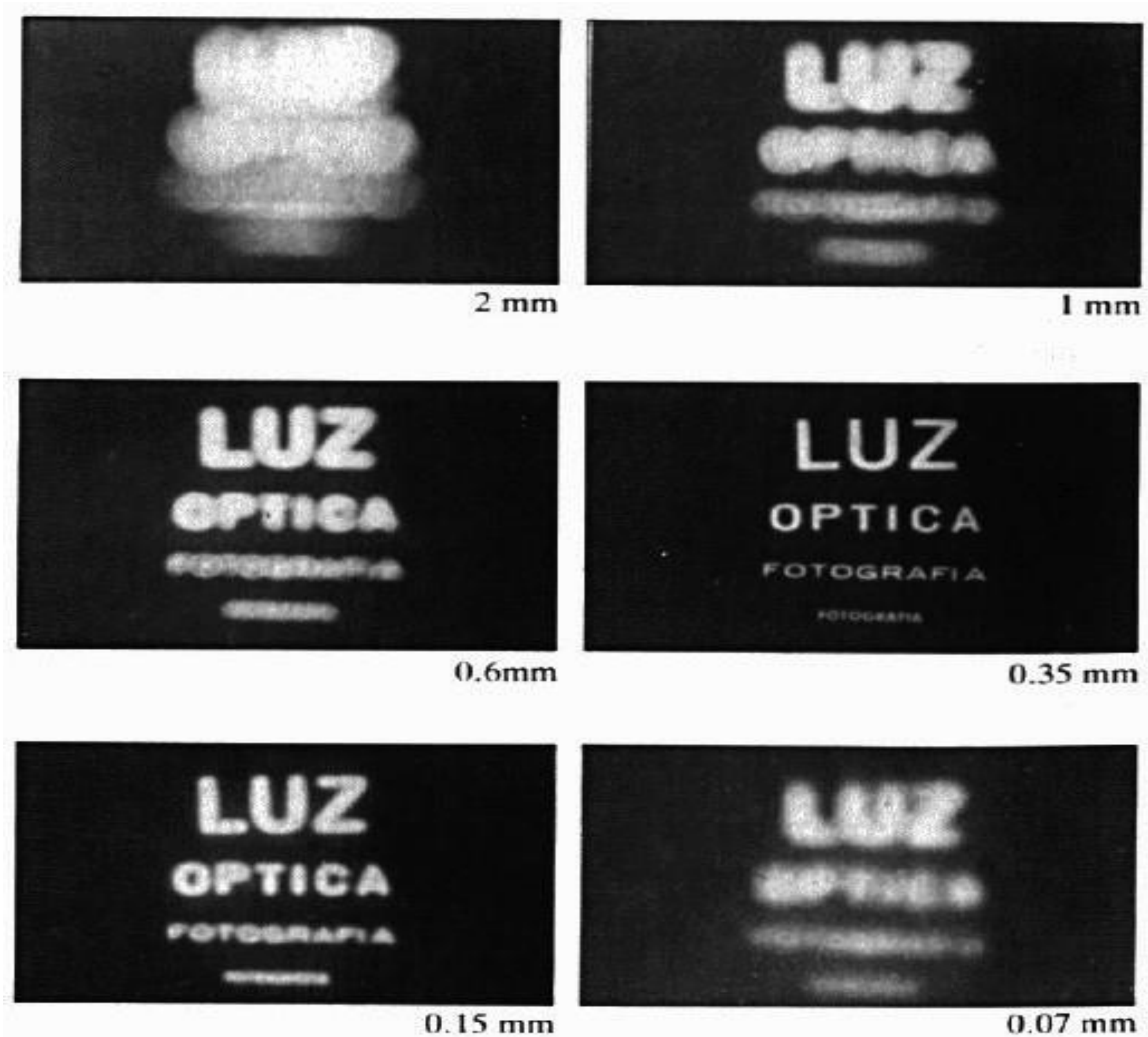
Shrinking the aperture



- Why not make the aperture as small as possible?
  - Less light gets through
  - Diffraction effects

Slide by Steve Seitz

Shrinking the aperture



The Photographer’s Great Compromise

What we want	How we get it	Cost
More spatial resolution	Increase focal length	Light, FOV
Broader field of view	Decrease focal length	DOF
More depth of field	Decrease aperture	Light
More temporal resolution	Increase aperture	DOF
More light	Shorten exposure	Light
	Lengthen exposure	Temporal Res

Difficulty in macro (close-up) photography

- For close objects, we have a small relative DOF
- Can only shrink aperture so far

How to get both bugs in focus?

Solution: Focus stacking

1. Take pictures with varying focal length

Example from
http://www.wonderfulphotos.com/articles/macro/focus_stacking/

Solution: Focus stacking

1. Take pictures with varying focal length
2. Combine

Focus stacking

http://www.wonderfulphotos.com/articles/macro/focus_stacking/

Focus stacking

How to combine?

Web answer: With software (Photoshop, CombineZM)

How to do it automatically?

Focus stacking

How to combine?

