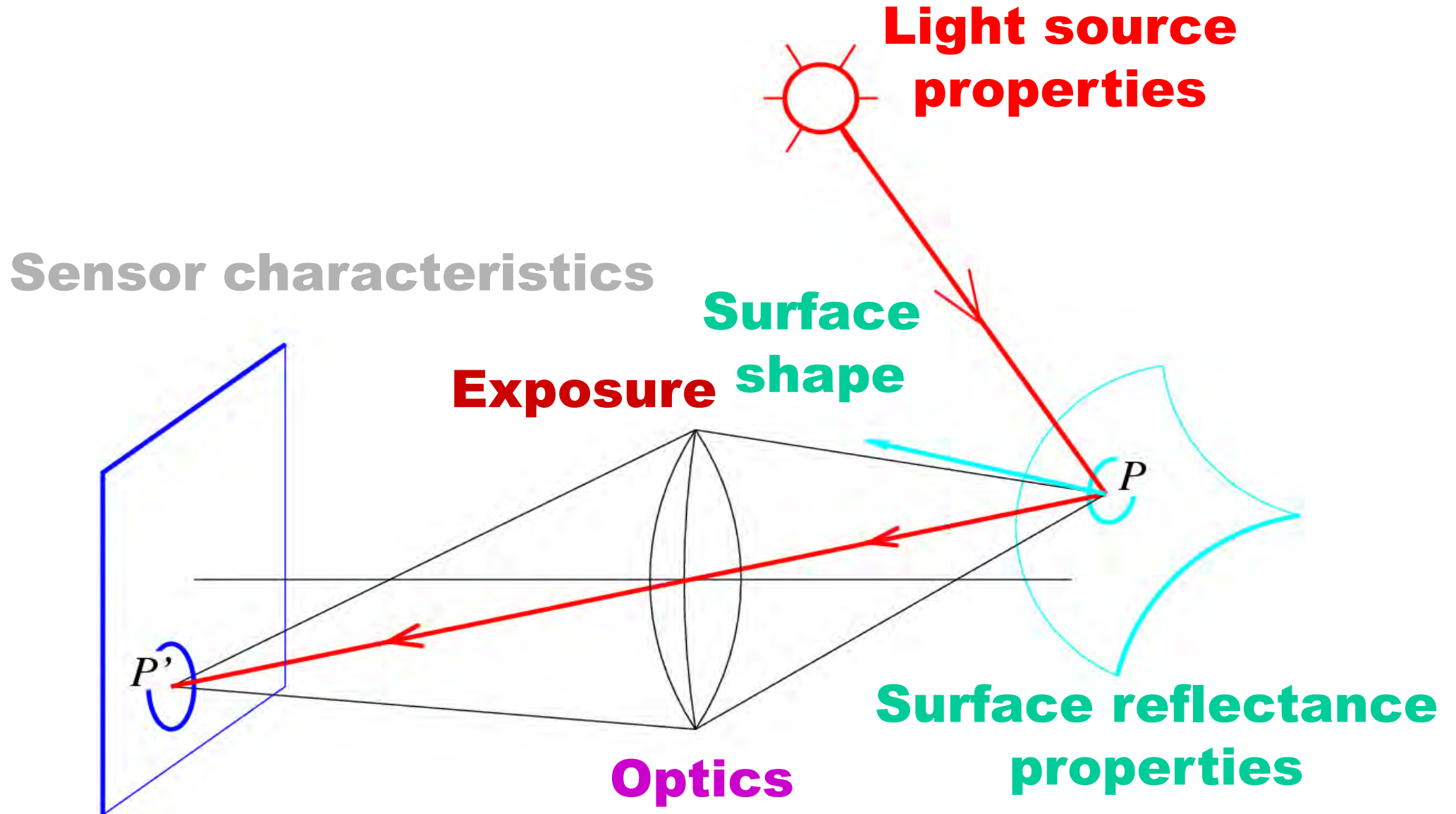
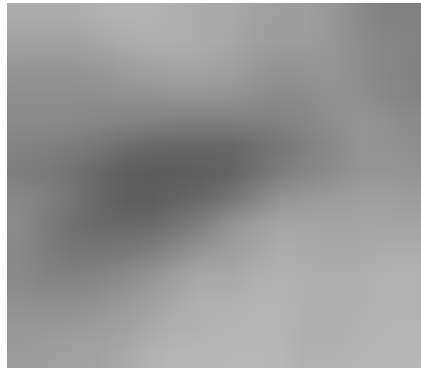


Image Formation



Analog Images

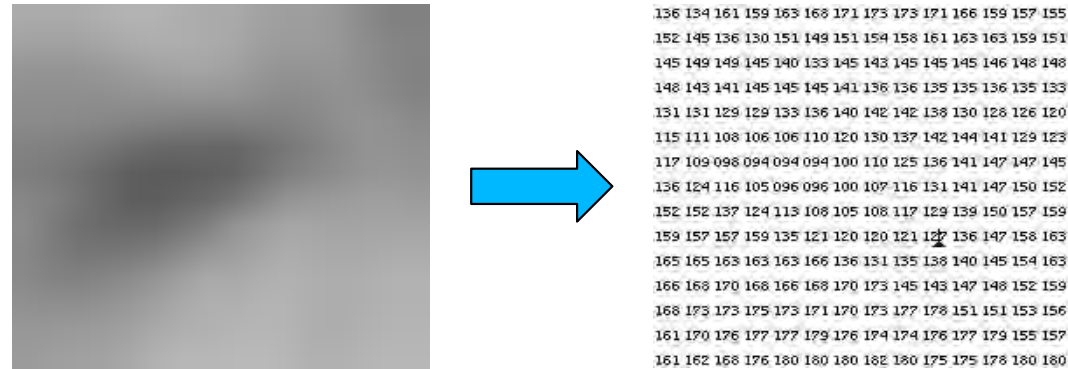


An image can be understood as a 2D light intensity function $f(x,y)$ where:

- x and y are spatial coordinates
- $f(x, y)$ is proportional to the brightness or gray value of the image at that point.

→ Cannot be stored as such on a digital computer.

Digital Images

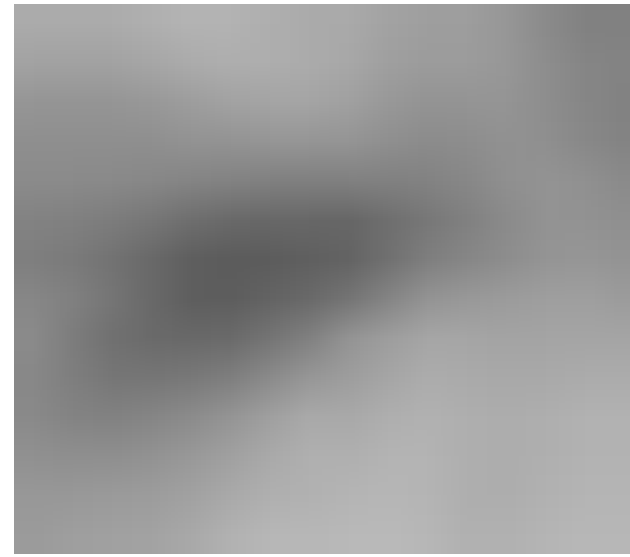


A digitized image is one in which:

- Spatial and grayscale values have been made discrete.
- Intensities measured across a regularly spaced grid in x and y directions are sampled to
 - 8 bits (256 values) per point for grayscale,
 - 3x8 bits per point for color images.

They are stored as two-dimensional arrays of gray-level values. The array elements are called pixels and identified by their x, y coordinates.

Black and White Images



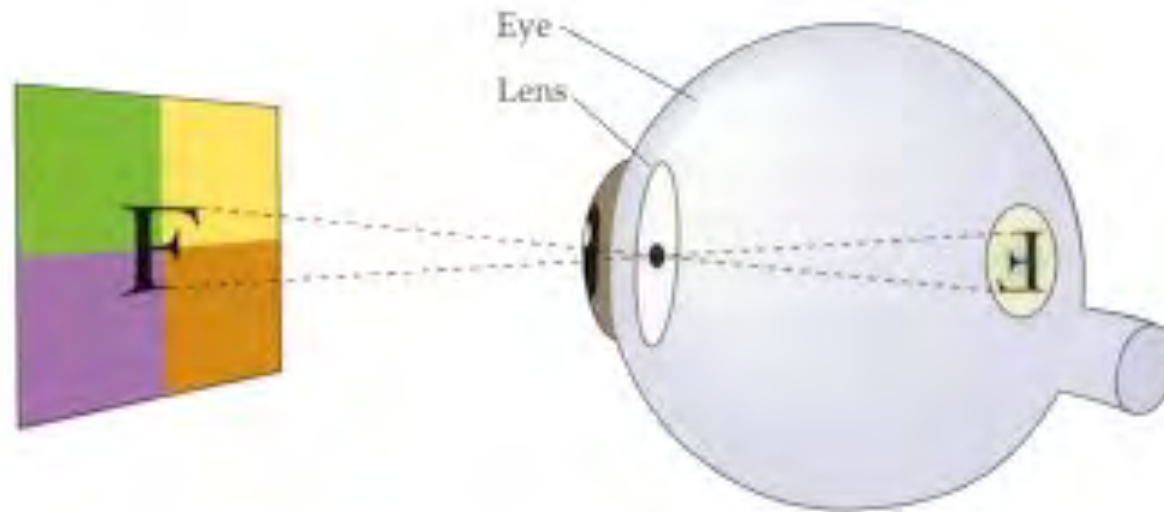
136 134 161 159 163 168 171 173 173 171 166 159 157 155
152 145 136 130 151 149 151 154 158 161 163 163 159 151
145 149 149 145 140 133 145 143 145 145 146 148 148
148 143 141 145 145 145 141 136 136 135 135 136 135 133
131 131 129 129 133 136 140 142 142 138 130 128 126 120
115 111 108 106 106 110 120 130 137 142 144 141 129 123
117 109 098 094 094 094 100 110 125 136 141 147 147 145
136 124 116 105 096 096 100 107 116 131 141 147 150 152
152 152 137 124 113 108 105 108 117 129 139 150 157 159
159 157 157 159 135 121 120 120 121 121 136 147 158 163
165 165 163 163 163 166 136 131 135 138 140 145 154 163
166 168 170 168 166 168 170 173 145 143 147 148 152 159
168 173 173 175 173 171 170 173 177 178 151 151 153 156
161 170 176 177 177 179 176 174 174 176 177 179 155 157
161 162 168 176 180 180 180 182 180 175 175 178 180 180

Color Images



A color image is often represented by three 8-bit images, one for red, one for green, and one for blue.

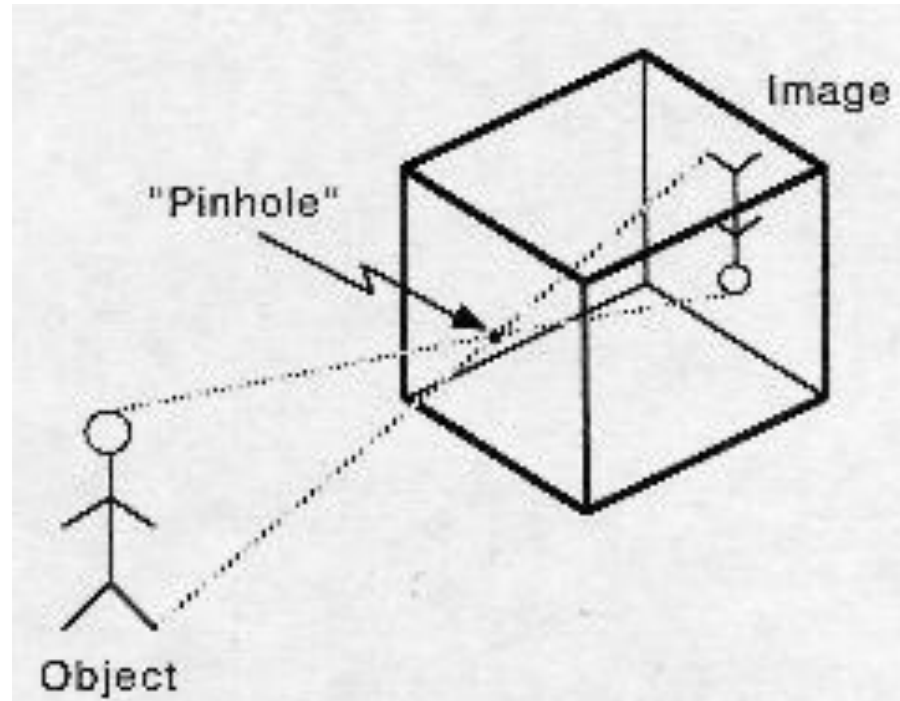
Image Formation



Projection from surfaces to 2-D sensor.

- Where: Geometry
- How bright: Radiometry
- Stored how: Sensing

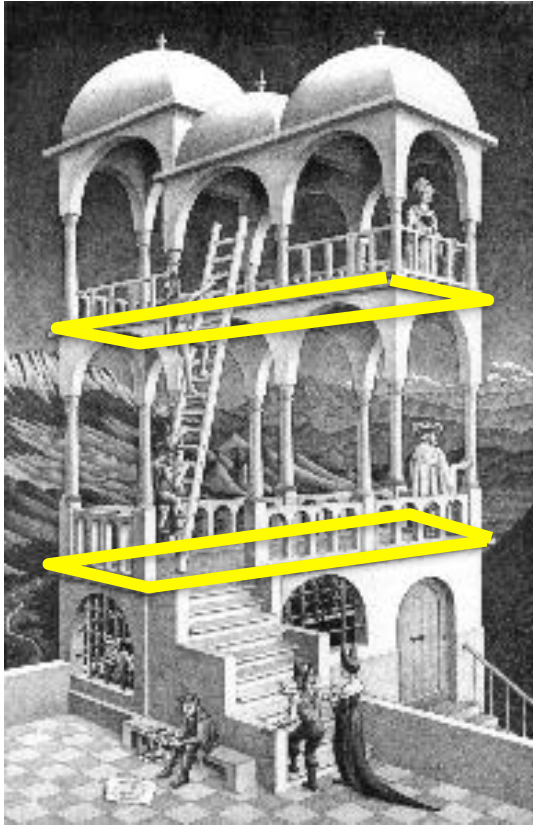
Pinhole Camera Model



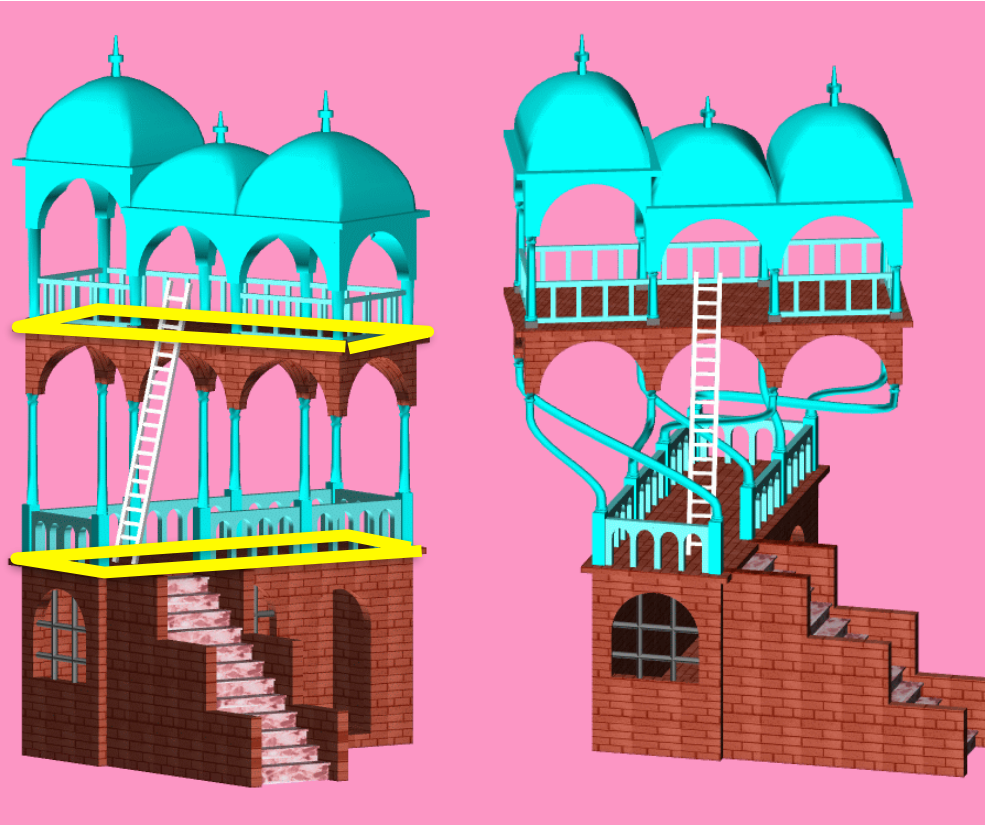
Idealized model of the perspective projection:

- All rays go through a hole and form a pencil of lines.
- The hole acts as a ray selector that allows an inverted image to form.

