

Contents

1. Introduction	1
1.1 Formulation of the Problem	2
1.2 Overview of Recent Progress	4
1.3 Bibliographical Notes	6
2. Image Matching	7
2.1 Approaches to Establishing Correspondences	7
2.2 An Approach to Image Matching	10
2.2.1 Image Attributes	12
2.2.2 Relationships of the Attributes	14
2.2.3 Intra-Regional Smoothness and Occlusion	14
2.2.4 Multi-Resolution Multi-Grid Structure	17
2.2.5 Limitations	19
2.3 Algorithm	20
2.3.1 Locally Rigid Motion	20
2.3.2 3-D Motion and Image Plane Motion	21
2.3.3 Motion Insensitive Image Attributes	24
2.3.4 Edgeness and Cornerness	26
2.3.5 Smoothness	29
2.3.6 Minimizing Residuals	31
2.3.7 Recursive Blurring	34
2.3.8 Preprocessing and Normalization	35
2.3.9 Outline of the Matching Algorithm	37
2.4 Motion and Structure Computation	38
2.5 Refinements	39

2.5.1	Bottom-Up and Top-Down	39
2.5.2	Refinement Based on Rigidity	40
2.6	Examples	41
2.7	Summary	59
2.8	Bibliographical Notes	61
	Appendix	62
3.	Two-View Analysis	65
3.1	Some Basic Issues	65
3.2	An Algorithm	67
3.2.1	Problem Statement	68
3.2.2	Algorithm	70
3.2.3	Justification of the Algorithm	73
3.3	Error Estimation	78
3.3.1	Algorithm and Perturbation	79
3.3.2	Perturbation of Eigenvalues and Eigenvectors	81
3.3.3	Error Estimation for the Algorithm	83
3.4	Error Analysis	90
3.4.1	Structure of the Scene	90
3.4.2	Motion Parameters	91
3.4.3	System Parameters	97
3.5	Performance	98
3.5.1	Performance	99
3.5.2	Error Estimation	100
3.5.3	Error versus Motion and System Parameters	106
3.5.4	Real Images	115
3.6	Summary	117
3.7	Bibliographical Notes	118
	Appendix 3.A Perturbation of Eigenspace	119
	Appendix 3.B Quaternions	122
	Appendix 3.C Alternative Fitting	125
4.	Optimization	127
4.1	Motivations	127
4.2	Stability of Linear Algorithms	129

4.2.1	The Linear Algorithms	131
4.2.2	The Epipolar Constraint	132
4.2.3	Using the Constraint in Matrix E	134
4.2.4	A Type of Motion	135
4.2.5	Beyond the Epipolar Constraint	140
4.3	Maximum Likelihood Estimation	141
4.3.1	Gaussian Distribution	143
4.3.2	Uncertainty Polyhedron Distribution	146
4.4	A Two-Step Approach and Computation	149
4.5	Minimum Variance Estimation	154
4.6	Error Estimation and Error Bounds	157
4.6.1	Error Estimation	157
4.6.2	Error Bounds	158
4.7	Batch and Sequential Methods	162
4.7.1	Linear Systems	163
4.7.2	Nonlinear Systems	166
4.7.3	Recursive-Batch Solution	172
4.8	Numerical Examples	174
4.8.1	Whether a Good Initial Guess Is Necessary	174
4.8.2	Epipolar Improvement versus Optimization	175
4.8.3	Sequential versus Batch Solutions	176
4.8.4	Uncertainty Polyhedron Model	185
4.8.5	Error Estimation and Error Bound	188
4.8.6	Inherent Limitation of Optical Flow	193
4.8.7	Real World Images	195
4.9	Summary	195
4.10	Bibliographical Notes	197
	Appendix 4.A Decomposability	197
	Appendix 4.B Weights	199
	Appendix 4.C Triangulation with Noise	200
	Appendix 4.D Matrix Derivatives	202
	Appendix 4.E Cramér-Rao Bound	203
5.	Planar Scenes	205
5.1	Planar Scene as a Degenerate Case	205

