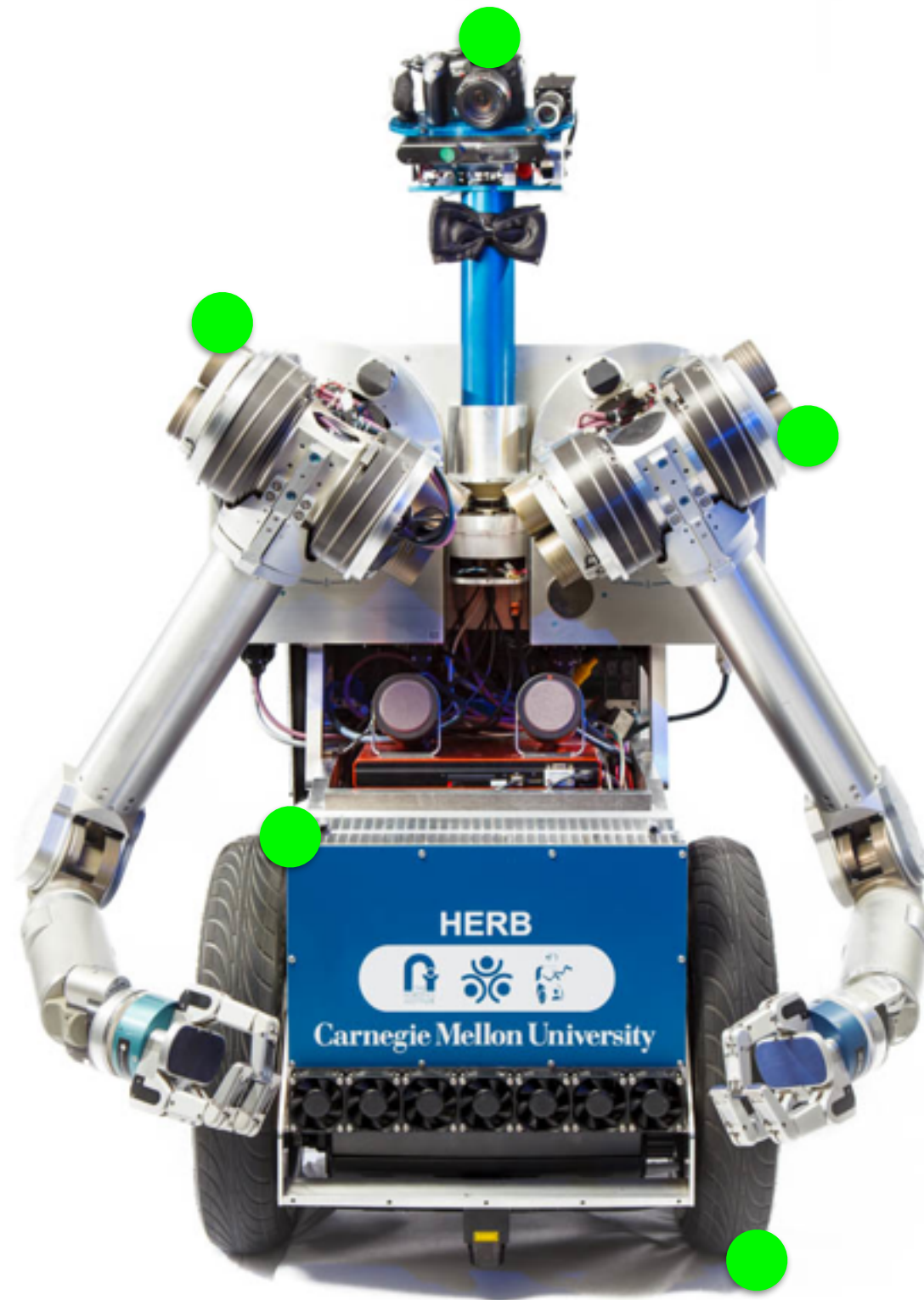


# Epipolar Geometry

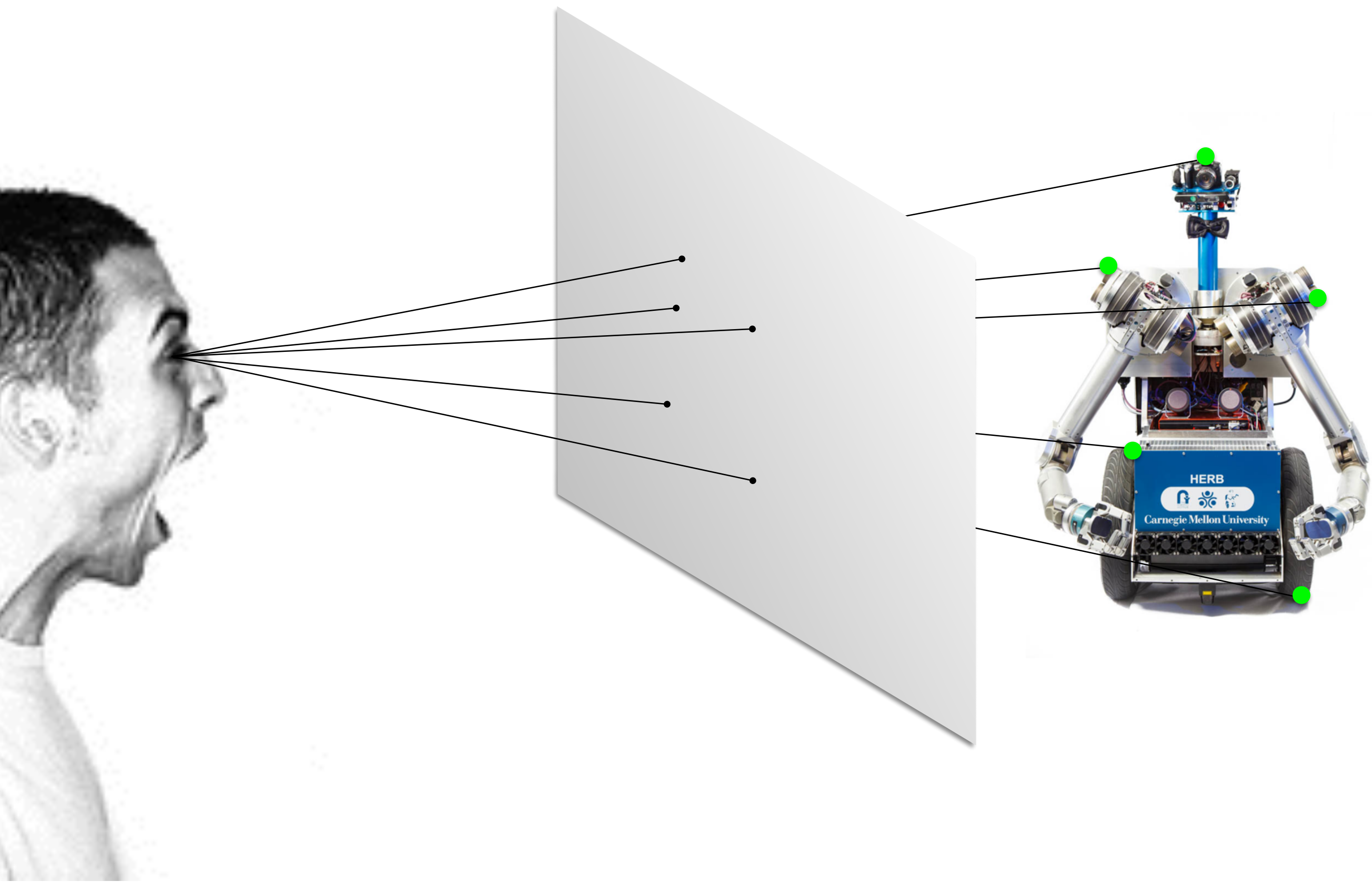
16-385 Computer Vision (Kris Kitani)  
**Carnegie Mellon University**



