
Camera Calibration

COMP4102A

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Finding camera parameters (intrinsic)

- Can use the EXIF tag for any digital image
 - Has focal length f in millimeters but not the pixel size
 - But you can get the pixel size from the camera manual
 - There are only a finite number of different pixels sizes because number of sensing element sizes is limited
 - If there is not a lot of image distortion due to optics then this approach is sufficient (only linear calibration)
- Can perform explicit camera calibration
 - Put a calibration pattern in front of the camera
 - Take a number of different pictures of this pattern
 - Now run the calibration algorithm (different types)
 - Result is intrinsic camera parameters (linear and non-linear) and the extrinsic camera parameters of all the images

Explicit camera calibration

- Use a calibration pattern with known geometry
 - In Opencv use a checkerboard
 - Other systems use special targets with known 3d geometry
- Write equations linking co-ordinates of the projected points, and the camera parameters
- From images of the calibration target
 - Intrinsic camera parameters
 - (depend only on camera characteristics)
 - Extrinsic camera parameters
 - (depend only on position camera)
 - In OpenCV the calibration process finds f_x , f_y , o_x , o_y , along with the distortion parameters
 - We study a method that does not find the distortion parameters

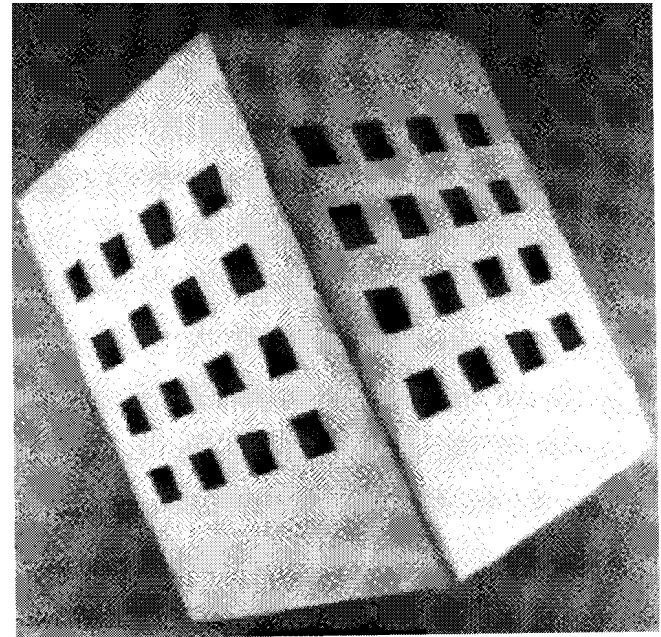
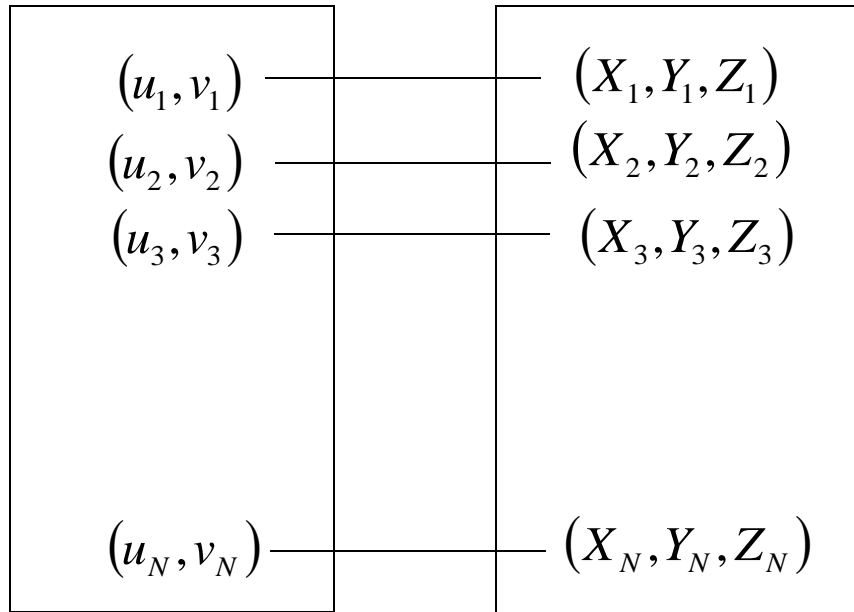
Calibration using known 3d geometry