Escher's Belvedere



M. C. Escher



Impossible

Possible

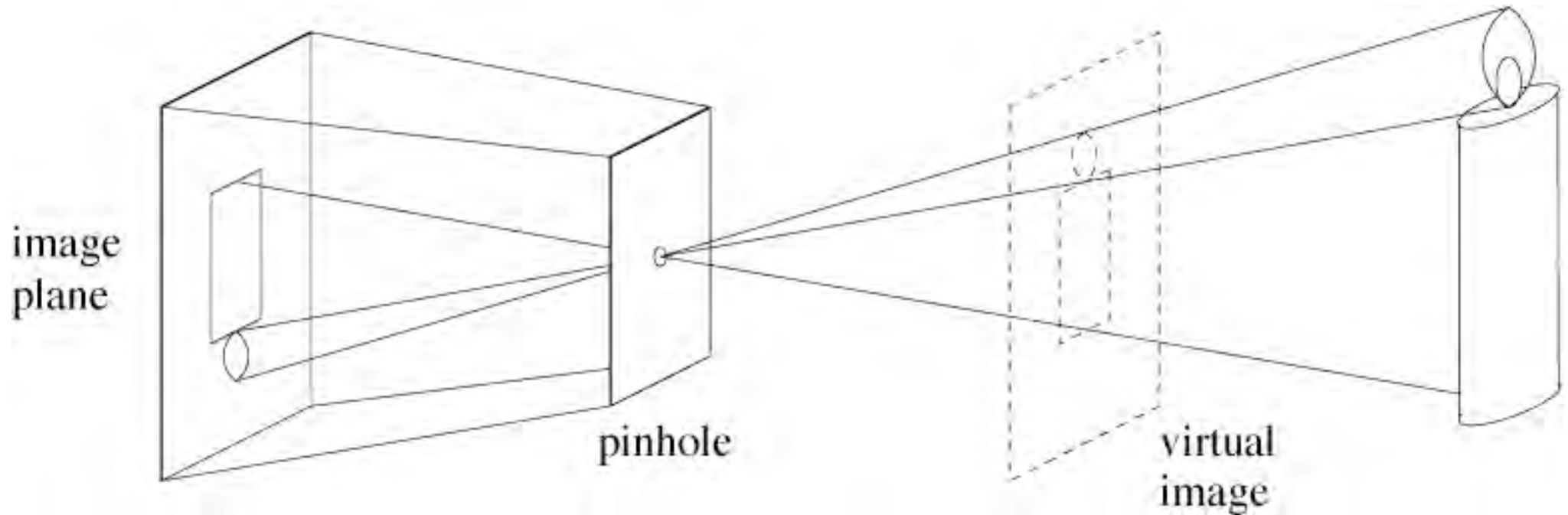


Done

Magnet Like Slopes

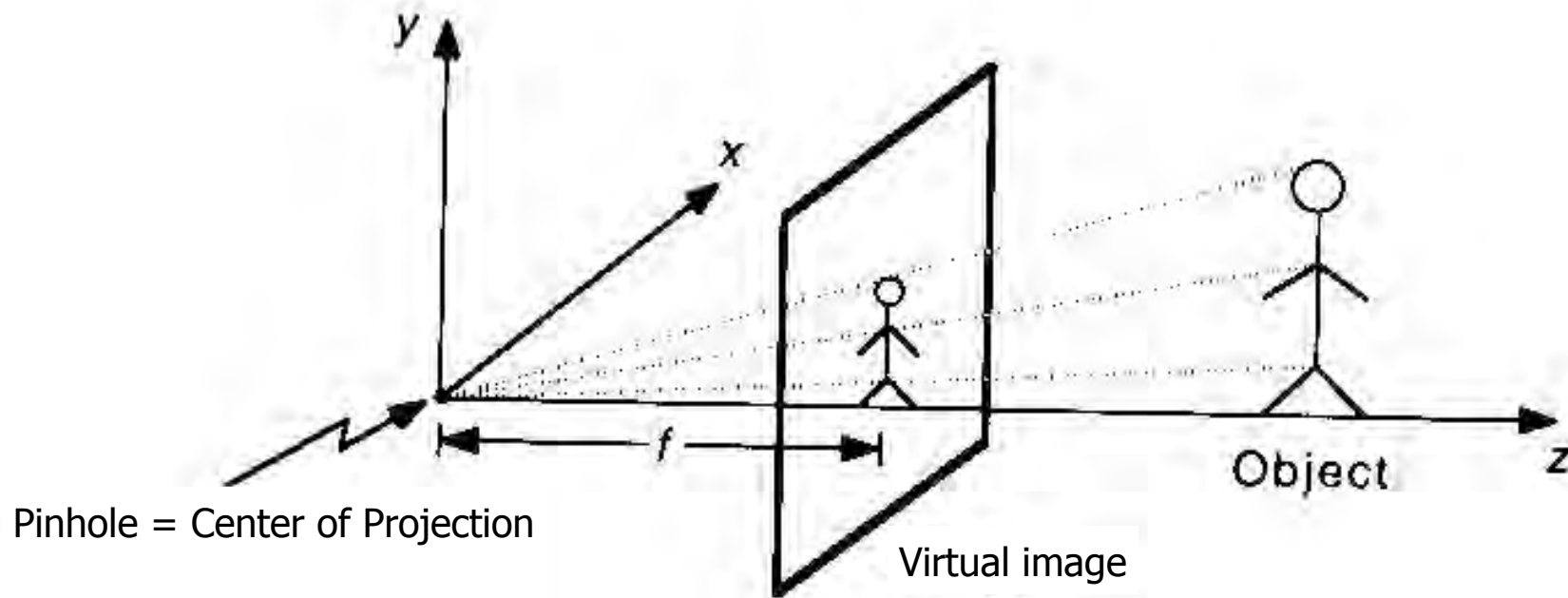


Virtual Image



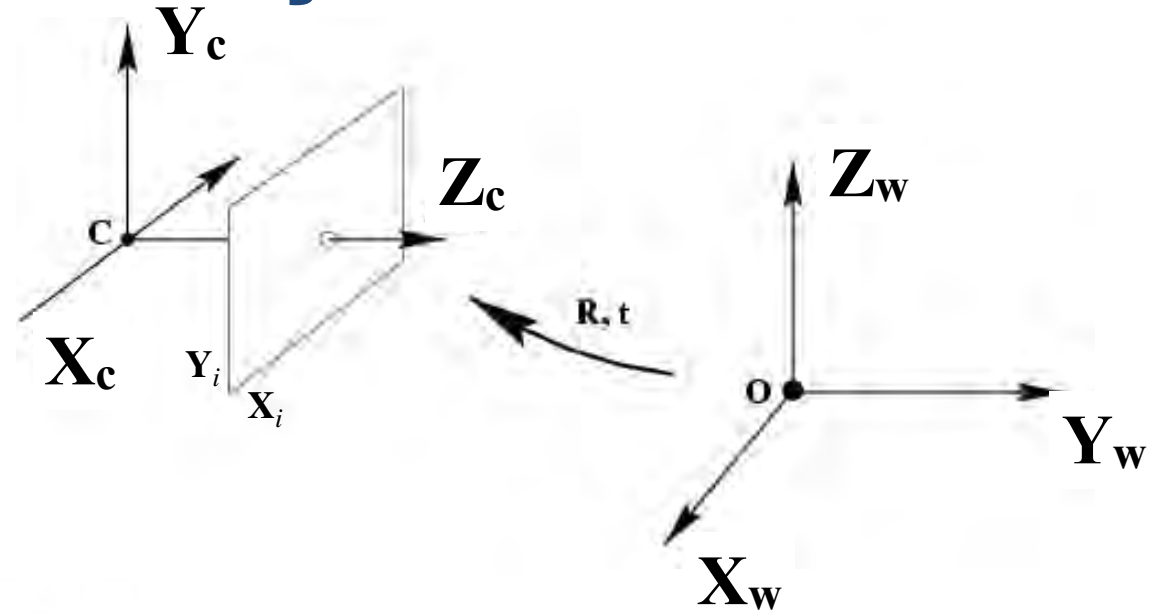
- The real image forms on the image plane and is inverted.
 - Let us consider a virtual plane in front of the camera.
 - On this plane, we have a virtual non-inverted image.
- > It is simpler to reason in terms of that virtual image.

Camera Geometry



From now on, we will use this formalism.

Coordinate Systems



Camera Coordinate System:

$$(X_c, Y_c, Z_c)$$

Image Coordinate System:

$$(X_i, Y_i, Z_i)$$

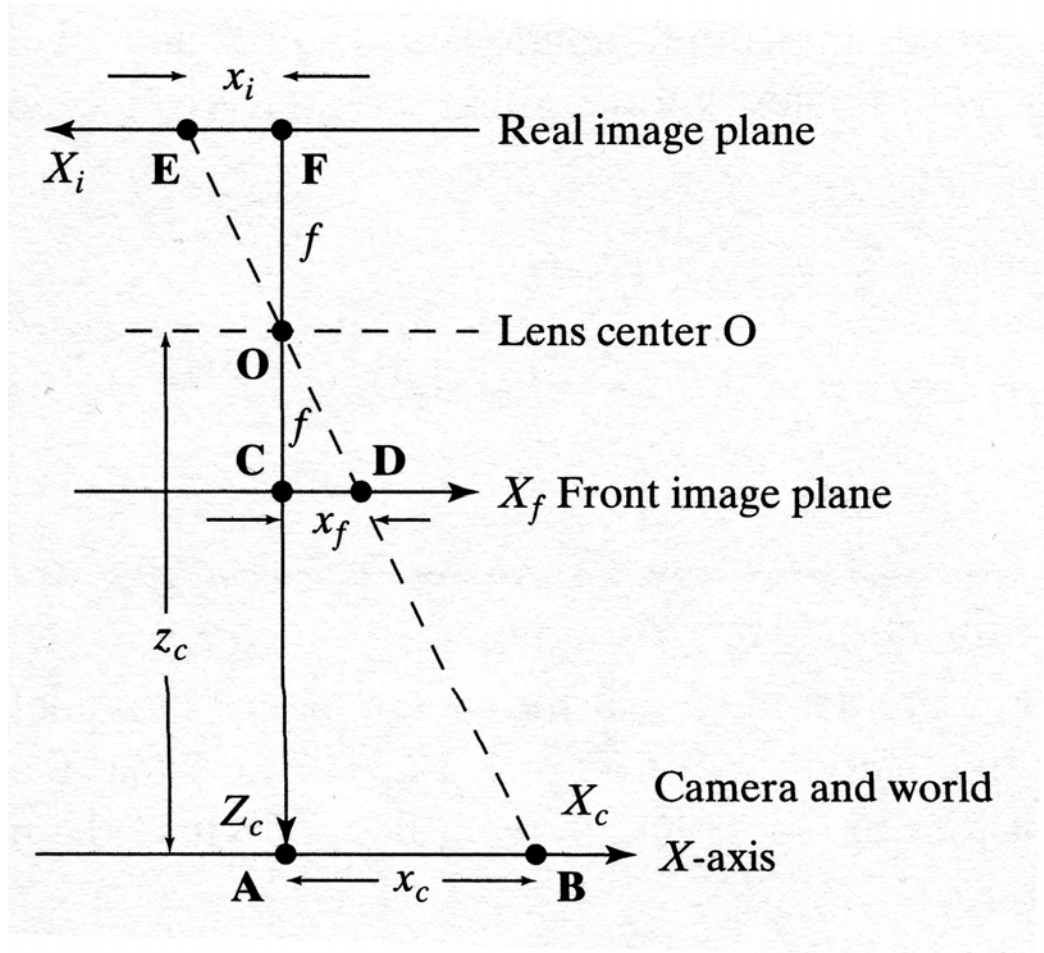
World Coordinate System:

$$(X_w, Y_w, Z_w)$$

Camera Coordinate System

- The center of the projection coincides with the origin of the world.
- The camera axis (optical axis) is aligned with the world's z-axis.
- To avoid image inversion, the image plane is in front of the center of projection.