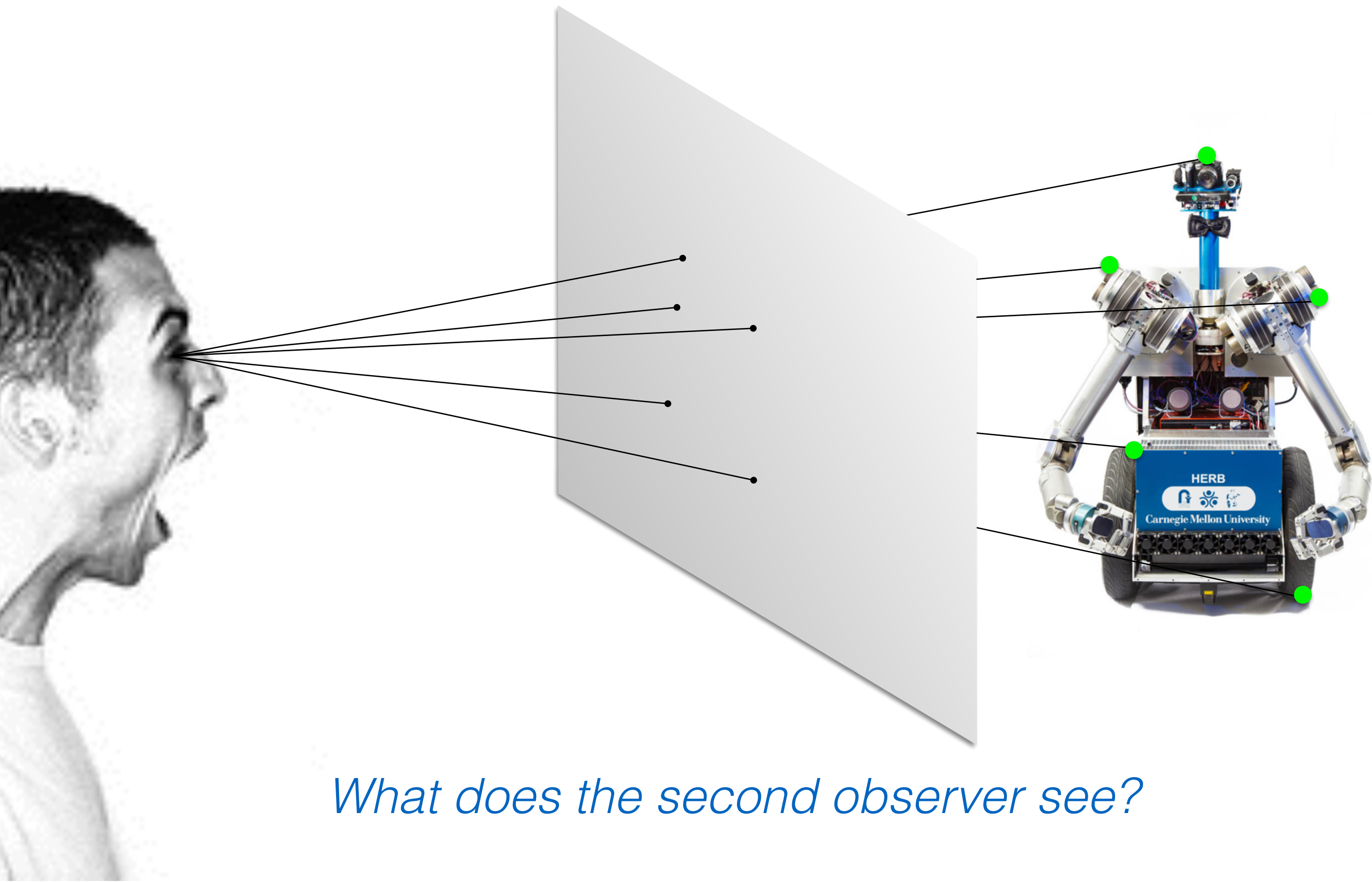


Tie tiny threads on HERB and pin them to your eyeball

*What would it look like?*

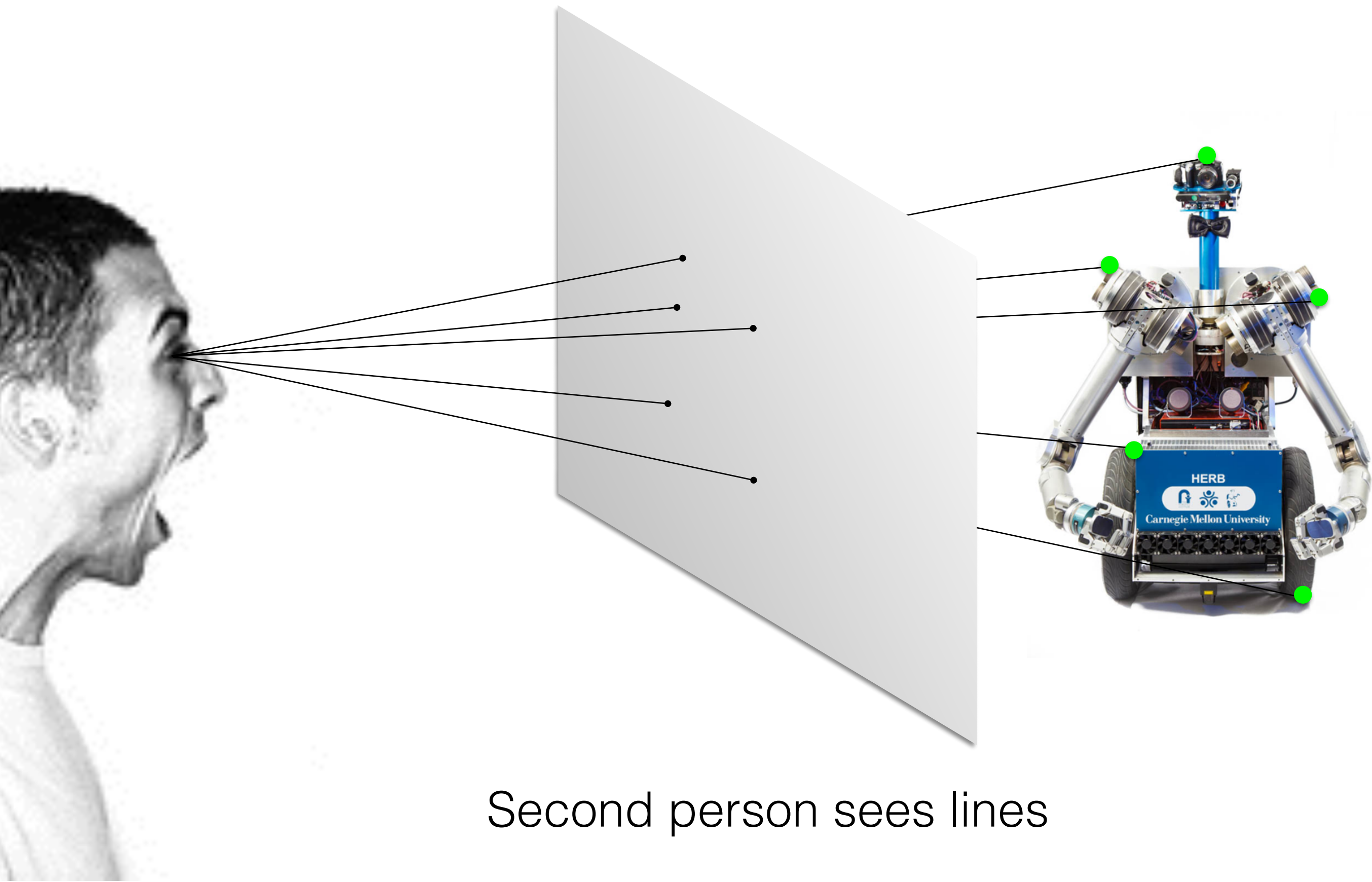