- Use a calibration pattern with known 3d geometry (often a box, not planar)
- Write projection equations linking known coordinates of a set of 3-D points and their projections and solve for camera parameters
- Given a set of one or more images of the calibration pattern estimate
 - Intrinsic camera parameters
 - (depend only on camera characteristics)
 - Extrinsic camera parameters
 - (depend only on position camera)
- We do not estimate distortion parameters

Estimating camera parameters

- Projection matrix

Calibration pattern



Camera parameters

- Intrinsic parameters (K matrix)
 - There are 5 intrinsic parameters
 - Focal length f
 - Pixel size in x and y directions, s_x and s_y
 - Principal point o_x, o_y
- But they are not independent
 - Focal length $f_x = f / s_x$ and $f_y = f / s_y$
 - Principal point o_x, o_y
 - This makes four intrinsic parameters
- Extrinsic parameters $[R | T]$
 - Rotation matrix and translation vector of camera
 - Relations camera position to a known frame
 - $[R|T]$ are the extrinsic parameters
- Projection matrix
 - 3 by 4 matrix $P = K [R | T]$ is called projection matrix

Projection Equations

Projective Space

- Add fourth coordinate
 - $P_w = (X_w, Y_w, Z_w, 1)^T$
- Define $(u, v, w)^T$ such that
 - $u/w = x_{im}, v/w = y_{im}$

$$\begin{pmatrix} x_{im} \\ y_{im} \end{pmatrix} = \begin{pmatrix} u/w \\ v/w \end{pmatrix}$$



$$\begin{pmatrix} u \\ v \\ w \end{pmatrix} = \mathbf{M}_{int} \mathbf{M}_{ext} \begin{pmatrix} X_w \\ Y_w \\ Z_w \\ 1 \end{pmatrix}$$

3x4 Matrix \mathbf{E}_{ext}

- Only extrinsic parameters
- World to camera

$$\mathbf{M}_{ext} = \begin{bmatrix} r_{11} & r_{12} & r_{13} & T_x \\ r_{21} & r_{22} & r_{23} & T_y \\ r_{31} & r_{32} & r_{33} & T_z \end{bmatrix} = \begin{bmatrix} \mathbf{R}_1^T & T_x \\ \mathbf{R}_2^T & T_y \\ \mathbf{R}_3^T & T_z \end{bmatrix}$$

3x3 Matrix \mathbf{E}_{int}

- Only intrinsic parameters
- Camera to frame

$$\mathbf{M}_{int} = \begin{bmatrix} -f_x & 0 & o_x \\ 0 & -f_y & o_y \\ 0 & 0 & 1 \end{bmatrix}$$

Simple Matrix Product! Projective Matrix

$$\mathbf{M} = \mathbf{M}_{int} \mathbf{M}_{ext}$$

- $(X_w, Y_w, Z_w)^T \rightarrow (x_{im}, y_{im})^T$
- Linear Transform from projective space to projective plane
- \mathbf{M} defined up to a scale factor – 11 independent entries

Two different calibration methods

- Both use a set of 3d points and 2d projections
- Direct approach (called Tsai method)
 - Write projection equations in terms of all the parameters
 - That is all the unknown intrinsic and extrinsic parameters
 - Solve for these parameters using non-linear equations
- Projection matrix approach
 - Compute the projection matrix (the 3x4 matrix M)

$$\begin{bmatrix} m_{11} & m_{12} & m_{13} & m_{14} \\ m_{21} & m_{22} & m_{23} & m_{24} \\ m_{31} & m_{32} & m_{33} & m_{34} \end{bmatrix}$$

- Compute camera parameters as closed-form functions of M

•Two different calibration methods

- Both approaches work with same data
 - Projection matrix approach is simpler to explain than the direct approach
- Direct approach requires an extra step
 - There are also other calibration methods
- But all calibration methods
 - Use patterns with know geometry or shape
 - Take multiple views of theses patterns
 - Match the information across the different views
- Perform some mathematics to calculate the intrinsic and extrinsic camera parameters
- We look at simplified case of only one view!

