
Homography

Dr. Gerhard Roth

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Linear Mappings

- linear mappings from one particular space to the other, also called transformations
- Different types of transformations from a 2d image to another 2d images
 - Translation, rigid, similarity, affine, projective
 - Next one in the list includes all the previous members
 - i.e. Perspective transformation is a superset of all previous
- A 2d perspective transformation is commonly called an image warp or a homography
- Warp takes a 2d image and produces another 2d image
 - Maps from a pixel in source image to a pixel destination

Homography = Linear warp

- Consider a point $x = (u, v, 1)$ in one image and $x' = (u', v', 1)$ in another image
- A homography is a 3 by 3 matrix M

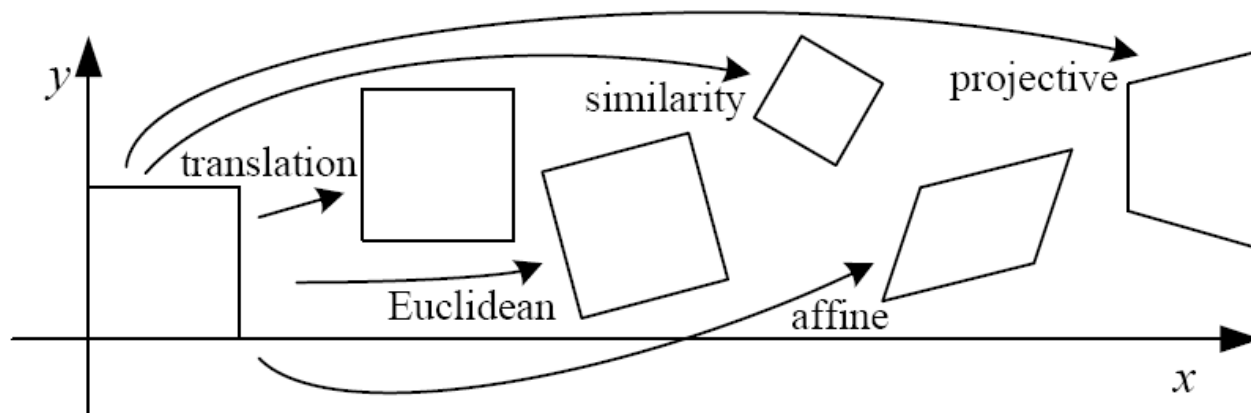
$$M = \begin{bmatrix} m_{11} & m_{12} & m_{13} \\ m_{21} & m_{22} & m_{23} \\ m_{31} & m_{32} & m_{33} \end{bmatrix}$$

- The homography relates the pixel co-ordinates in the two images if $x' = M x$
 - Works on pixel co-ordinates (pixels) not camera co-ordinates (mm)
- When applied to every pixel the new image is a warped version of the original image

Two images related by homography



2D image transformations

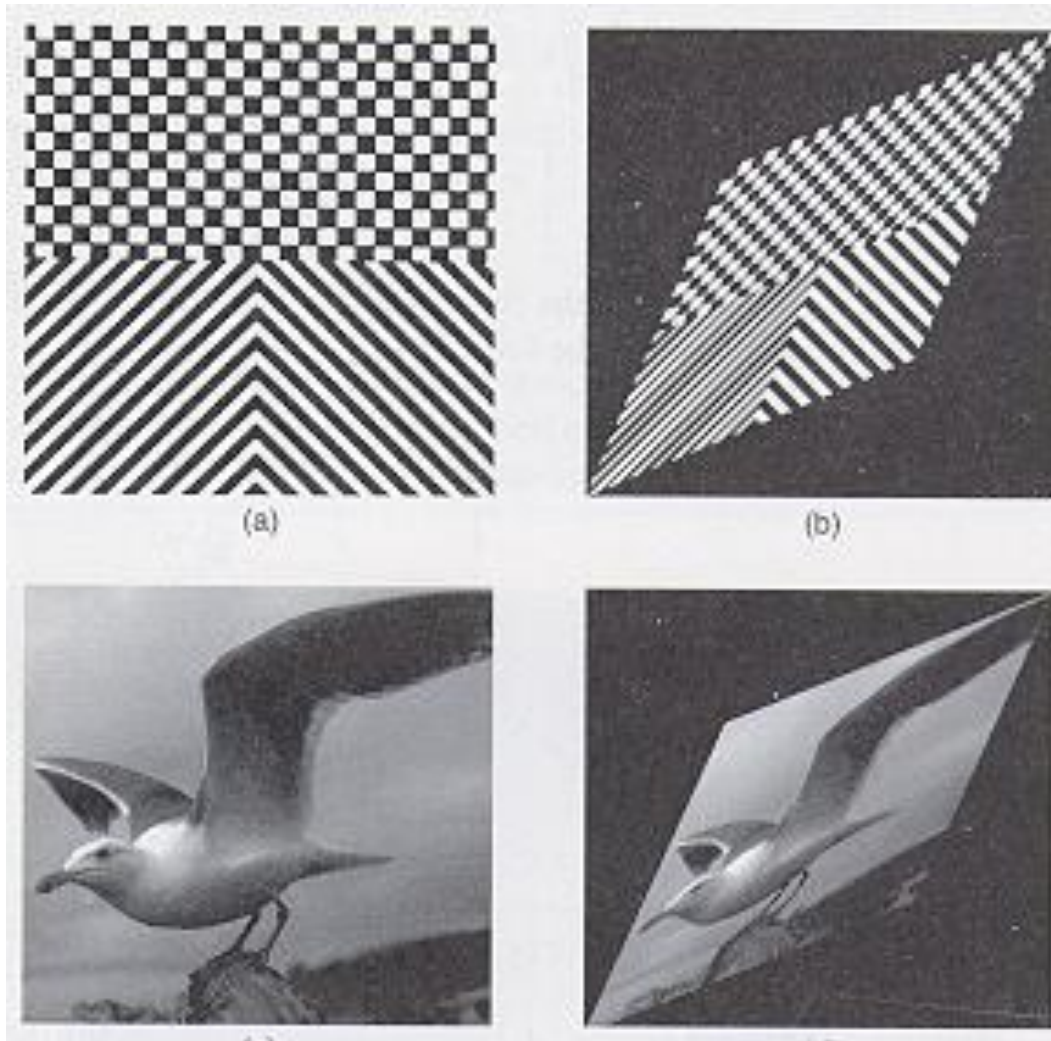


Name	Matrix	# D.O.F.	Preserves:	Icon
translation	$\begin{bmatrix} \mathbf{I} & \mathbf{t} \end{bmatrix}_{2 \times 3}$			
rigid (Euclidean)	$\begin{bmatrix} \mathbf{R} & \mathbf{t} \end{bmatrix}_{2 \times 3}$			
similarity	$\begin{bmatrix} s\mathbf{R} & \mathbf{t} \end{bmatrix}_{2 \times 3}$			
affine	$\begin{bmatrix} \mathbf{A} \end{bmatrix}_{2 \times 3}$			
projective	$\begin{bmatrix} \tilde{\mathbf{H}} \end{bmatrix}_{3 \times 3}$			

