KECE471 Computer Vision

Stereo

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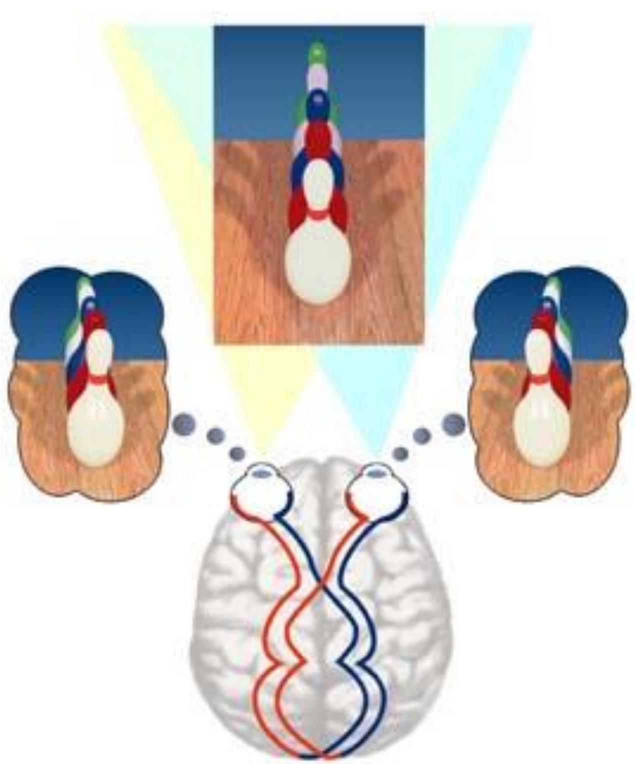
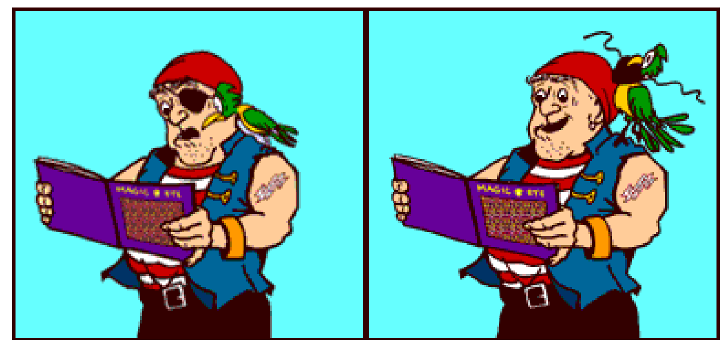
Chapter 11, Computer Vision by Forsyth and Ponce
Note: Most contents were copied from the lecture notes of Prof. Kyeong Mu Lee in SNU

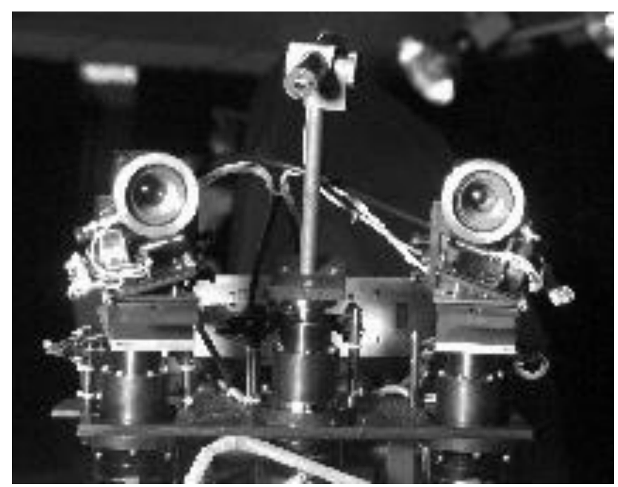
Stereo

- Inferring depth information using two cameras like a human
- Two eyes perceives three-dimension



Human eyes

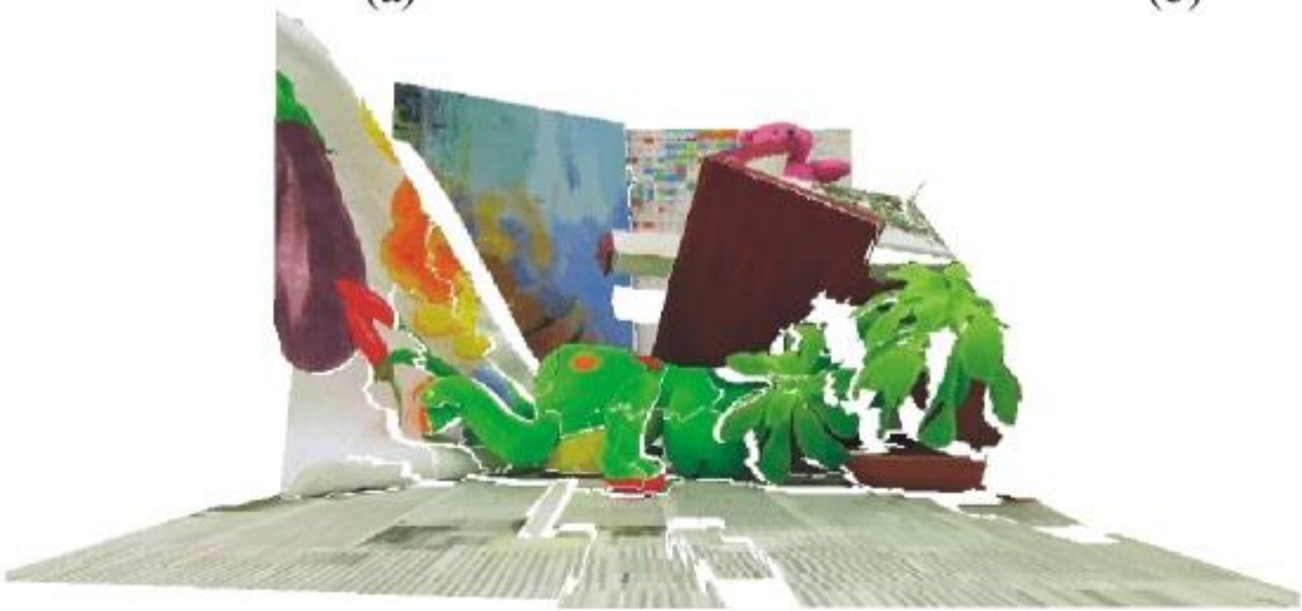




Robot eyes

Stereo

(a) (b)



(c)

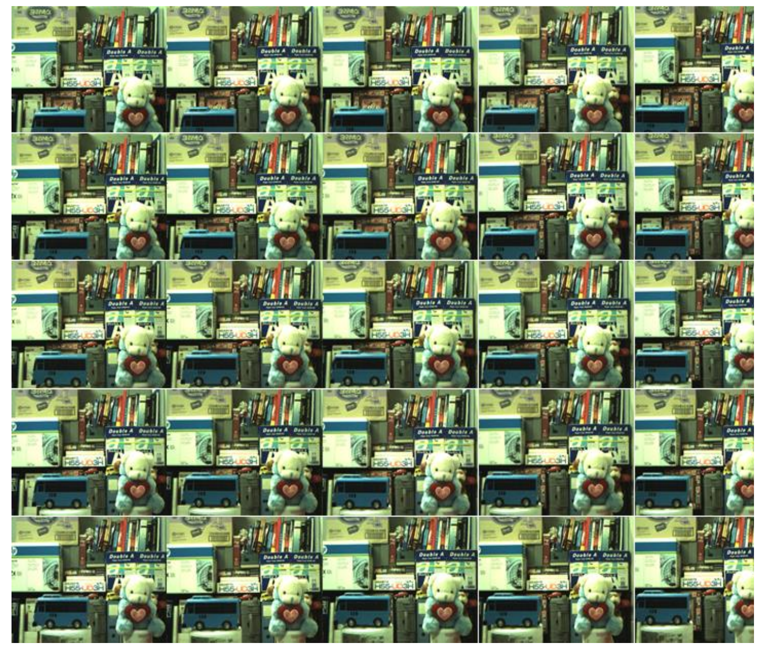
Public Library, Stereoscopic Looking Room, Chicago, by Phillips, 1923

Teesta suspension bridge-Darjeeling, India

Stereo

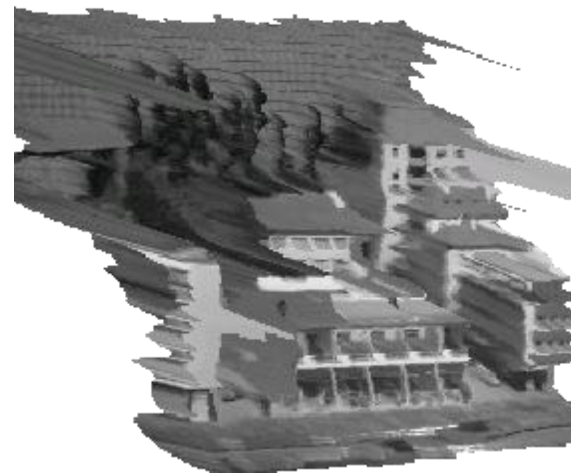
- Inferring depth information using two eyes or cameras
- Two eyes perceive 3rd dimension