Estimating the projection matrix

World – Frame Transform

- Drop “im” and “w”
- N pairs $(x_i, y_i) \leftrightarrow (X_i, Y_i, Z_i)$

$$x_i = \frac{u_i}{w_i} = \frac{m_{11}X_i + m_{12}Y_i + m_{13}Z_i + m_{14}}{m_{31}X_i + m_{32}Y_i + m_{33}Z_i + m_{34}}$$
$$y_i = \frac{u_i}{w_i} = \frac{m_{21}X_i + m_{22}Y_i + m_{23}Z_i + m_{24}}{m_{31}X_i + m_{32}Y_i + m_{33}Z_i + m_{34}}$$

Linear equations of m

- 2N equations, 11 independent variables
- $N \geq 6$, SVD \Rightarrow m up to a unknown scale

$$\mathbf{A}\mathbf{m} = \mathbf{0}$$

$$\mathbf{A} = \begin{bmatrix} X_1 & Y_1 & Z_1 & 1 & 0 & 0 & 0 & 0 & -x_1X_1 & -x_1Y_1 & -x_1Z_1 & -x_1 \\ 0 & 0 & 0 & 0 & X_1 & Y_1 & Z_1 & 1 & -y_1X_1 & -y_1Y_1 & -y_1Z_1 & -y_1 \\ \cdot & \cdot & \cdot & \cdot & \cdot & \cdot & \cdot & \cdot & \cdot & \cdot & \cdot & \cdot \end{bmatrix}$$

$$\mathbf{m} = [m_{11} \quad m_{12} \quad m_{13} \quad m_{14} \quad m_{21} \quad m_{22} \quad m_{23} \quad m_{24} \quad m_{31} \quad m_{32} \quad m_{33} \quad m_{34}]^T$$

Homogeneous System

- M linear equations of form $A\mathbf{x} = 0$
- If we have a given solution \mathbf{x}_1 , s.t. $A\mathbf{x}_1 = 0$ then $c * \mathbf{x}_1$ is also a solution $A(c * \mathbf{x}_1) = 0$
- Need to add a constraint on \mathbf{x} ,
 - Basically make \mathbf{x} a unit vector $\mathbf{x}^T \mathbf{x} = 1$
- Can prove that the solution is the eigenvector corresponding to the single zero eigenvalue of that matrix $A^T A$
 - This can be computed using eigenvector of SVD routine
 - Then finding the zero eigenvalue (actually smallest)
 - Returning the associated eigenvector

Decompose projection matrix

- 3x4 Projection Matrix \mathbf{M} computed previously
 - Both intrinsic (4) and extrinsic (6) – 10 parameters

$$\mathbf{M} = \begin{bmatrix} -f_x r_{11} + o_x r_{31} & -f_x r_{12} + o_x r_{32} & -f_x r_{13} + o_x r_{33} & -f_x T_x + o_x T_z \\ -f_y r_{21} + o_y r_{31} & -f_y r_{22} + o_y r_{32} & -f_y r_{23} + o_y r_{33} & -f_y T_y + o_y T_z \\ r_{31} & r_{32} & r_{33} & T_z \end{bmatrix}$$

From \mathbf{M} to parameters (p134-135)

- Find scale $|\gamma|$ by using unit vector \mathbf{R}_3^\top
- Determine T_z and sign of γ from m_{34} (i.e. q_{43})
- Obtain \mathbf{R}_3^\top
- Find (O_x, O_y) by dot products of Rows q_1, q_3, q_2, q_3 , using the orthogonal constraints of \mathbf{R}
- Determine f_x and f_y from q_1 and q_2 All the rests: $\mathbf{R}_1^\top, \mathbf{R}_2^\top, T_x, T_y$