These transformations are a nested set of groups

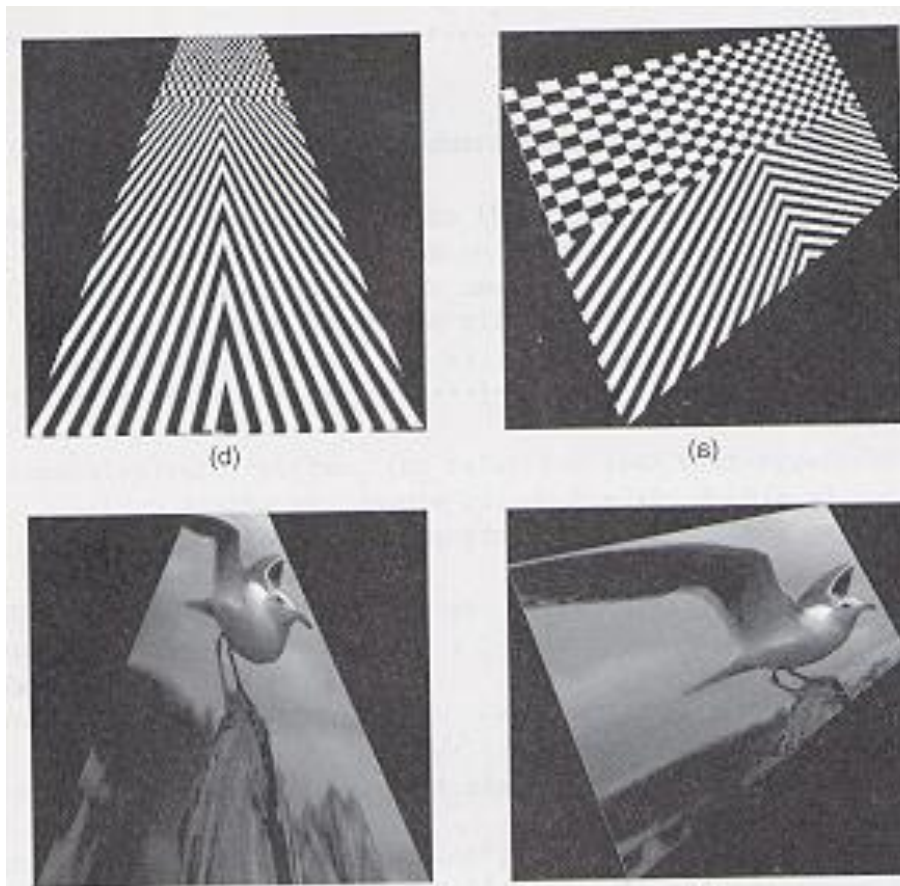
- Closed under composition and inverse is a member

Affine example



Perspective transformation

a straight line is a straight line



Homography conditions

- Two images are related by a homography if and only if (2 conditions)
- Both images are viewing the same plane from a different angle (was on your assignment)
- Both images are taken from the same camera but from a different angle
 - Camera is rotated about its center of projection without any translation
- Note that the homography relationship is independent of the scene structure
 - It does not depend on what the cameras are looking at
 - Relationship holds regardless of what is seen in the images

Homography does not work in general!



Homography when viewing a plane

- Normal projection matrix

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

- All world points on a plane, choose $Z = 0$ to be on the plane

$$\begin{bmatrix} x \\ y \\ w \end{bmatrix} = \begin{bmatrix} m_{11} & m_{12} & 0 & m_{14} \\ m_{21} & m_{22} & 0 & m_{24} \\ m_{31} & m_{32} & 0 & m_{34} \end{bmatrix} \begin{bmatrix} X \\ Y \\ 0 \\ 1 \end{bmatrix}$$

- Final matrix relates points on world plane to image plane

$$\begin{bmatrix} x \\ y \\ w \end{bmatrix} = \begin{bmatrix} m_{11} & m_{12} & m_{14} \\ m_{21} & m_{22} & m_{24} \\ m_{31} & m_{32} & m_{34} \end{bmatrix} \begin{bmatrix} X \\ Y \\ 1 \end{bmatrix}$$

Homography when rotating camera

- No translation, here X is a 3d point, and x, x' projection
- Home position – projection equation

$$x = K \begin{bmatrix} I & | & 0 \end{bmatrix} \begin{bmatrix} X \\ 1 \end{bmatrix} = KX$$

- Rotation by a matrix R – projection equation

$$x' = K \begin{bmatrix} R & | & 0 \end{bmatrix} \begin{bmatrix} X \\ 1 \end{bmatrix} = KRX$$

- So $x' = KRK^{-1}x$ where K is calibration matrix
- Where KRK^{-1} is a 3by3 matrix M called a homography

•Compute homography

- If we know rotation K , R , then homography H can be computed directly $x' = KRK^{-1}x$
 - Applying this homography to one image gives image that we would get if the camera was rotated by R
- If we know, K , R and T and are looking at a plane we can also compute the homography
 - Just look at your last assignment, where you have the full projection matrix (p. 134 of book)
 - Now drop the 3d column, then we have a homography matrix
 - If we know f_x , f_y , o_x , o_y , R and T we can define this matrix
- So if we have this info we can always compute the homography
- But what if we only have two images, and a set of correspondences?

Computing M: The four point Algorithm

Input: n point correspondences ($n \geq 4$)

- Construct homogeneous system $Ax=0$ from $x' = xM$
 - $x = (m_{11}, m_{12}, m_{13}, m_{21}, m_{22}, m_{23}, m_{31}, m_{32}, m_{33})$: entries in m
 - Each correspondence gives two equations
 - A is a $2n \times 9$ matrix
- Obtain estimate M by Eigenvector with smallest eigenvalue
 - Do not have any singularity constraint as we did with the fundamental matrix
 - Finding the homography that solves $Ax = 0$ subject to the constraint that
 - x is a unit vector $\|x\| = 1$

Output: the homography matrix, M that is the best least squares solution to this problem

• Similar to how you compute a projection matrix, but the correspondences are 2d pixels to 2d pixels, and not 3d points to 2d pixels!

Recover Homography matrix from correspondences

$$\begin{bmatrix} \mathbf{u}_2 \\ \mathbf{v}_2 \\ \mathbf{w}_2 \end{bmatrix} = \begin{bmatrix} \mathbf{H}_{11} & \mathbf{H}_{12} & \mathbf{H}_{13} \\ \mathbf{H}_{21} & \mathbf{H}_{22} & \mathbf{H}_{23} \\ \mathbf{H}_{31} & \mathbf{H}_{32} & \mathbf{H}_{33} \end{bmatrix} \begin{bmatrix} \mathbf{u}_1 \\ \mathbf{v}_1 \\ \mathbf{w}_1 \end{bmatrix}$$

$$\mathbf{u}_2 = \frac{\mathbf{H}_{11} \mathbf{u}_1 + \mathbf{H}_{12} \mathbf{v}_1 + \mathbf{H}_{13}}{\mathbf{H}_{31} \mathbf{u}_1 + \mathbf{H}_{32} \mathbf{v}_1 + \mathbf{H}_{33}}$$

$$\mathbf{v}_2 = \frac{\mathbf{H}_{21} \mathbf{u}_1 + \mathbf{H}_{22} \mathbf{v}_1 + \mathbf{H}_{23}}{\mathbf{H}_{31} \mathbf{u}_1 + \mathbf{H}_{32} \mathbf{v}_1 + \mathbf{H}_{33}}$$

Here $u = x$, and $v = y$

Multiply up denominators

$$\mathbf{H}_{31} \mathbf{u}_1 \mathbf{u}_2 + \mathbf{H}_{32} \mathbf{v}_1 \mathbf{u}_2 + \mathbf{H}_{33} \mathbf{u}_2 = \mathbf{H}_{11} \mathbf{u}_1 + \mathbf{H}_{12} \mathbf{v}_1 + \mathbf{H}_{13}$$

$$\mathbf{H}_{31} \mathbf{u}_1 \mathbf{v}_2 + \mathbf{H}_{32} \mathbf{v}_1 \mathbf{v}_2 + \mathbf{H}_{33} \mathbf{v}_2 = \mathbf{H}_{21} \mathbf{u}_1 + \mathbf{H}_{22} \mathbf{v}_1 + \mathbf{H}_{23}$$

Solving for $AX=0$ -gives us 2 equations/correspondence -need 4 correspondences

$$\mathbf{H}_{31} \mathbf{u}_1 \mathbf{u}_2 + \mathbf{H}_{32} \mathbf{v}_1 \mathbf{u}_2 + \mathbf{H}_{33} \mathbf{u}_2 - \mathbf{H}_{11} \mathbf{u}_1 - \mathbf{H}_{12} \mathbf{v}_1 - \mathbf{H}_{13} = 0$$

$$\mathbf{H}_{31} \mathbf{u}_1 \mathbf{v}_2 + \mathbf{H}_{32} \mathbf{v}_1 \mathbf{v}_2 + \mathbf{H}_{33} \mathbf{v}_2 - \mathbf{H}_{21} \mathbf{u}_1 - \mathbf{H}_{22} \mathbf{v}_1 - \mathbf{H}_{23} = 0$$