(a)



(b)

Applications



[Matthies,Szeliski,Kanade'88]

Applications

input image

317 images
(hemisphere)

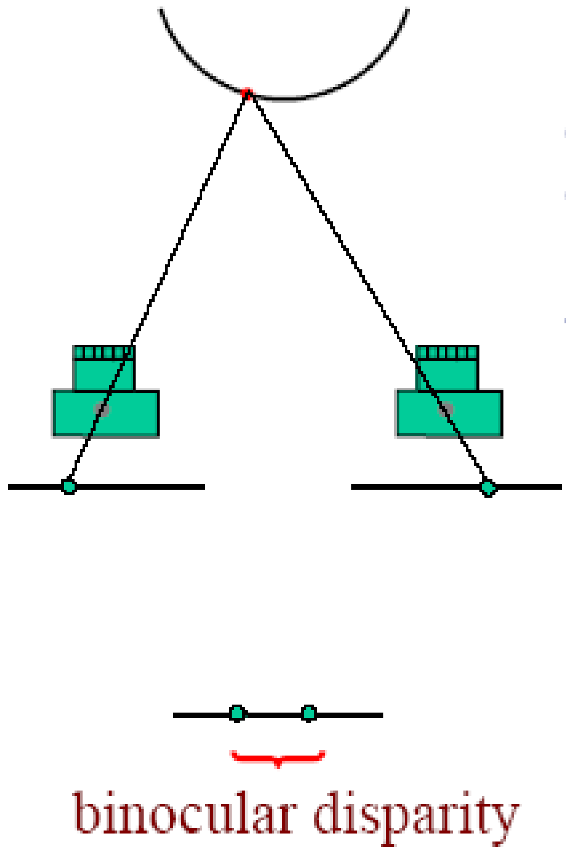
ground truth model

Goesele, Curless, Seitz, 2006

Binocular Stereo

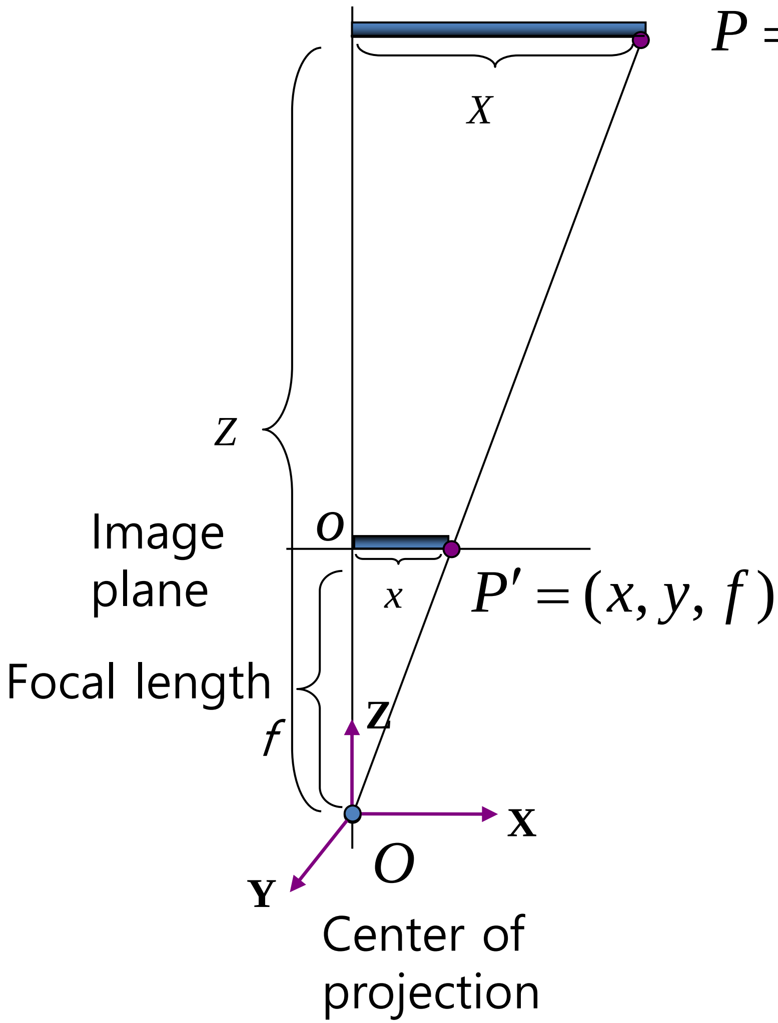
From known geometry of the cameras and estimated disparity, recover depth in the scene

Left



Right

Pinhole Camera Model



- 3D to 2D projection:

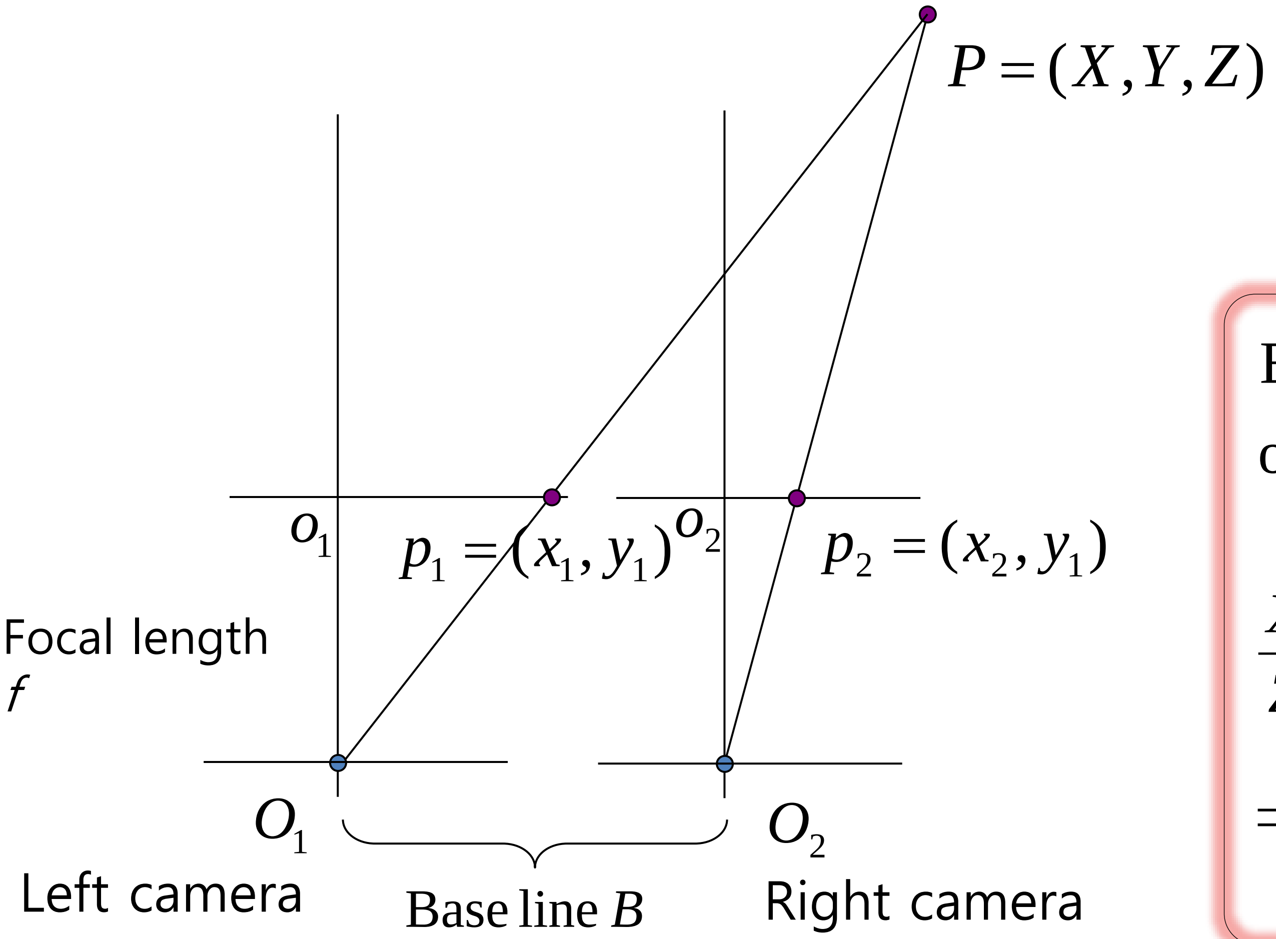
$$\frac{x}{X} = \frac{f}{Z} \Rightarrow x = f\,\frac{X}{Z}$$