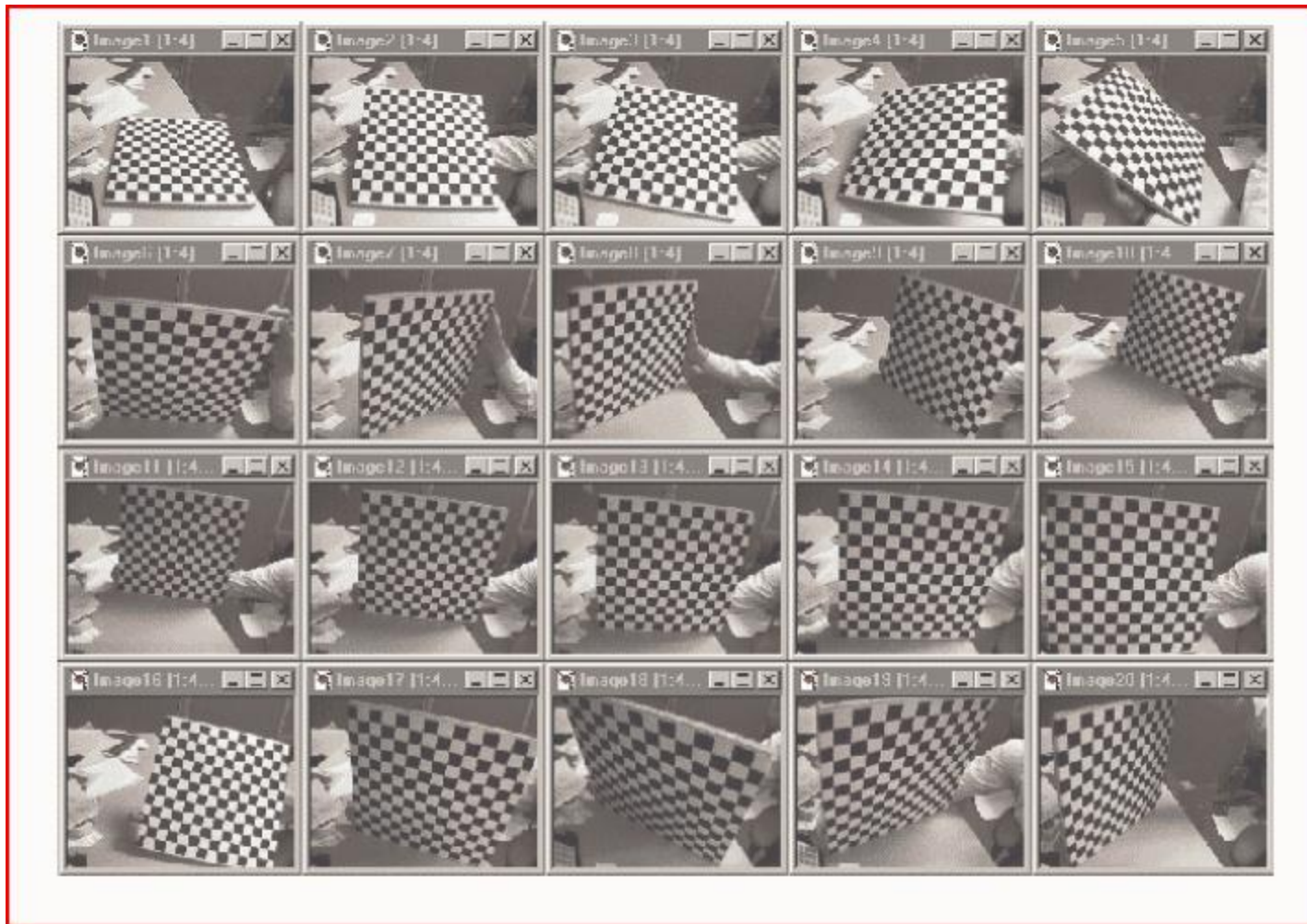
Calibration Summary

- Comparison of methods
 - Direct approach requires extra step to find O_x , O_y
 - Projection approach finds O_x , and O_y at same time
 - Is simpler mathematically than the direct approach
 - Both methods require a refit to find a “valid” R matrix
- There are other calibration methods
 - Zhang approach uses flat plane (implemented in OpenCV)
 - Plane must be flat, but do not need 3D co-ordinates
- But all calibration methods
 - Have some known targets with known 3D geometry or shape
 - Take a number of images of these targets
 - From these measurements calculate the camera parameters
 - Are essential for further processing like reconstruction

Multiple View/Camera Calibration

- Previous math describes the calibration process for a single image
 - We usually take multiple images of the same calibration target (from a variety of different views)
 - Simultaneously find all extrinsic parameters and all the intrinsic parameters of the single camera
- Also calibrate radial distortion using fact that there are straight lines in the pattern
- OpenCV code can do this using a checkerboard pattern
- Zhang's algorithm is used most in practice

Input set of 2d Calibration Patterns



Final Camera positions and the pattern