Each correspondence provides two rows of A matrix

$$\begin{bmatrix} -\mathbf{u}_1 & -\mathbf{v}_1 & -1 & 0 & 0 & 0 & \mathbf{u}_1 \mathbf{u}_2 & \mathbf{v}_1 \mathbf{u}_2 & \mathbf{u}_2 \\ 0 & 0 & 0 & -\mathbf{u}_1 & -\mathbf{v}_1 & -1 & \mathbf{u}_1 \mathbf{v}_2 & \mathbf{v}_1 \mathbf{v}_2 & \mathbf{v}_2 \end{bmatrix} \begin{bmatrix} \mathbf{H}_{11} \\ \mathbf{H}_{12} \\ \mathbf{H}_{13} \\ \dots \end{bmatrix}$$

Recover Homography matrix from correspondences

Each correspondence provides two rows of A matrix

$$\begin{bmatrix} -\mathbf{u}_1 & -\mathbf{v}_1 & -1 & 0 & 0 & 0 & \mathbf{u}_1\mathbf{u}_2 & \mathbf{v}_1\mathbf{u}_2 & \mathbf{u}_2 \\ 0 & 0 & 0 & -\mathbf{u}_1 & -\mathbf{v}_1 & -1 & \mathbf{u}_1\mathbf{v}_2 & \mathbf{v}_1\mathbf{v}_2 & \mathbf{v}_2 \end{bmatrix}$$

8 equations, 9 unknowns (from 4 correspondences)

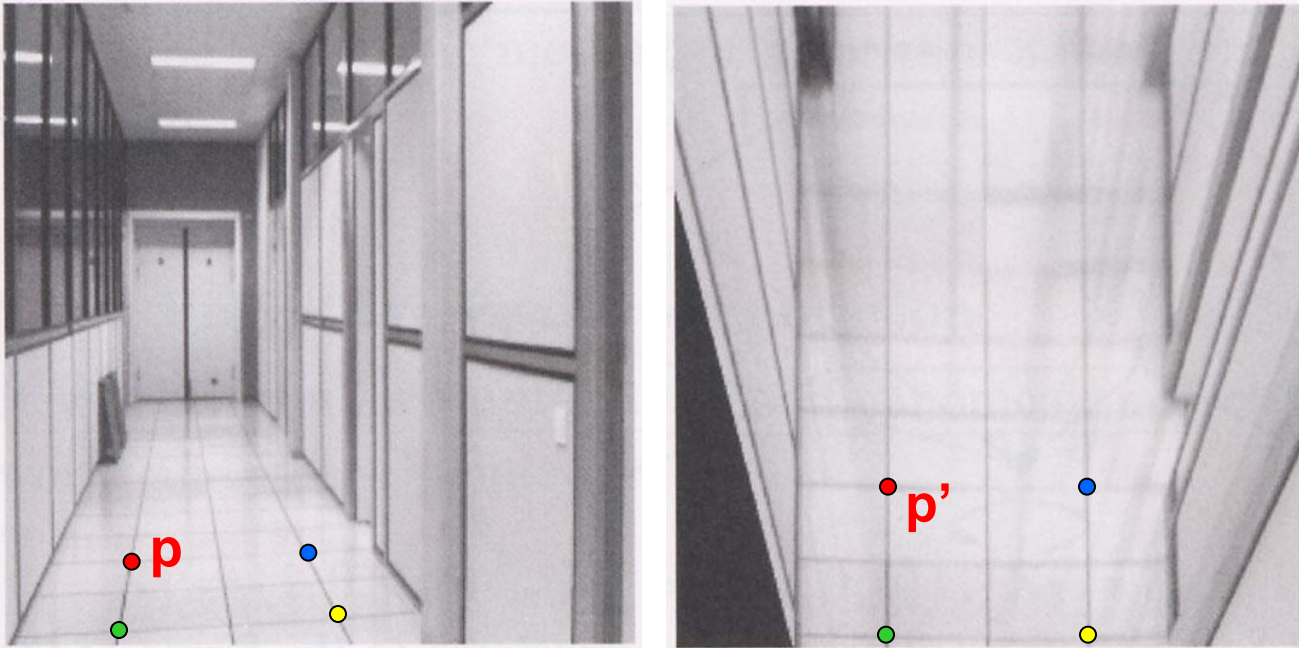
$$\begin{bmatrix} -\mathbf{u}_{11} & -\mathbf{v}_{11} & -1 & 0 & 0 & 0 & \mathbf{u}_{11}\mathbf{u}_{21} & \mathbf{v}_{11}\mathbf{u}_{21} & \mathbf{u}_{21} \\ 0 & 0 & 0 & -\mathbf{u}_{11} & -\mathbf{v}_{11} & -1 & \mathbf{u}_{11}\mathbf{v}_{21} & \mathbf{v}_{11}\mathbf{v}_{21} & \mathbf{v}_{21} \\ -\mathbf{u}_{12} & -\mathbf{v}_{12} & -1 & 0 & 0 & 0 & \mathbf{u}_{12}\mathbf{u}_{22} & \mathbf{v}_{12}\mathbf{u}_{22} & \mathbf{u}_{22} \\ 0 & 0 & 0 & -\mathbf{u}_{12} & -\mathbf{v}_{12} & -1 & \mathbf{u}_{12}\mathbf{v}_{22} & \mathbf{v}_{12}\mathbf{v}_{22} & \mathbf{v}_{22} \\ -\mathbf{u}_{13} & -\mathbf{v}_{13} & -1 & 0 & 0 & 0 & \mathbf{u}_{13}\mathbf{u}_{23} & \mathbf{v}_{13}\mathbf{u}_{23} & \mathbf{u}_{23} \\ 0 & 0 & 0 & -\mathbf{u}_{13} & -\mathbf{v}_{13} & -1 & \mathbf{u}_{13}\mathbf{v}_{23} & \mathbf{v}_{13}\mathbf{v}_{23} & \mathbf{v}_{23} \\ -\mathbf{u}_{14} & -\mathbf{v}_{14} & -1 & 0 & 0 & 0 & \mathbf{u}_{14}\mathbf{u}_{24} & \mathbf{v}_{14}\mathbf{u}_{24} & \mathbf{u}_{24} \\ 0 & 0 & 0 & -\mathbf{u}_{14} & -\mathbf{v}_{14} & -1 & \mathbf{u}_{14}\mathbf{v}_{24} & \mathbf{v}_{14}\mathbf{v}_{24} & \mathbf{v}_{24} \end{bmatrix} \begin{bmatrix} \mathbf{H}_{11} \\ \mathbf{H}_{12} \\ \mathbf{H}_{13} \\ \mathbf{H}_{21} \\ \mathbf{H}_{22} \\ \mathbf{H}_{23} \\ \mathbf{H}_{31} \\ \mathbf{H}_{32} \\ \mathbf{H}_{33} \end{bmatrix} = \mathbf{0}$$

$\mathbf{AX}=\mathbf{b}$ \mathbf{X} =column vector of homography matrix elements
 Get last vector using SVD

Uses of a homography

- Consider two images (two different views of a plane, or two different rotated views)
- We can synthesize second image from first!
- Take the first image
 - With appropriate homography we can create equivalent of the second image without needing to take that image!
 - In other words, just compute the proper homography and then apply it to the first image to get a new image
 - This new image is the image we would get if we actually physically captured the second image
 - Can not do this in general (only when we are not looking at a plane or when we translate)
- What can we do with this fact?

Image rectification (square views)



To unwarped (rectify) an image

- Find the homography \mathbf{H} given a set of \mathbf{p} and \mathbf{p}' pairs
- How many correspondences are needed?
- Tricky to write \mathbf{H} analytically, but we can solve for it!
 - Find such \mathbf{H} that “best” transforms points \mathbf{p} into \mathbf{p}'
 - Use least-squares!