You see points on HERB



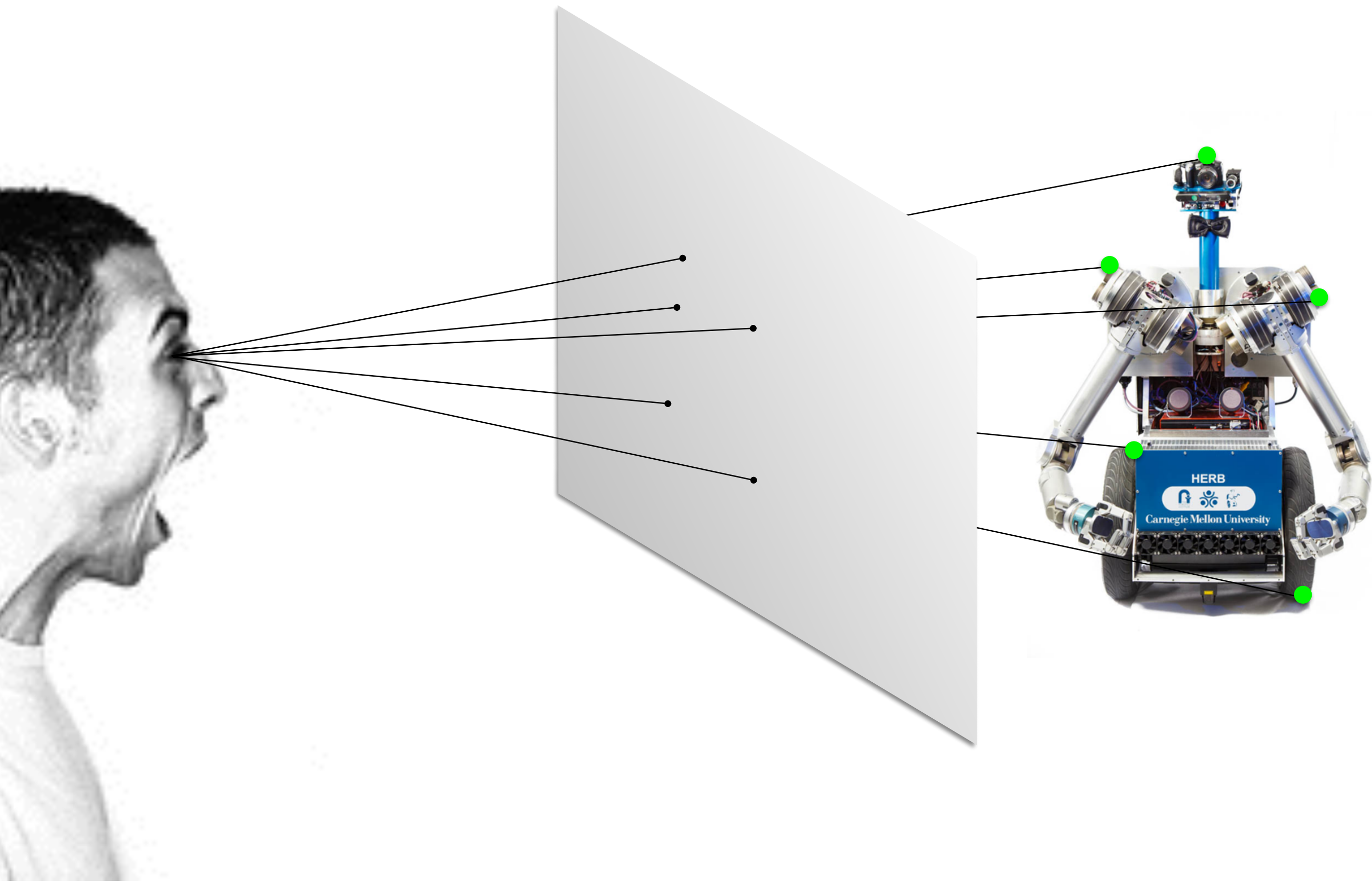
*What does the second observer see?*

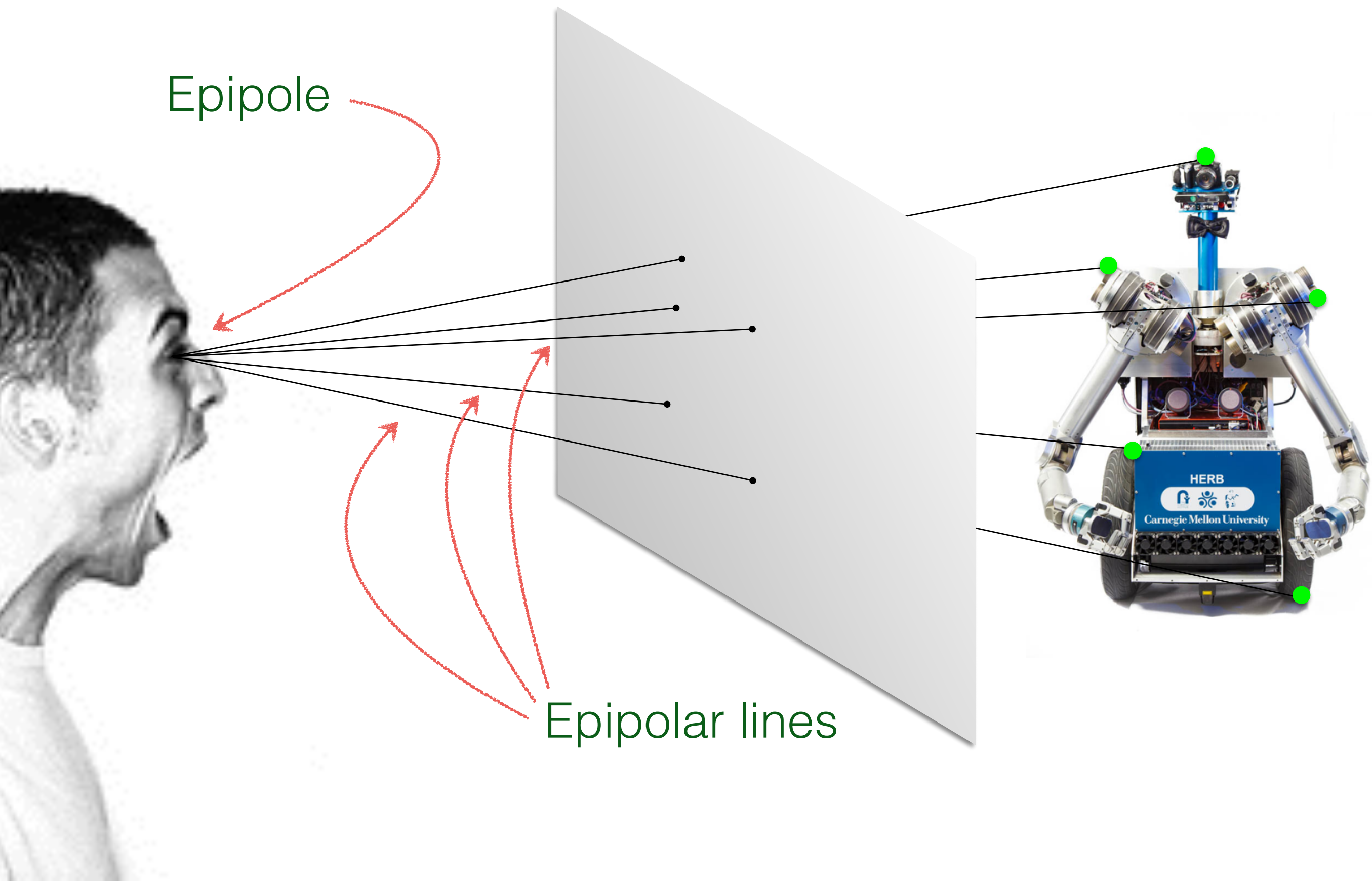
You see points on HERB