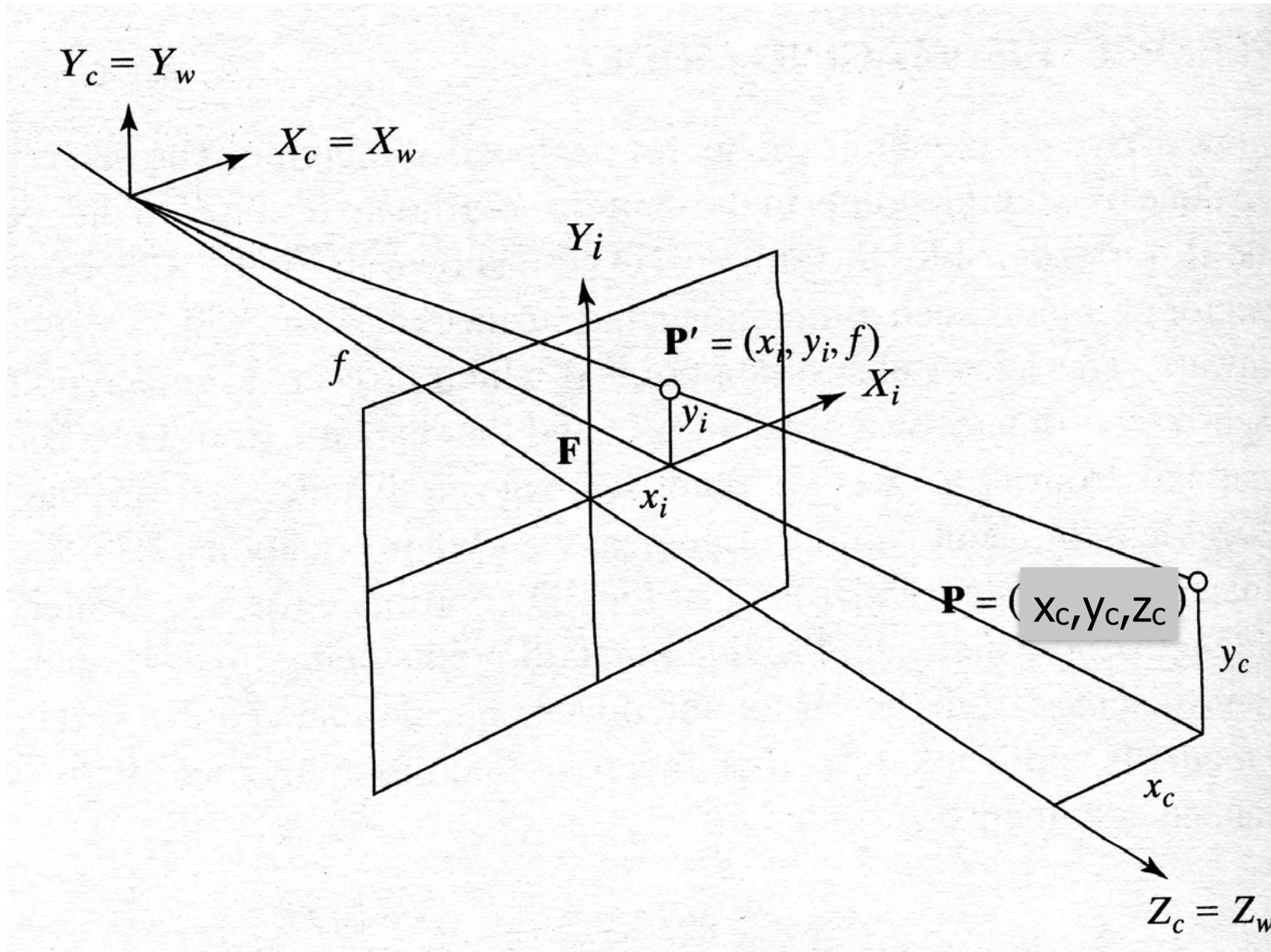
1D Image



$$\frac{x_f}{f} = \frac{x_c}{z_c}$$

$$\Rightarrow x_i = x_f = f \frac{x_c}{z_c}$$

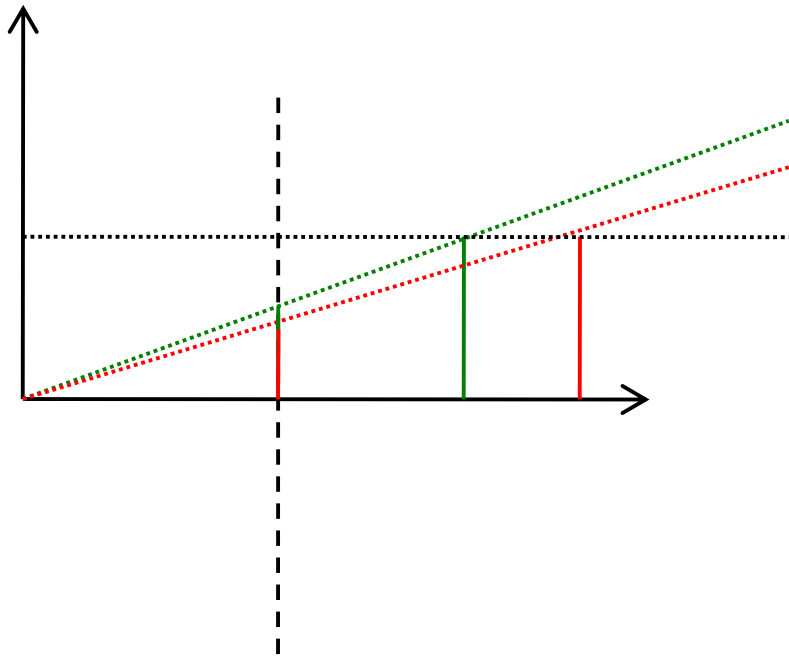
2D Image



$$x_i = f \frac{x_c}{z_c}$$
$$y_i = f \frac{y_c}{z_c}$$

We dropped the distinction between (x_f, y_f) and (x_i, y_i) .

Distant Objects Appear Smaller

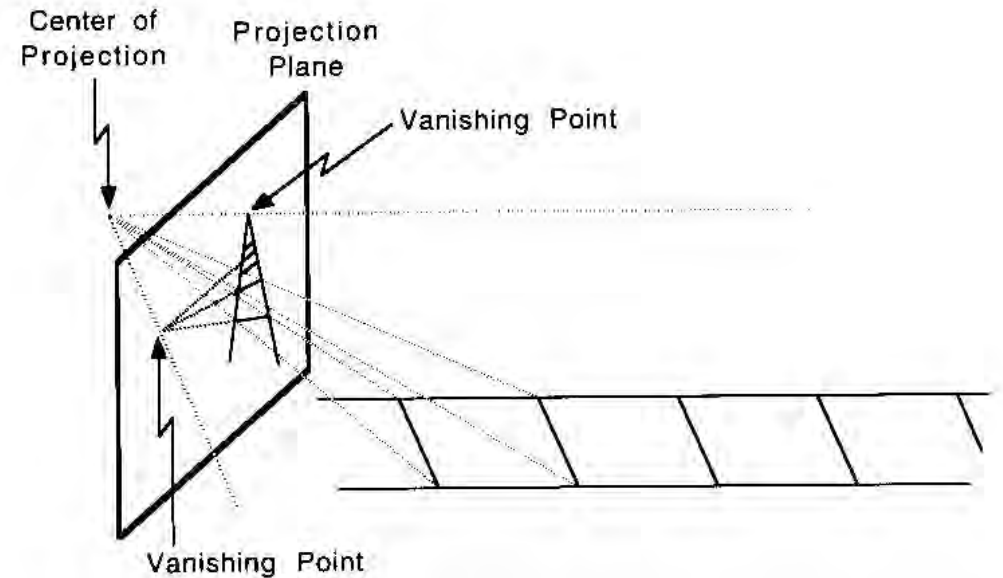


The green and red objects are of the same size but the red one is farther and therefore its projection smaller.



Because the car at the back has the same size in projection, we perceive it as being larger.

Projected Parallel Lines Meet



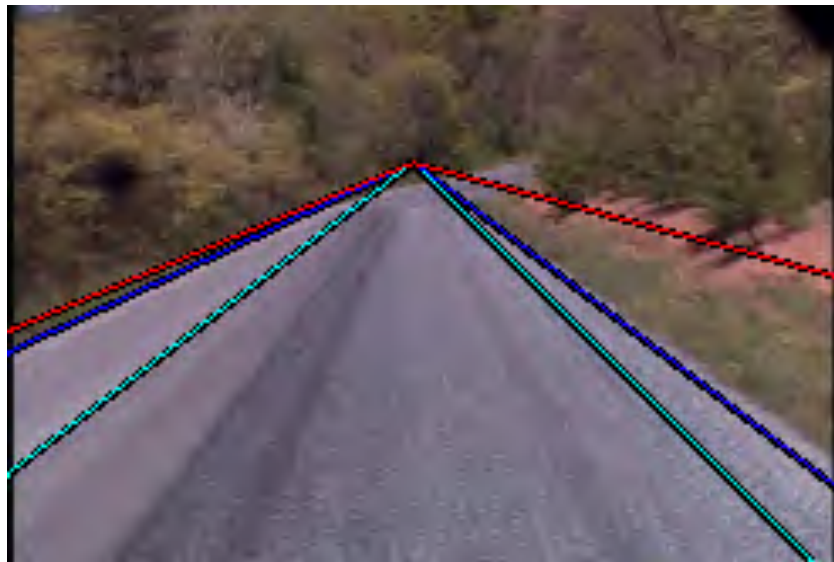
- Their intersection is referred to as the vanishing point.
- There is one per set of parallel 3D lines with the same direction vector.

Vanishing Points



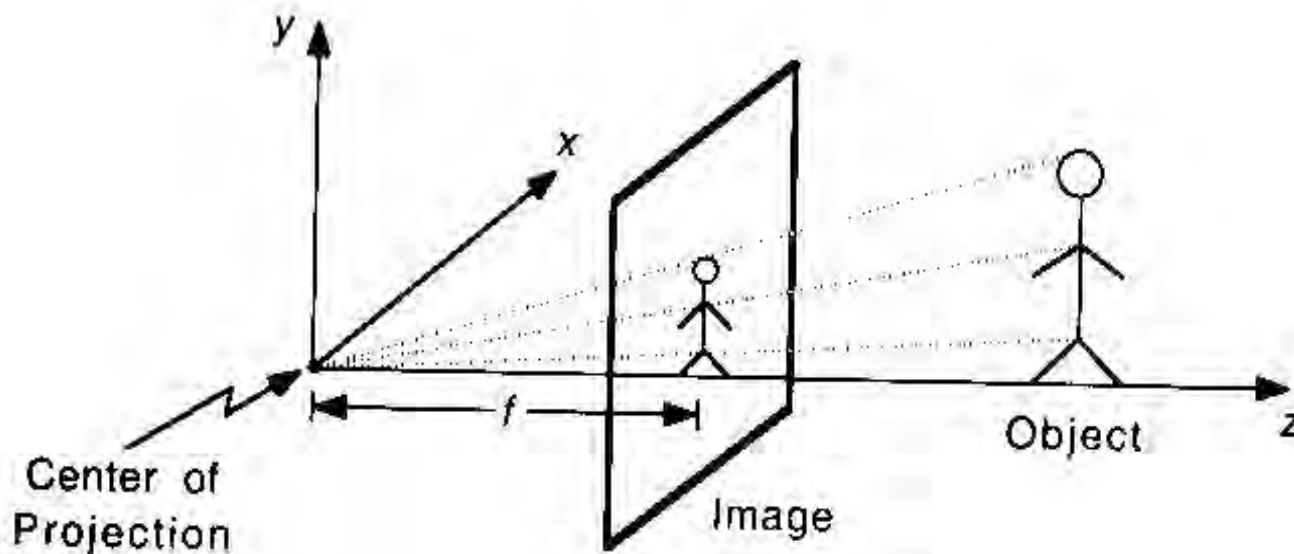
- The projections of parallel lines all meet at one point, called the vanishing point.
- As the focal length increases, the vanishing point moves towards infinity.

Road Following



The vanishing point can be computed and used to direct an autonomous car.

Projection is Non Linear



In pixels

$$u \propto x_i = f \frac{x_c}{z_c}$$

$$v \propto y_i = f \frac{y_c}{z_c}$$

In meters

→ Reformulate it as a linear operation using homogeneous coordinates.

Homogeneous Coordinates

- Homogeneous representation of 2D point:

$$\mathbf{x} = (x_1, x_2, x_3) \text{ represents } (x_1/x_3, x_2/x_3)$$

- Homogeneous representation of 3D point:

$$\mathbf{X} = (x_1, x_2, x_3, x_4) \text{ represents } (x_1/x_4, x_2/x_4, x_3/x_4)$$

- Scale invariance:

\mathbf{X} and $\lambda\mathbf{X}$ represent the same point, same for \mathbf{x} and $\lambda\mathbf{x}$.

Simple Projection Matrix

2D point expressed in projective coordinates.

3D point expressed in projective coordinates.

Let us write:

$$\begin{bmatrix} x \\ y \\ z \end{bmatrix} = \begin{bmatrix} f & 0 & 0 & 0 \\ 0 & f & 0 & 0 \\ 0 & 0 & 1 & 0 \end{bmatrix} \begin{bmatrix} X_c \\ Y_c \\ Z_c \\ 1 \end{bmatrix}$$
$$= \begin{bmatrix} f & 0 & 0 \\ 0 & f & 0 \\ 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} 1 & 0 & 0 & 0 \\ 0 & 1 & 0 & 0 \\ 0 & 0 & 1 & 0 \end{bmatrix} \begin{bmatrix} X_c \\ Y_c \\ Z_c \\ 1 \end{bmatrix}$$

- $[x, y, z]^T$ represents

$$X_i = \frac{x}{z} = f \frac{X_c}{Z_c}$$

$$Y_i = \frac{y}{z} = f \frac{Y_c}{Z_c}$$

- Therefore $[x, y, z]^T$ is the projection of $[X_c, Y_c, Z_c, 1]^T$.

—> We have expressed the projection of a 3D point as the multiplication of its projective coordinates by a projection matrix.

Intrinsic And Extrinsic Parameters

$$\begin{bmatrix} x \\ y \\ z \end{bmatrix} = \begin{bmatrix} \text{Matrix of} \\ \text{intrinsic parameters} \end{bmatrix} \begin{bmatrix} 1 & 0 & 0 & 0 \\ 0 & 1 & 0 & 0 \\ 0 & 0 & 1 & 0 \end{bmatrix} \begin{bmatrix} \text{Matrix of} \\ \text{extrinsic parameters} \end{bmatrix} \begin{bmatrix} X \\ Y \\ Z \\ 1 \end{bmatrix}$$

- Camera may not be at the origin, looking down the z-axis
 - Extrinsic parameters
- One unit in image coordinates may not be the same as one unit in world coordinates
 - Intrinsic parameters

Complete Linear Camera Model

2D point expressed in projective coordinates and in pixels.

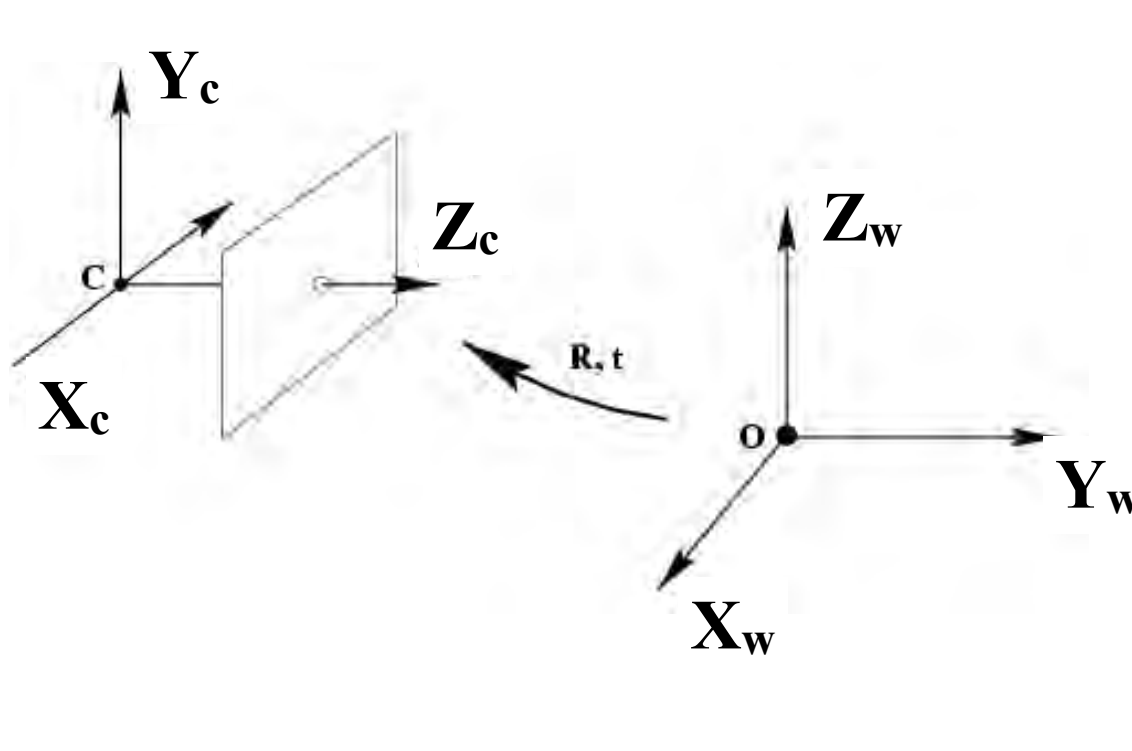
$$\begin{bmatrix} x \\ y \\ z \end{bmatrix} = \begin{bmatrix} \text{Matrix of} \\ \text{intrinsic parameters} \end{bmatrix} \begin{bmatrix} 1 & 0 & 0 & 0 \\ 0 & 1 & 0 & 0 \\ 0 & 0 & 1 & 0 \end{bmatrix} \begin{bmatrix} \text{Matrix of} \\ \text{extrinsic parameters} \end{bmatrix} \begin{bmatrix} X \\ Y \\ Z \\ 1 \end{bmatrix}$$
$$= \mathbf{K} \begin{bmatrix} 1 & 0 & 0 & 0 \\ 0 & 1 & 0 & 0 \\ 0 & 0 & 1 & 0 \end{bmatrix} \mathbf{Rt} \begin{bmatrix} X \\ Y \\ Z \\ 1 \end{bmatrix}$$

where \mathbf{K} is a 3×3 matrix and \mathbf{Rt} a 4×4 matrix.