Original camera view



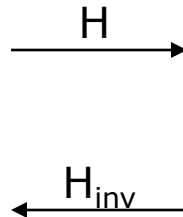
Downward rotation via homography



Sideways rotation via homography



Image Rectification using a homography matrix (from Lec 8)



Correspondences

```

u11=268; v11=10; u21=0; v21=0;
u12=558; v12=220; u22=499; v22=0;
u13=46; v13=152; u23=0; v23=399;
u14=334; v14=442; u24=499; v24=399;
    
```

```

u11=268; v11=10; u21=0; v21=0;
u12=558; v12=220; u22=499; v22=0;
u13=46; v13=152; u23=0; v23=399;
u14=334; v14=442; u24=499; v24=399;
    
```

$[u, d, v] = \text{svd}(a)$

```

xtemp=v(8*9+1:9*9)';
x=xtemp/xtemp(9)
    
```

$H = [x(1), x(2), x(3); x(4), x(5), x(6); x(7), x(8), x(9)]$

$H =$

```

0.9956 1.5566 -282.3961
-1.1124 1.5362 282.7675
-0.0000 0.0011 1.0000
    
```

$H_{inv} =$

```

0.3762 -0.5720 268.0000
0.3401 0.3042 10.0000
-0.0004 -0.0003 1.0000
    
```

```

a1 = [-u11, -v11, -1, 0, 0, 0, u11*u21, v11*u21, u21];
a2 = [0, 0, 0, -u11, -v11, -1, u11*v21, v11*v21, v21];
a3 = [-u12, -v12, -1, 0, 0, 0, u12*u22, v12*u22, u22];
a4 = [0, 0, 0, -u12, -v12, -1, u12*v22, v12*v22, v22];
a5 = [-u13, -v13, -1, 0, 0, 0, u13*u23, v13*u23, u23];
a6 = [0, 0, 0, -u13, -v13, -1, u13*v23, v13*v23, v23];
a7 = [-u14, -v14, -1, 0, 0, 0, u14*u24, v14*u24, u24];
a8 = [0, 0, 0, -u14, -v14, -1, u14*v24, v14*v24, v24];
    
```

See [matlab_lec9_solve_for_homog_matrix.txt](#)

view_homog_matrix.exe

H =

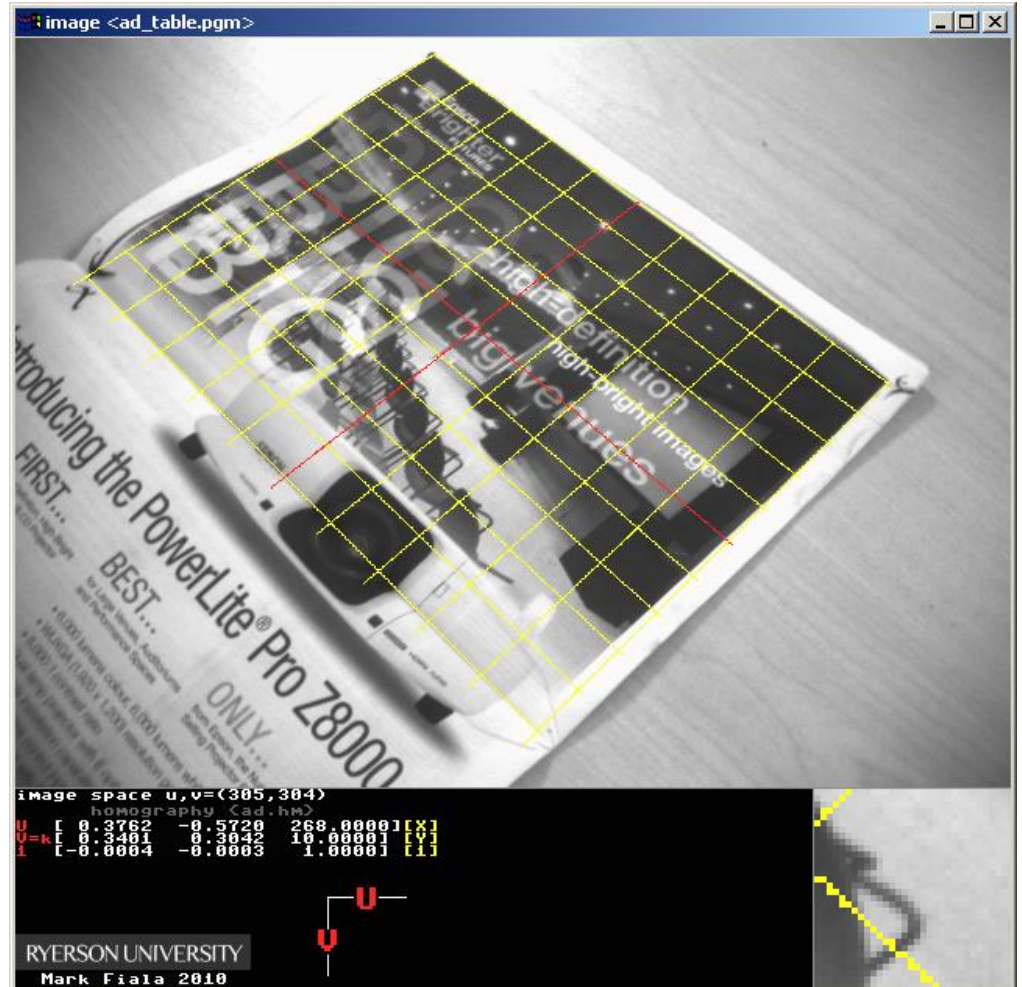
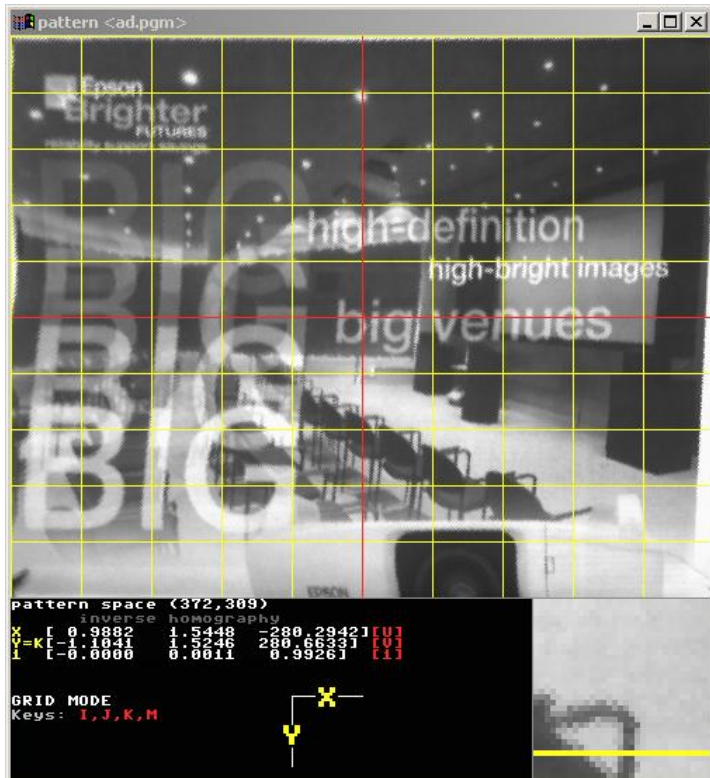
$$\begin{bmatrix} 0.3762 & -0.5720 & 268.0000 \\ 0.3401 & 0.3042 & 10.0000 \\ -0.0004 & -0.0003 & 1.0000 \end{bmatrix}$$


Image Rectification

- What are the uses of image rectification
- For a rectified image it is easy to compute object dimensions (given a known dimension)
 - Can not do this if the image is not rectified (even if you know the dimensions of an object in the image)
- A rectified image is straight on to the camera (along the z axis)
 - This geometry makes matching between two such images easier (called simple stereo matching)
 - Rectification is often done with two images in general position to place them in this standard position
 - Then stereo matching is much easier (will discuss this in the stereo section)