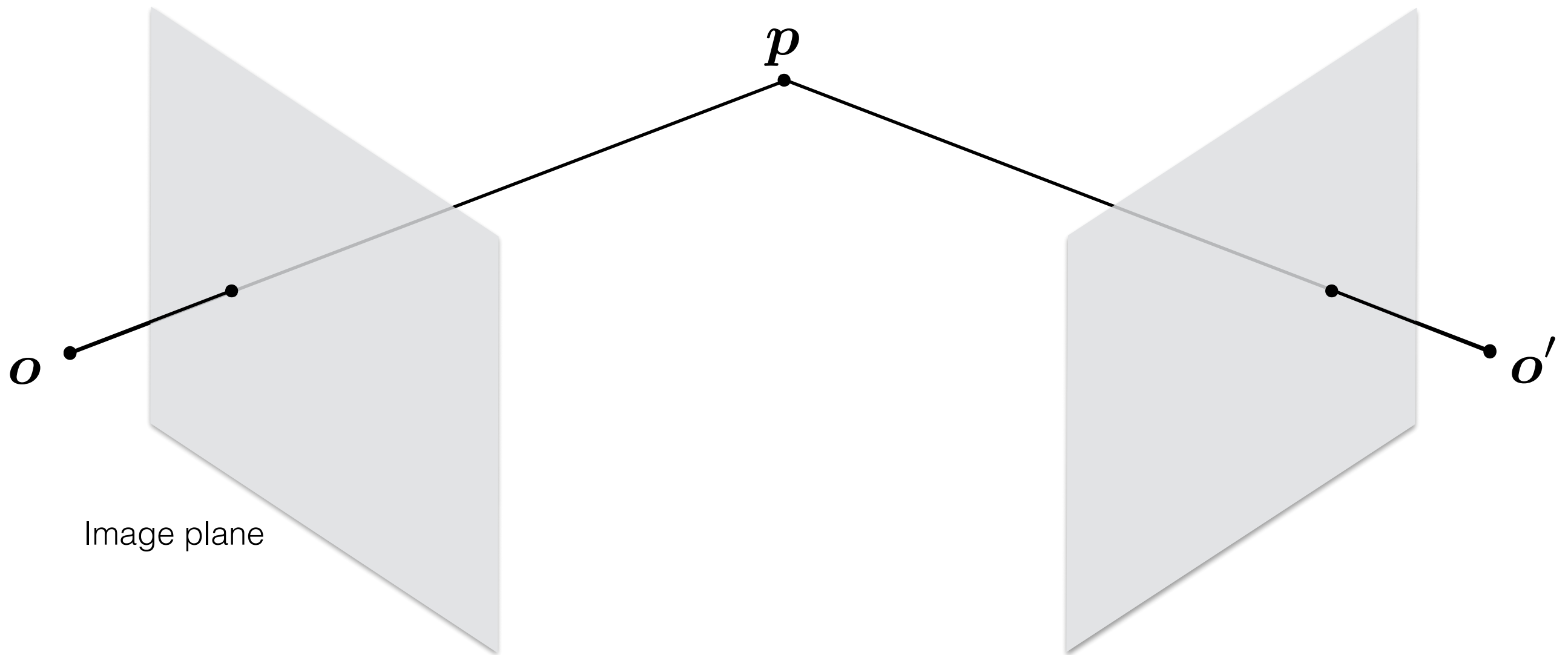


# This is Epipolar Geometry



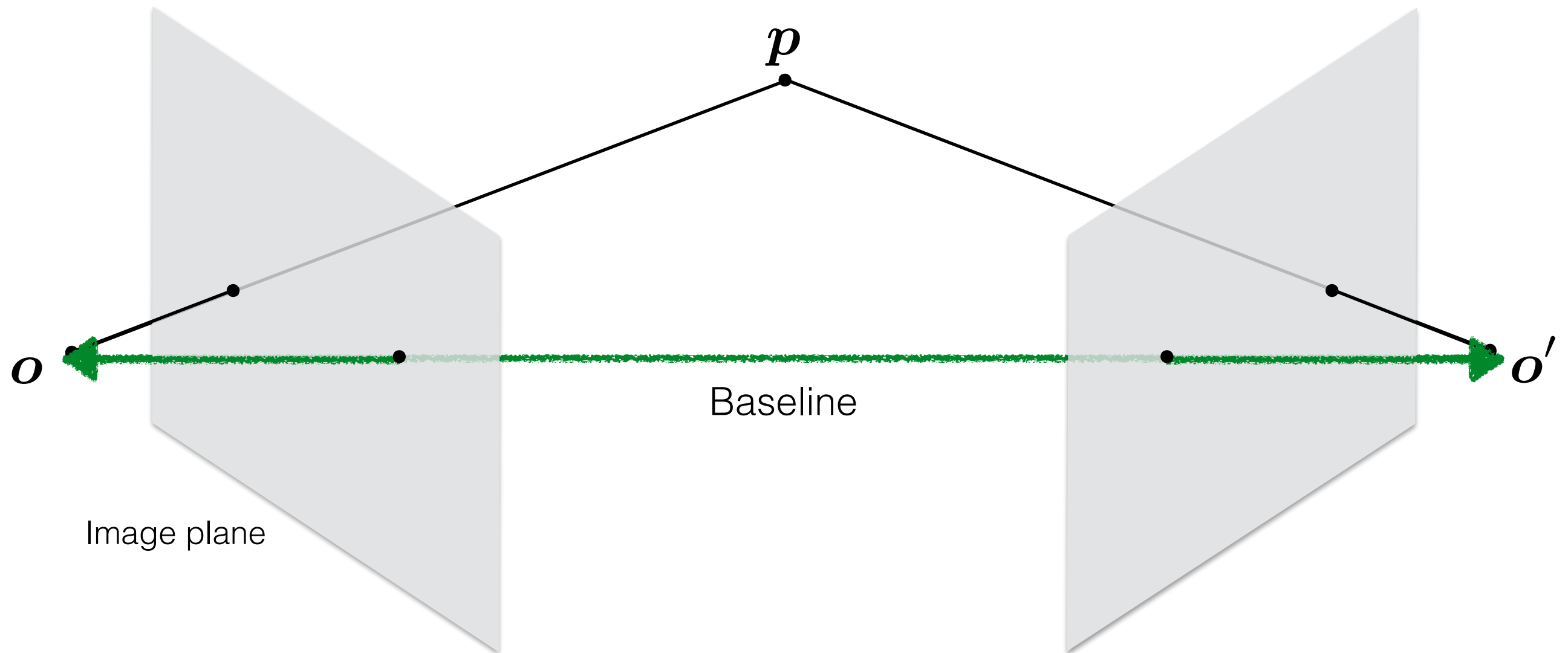


# Epipolar geometry