$$\frac{y}{Y} = \frac{f}{Z} \Rightarrow y = f\,\frac{Y}{Z}$$

Thus

$$(X, Y, Z) \rightarrow (x, y) = (f\,\frac{X}{Z},\ f\,\frac{Y}{Z})$$

Basic Stereo Model

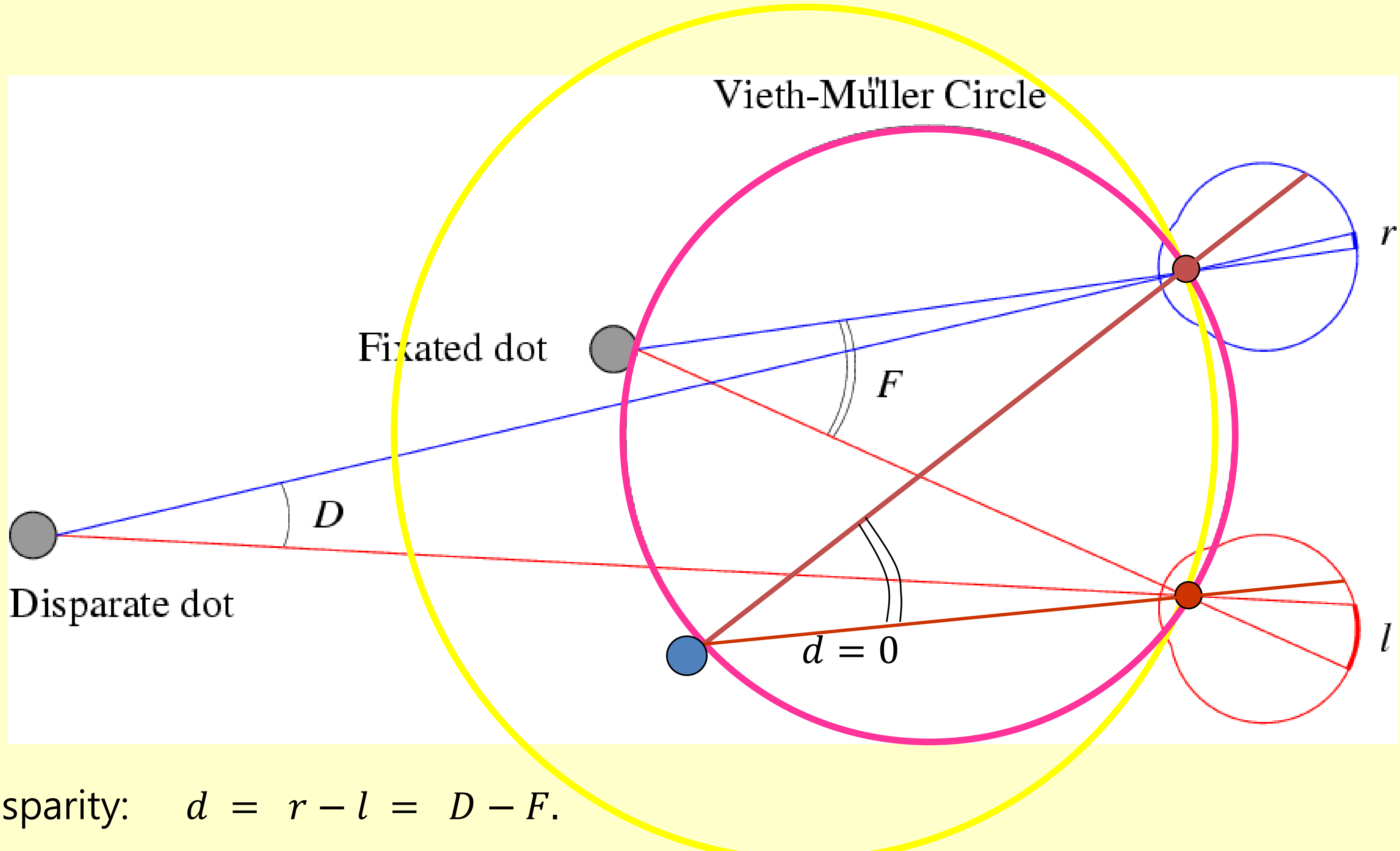


Express Z as a function of x_1, x_2, f, B

$$\frac{X}{Z} = \frac{x_1}{f} \text{ and } \frac{X - B}{Z} = \frac{x_2}{f}$$

$$\Rightarrow \boxed{Z = \frac{fB}{x_1 - x_2} = \frac{fB}{d(p_1)}}$$

Human Stereopsis: Reconstruction



Disparity: $d = r - l = D - F$.

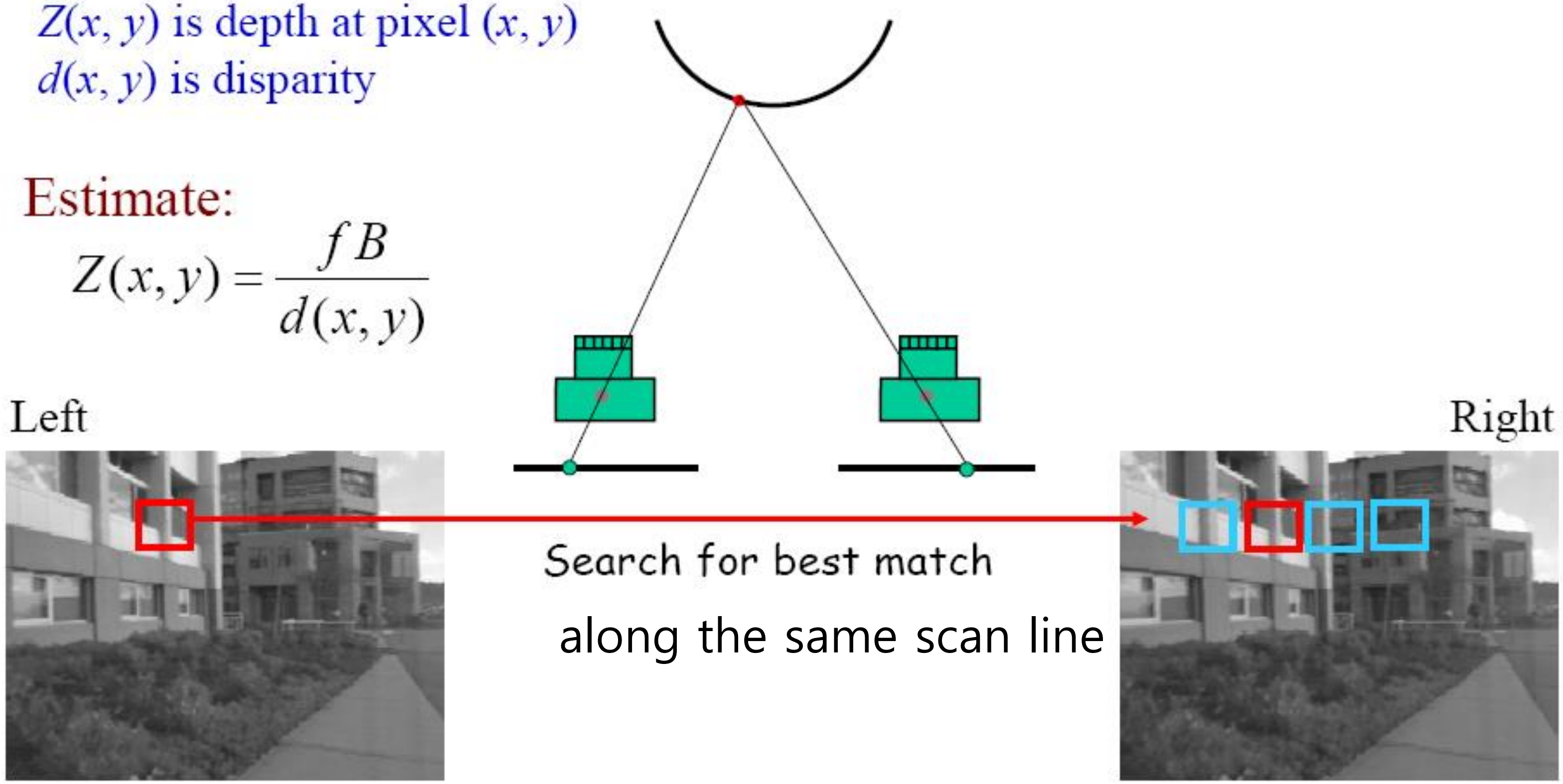
$d < 0$

Finding Correspondence

$Z(x, y)$ is depth at pixel (x, y)
$d(x, y)$ is disparity

Estimate:

$$Z(x,y) = \frac{f\,B}{d(x,y)}$$



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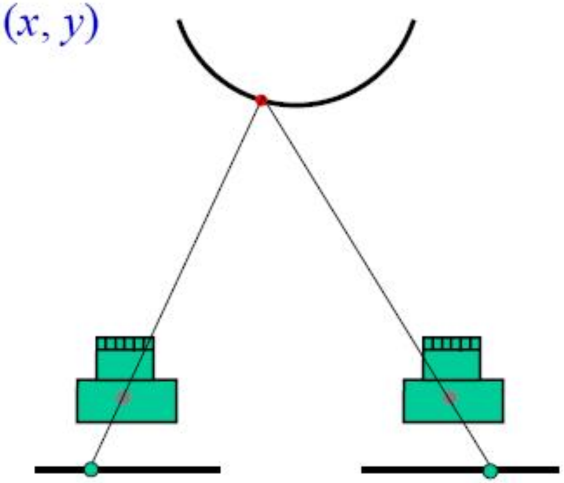
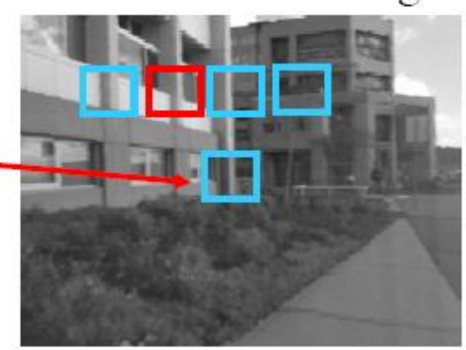