5.2	Motion from a Plane	206
5.2.1	Problem Statement	206
5.2.2	Algorithm Overview	208
5.2.3	Intermediate Parameter Matrix F	209
5.2.4	General Case	211
5.2.5	Two Solutions Are Both Valid	216
5.2.6	Special Cases	218
5.3	Inherent Uniqueness	222
5.3.1	Decomposability	223
5.3.2	Rank Condition Is Algorithm-Independent	225
5.3.3	The Fundamental Theorem	226
5.3.4	Plane-Perceivable Surfaces	228
5.3.5	Optimality	230
5.3.6	Three-View Problem	231
5.4	Examples	233
5.4.1	Simulations	233
5.4.2	Real Images	239
5.5	Conclusions	243
5.6	Bibliographical Notes	244
	Appendix 5.A Conditions on the Rank of A	245
	Appendix 5.B Two Solutions from F	248
	Appendix 5.C Plane-Perceivable Surfaces	249
	Appendix 5.D Condition on Consistent Normals	250
	Appendix 5.E Two-View Algorithm	254
	Appendix 5.F Error Estimation	257
6.	From Line Correspondences	265
6.1	Lines as Features	265
6.2	Solution and Algorithm	266
6.2.1	Why Two Views Are Not Sufficient	267
6.2.2	From Three Views	268
6.2.3	Two Important Equations	269
6.2.4	A Geometrical View	270
6.2.5	Intermediate Parameters	272
6.2.6	Motion from Intermediate Parameters	274

6.2.7	Structure and Sign of Translation Vectors	277
6.2.8	In the Presence of Noise	279
6.2.9	Algorithm	280
6.3	Degeneracy	284
6.4	Optimization	288
6.4.1	Lines from Pixels	288
6.4.2	Optimal Solution	290
6.4.3	How Accurate It Can Be	291
6.5	Simulations	292
6.5.1	Setup	292
6.5.2	Linear Algorithm	293
6.5.3	Algorithm with Optimization	297
6.5.4	Comparison with the Bound	301
6.5.5	Comparison with the Point-Based Algorithm	301
6.6	Conclusions and Discussions	303
6.7	Bibliographical Notes	303
	Appendix 6.A Ranks	304
	Appendix 6.B Unique Consistent Assignment	308
	Appendix 6.C Degeneracy	311
	Appendix 6.D Distinct Locations Are Necessary	312
	Appendix 6.E Alternative Degeneracy Condition	312
7.	Stereo	315
7.1	Stereo Camera Systems	315
7.2	Stereo Triangulation	317
7.3	Closed-Form Solution	320
7.3.1	A Matrix-Weighted Objective Function	321
7.3.2	Unweighted and Scalar-Weighted Versions	322
7.3.3	Matrix-Weighted Least-Squares Solution	322
7.3.4	Uniqueness	327
7.4	Iterative Optimal Solution	328
7.4.1	A Basic Objective Function	328
7.4.2	Optimization Using Space Decomposition	330
7.4.3	Estimating Errors	333
7.5	Outliers and Robust Estimators	335

7.5.1	Some Basic Concepts of Robust Statistics	336
7.5.2	A Robust Method for Motion Estimation	337
7.5.3	Using Closed-Form Solution	339
7.6	Examples	339
7.6.1	Simulations	340
7.6.2	Experiments with a Real Stereo Setup	348
7.7	Without Stereo Correspondences	355
7.7.1	Motivations	355
7.7.2	Motions Seen from Two Cameras	357
7.7.3	Determining Complete Motion and Structure	357
7.7.4	Computational Aspect of the Degeneracy	359
7.8	Long Image Sequences	361
7.8.1	Local and Global Coordinate Systems	363
7.8.2	A Recursive-Batch Approach	364
7.8.3	Recursive-Batch Updating	367
7.8.4	Local and Global Representations	368
7.8.5	Numerical Examples	371
7.9	Conclusions	376
7.10	Bibliographical Notes	377
	Appendix 7.A MWCC Theorem	378
	Appendix 7.B Least-Squares Matrix Fitting	379
8.	Motion Modeling and Prediction	381
8.1	Coherence of Motion	381
8.2	The LCAM Model	384
8.2.1	Motion of a Rigid Body in 3-D	384
8.2.2	Motion of Rotation Center	387
8.2.3	Solutions of the Coefficient Equation	391
8.2.4	Continuous and Discrete Motions	395
8.3	Estimation and Prediction	400
8.4	Monocular Vision	403
8.5	Optimization	406
8.6	Experimental Examples	408
8.6.1	Computer Simulation	408
8.6.2	Experiment with Real Images	412

8.7 Summary	413
8.8 Bibliographical Notes	414
Appendix 8.A Solution of Coefficient Equations	415
Appendix 8.B Rotation without Precession	420
Appendix 8.C Singularity of the Matrix	421
References	423
Subject Index	441