3D point expressed in projective coordinates using the world coordinate system.

Matrix of Extrinsic Parameters

It converts world coordinates into camera coordinates:



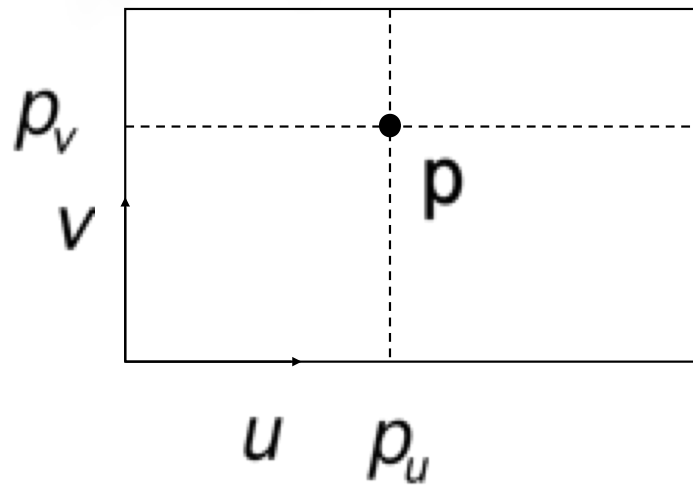
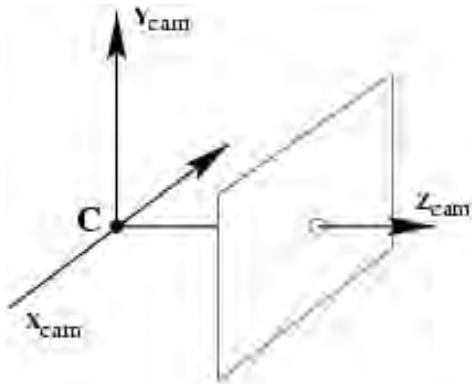
$$\begin{bmatrix} X_c \\ Y_c \\ Z_c \end{bmatrix} = \mathbf{R} \left(\begin{bmatrix} X_w \\ Y_w \\ Z_w \end{bmatrix} - \tilde{\mathbf{C}} \right) \text{ with } \mathbf{R}^t \mathbf{R} = \mathbf{I}$$

$$\begin{bmatrix} X_c \\ Y_c \\ Z_c \\ 1 \end{bmatrix} = \begin{bmatrix} \mathbf{R} & \mathbf{T} \\ 0 & 1 \end{bmatrix} \begin{bmatrix} X_w \\ Y_w \\ Z_w \\ 1 \end{bmatrix} \text{ with } \mathbf{T} = -\mathbf{R}\tilde{\mathbf{C}}$$

→ Rotations and translations also expressed in terms of matrix multiplications in projective space.

Matrix of Intrinsic Parameters

It converts image coordinates into pixels:



$$u = X_i + p_u = fX/Z + p_u$$

$$v = Y_i + p_v = fY/Z + p_v$$

$$\mathbf{K} = \begin{bmatrix} f & 0 & p_u \\ 0 & f & p_v \\ 0 & 0 & 1 \end{bmatrix}$$

Matrix of Intrinsic Parameters

It converts image coordinates into pixels:

$$u = \alpha_u X_i + p_u = \alpha_u X/Z + p_u$$

$$v = \alpha_v Y_i + p_v = \alpha_v Y/Z + p_v$$

$$\mathbf{K} = \begin{bmatrix} \alpha_u & 0 & p_u \\ 0 & \alpha_v & p_v \\ 0 & 0 & 1 \end{bmatrix}$$

The pixels are not necessarily square, must account for different scaling in x and y.

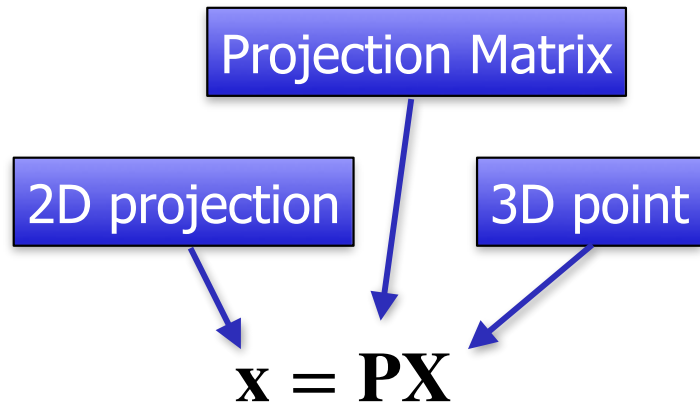
Matrix of Intrinsic Parameters

It converts image coordinates into pixels:

$$\mathbf{K} = \begin{bmatrix} \alpha_u & s & p_u \\ 0 & \alpha_v & p_v \\ 0 & 0 & 1 \end{bmatrix}$$

s encodes the non-orthogonality of the u and v directions. It is very close to zero in modern cameras.

Putting it All Together



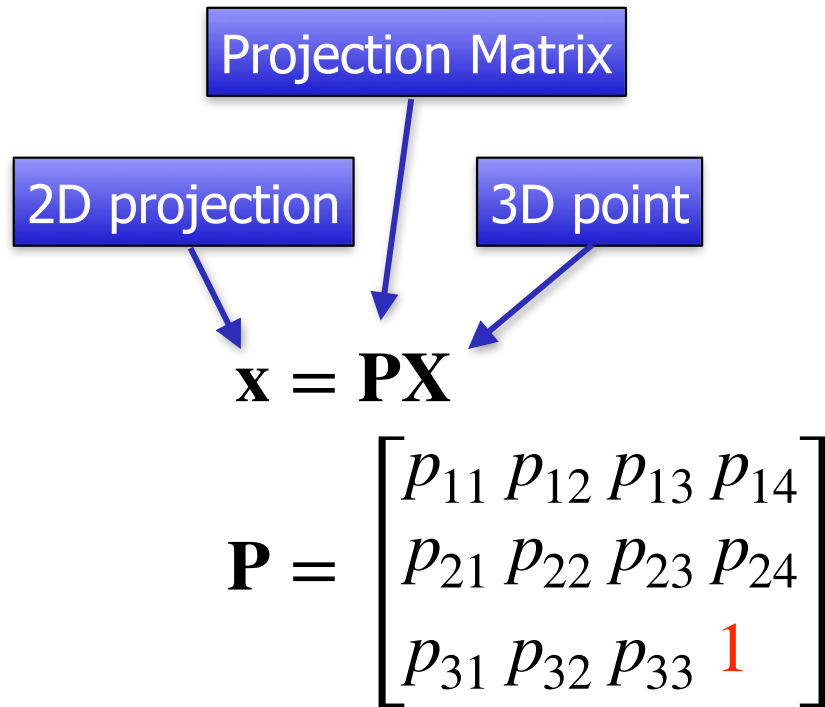
$$\mathbf{P} = \mathbf{K} \begin{bmatrix} 1 & 0 & 0 & 0 \\ 0 & 1 & 0 & 0 \\ 0 & 0 & 1 & 0 \end{bmatrix} \mathbf{Rt}$$

$$\text{with } \mathbf{K} = \begin{bmatrix} \alpha_u & s & p_u \\ 0 & \alpha_v & p_v \\ 0 & 0 & 1 \end{bmatrix}, \mathbf{Rt} = \begin{bmatrix} \mathbf{R} & \mathbf{T} \\ \mathbf{0} & 1 \end{bmatrix}, \text{ and } \mathbf{R}^T \mathbf{R} = \mathbf{I}.$$

Intrinsics

Extrinsics

Another Way to Write the Projection Matrix



- In projective geometry, $\lambda \mathbf{x} = \mathbf{x}$. Therefore the matrix \mathbf{P} can always be rescaled so that its last element is one.
- The 3x4 matrix \mathbf{P} has 11 degrees of freedom.

Camera Calibration

Internal Parameters:

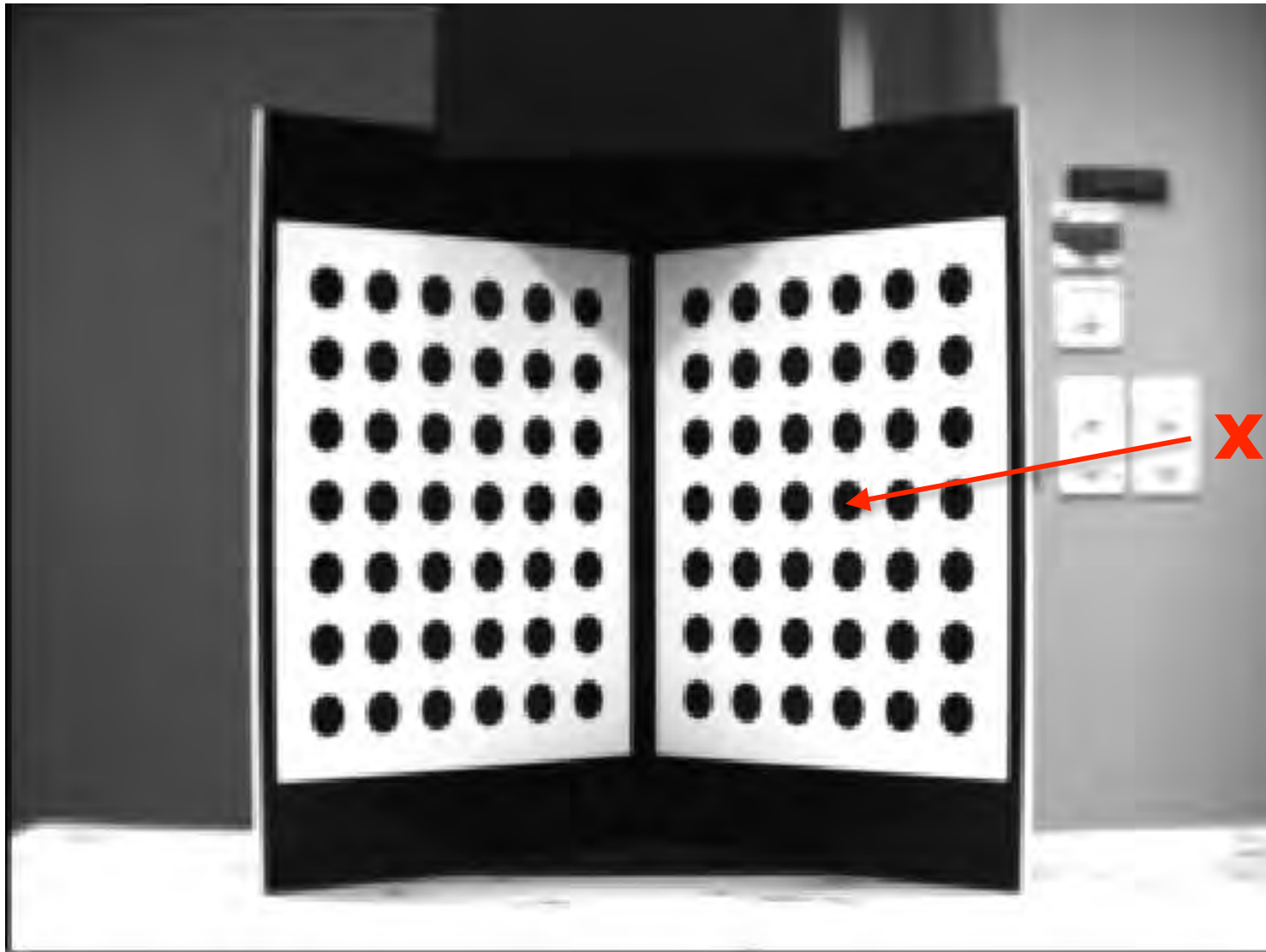
- Horizontal and vertical scaling (2)
- Principal points (2)
- Skew of the axis (1)

External Parameters:

- Rotations (3)
- Translations (3)

→ There are 11 free parameters to estimate. This is known as **calibrating** the camera.

Calibration Grid



$$x_i = PX_i$$

One way to calibrate: Take a picture of a calibration grid.

Estimating the Camera Parameters

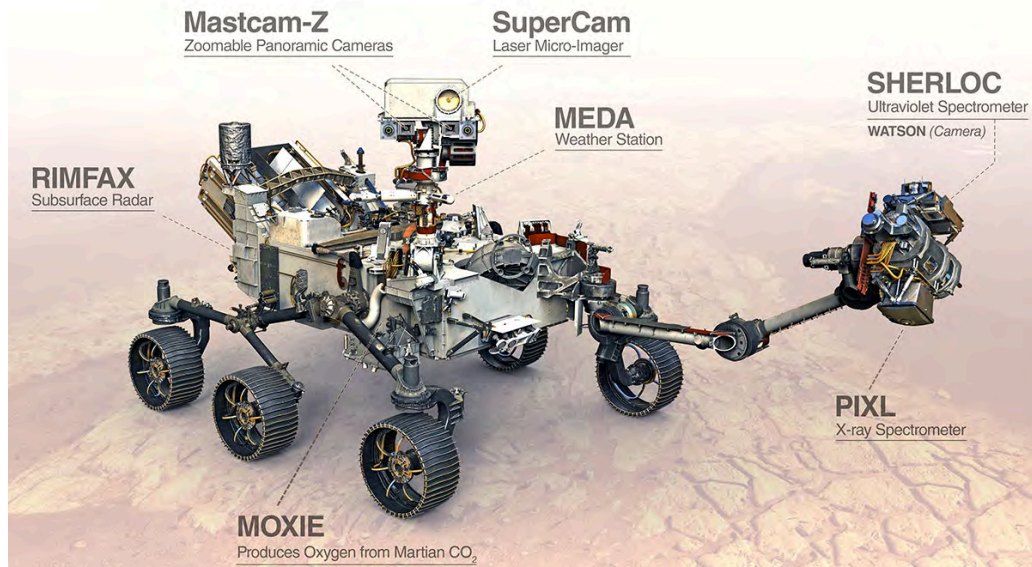
- Number of measurements required:
 - 11 degrees of freedom.
 - 2 constraints per correspondence.
- Direct linear transform:
 - Minimal solution for 6 correspondences
 - Over-constrained solutions by imposing

For all i , $\mathbf{x}_i = \mathbf{P}\mathbf{X}_i$, with $\|\mathbf{P}\| = 1$ or $P_{34} = 1$

- Non linear optimization.