Left

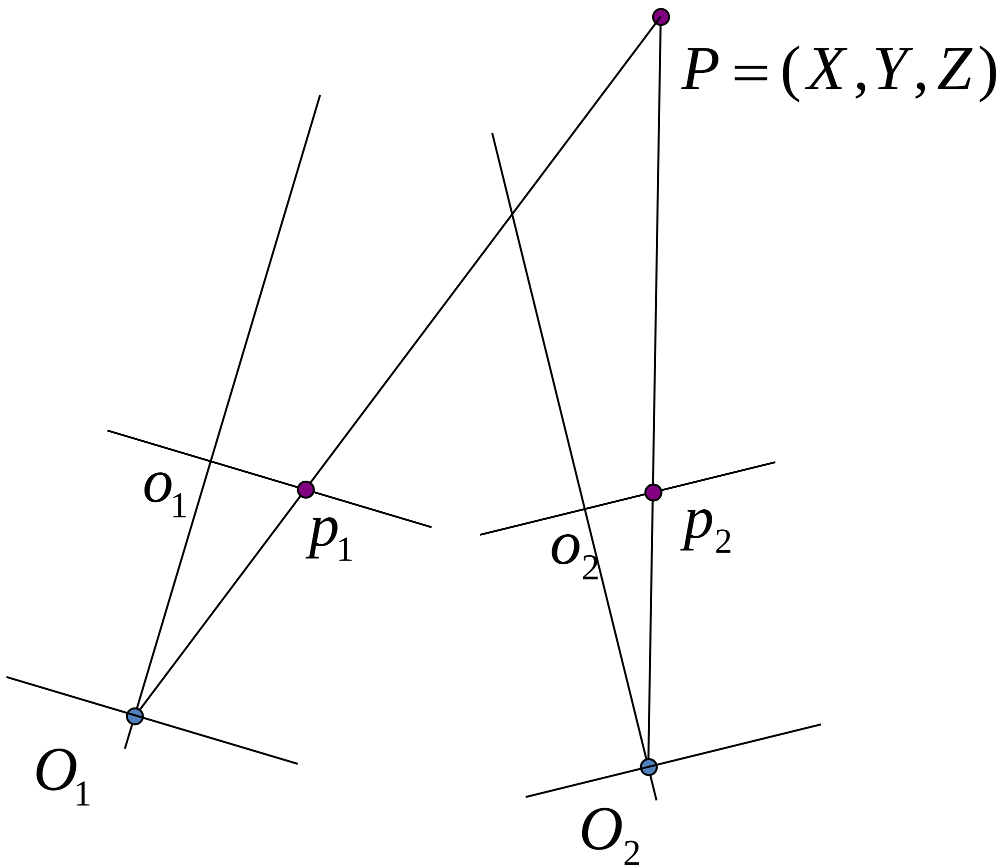
Right



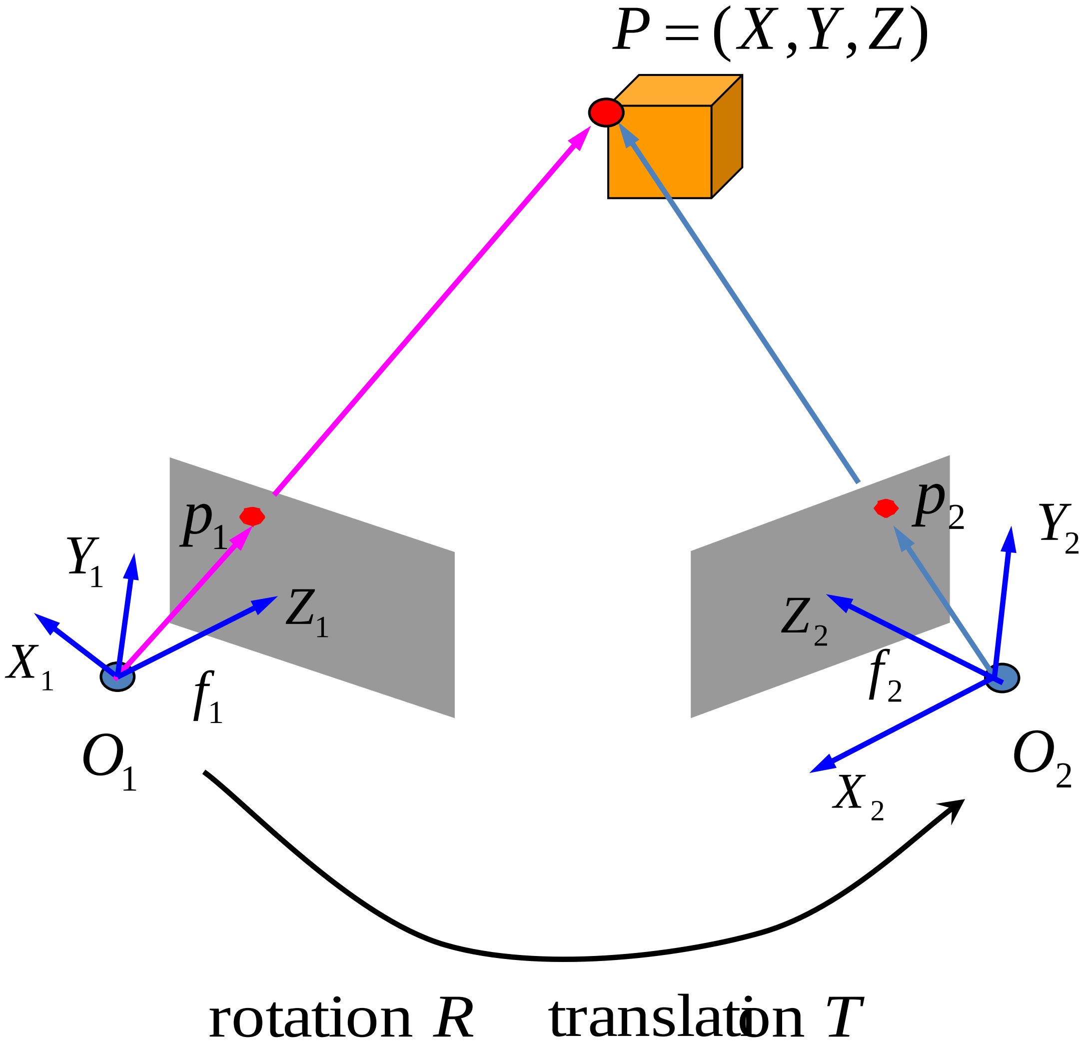
Do I need to consider this region?

General stereo

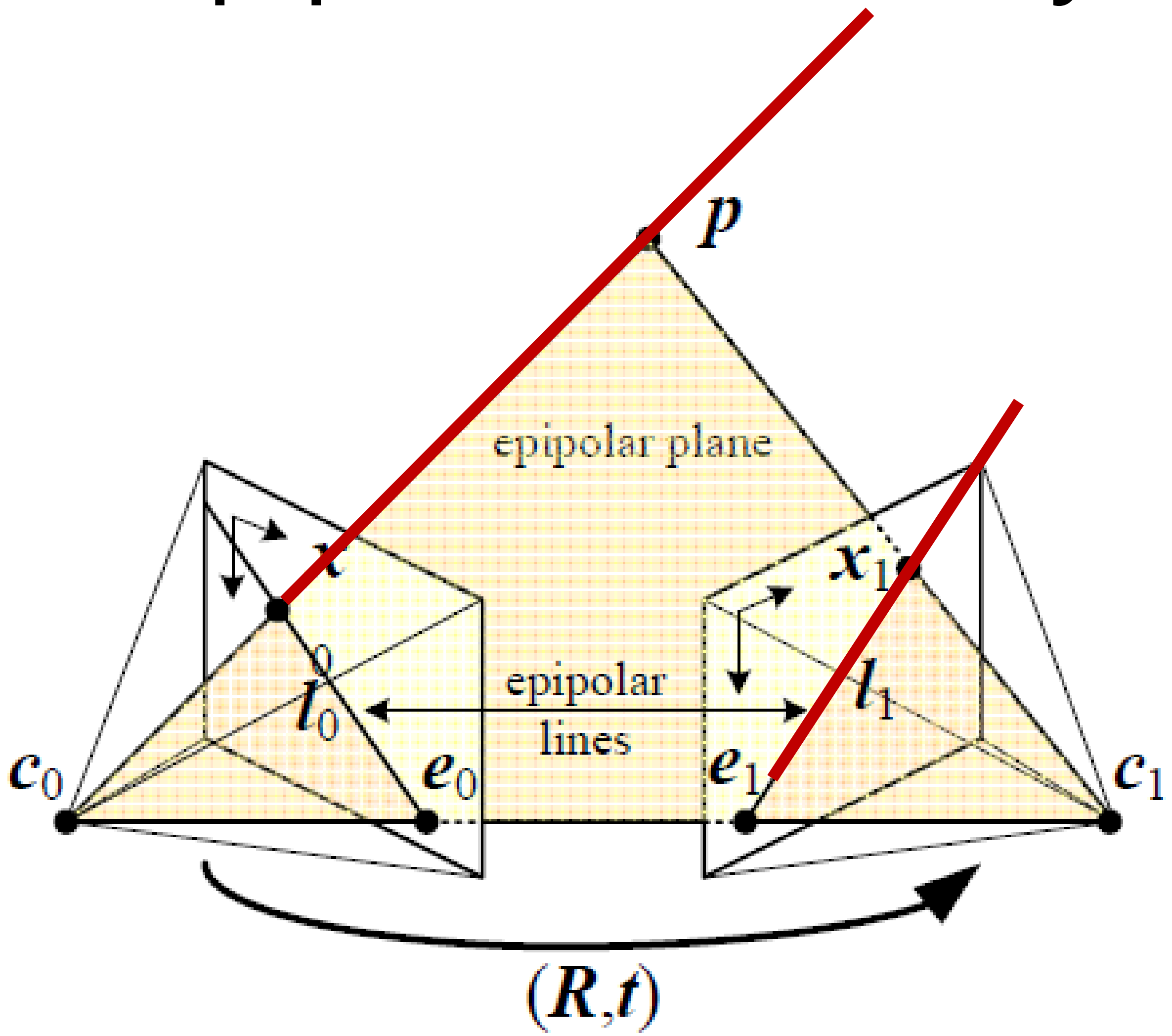
- What if two cameras are not parallel?