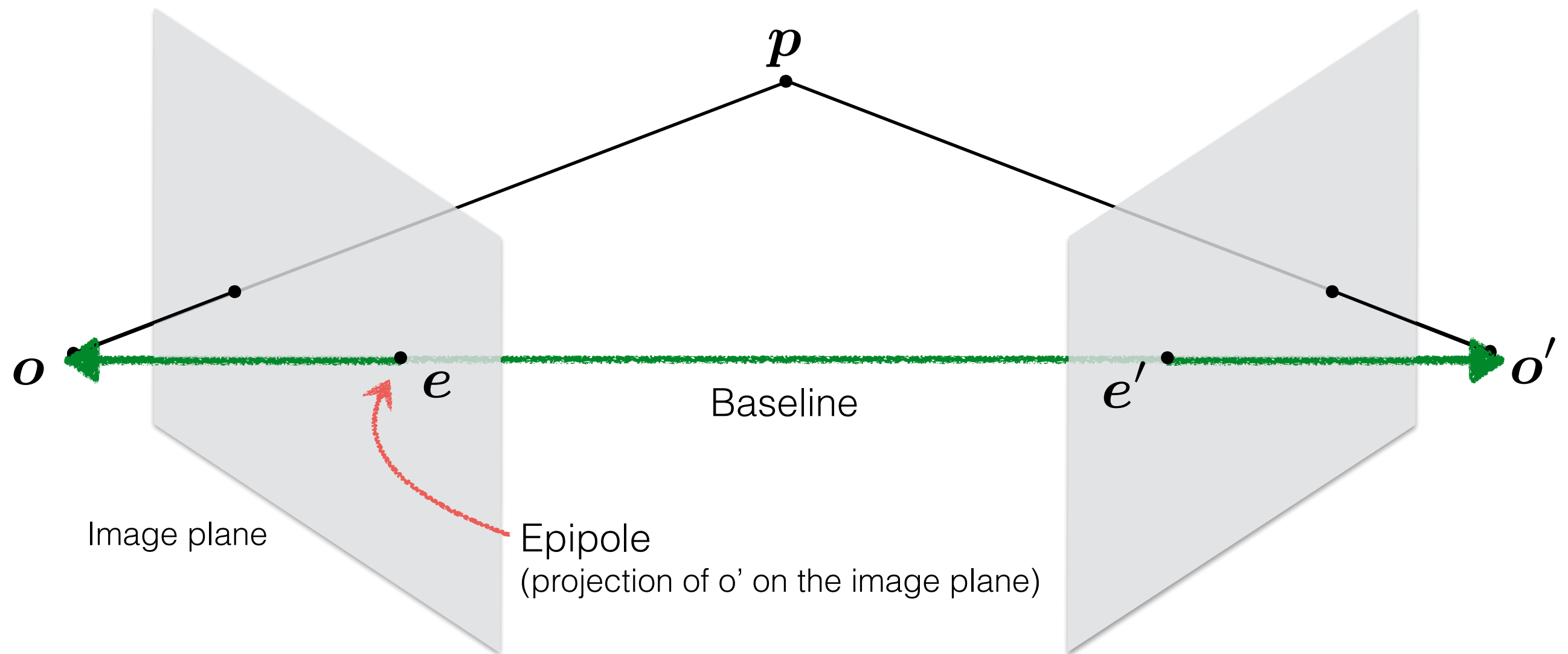




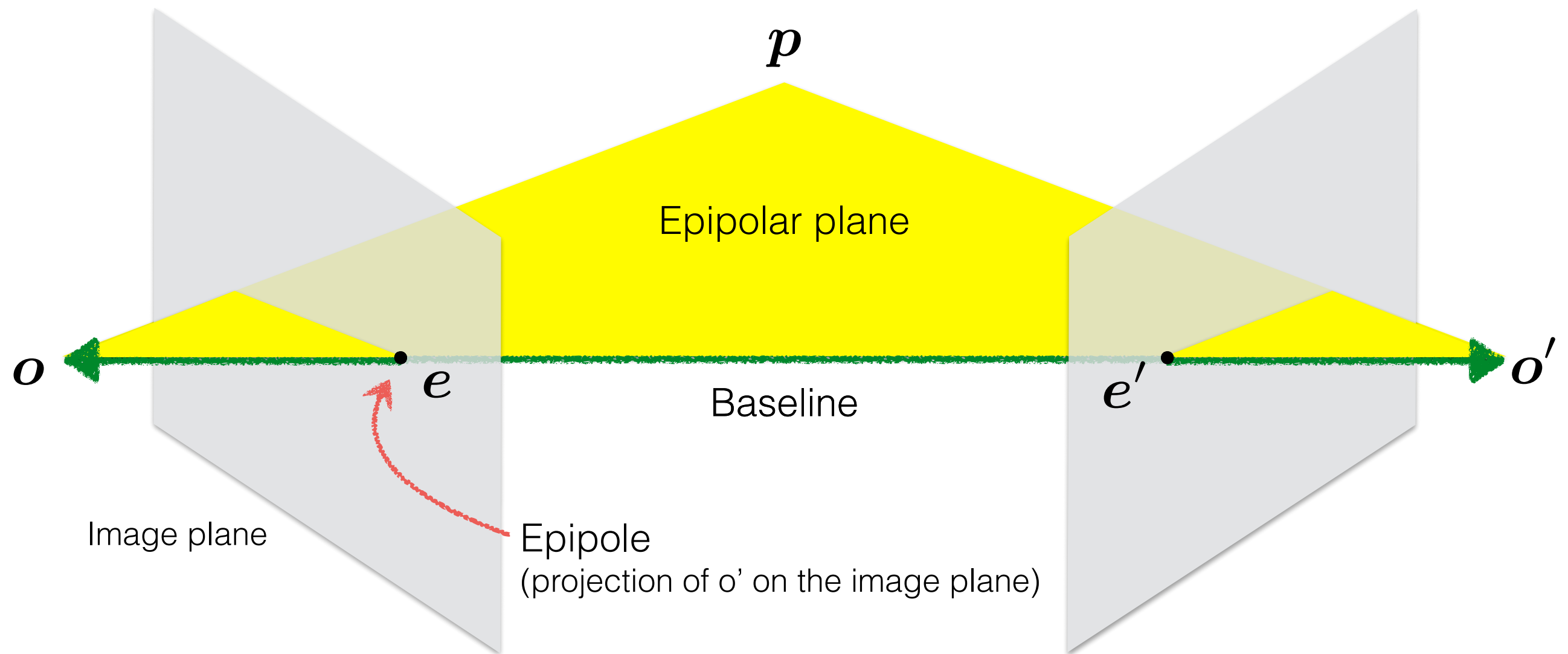
# Epipolar geometry



# Epipolar geometry

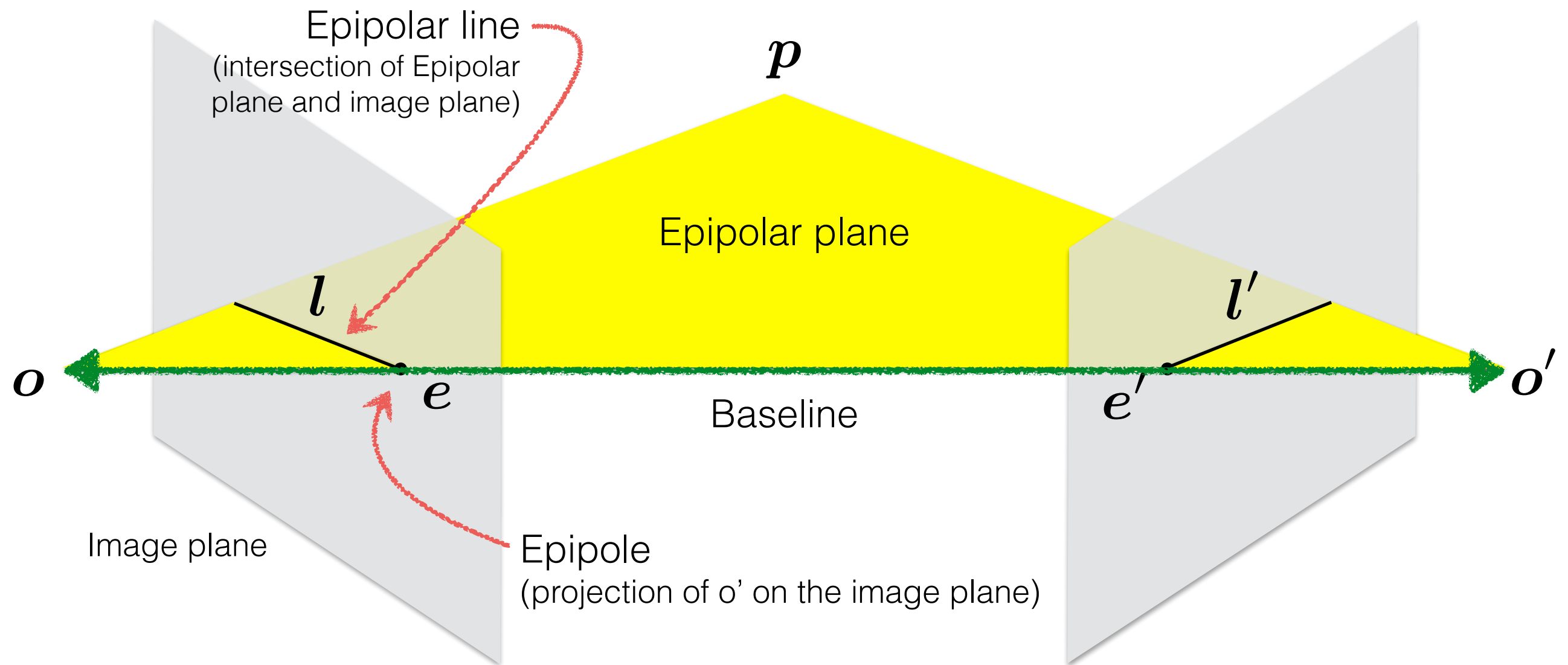