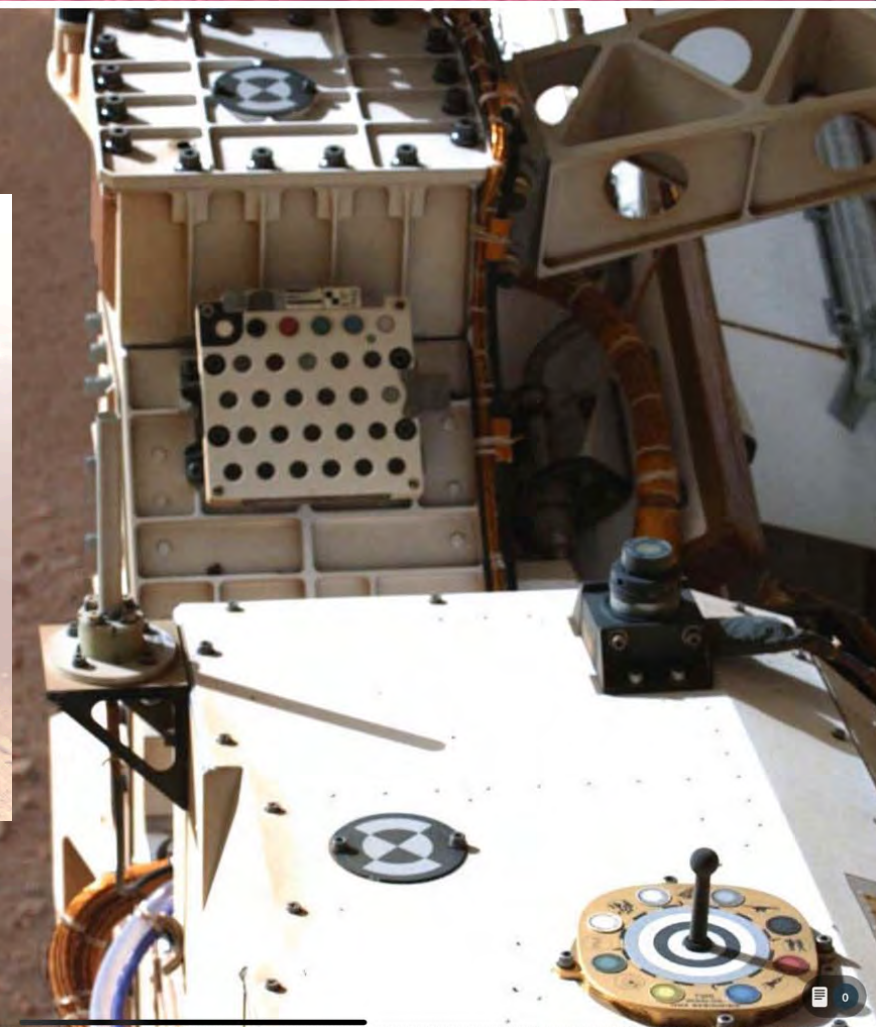
Martian Calibration

Mastcam-Z : deux caméras, capables de zoomer, effectuent le premier test de calibrage afin d'équilibrer les variations de luminosité sur Mars.



PARIS MATCH DU 25 FÉVRIER AU 3 MARS 2021

40



Nostalgia



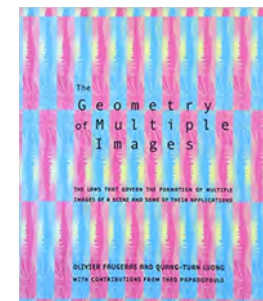
Je vous parle d'un temps
Que les moins de vingt ans
Ne peuvent pas connaître

I talk about a time
That those under twenty
Would not know

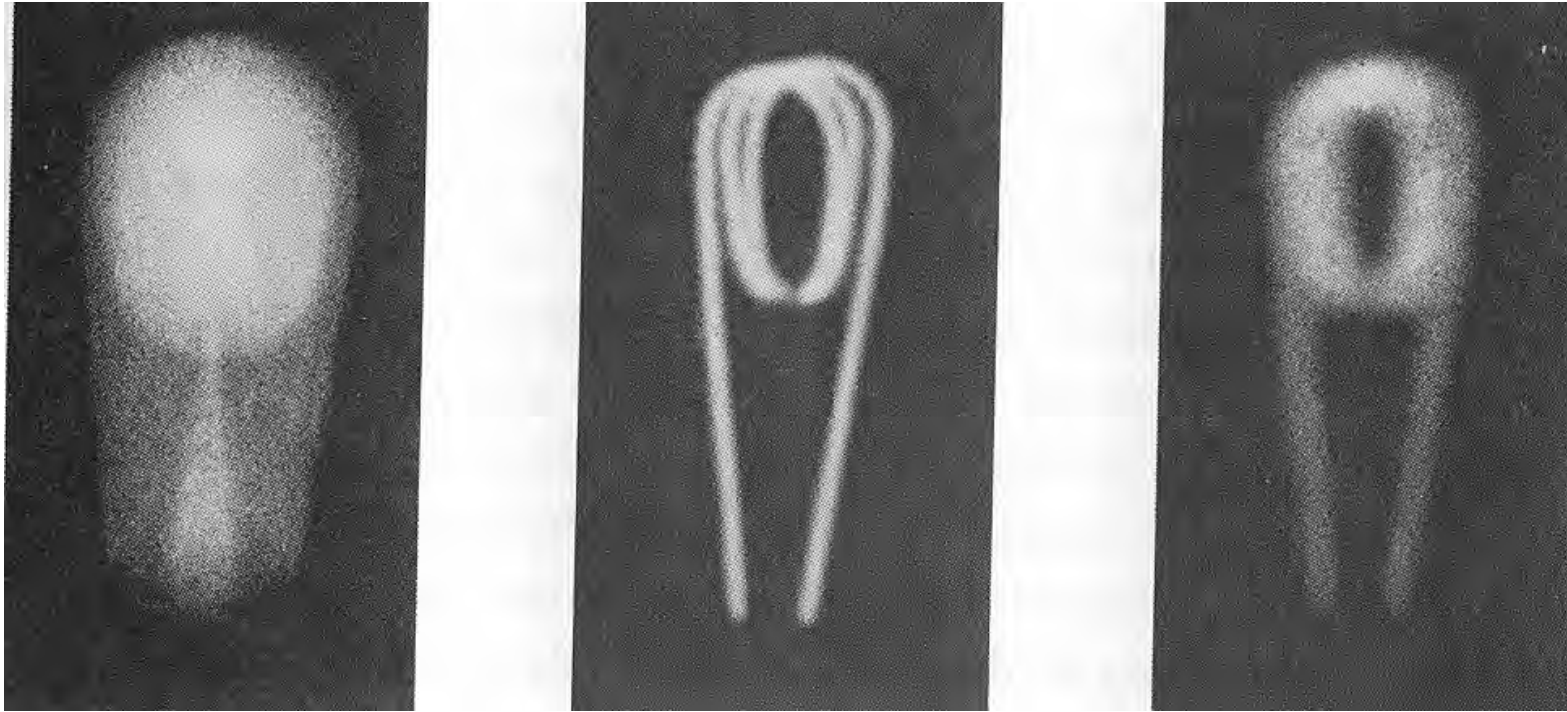
1993:



2001:



Limitations of the Pinhole Model

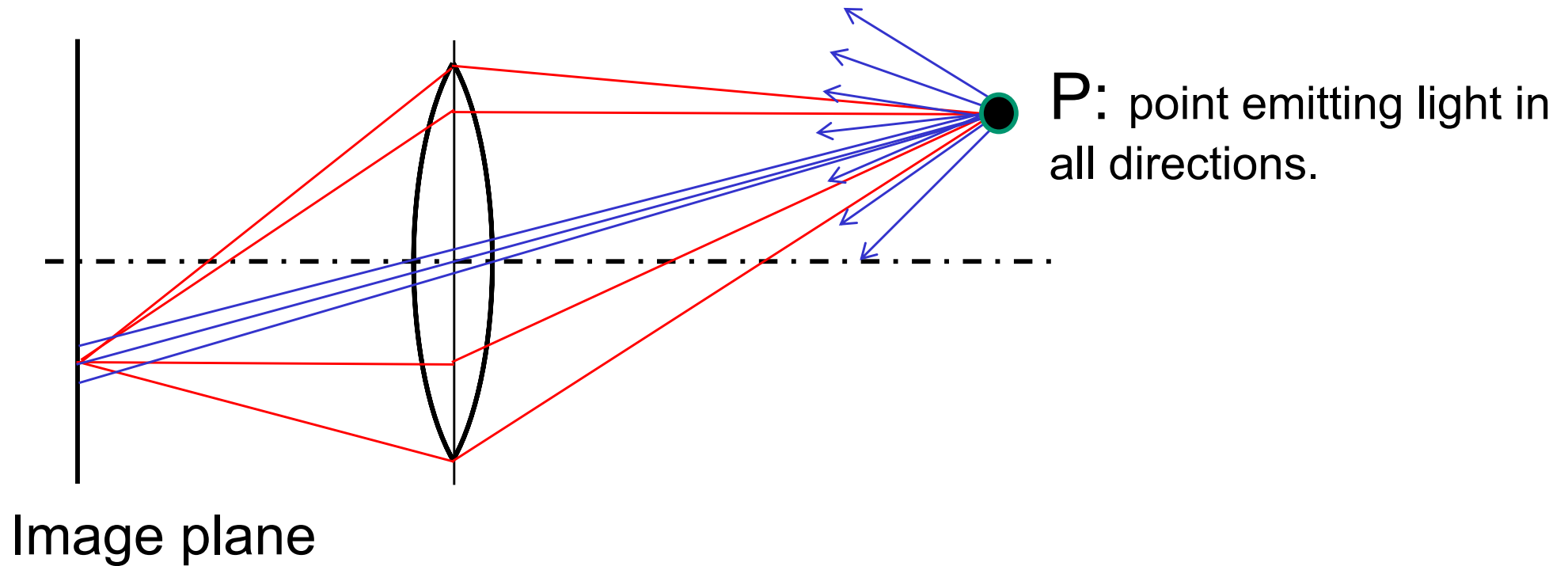


Idealization because the hole cannot be infinitely small

- Image would be infinitely dim
- Diffraction effects

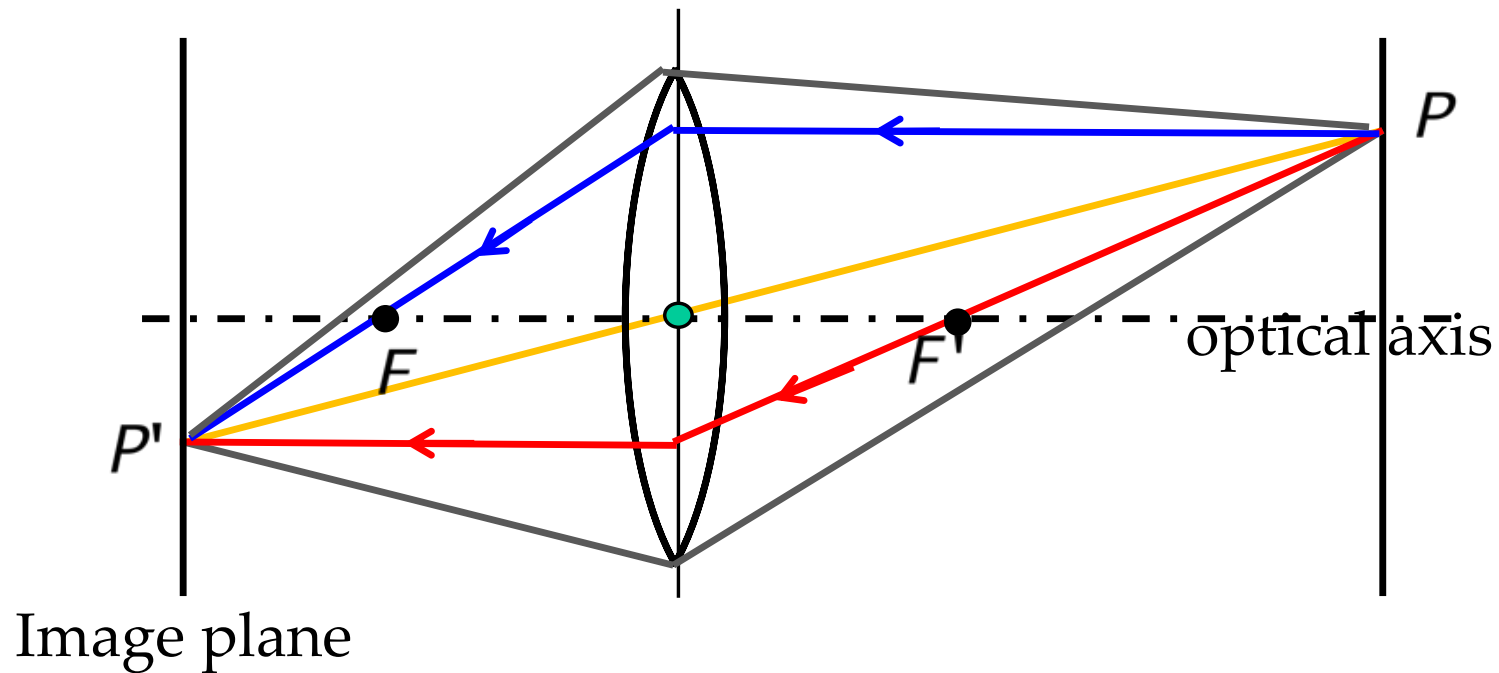
→ Use a lens to overcome this problem.

Imaging With a Lens



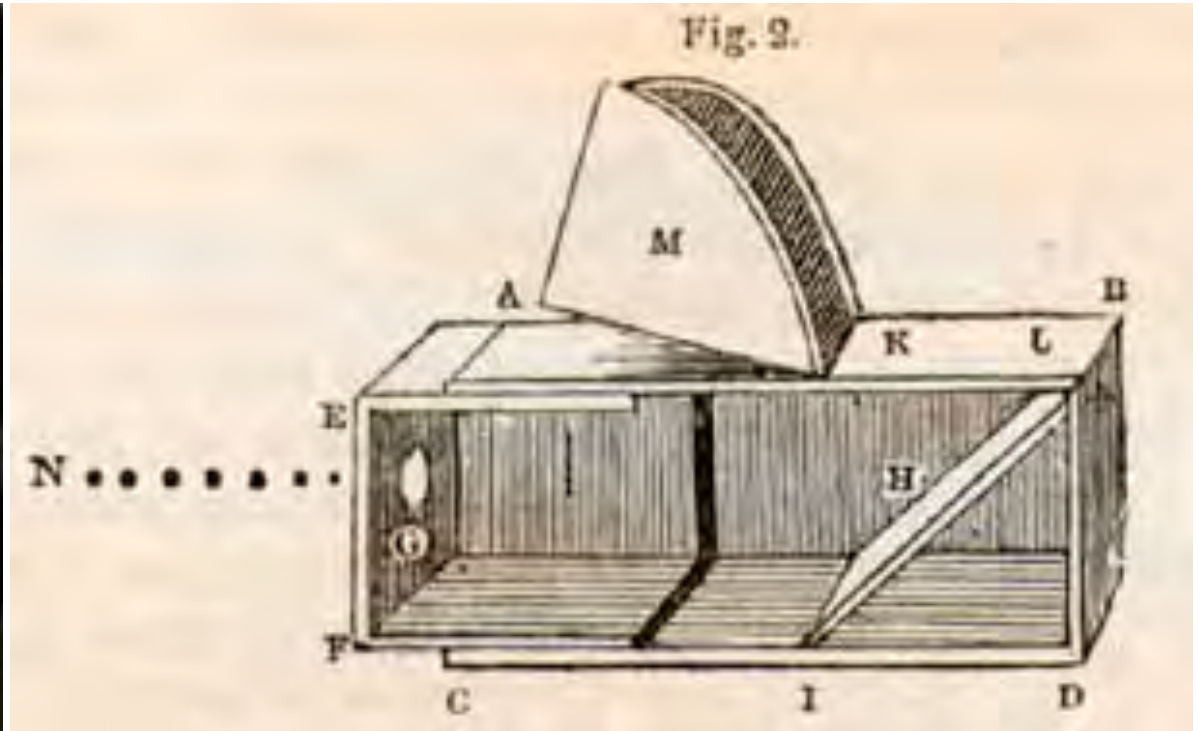
An ideal lens performs the same projection as a pinhole but **gathers much more light!**

Thin Lens Properties



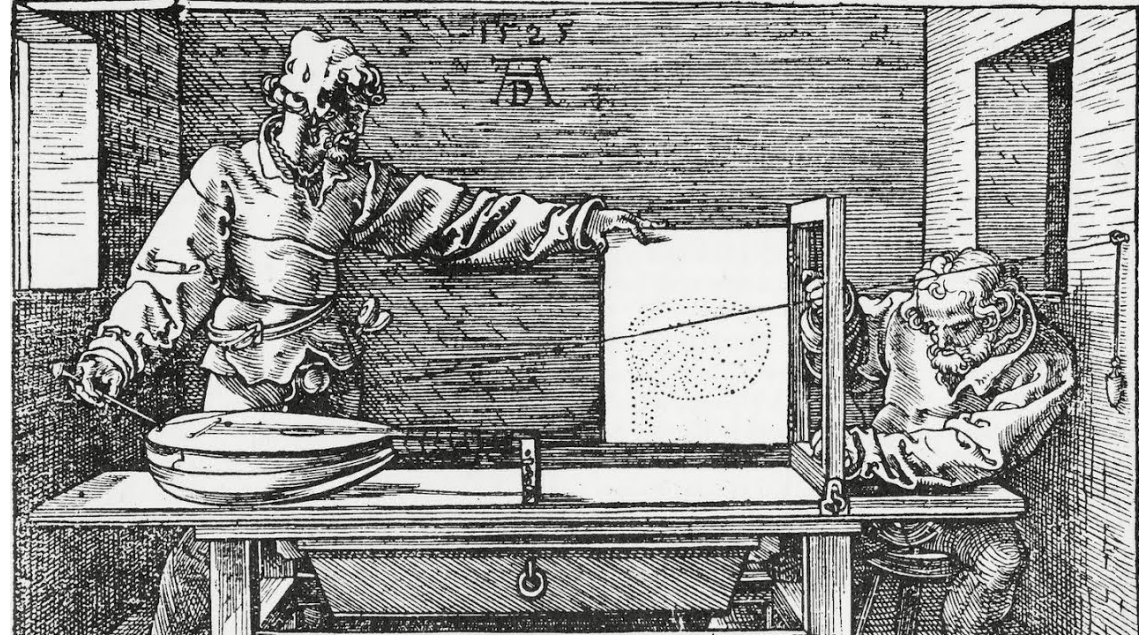
- An incident ray that passes through the center of the lens will in effect continue in the direction it had when it entered the lens.
- Any incident ray traveling parallel to the optical axis, will refract and travel through the focal point on the opposite side of the lens.
- Any incident ray traveling through the focal point on the way to the lens will be refracted and travel parallel to the principal axis.
- All rays emanating from P and entering the lens will converge at P' .