Epipolar Geometry

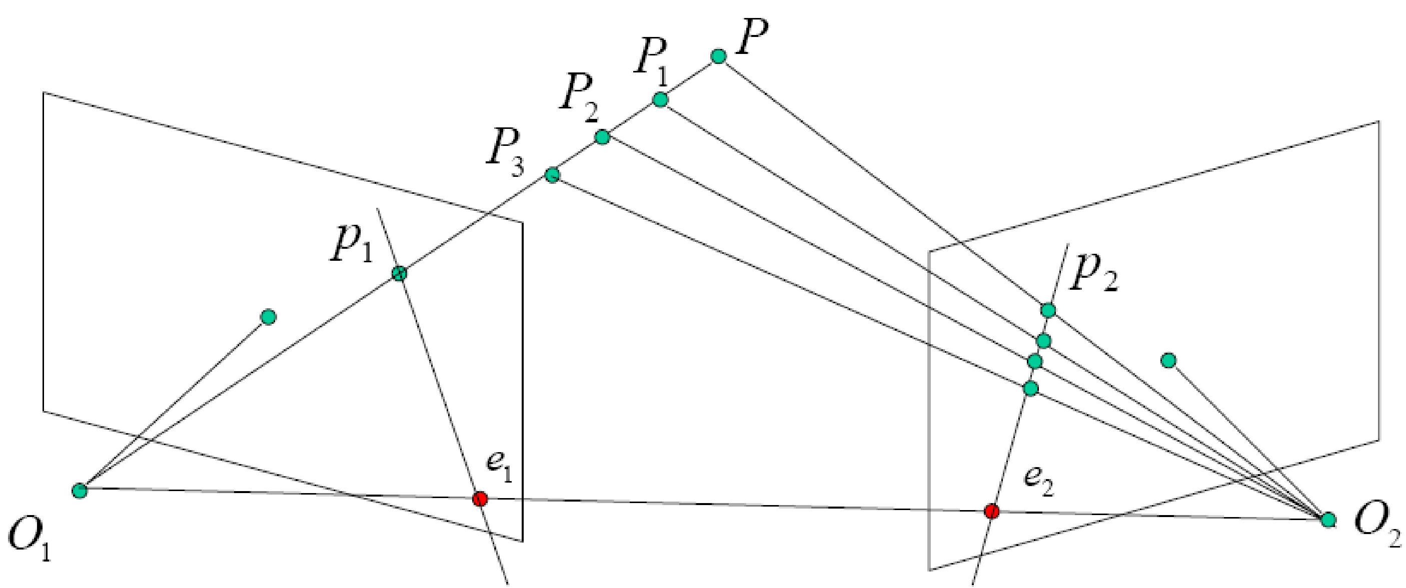


Epipolar Geometry



Epipolar Geometry

- Epipolar Constraint
  - A matching points lies on the associated epipolar line
  - It reduces the correspondence problem to 1D search along the epipolar line
  - It reduces the cost and ambiguity of matching



Rectification

- Simple case
  - Cameras are parallel
  - Focal lengths are the same
  - Two image planes lie on the same plane

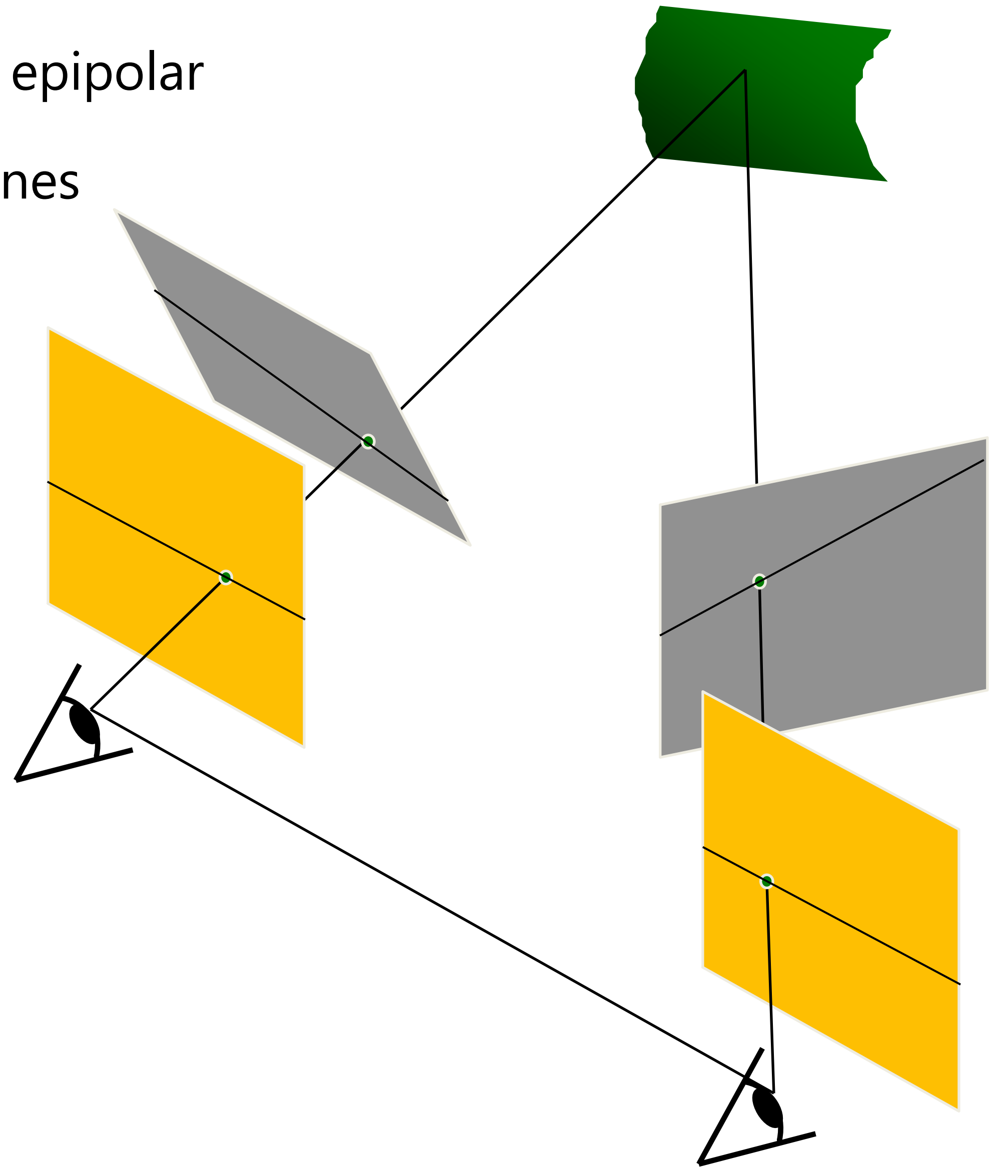
- Then, epipolar lines correspond to scan lines

- Rectification is a procedure to convert images so that the assumptions are satisfied
  - It simplifies algorithms
  - It improves efficiency

[KM Lee, Lecture Notes]