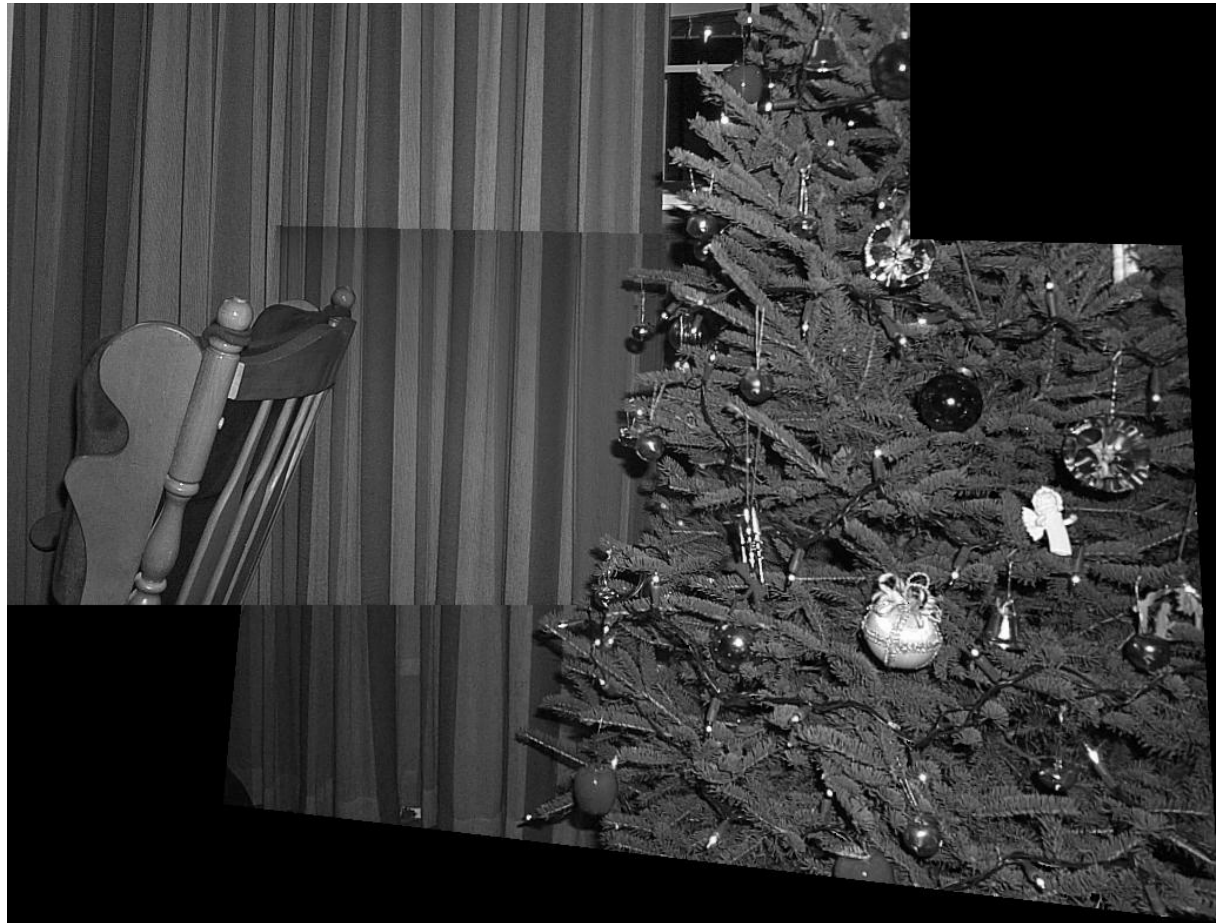
Automatic Mosaicing – Input



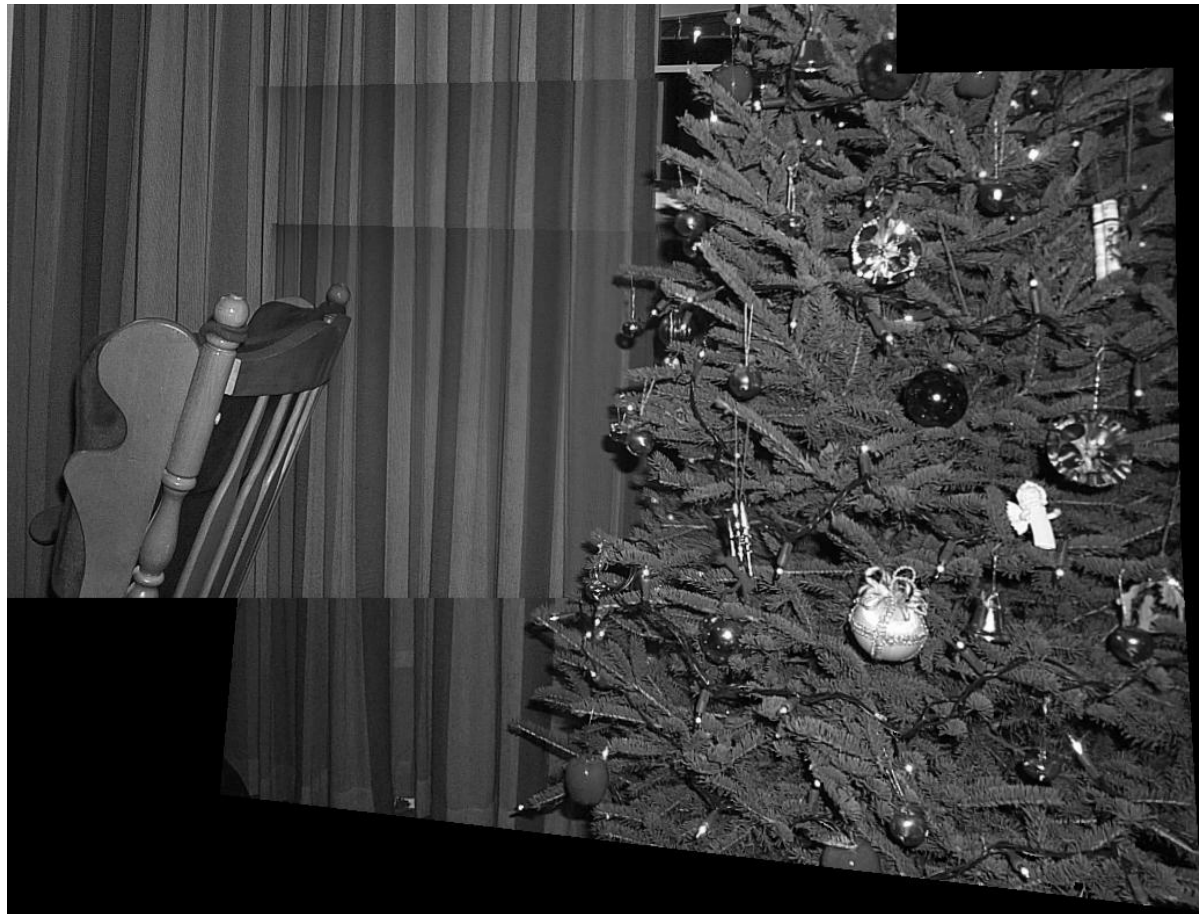
Automatic Mosaicing - Output



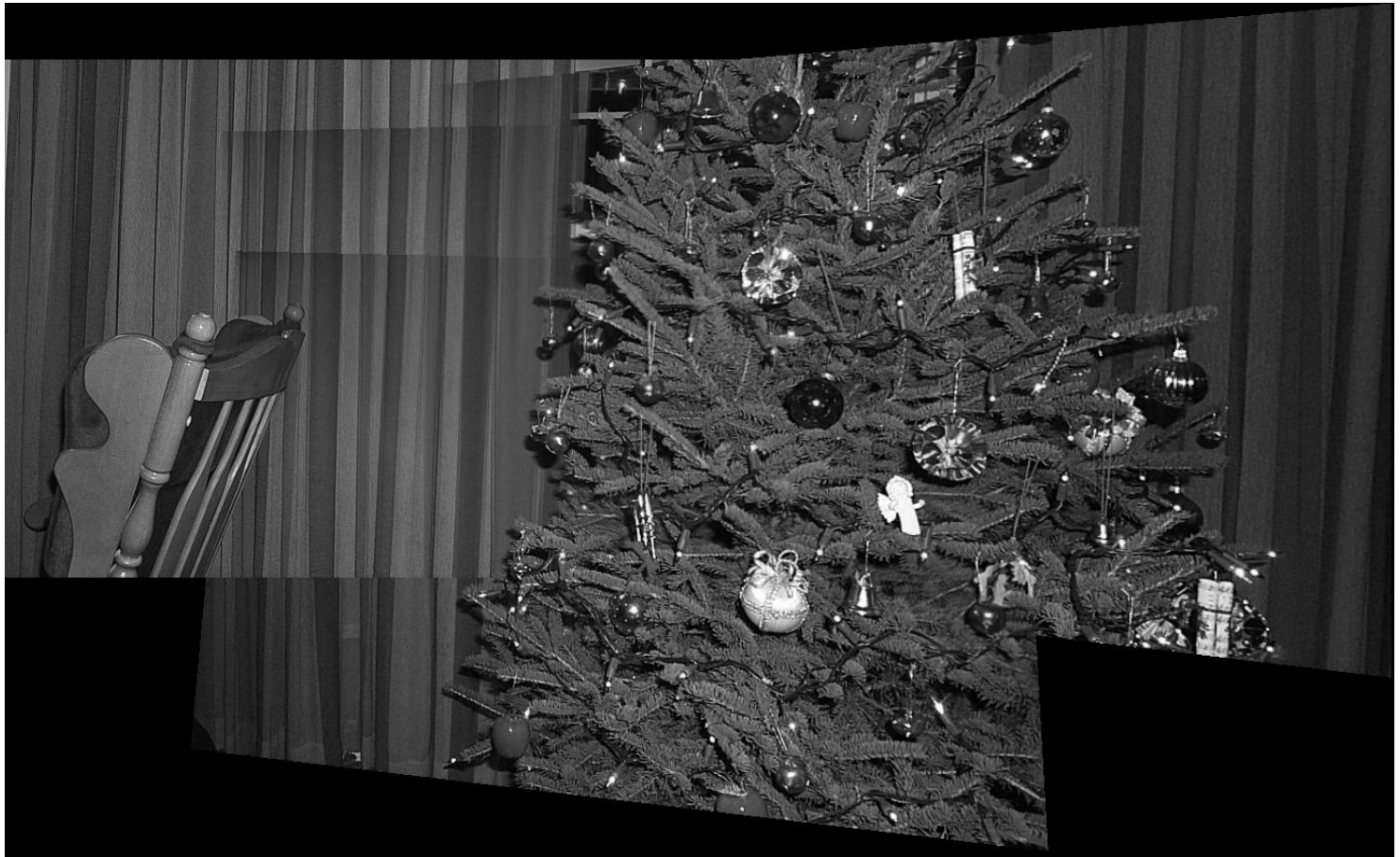
Automatic Mosaicing - Output



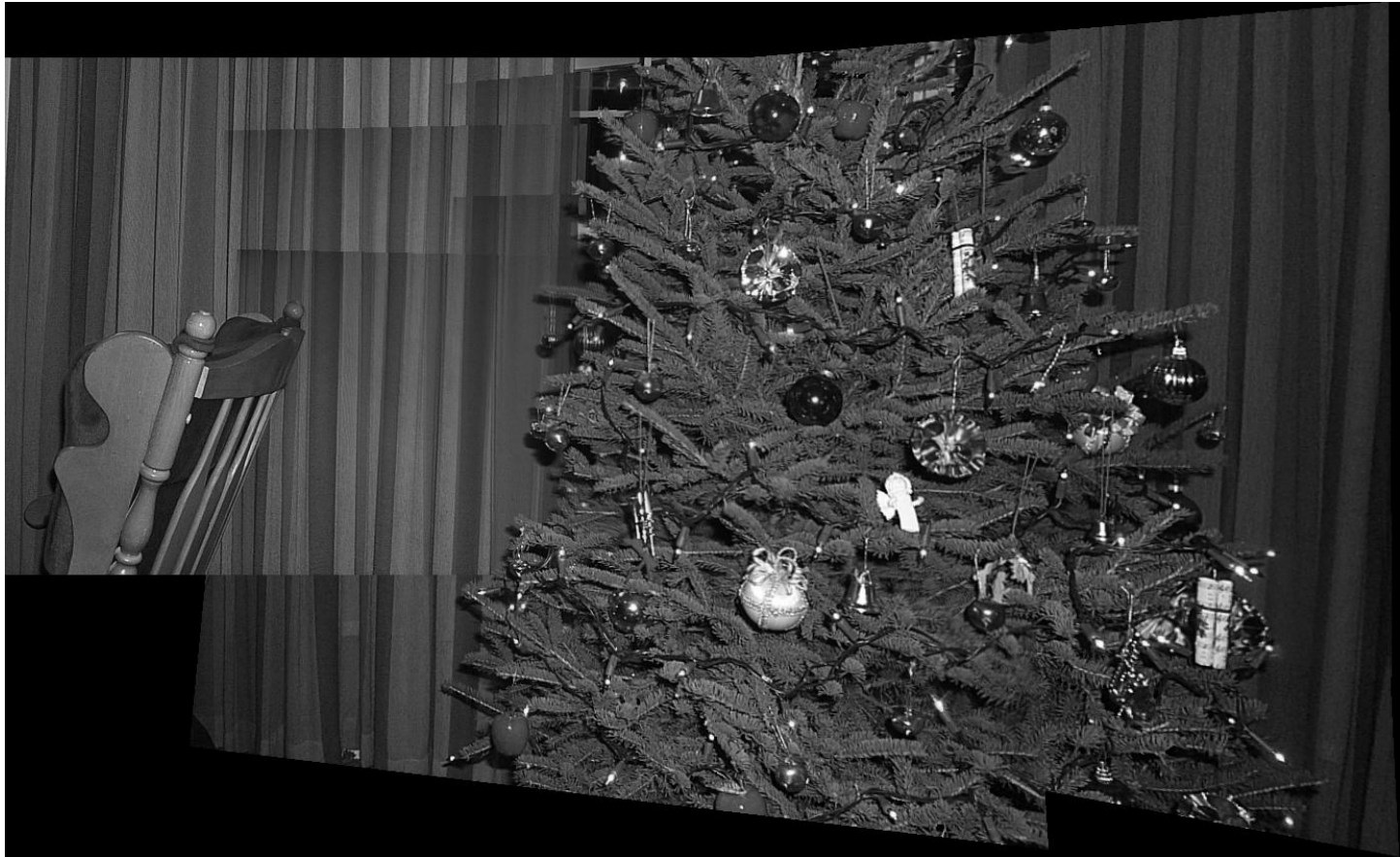
Automatic Mosaicing - Output



Automatic Mosaicing - Output



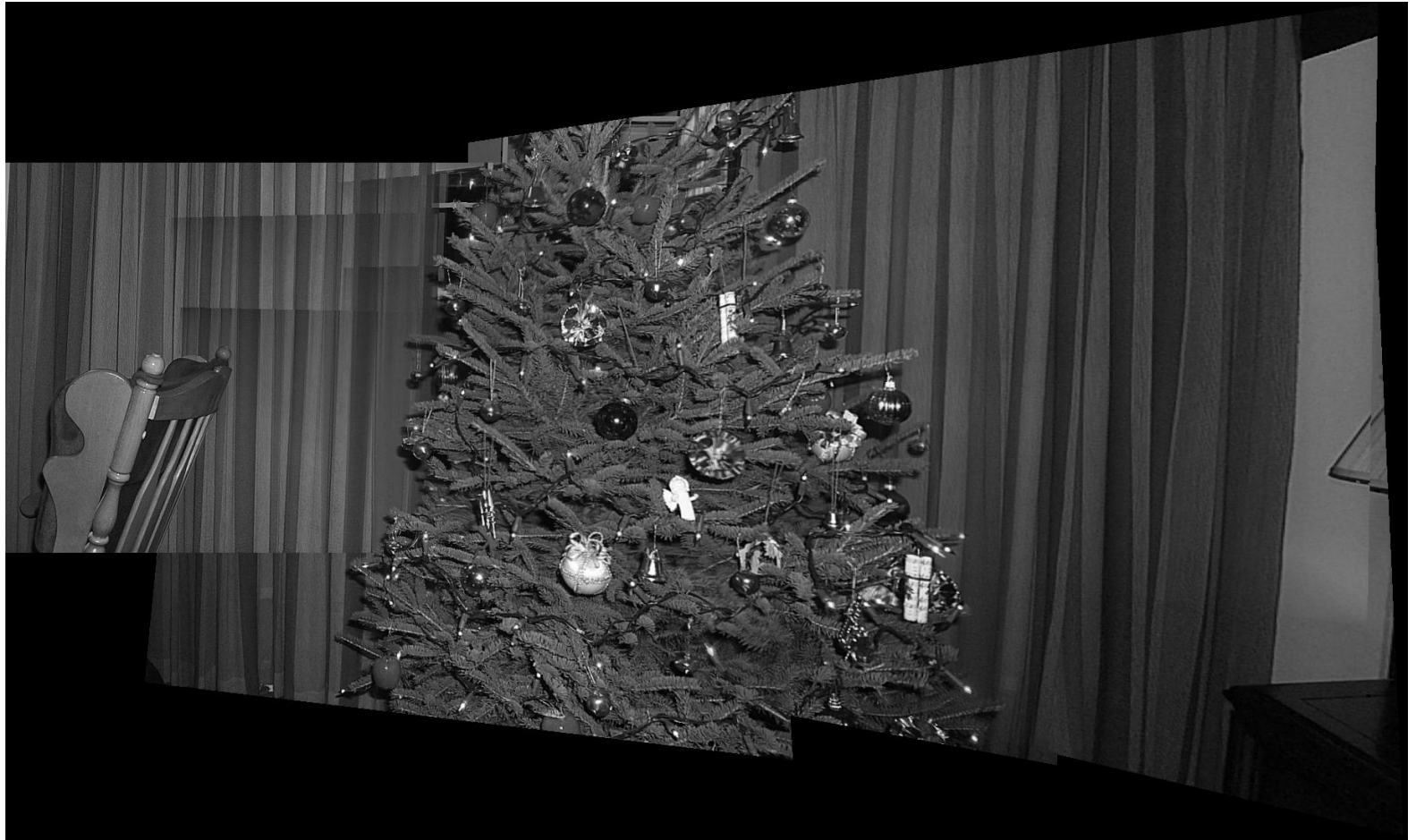
Automatic Mosaicing - Output



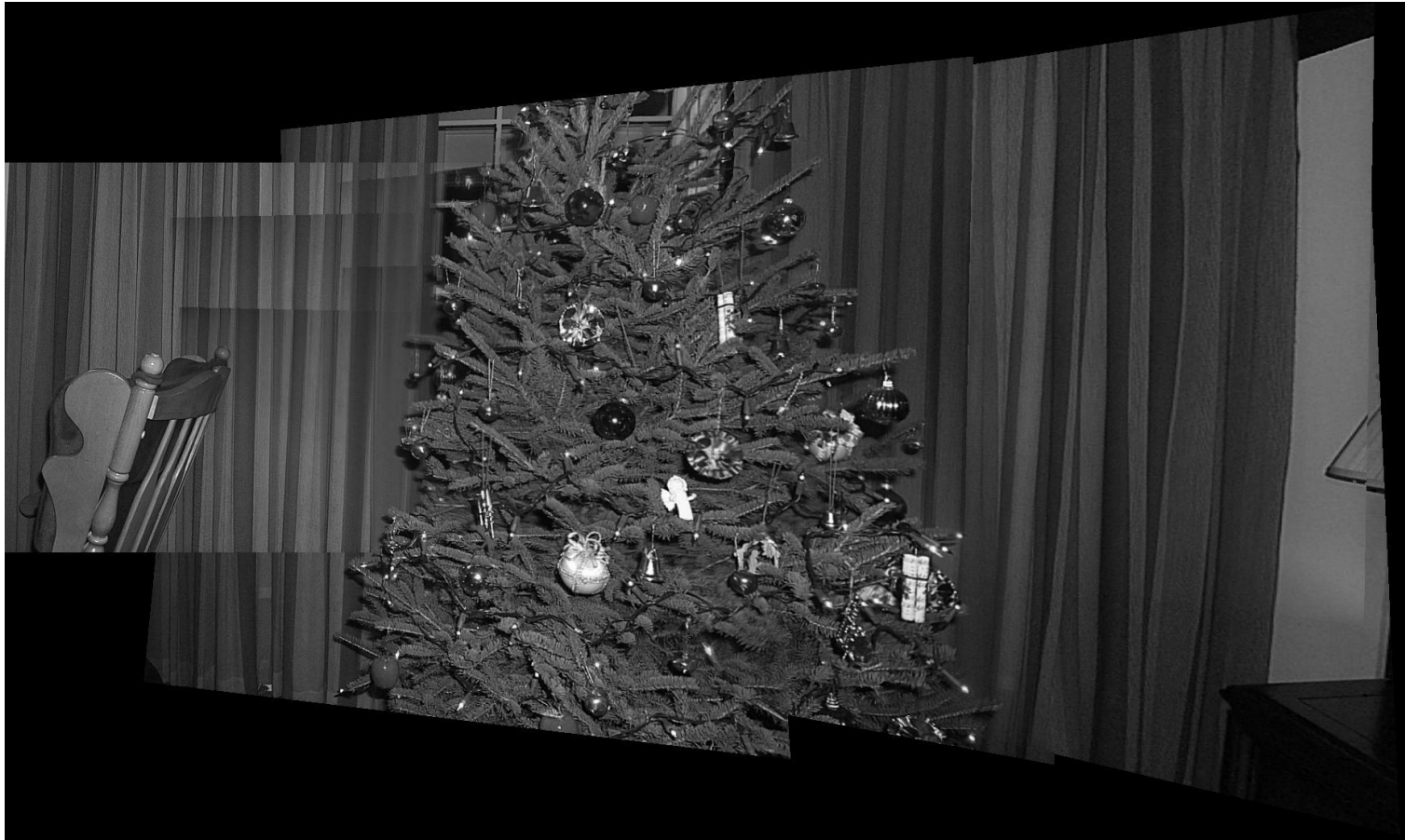
Automatic Mosaicing - Output



Automatic Mosaicing - Output



Automatic Mosaicing – Output

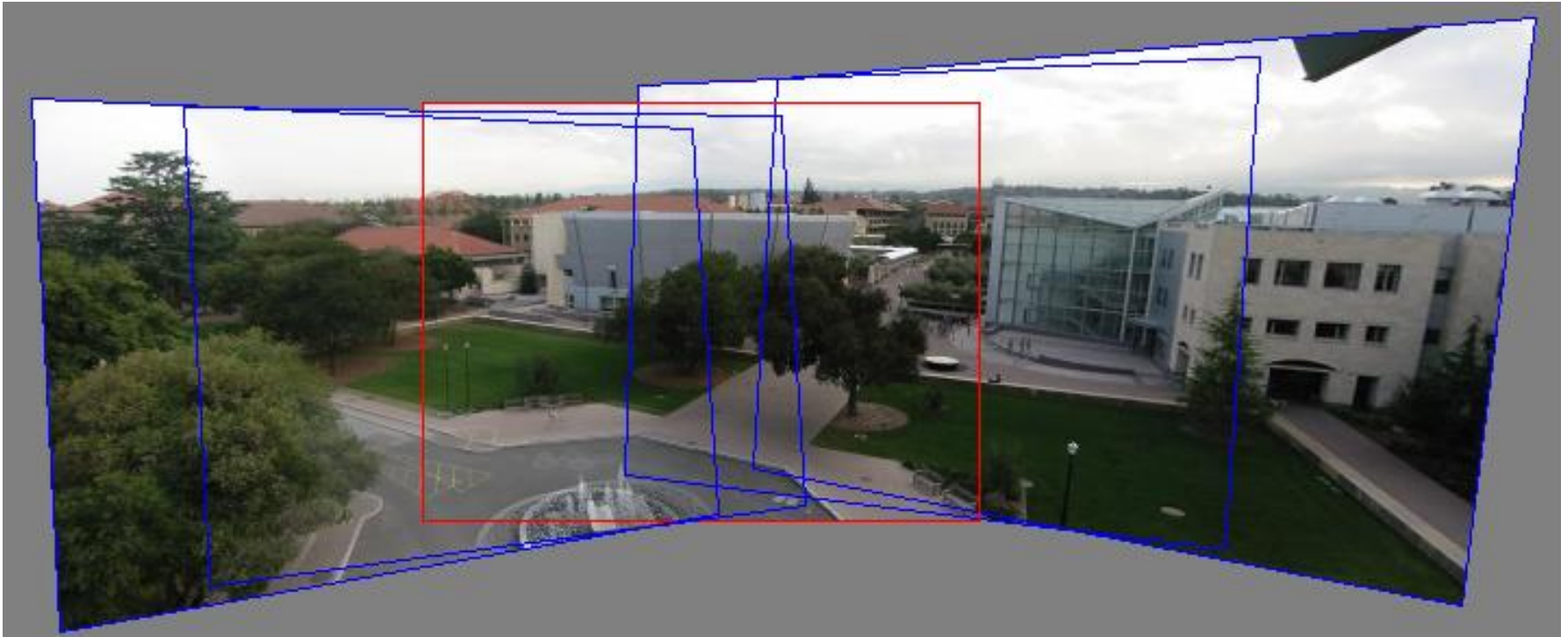


Mosaics: stitching images together



virtual wide-angle camera

Mosaics

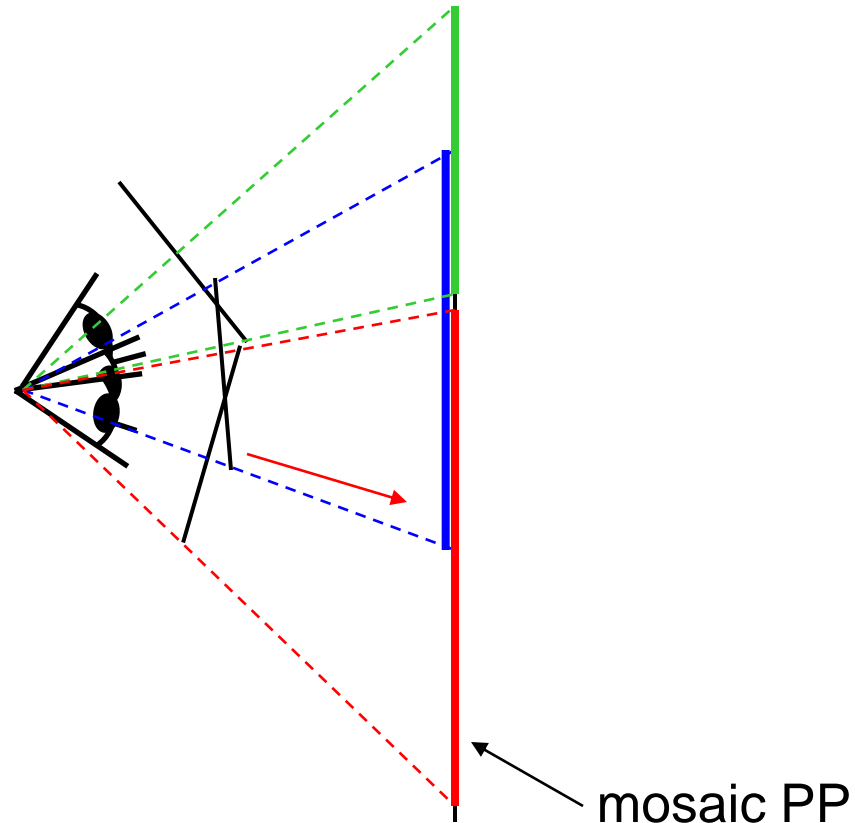


1. Pick one image (red)
2. Warp the other images towards it (usually, one by one)
3. blend

Computing a mosaic from an image set

- Take a camera on a tripod
 - Rotate it around the axis of projection