Camera Obscura



- Used by painters since the Renaissance to produce perspective projections.
- Direct ancestors to the first film cameras.

Durer 1471-1528



- He clearly knew all about the perspective transform!

Shifting Perspective

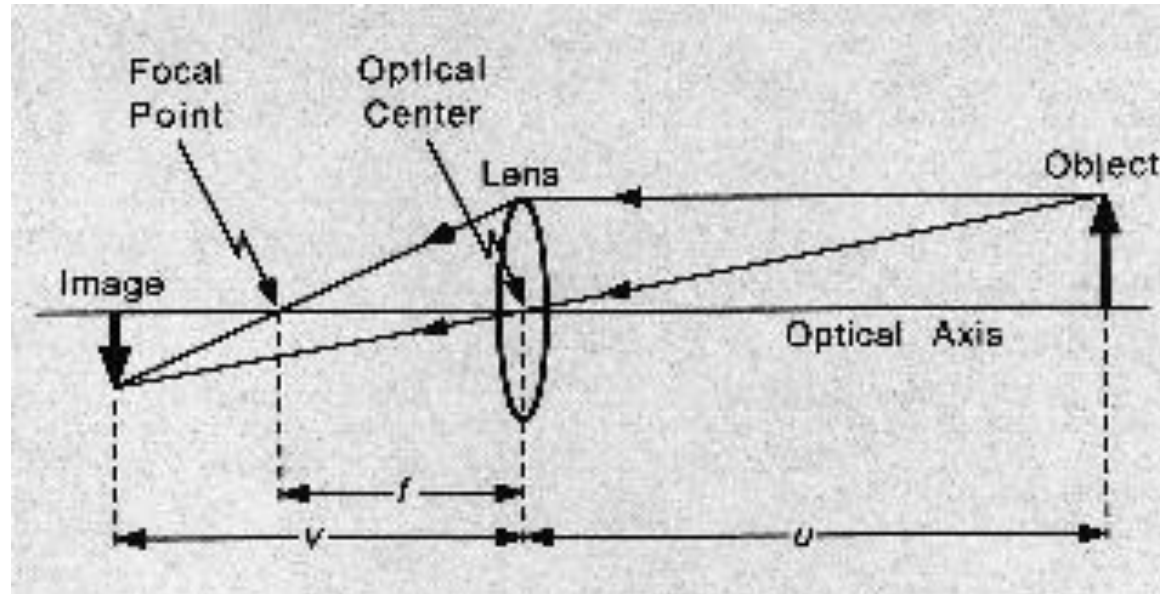


Buddha cutting his hair, 8th c.

China, 8th century:

- The focal point moves from one part of the image to the other.
- The characters are always seen at eye-level as the picture is unrolled.

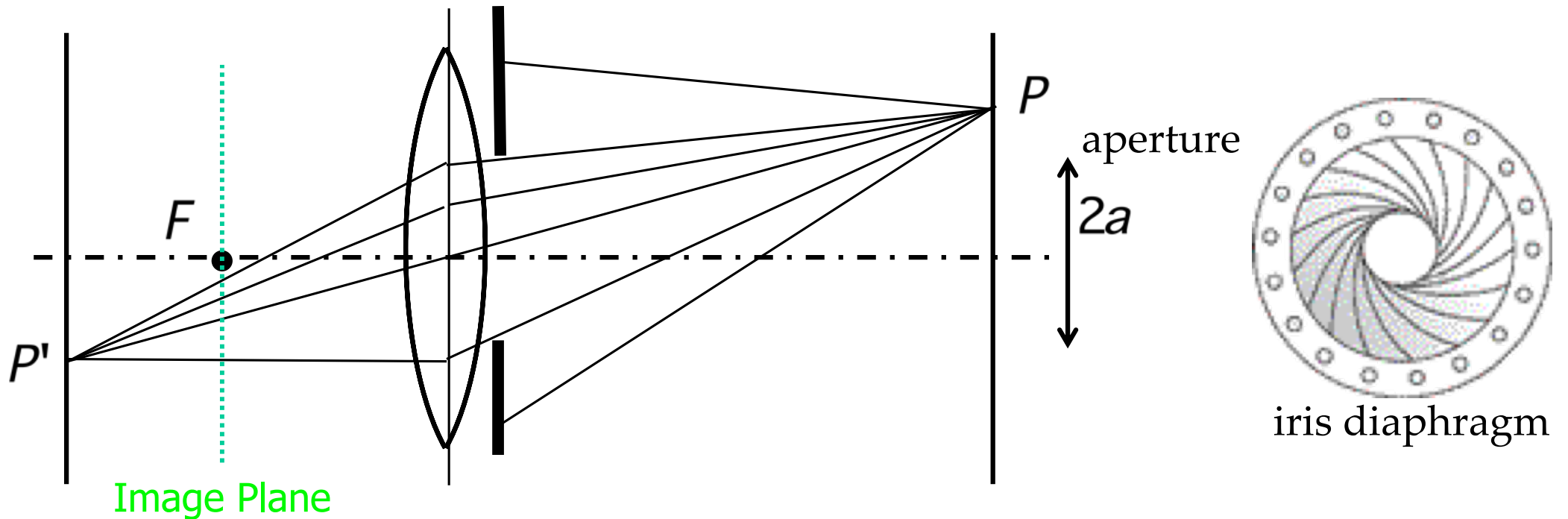
Thin Lens Equation



$$\cancel{\frac{1}{u}} + \frac{1}{v} = \frac{1}{f}$$

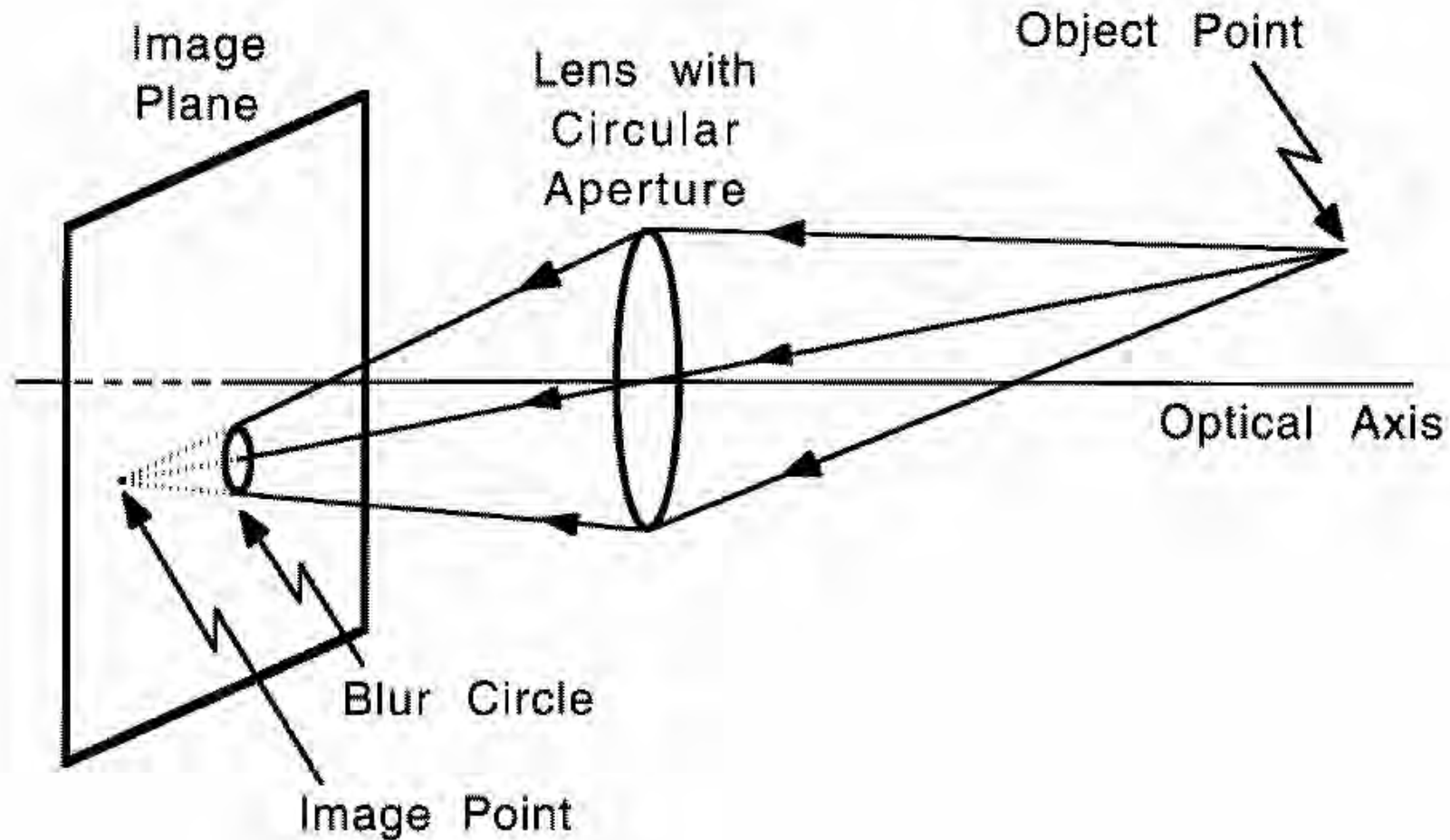
→ Lens with focal distance f equivalent to pinhole camera with similar focal distance but larger aperture.

Aperture



- Diameter $d=2a$ of the lens that is exposed to light.
- The image plane is not located exactly where the rays meet.
- The greater a , the more blur there will be.

Blur Circle



The size of the blur circle is proportional to the aperture.

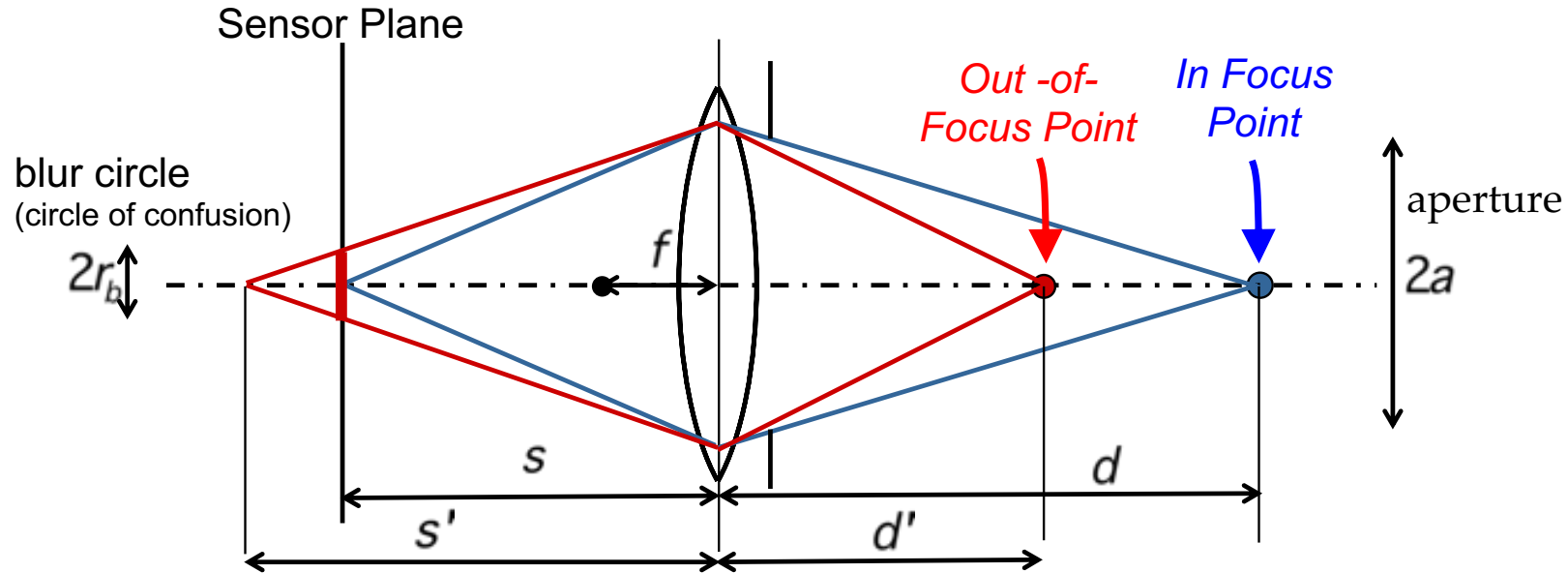
Depth of Field



- Range of object distances ($d-d'$) over which the image is sufficiently well focused.
- Range for which blur circle is less than the resolution of the sensor.

Small focal length \rightarrow Large depth of field.

Proof



- Simple geometry:

$$r_b = \frac{a}{s'} |s - s'|$$

$$s' - s = \frac{f}{d - f} \frac{f}{d' - f} (d - d')$$

- Thin lens equation:

$$\frac{1}{d} + \frac{1}{s} = \frac{1}{f} \Rightarrow s = \frac{df}{d - f}$$

$$\frac{1}{d'} + \frac{1}{s'} = \frac{1}{f} \Rightarrow s' = \frac{d'f}{d' - f}$$

$$r_b = \frac{af^2}{s'} \left| \frac{(d - d')}{(d - f)(d' - f)} \right|$$

Large f and a \rightarrow Large r_b .

Changing the Focal Length



Wide field of view (small f):
Large depth of field.