Rectification

- Reproject (warp) images so that epipolar lines are aligned with the scan lines



Rectification

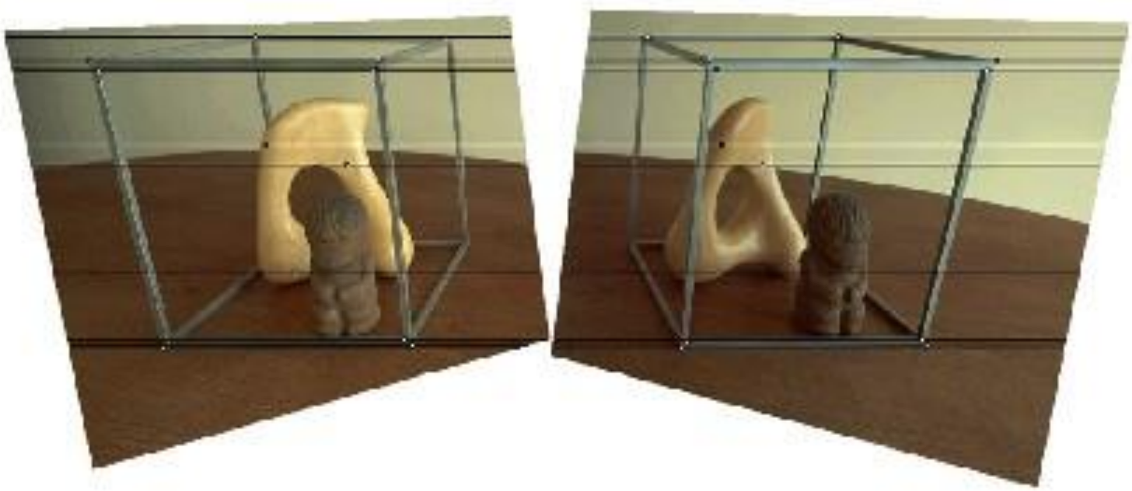
(a) Original image pair overlayed with several epipolar lines.

(b) Image pair transformed by the specialized projective mapping $\mathbf{H}_p$ and $\mathbf{H}'_p$. Note that the epipolar lines are now parallel to each other in each image.

[Loop and Zhang, CVPR'99]

Rectification

(c) Image pair transformed by the similarity $\mathbf{H}_r$ and $\mathbf{H}'_r$. Note that the image pair is now rectified (the epipolar lines are horizontally aligned).



(d) Final image rectification after shearing transform $\mathbf{H}_s$ and $\mathbf{H}'_s$. Note that the image pair remains rectified, but the horizontal distortion is reduced.

[Loop and Zhang, CVPR'99]

Correspondence: What to Match?

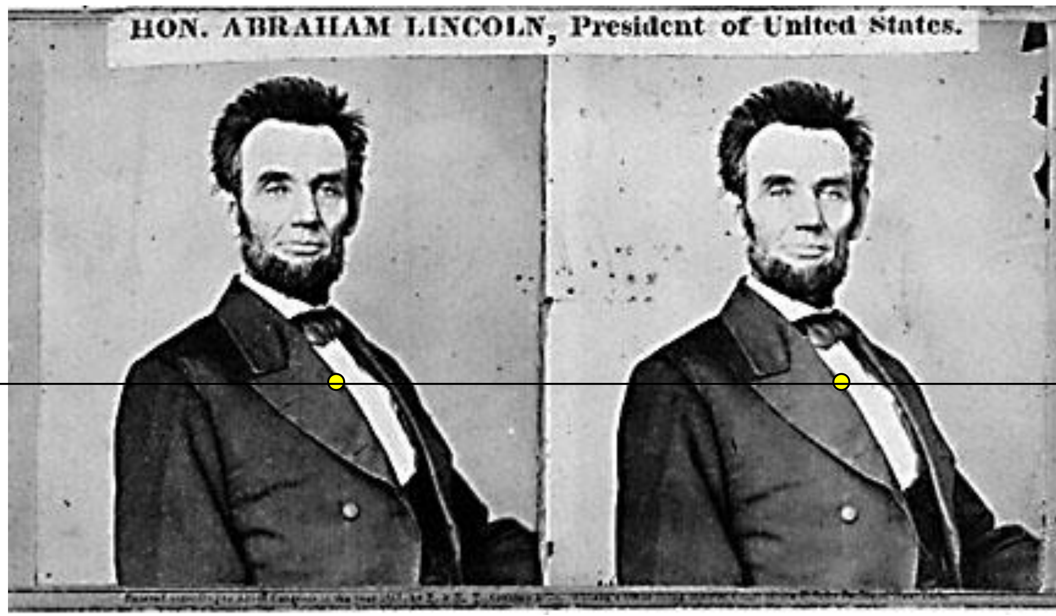
- Objects?
  - More identifiable, but difficult to compute
- Pixels?
  - Easier to handle, but maybe ambiguous
- Edges?
- Collections of pixels (regions)?

Correspondence: Photometric Constraint

- Assume that the same world point has the same intensity in both images.
  - However, it is not true in general
    - Noise
    - Illumination
    - Camera calibration

Pixel Matching

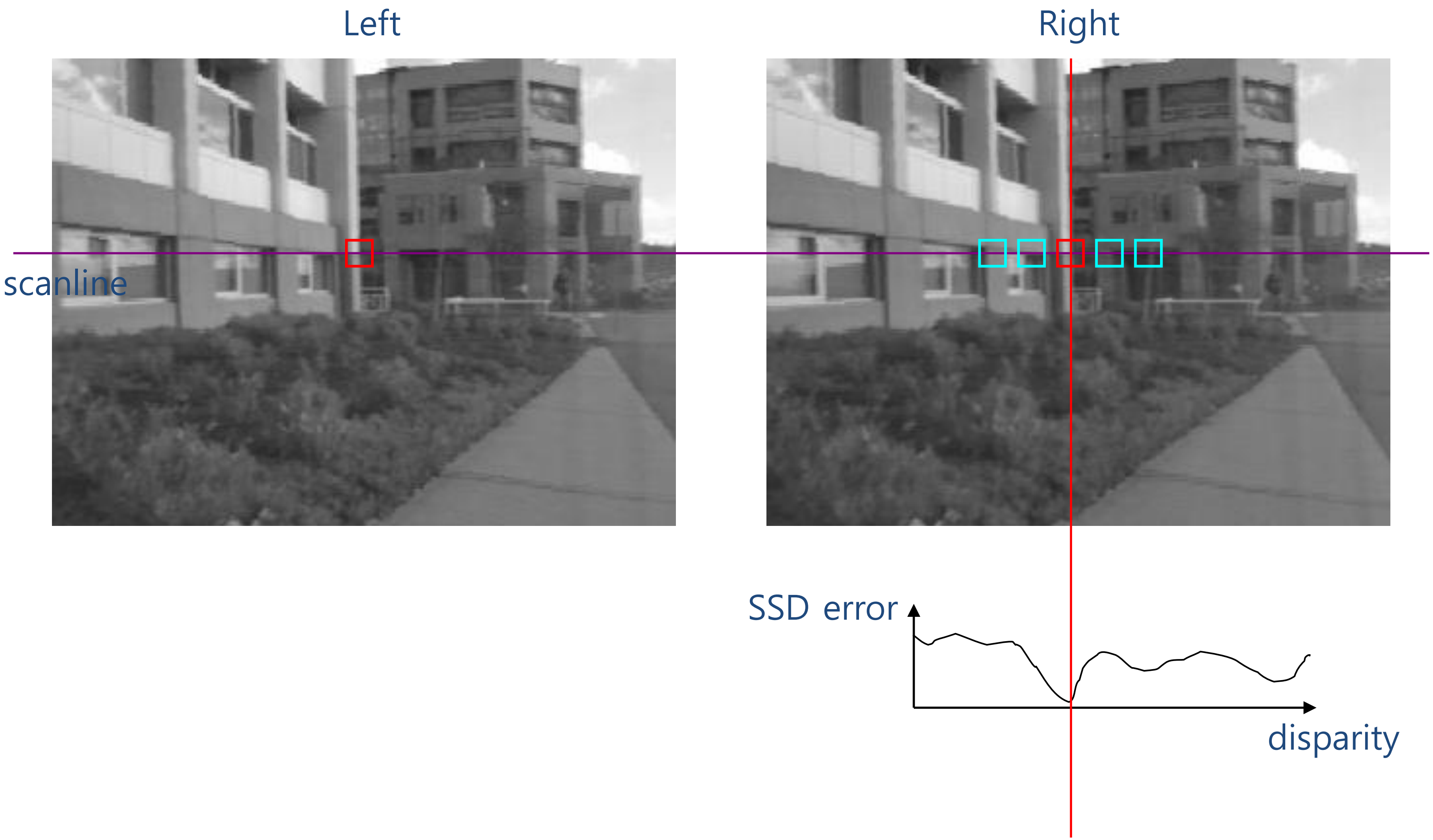
What if ?