- Choose one of the images as the base image
 - Compute the homography that aligns all the other images relative to that image
- You get a single large image, a mosaic which looks like a high resolution image taken from that viewpoint
 - This large image is called a mosaic
- Sometimes mosaics are called panoramas if they are wide enough (360 degrees or close)
 - Both names (mosaic/panorama) are used

Image reprojection



The mosaic has a natural interpretation in 3D

- The images are reprojected onto a common plane
- The mosaic is formed on this plane
- Mosaic is a *synthetic wide-angle camera*

Computing special mosaics

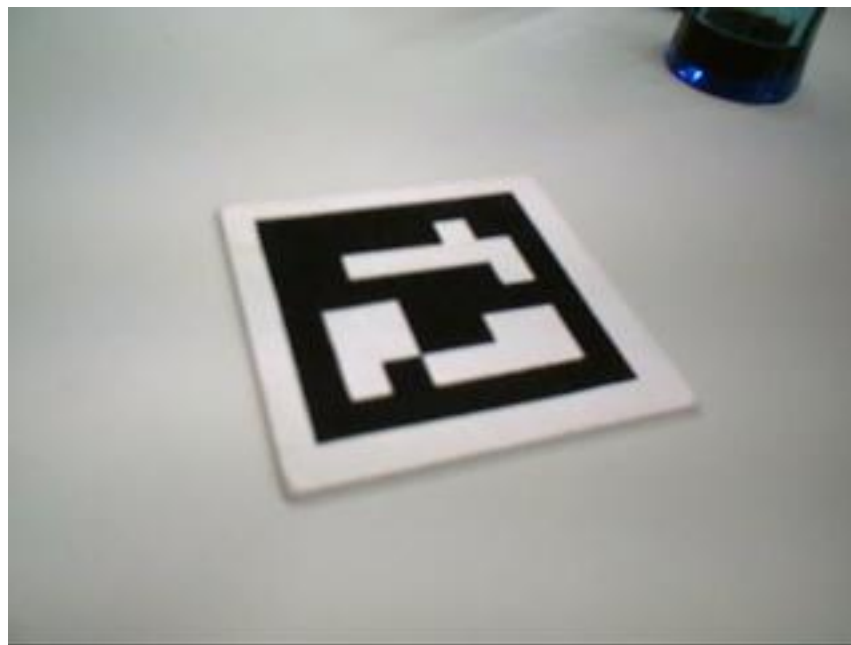
- You can synthesize any view (not a fixed reference view) to make a virtual camera
 - Need special real-time viewer to take mosaic and synthesize any rotated view