Narrow field of view (large f):
Small depth of field.

$$r_b \propto \frac{af^2}{s'}$$

Small f \longrightarrow Small r_b

Changing Aperture



f/11 1/30sec

Small aperture, long exposure:
Large depth of field.



f/2.8 1/500sec

Large aperture, short exposure:
Small depth of field.

$$r_b \propto \frac{af^2}{s'}$$

Small a \longrightarrow Small r_b

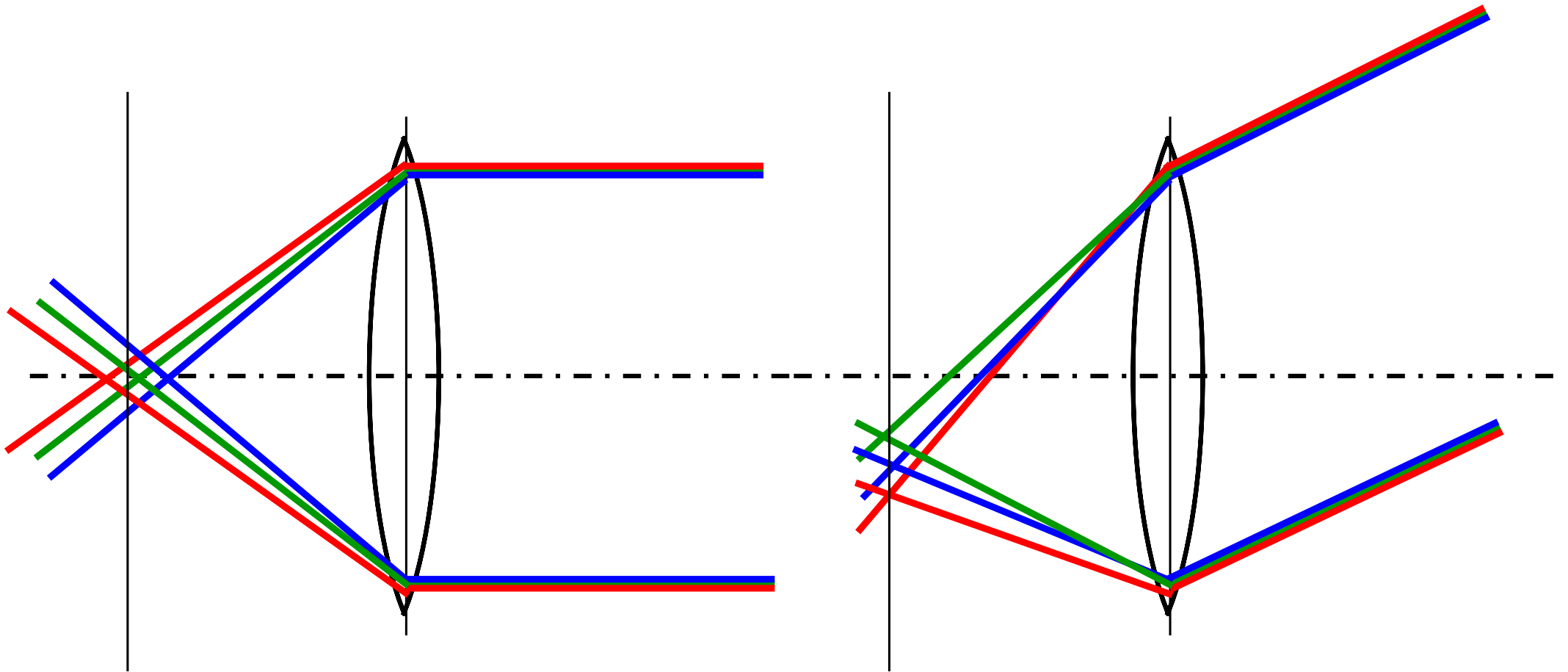
Distortions



The lens is not exactly a “thin lens:”

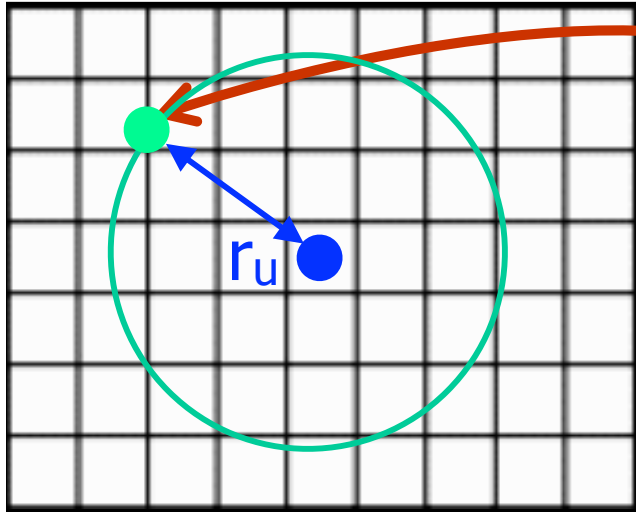
- Different wave lengths are refracted differently,
- Barrel Distortion.

Chromatic Aberration

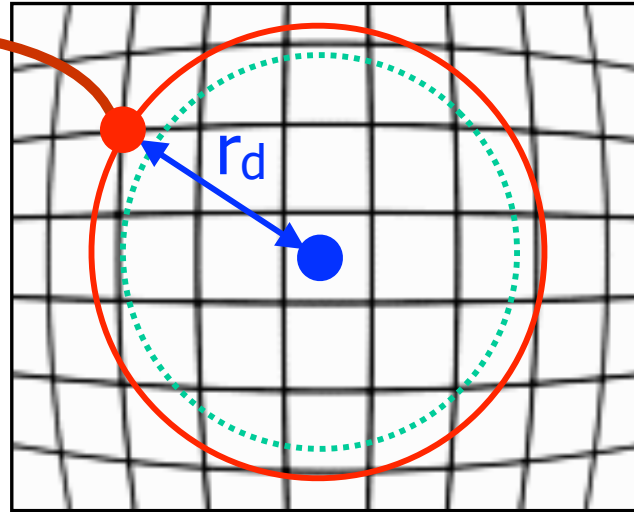


Different wavelengths are refracted differently.

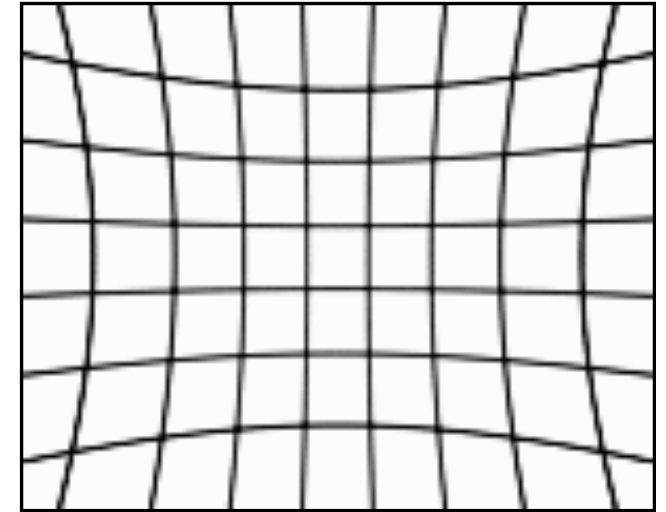
Radial Lens Distortion



No Distortion



Barrel Distortion



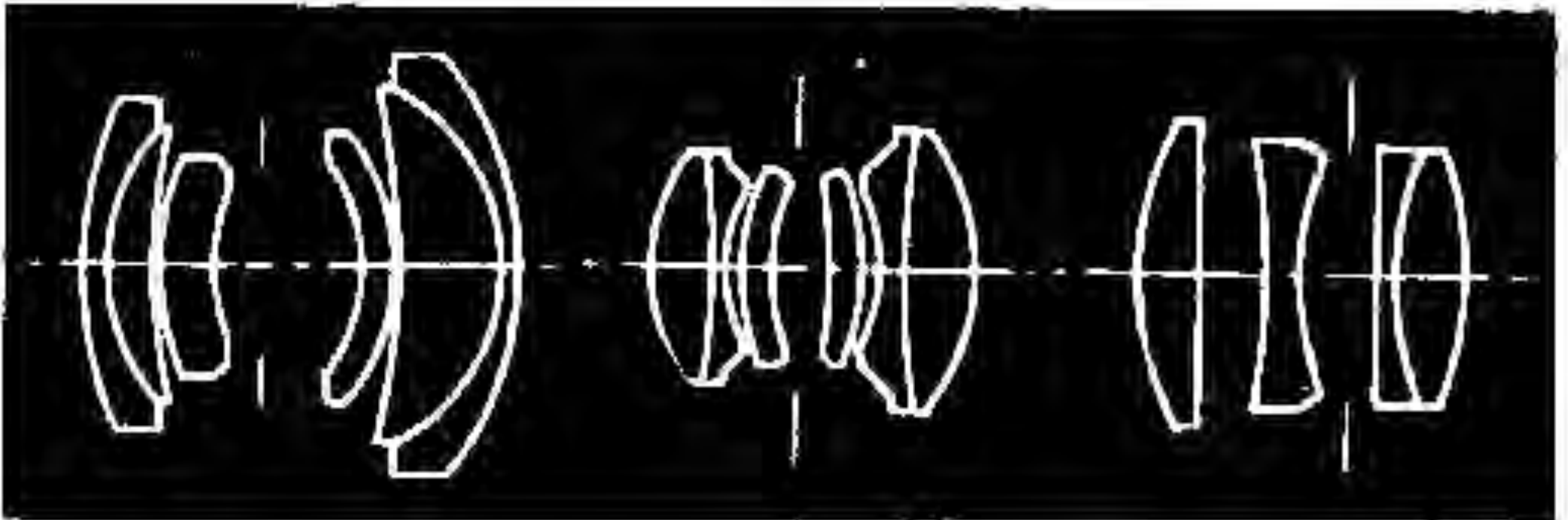
Pincushion Distortion

The distortion is a function of radial distance to the image center:

$$r_u = r_d(1 + k_1 r^2 + k_2 r^4 + \dots)$$

- r_d : Observed distance of the projected point to the center.
- r_u : Distance of the point to the center in an image without distortions.

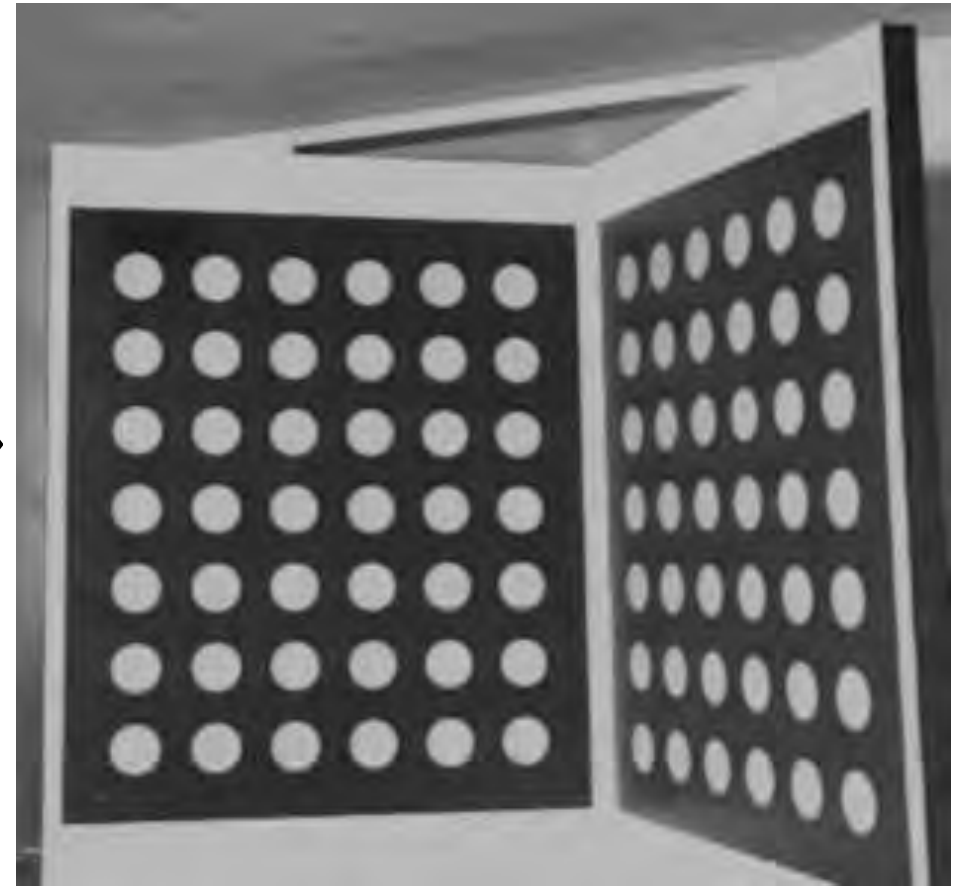
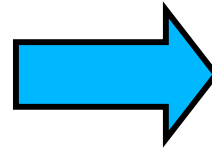
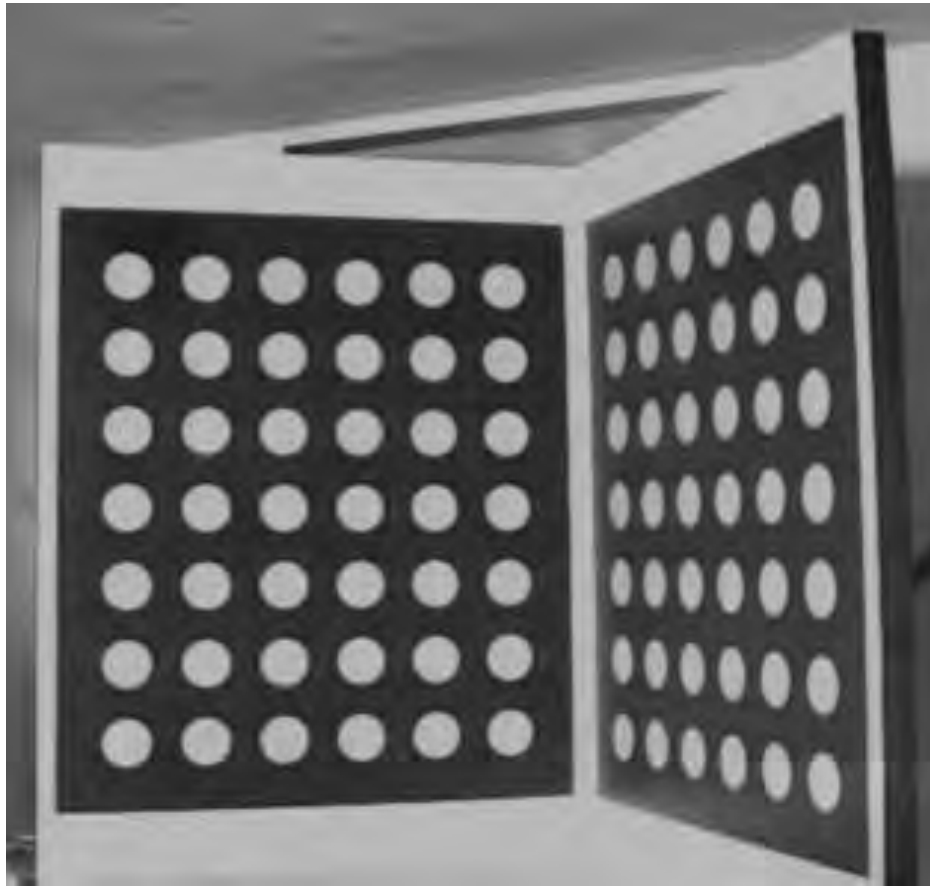
Lens Systems



Aberrations can be minimized by aligning several lenses with well chosen

- Shapes,
- Refraction indices.