# Epipolar geometry

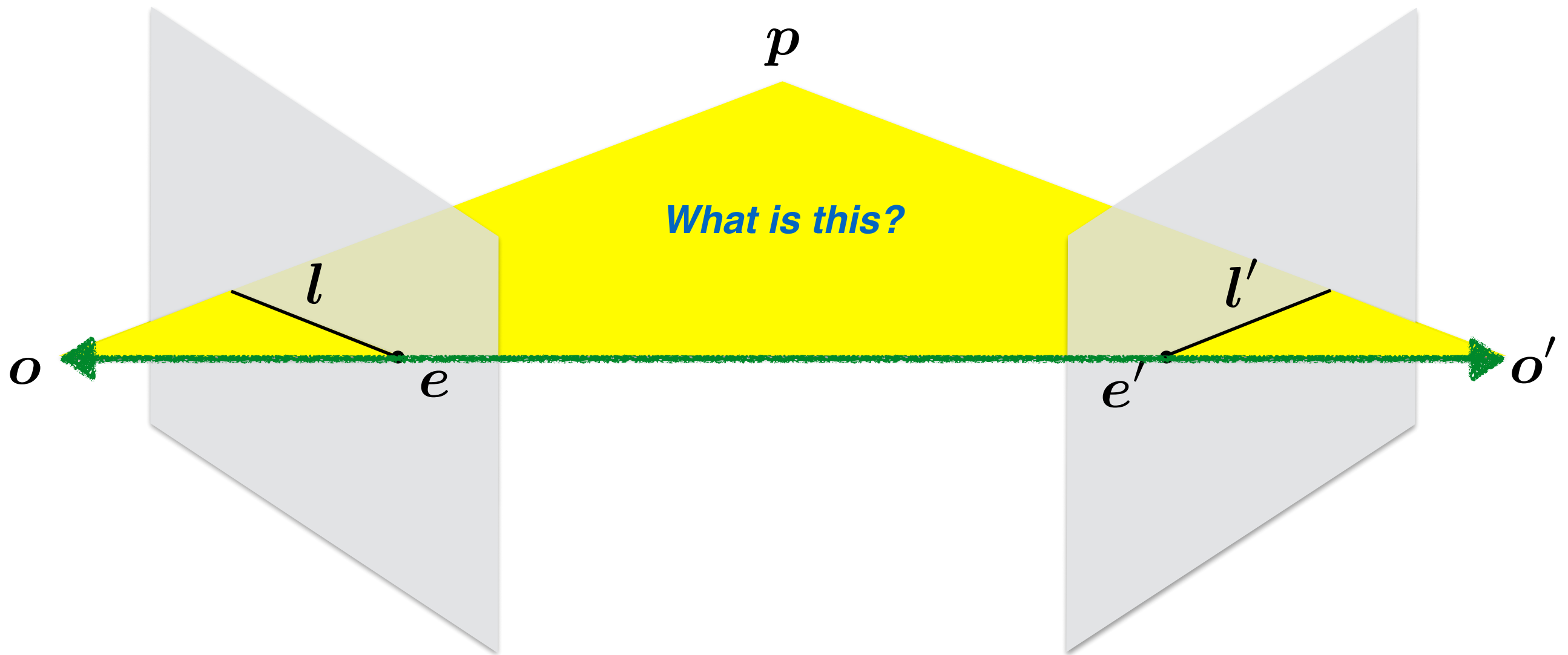




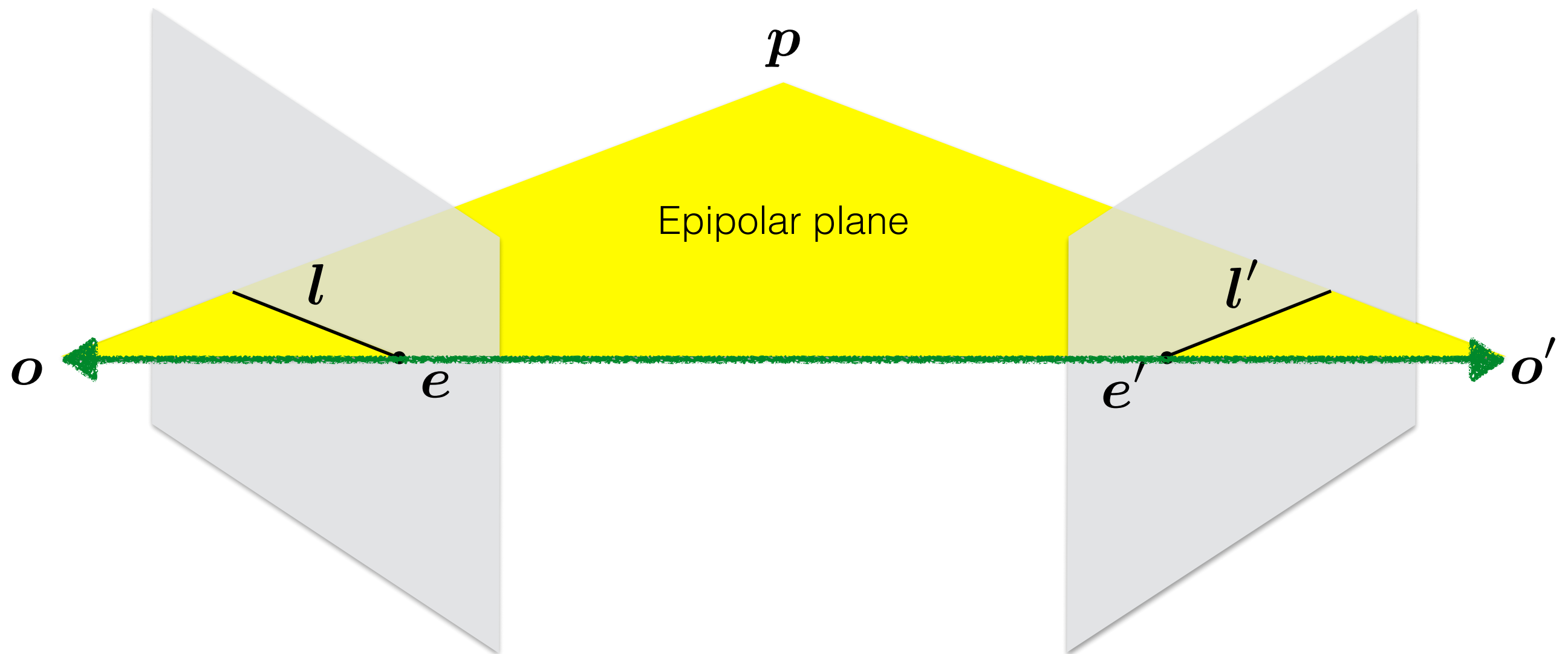
# Epipolar geometry



# Quiz

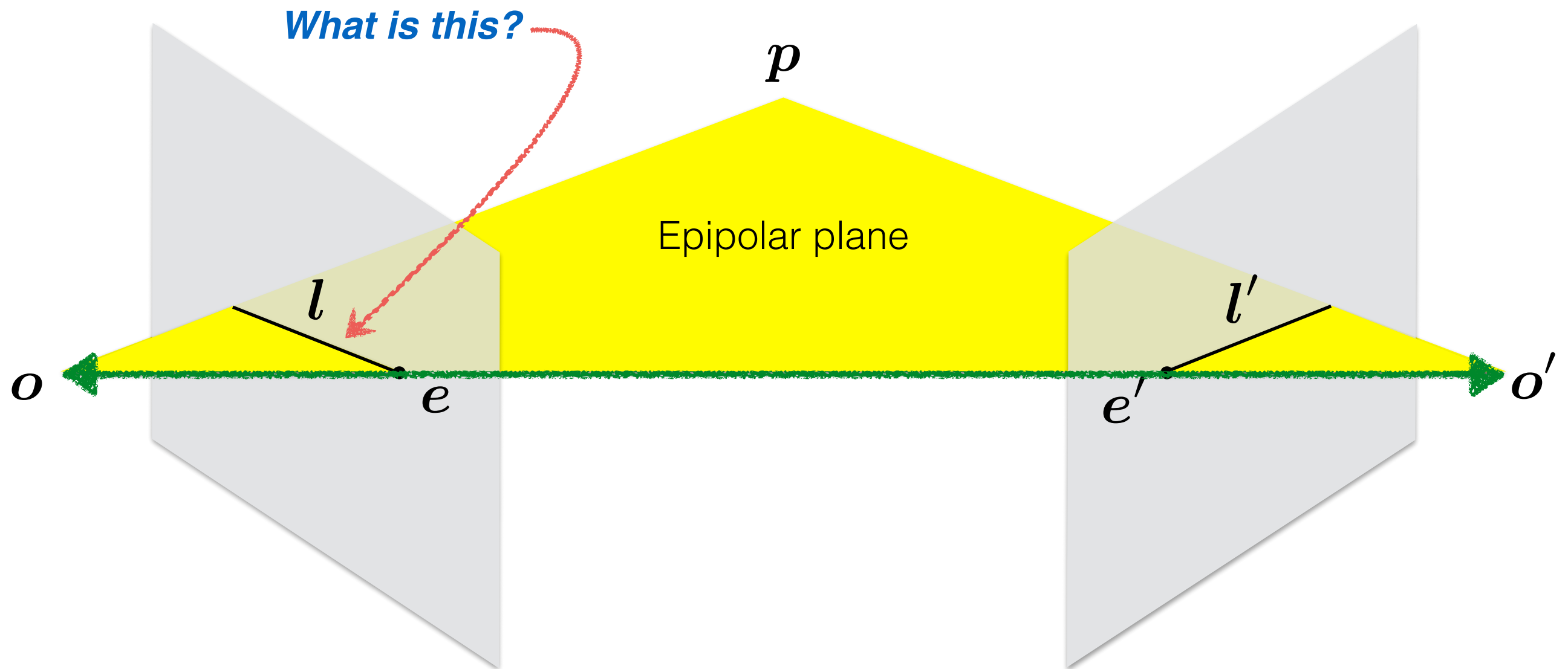