1. Align images (e.g., using corresponding points)
2. Two ideas
   a) Mask regions by hand and combine with pyramid blend
   b) Gradient domain fusion (mixed gradient) without masking

Automatic solution would make an interesting final project

Recommended Reading:

http://www.digital-photography-school.com/an-introduction-to-focus-stacking

http://www.zen20934.zen.co.uk/photography/Workflow.htm#Focus%20Stacking

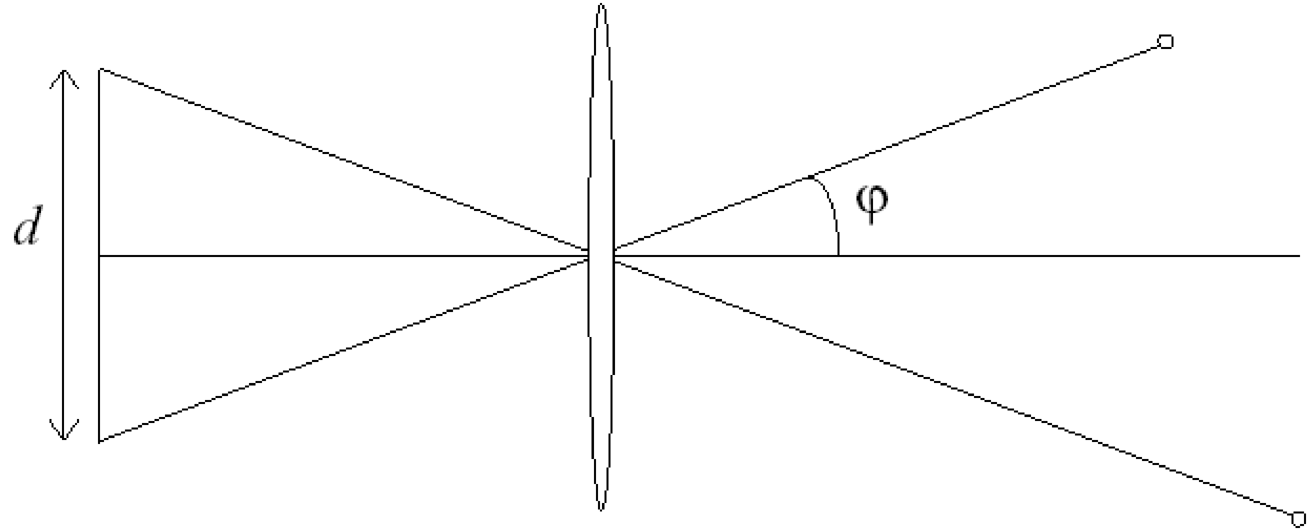
Relation between field of view and focal length

Field of view (angle width)

Film/Sensor Width

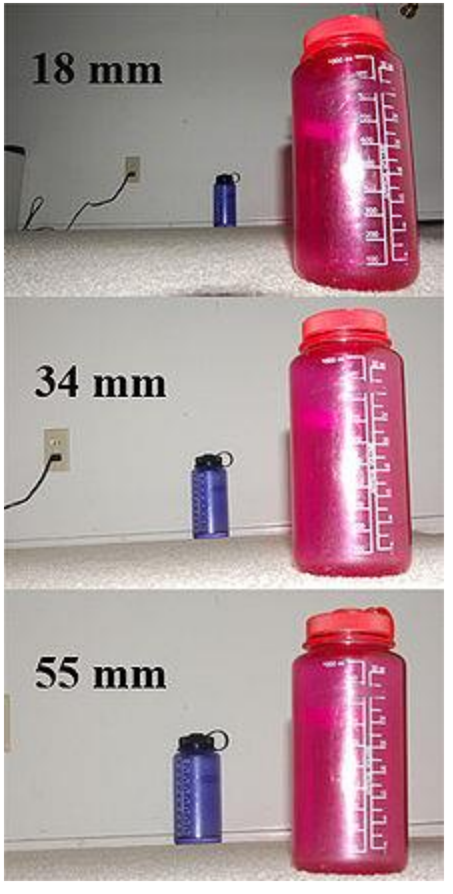
$$fov = 2\tan^{-1}\frac{d}{2f}$$

Focal length



Dolly Zoom or "Vertigo Effect"

http://www.youtube.com/watch?v=NB4bikrNzMk



How is this done?

Zoom in while moving away

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

Dolly zoom (or "Vertigo effect")

Field of view (angle width)

Film/Sensor Width

$$fov = 2\tan^{-1}\frac{d}{2f}$$

Focal length

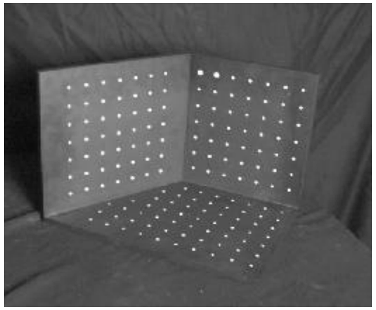
width of object

$$2\tan\frac{fov}{2} = \frac{width}{\text{distance}}$$

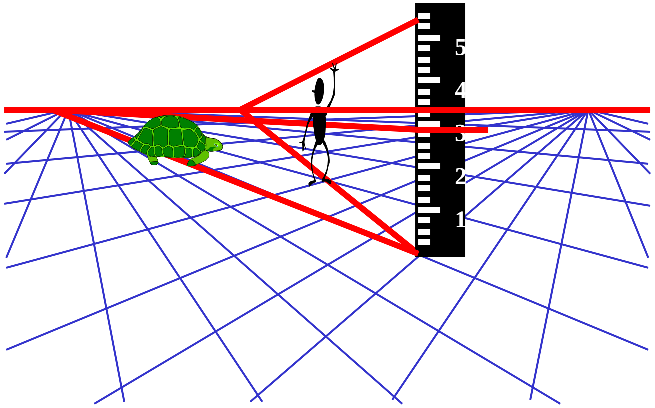
Distance between object and camera

Things to remember

- Can calibrate using grid or VP



- Can measure relative sizes using VP



- Effects of focal length, aperture + tricks

Next class

- Go over take-home questions from today
- Single-view 3D Reconstruction