Undistorting

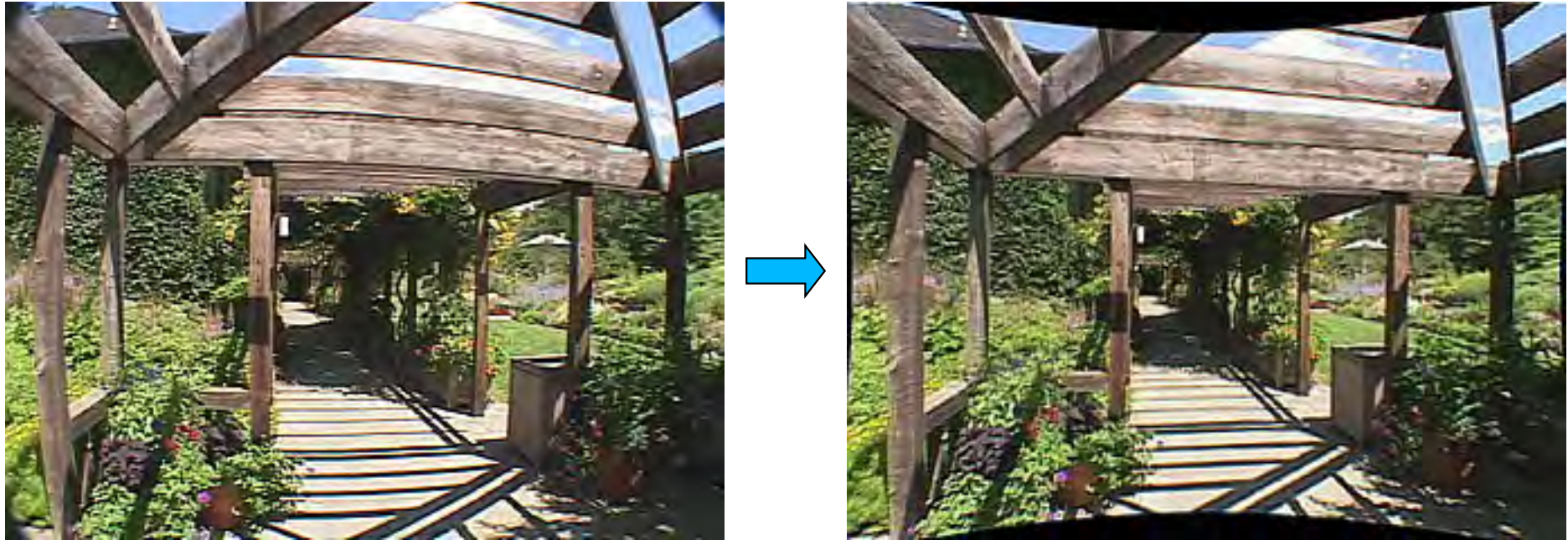


Real image

Synthetic image

—> Create the synthetic image a sense without distortion would have produced.

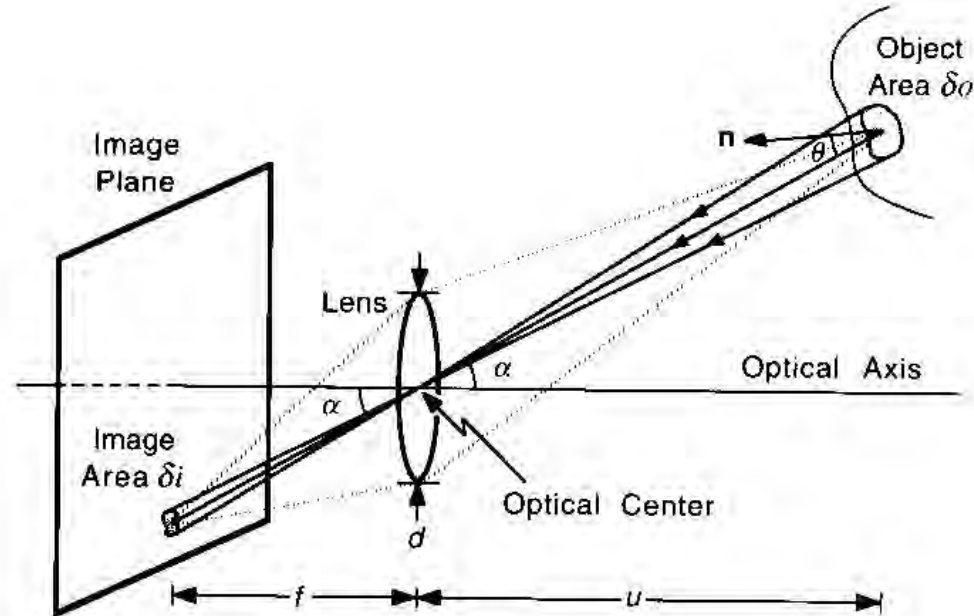
Undistorting



Once the image is undistorted, the camera projection can be formulated as a projective transform.

→ The pinhole camera model applies.

Fundamental Radiometric Equation



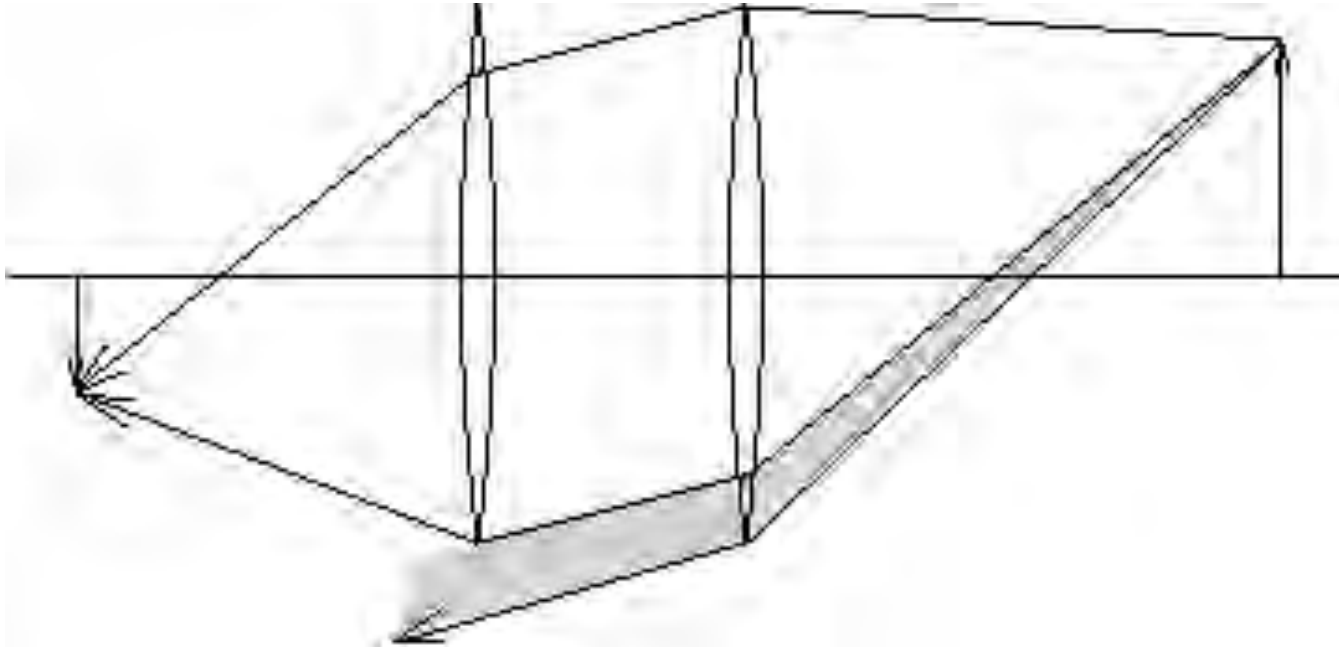
Scene Radiance (Rad) : Amount of light radiation emitted from a surface point (Watt / m² / Steradian).

Image Irradiance (Irr): Amount of light incident at the image of the surface point (Watt / m²).

$$\text{Irr} = \frac{\pi}{4} \left(\frac{d}{f} \right)^2 \cos^4(\alpha) \text{Rad} ,$$

\Rightarrow Irr \propto Rad for small values of α .

Vignetting



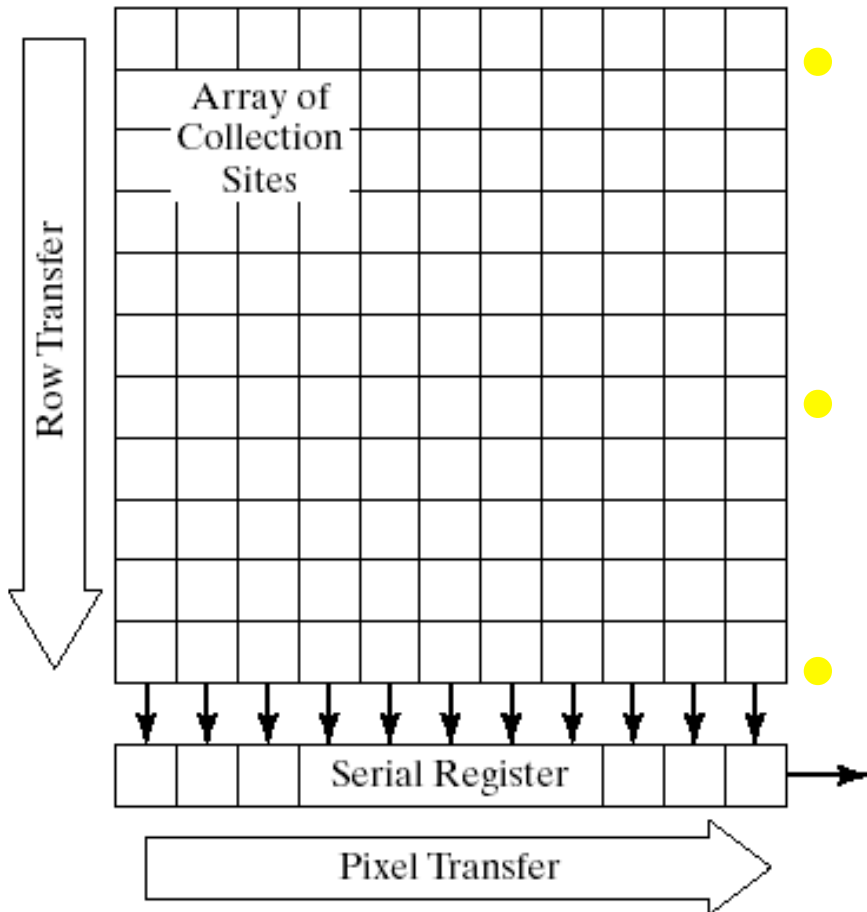
Images can get darker towards their edges because some of the light does not go through all the lenses.

De Vignetting



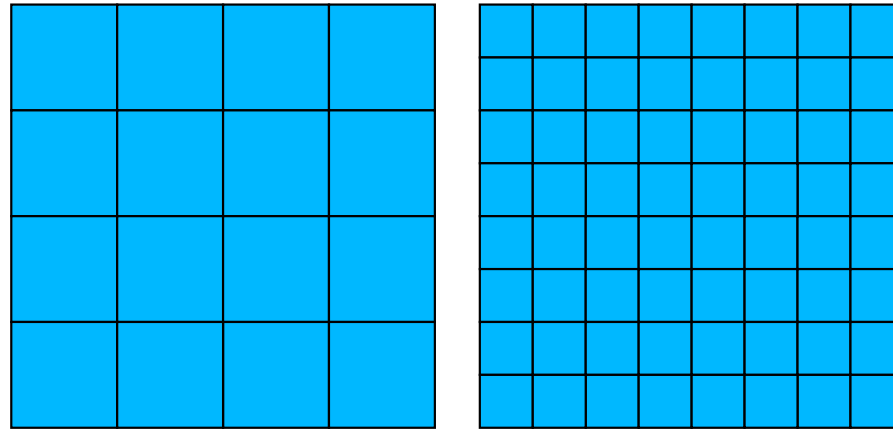
—> As for geometric undistortion, undo vignetting to create an image that an ideal camera would have produced.

Sensor Array



- Photons free up electrons that are then captured by a potential well.
- Charges are transferred row by row wise to a register.
- Pixel values are read from the register.

Sensing



Conversion of the “optical image” into an “electrical image”:

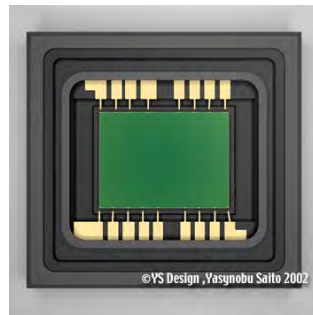
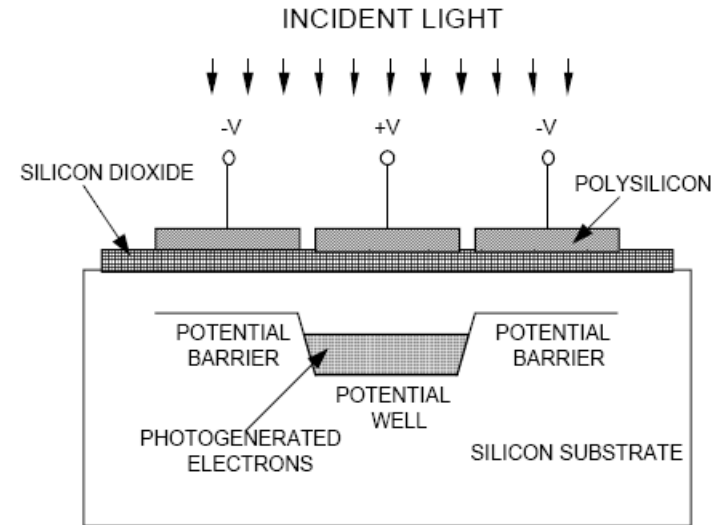
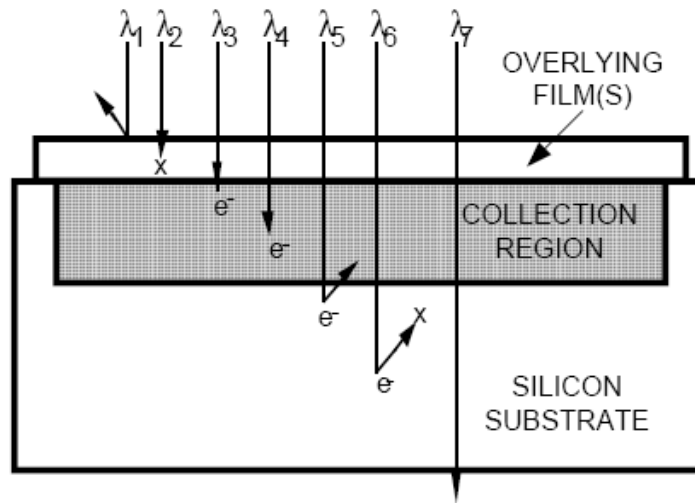
$$E(x, y) = \int_{t_0}^{t_1} \int_0^{\Lambda} \text{Irr}(x, y, t, \lambda) s(\lambda) dt d\lambda$$

$$I(m, n) = \text{Quantize}\left(\int_{x_0}^{x_1} \int_{y_0}^{y_1} E(x, y) dx dy\right)$$

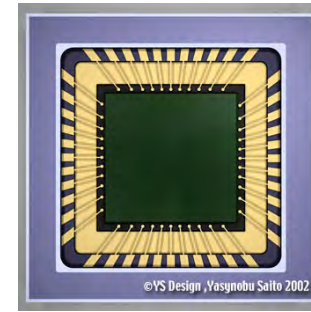
→ Quantization in

- Time
- Space

Sensors



CCD



CMOS

- Charged Coupling Devices (CCD): Made through a special manufacturing process that allows the conversion from light to signal to take place in the chip without distortion.
- Complimentary Metal Oxide Semiconductor (CMOS): Easier to produce and similar quality. Now used in most cameras except when quantum efficient pixels are needed, e.g. for astronomy.

In Short

- Camera geometry can be modeled in terms of the pinhole camera model, which is linear in projective space.
- Image radiance is roughly proportional to surface radiance and the two can be used interchangeably for our purposes.