# Quiz

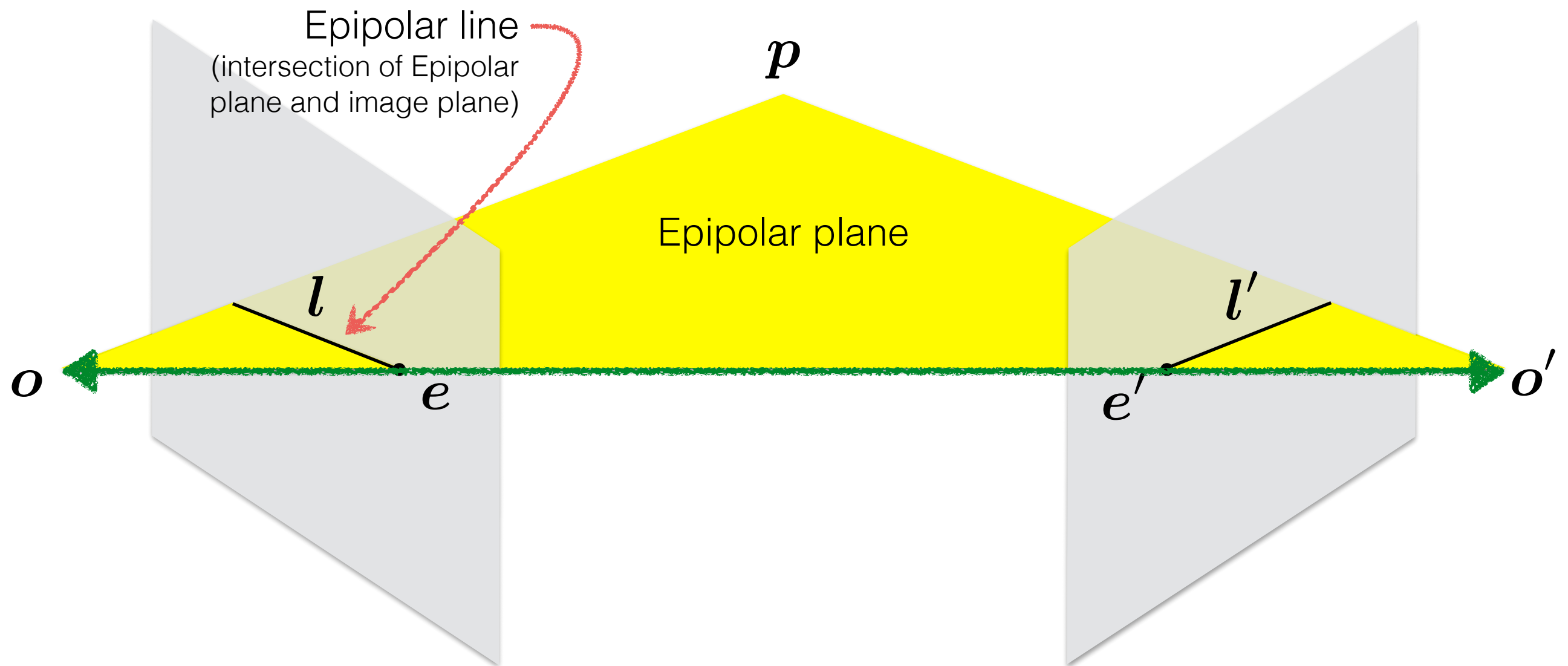




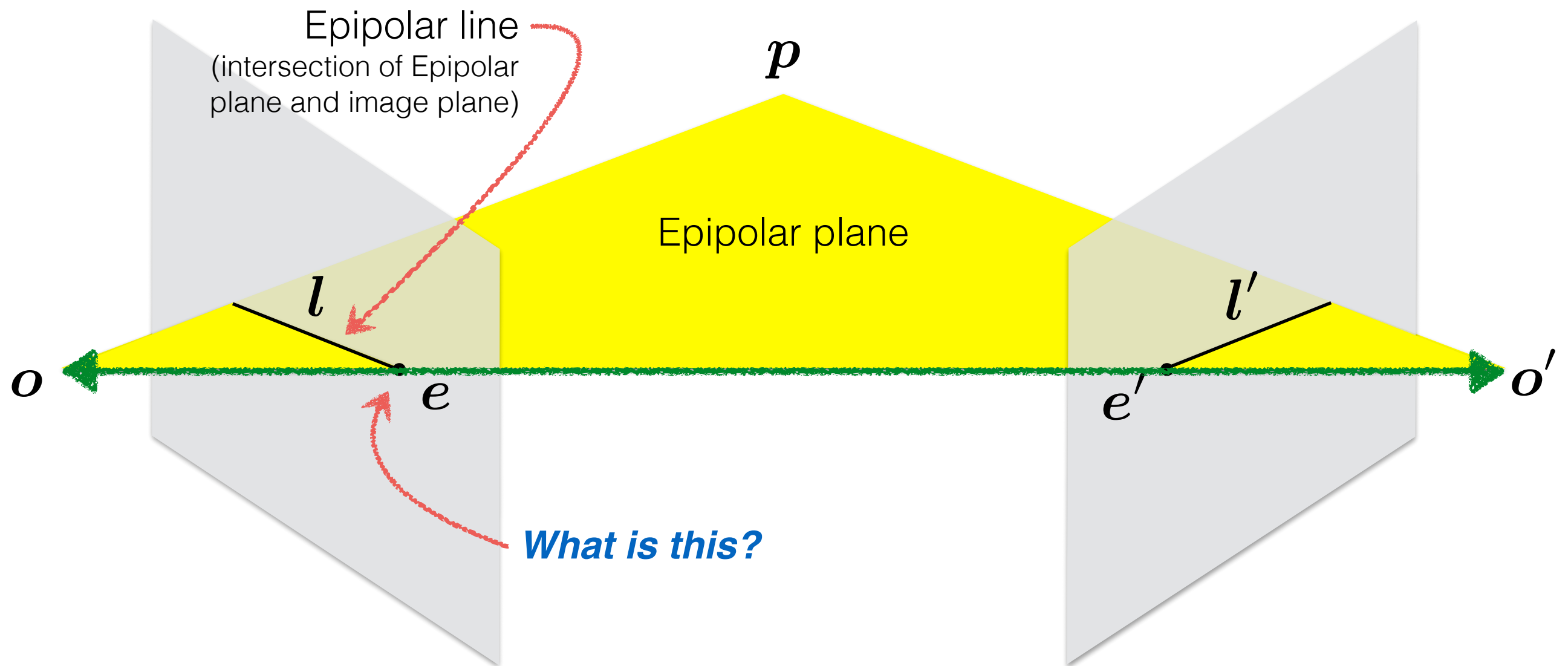
# Quiz



# Quiz

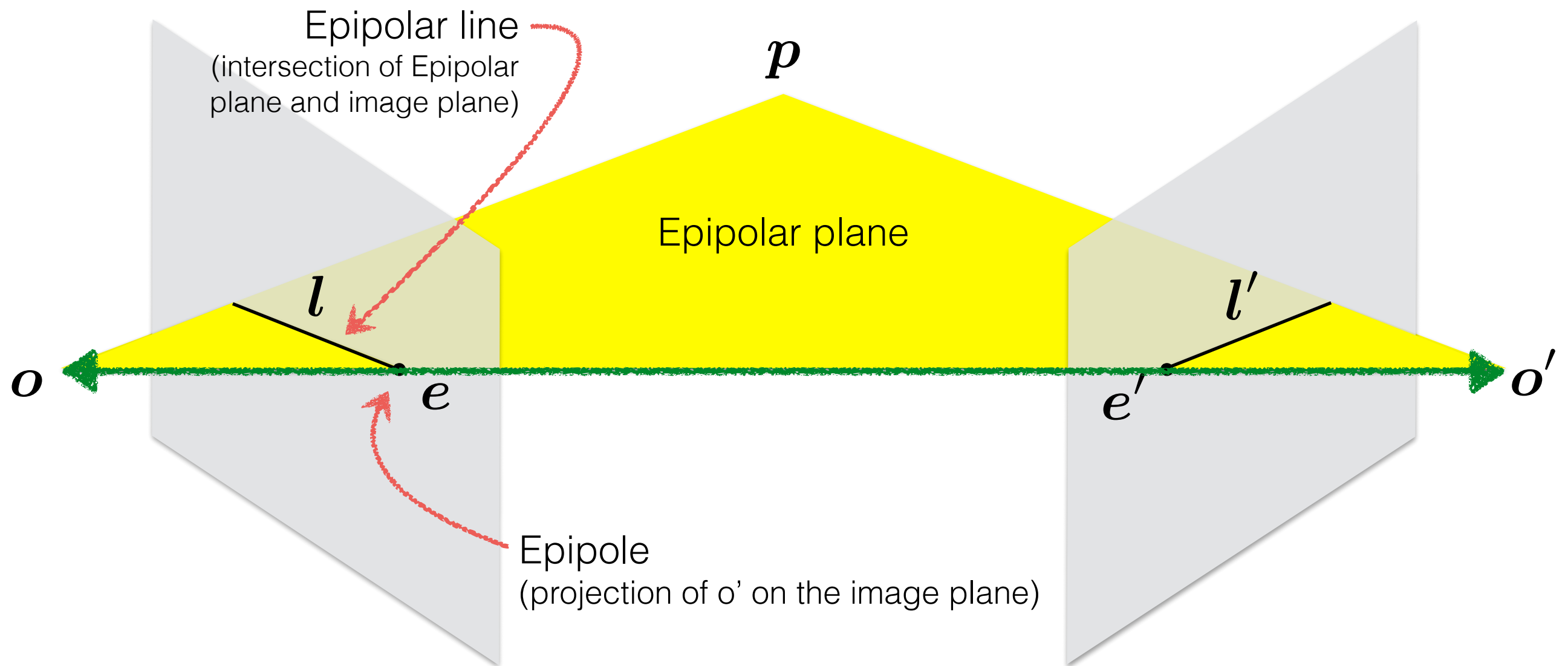