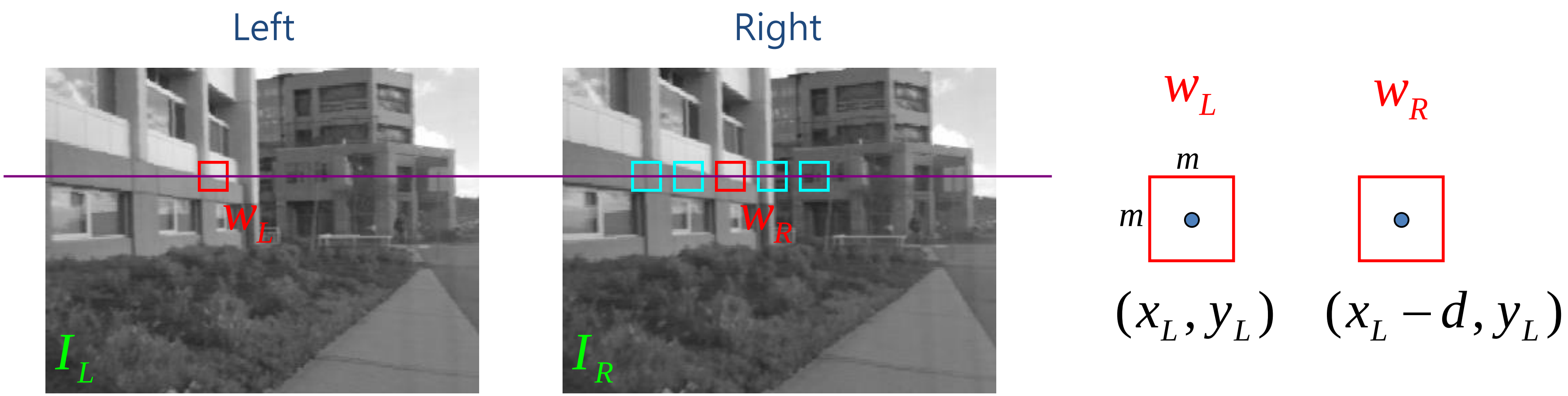
For each scanline , for each pixel in the left image

- compare with every pixel on same epipolar line in right image
- pick pixel with minimum match cost
- This will never work, so: **match windows**

Correspondence Using Window Matching



SSD



- Two blocks $\boldsymbol{w}_L$ and $\boldsymbol{w}_R$
- $SSD = \|\boldsymbol{w}_L - \boldsymbol{w}_R\|^2$

Normalization

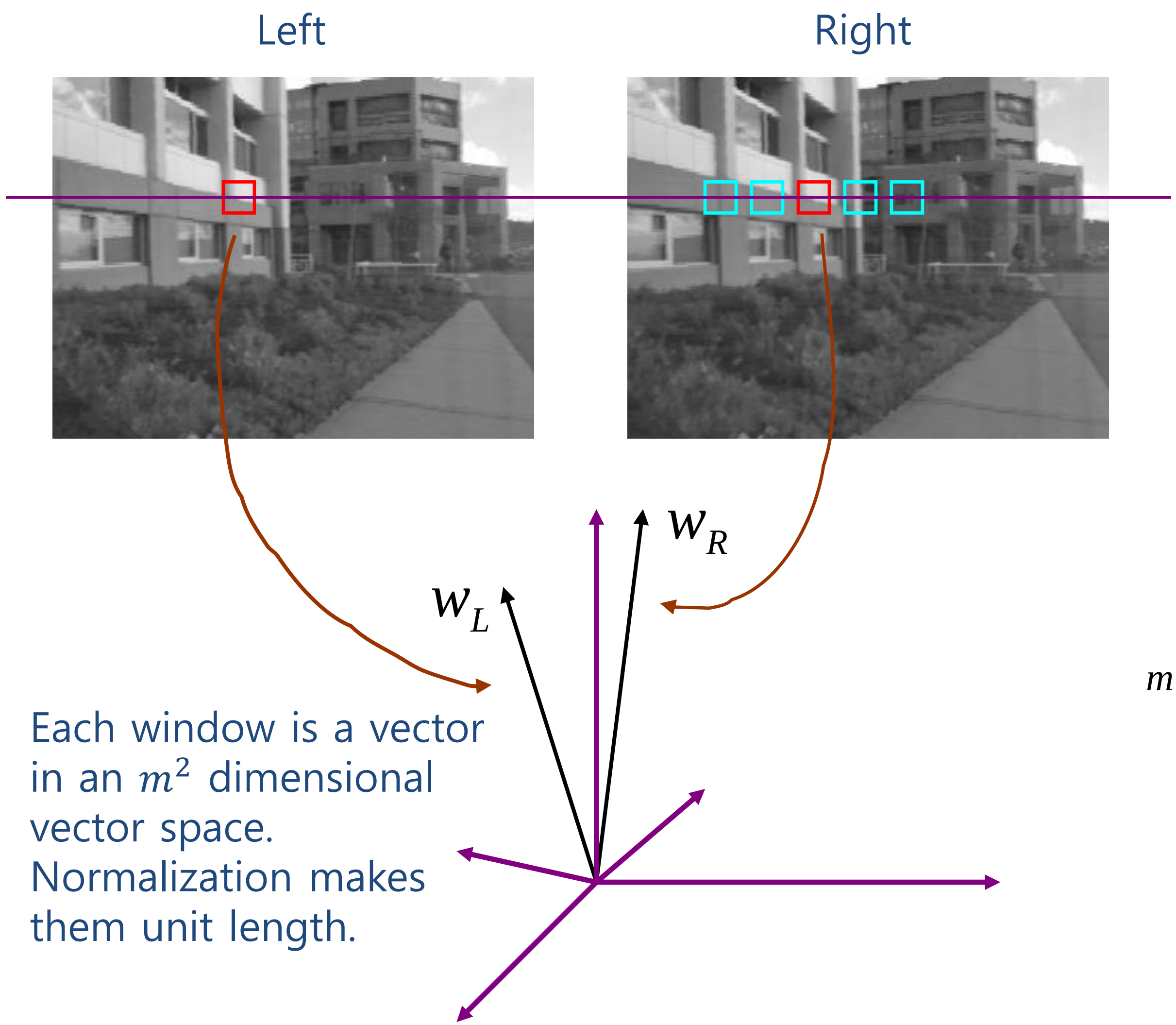
- There can be differences in gain and sensitivity
- Normalize the pixels in each window

$$\tilde{\boldsymbol{w}} = \frac{\boldsymbol{w} - \mu\mathbf{1}}{\|\boldsymbol{w} - \mu\mathbf{1}\|}$$

- Minimizing SSD becomes maximizing NCC (normalized cross correlation)

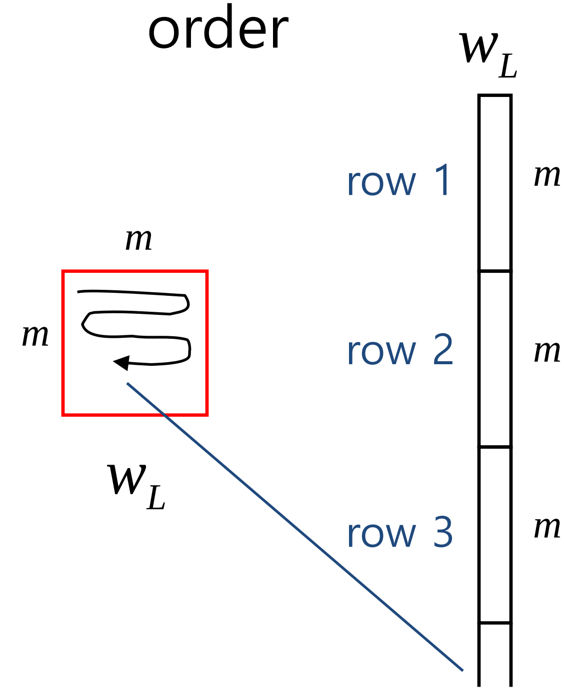
$$\|\tilde{\boldsymbol{w}}_L - \tilde{\boldsymbol{w}}_R\|^2 = 2 - 2\tilde{\boldsymbol{w}}_L \cdot \tilde{\boldsymbol{w}}_R$$

Normalization



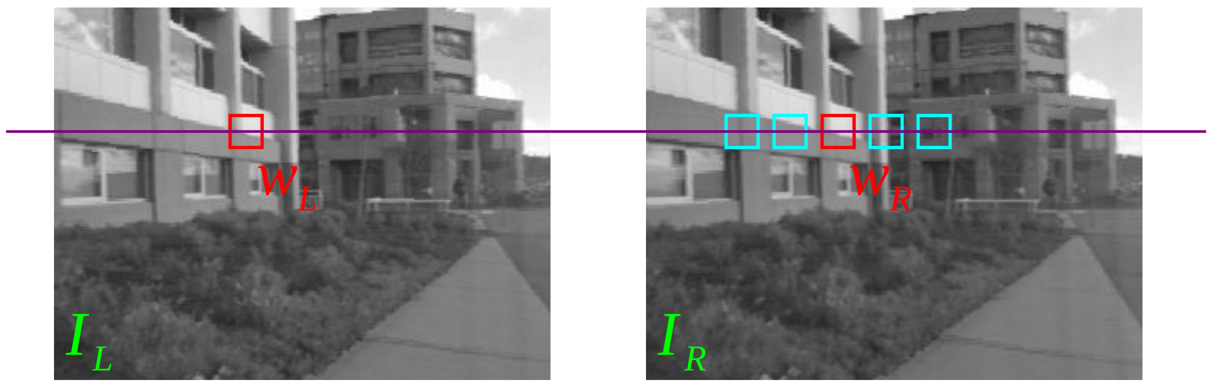
Each window is a vector in an m^2 dimensional vector space. Normalization makes them unit length.