 - Use a special re-sampling algorithm to create a new view
- Quicktime VR is a panorama creation/viewing system that can do this (many others)
 - Very commonly used in many practical applications
- Microsoft ICE = automatic panorama software
 - Rotate camera through any number of views
 - Give system views in any order (and views may be zoomed)
 - As long as have sufficient overlap, panorama will be created
 - Can even create High Definition panoramas!

Augmented Reality

- Print self encoding binary pattern (tags)
- In real-time AR software
 - Recognizes the tag, and finds pixel locations of 4 corners
 - Computes homography that maps these four corner pixels to a rectified front facing image
 - Uses this homography to compute the camera pose relative to the tag in the real world
 - Draws a virtual object on top of the tag in the world
- Virtual content can be any 3d model, etc.
- Very common systems in practice and available on cell phones
 - ARToolKit and ARTag

Typical binary tag pattern

- Bit string with error correction/detection is used to create a tag ID
- Predefined association of 3d models for each different tag ID



Using Tags for Augmentation

- In real-time find camera pose relative to the tag, and use this to draw virtual objects
- AR tags get an ID and camera position!



Homography

- Very useful in practice because of mosaics!
- Rectification is also important and will be used in stereo vision and other applications
- Many common mosaicing systems exist
- But math still depends on basic homography
 - Many other issues to create an automatic mosaicing system
 - Need to extract features (interest points!)
 - Match them between images
 - Align all the images with homographies
 - Then blend them all together properly