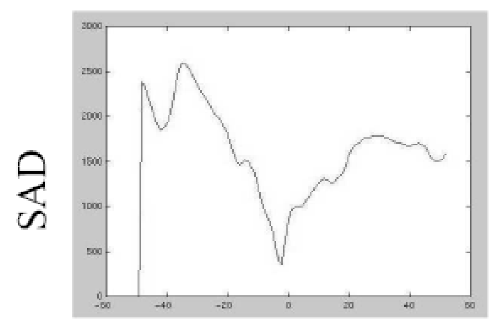
"Unwrap" image to form vector, using raster scan order

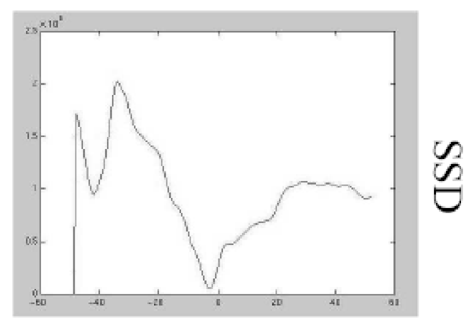


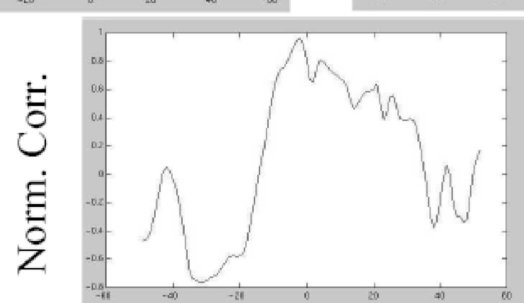
Distance Metrics

Left Right









Stereo Results

Images courtesy of Point Grey Research

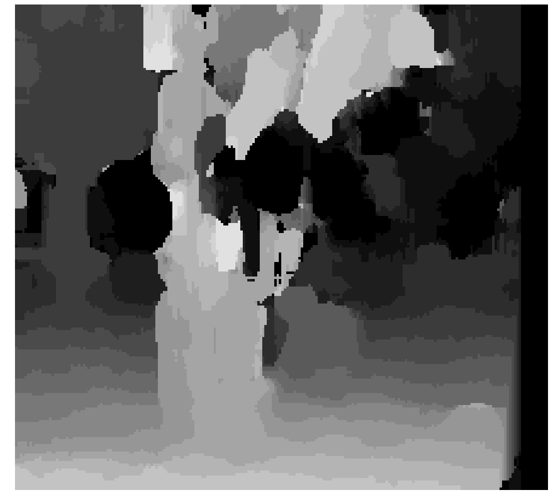
Disparity Map

Problems with Window-Based Matching

- Disparity within the window may not be constant
- Blur across depth discontinuities
- Poor performance in textureless regions
- Erroneous results in occluded regions

Window Size

W = 3



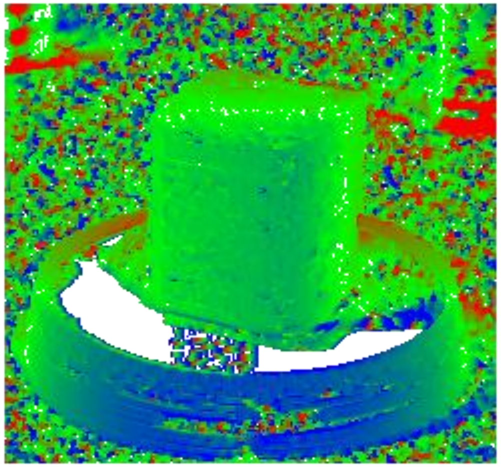
W = 20

- The results depend on the window size
- Some approaches have been developed to use an adaptive window size (try multiple sizes and select best match)

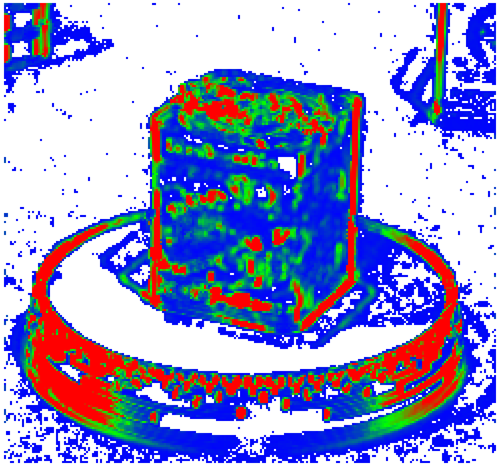
Certainty Modeling

- Compute certainty map from correlations

input



depth map



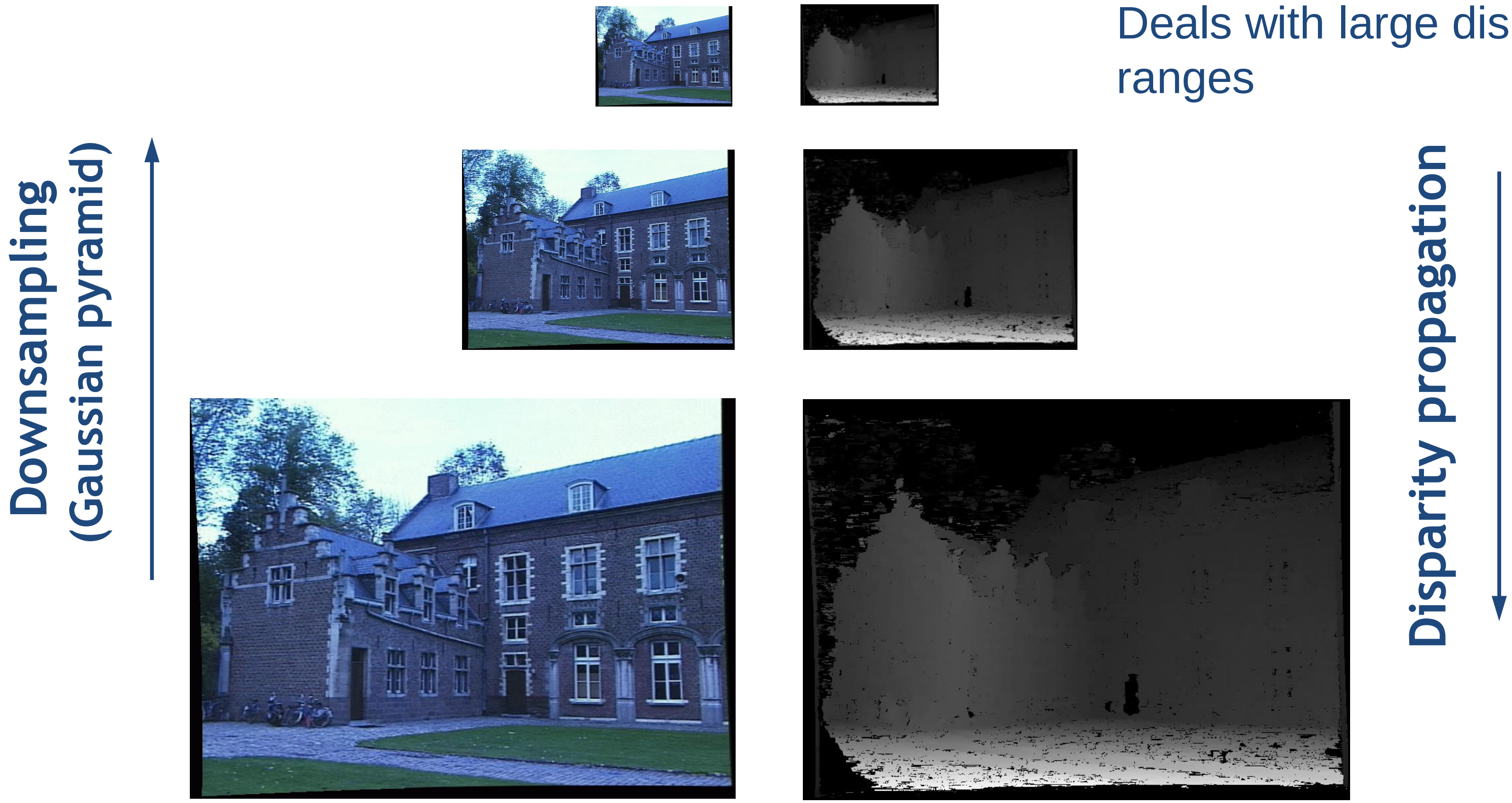
certainty map

[Szeliski, 1991]

Hierarchical Stereo Matching

Allows faster computation

Deals with large disparity ranges



(Falkenhagen´97;Van Meerbergen,Vergauwen,Pollefeys,VanGool IJCV'02)