# Quiz

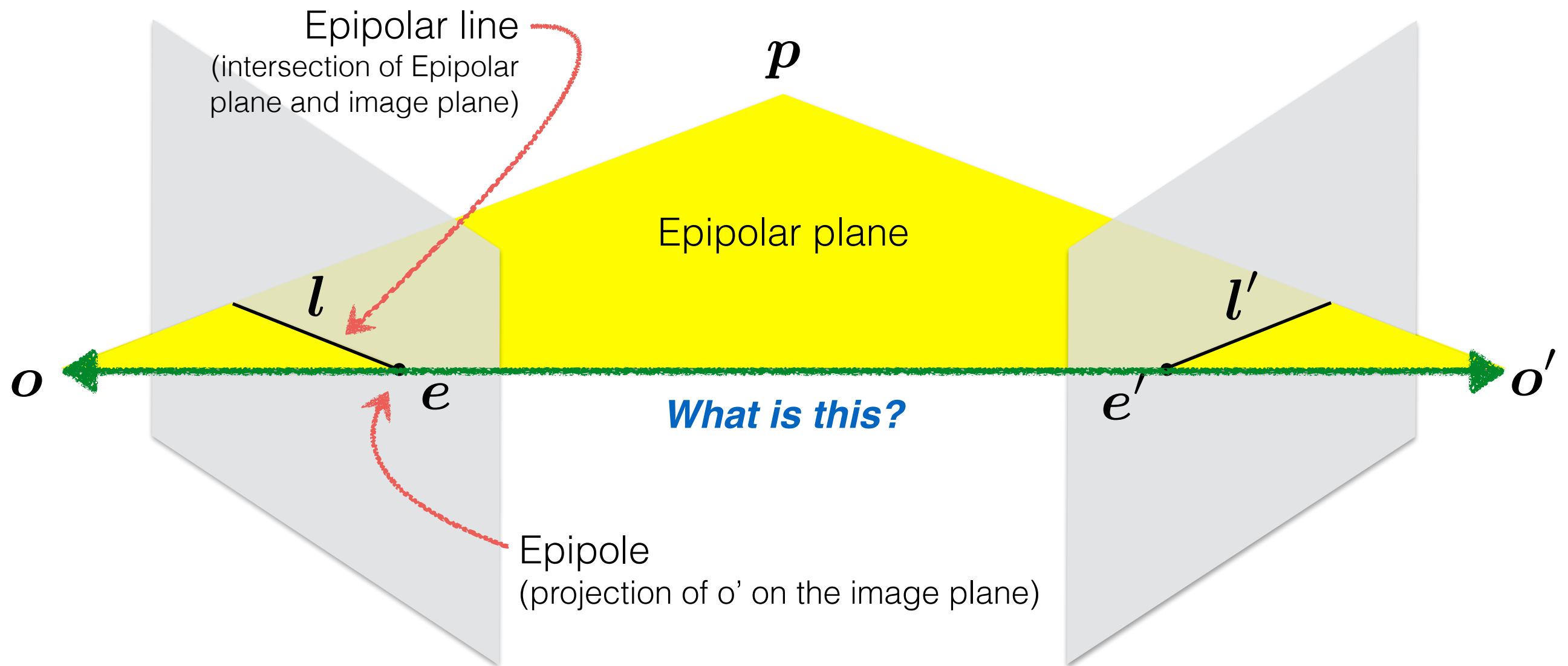




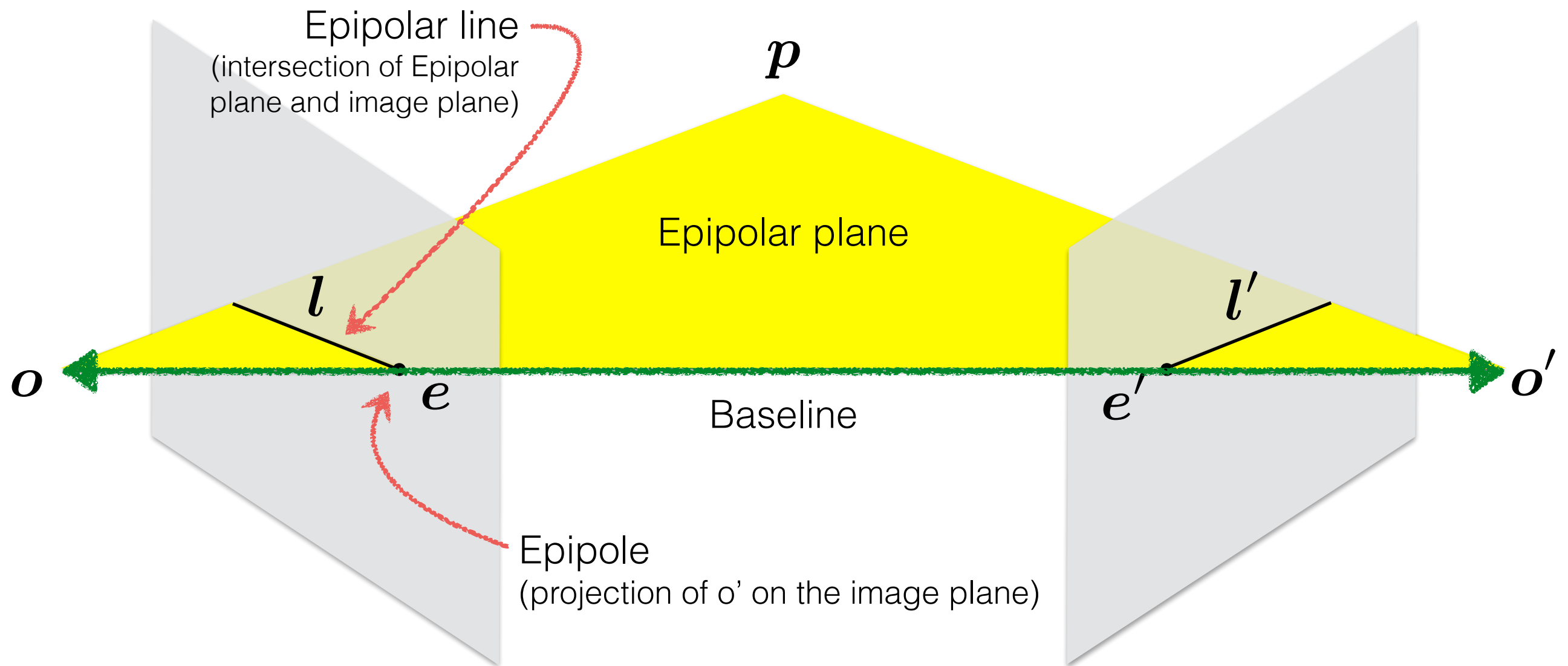
# Quiz



# Quiz

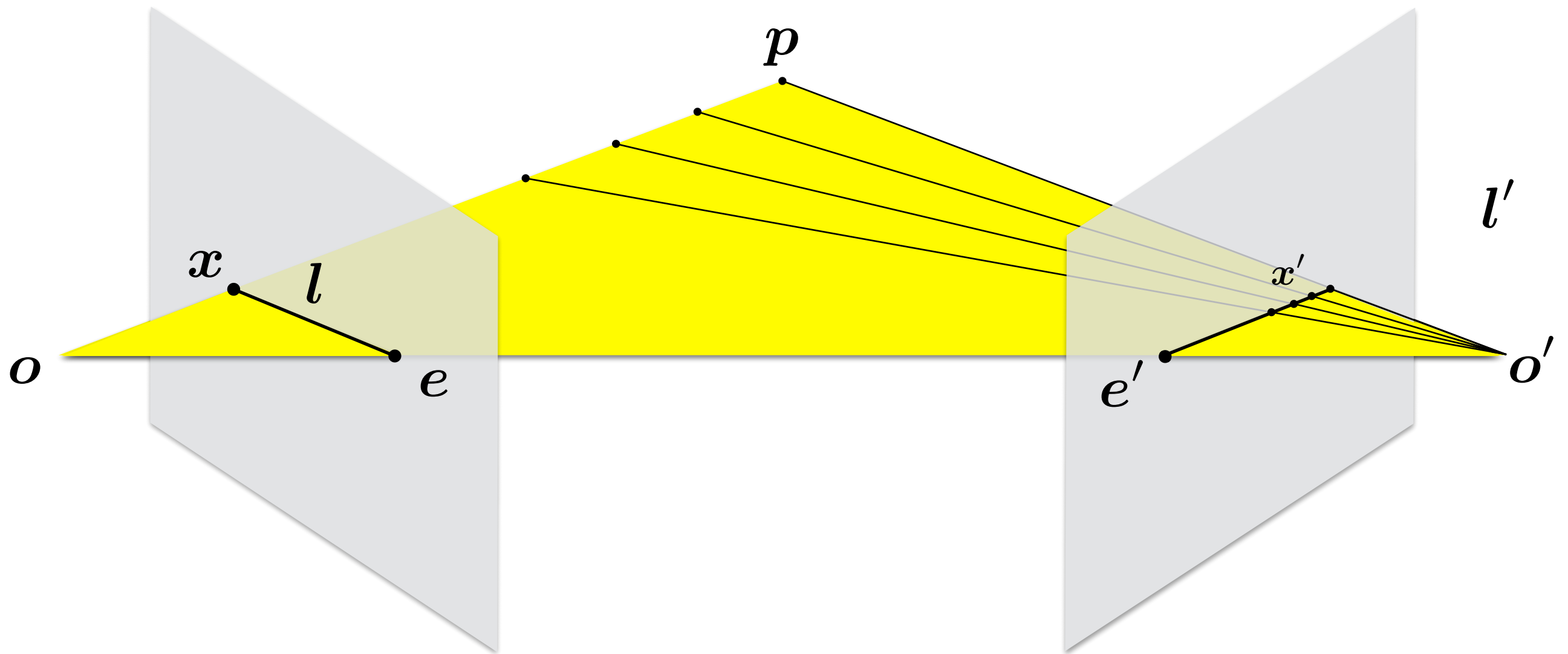


# Quiz



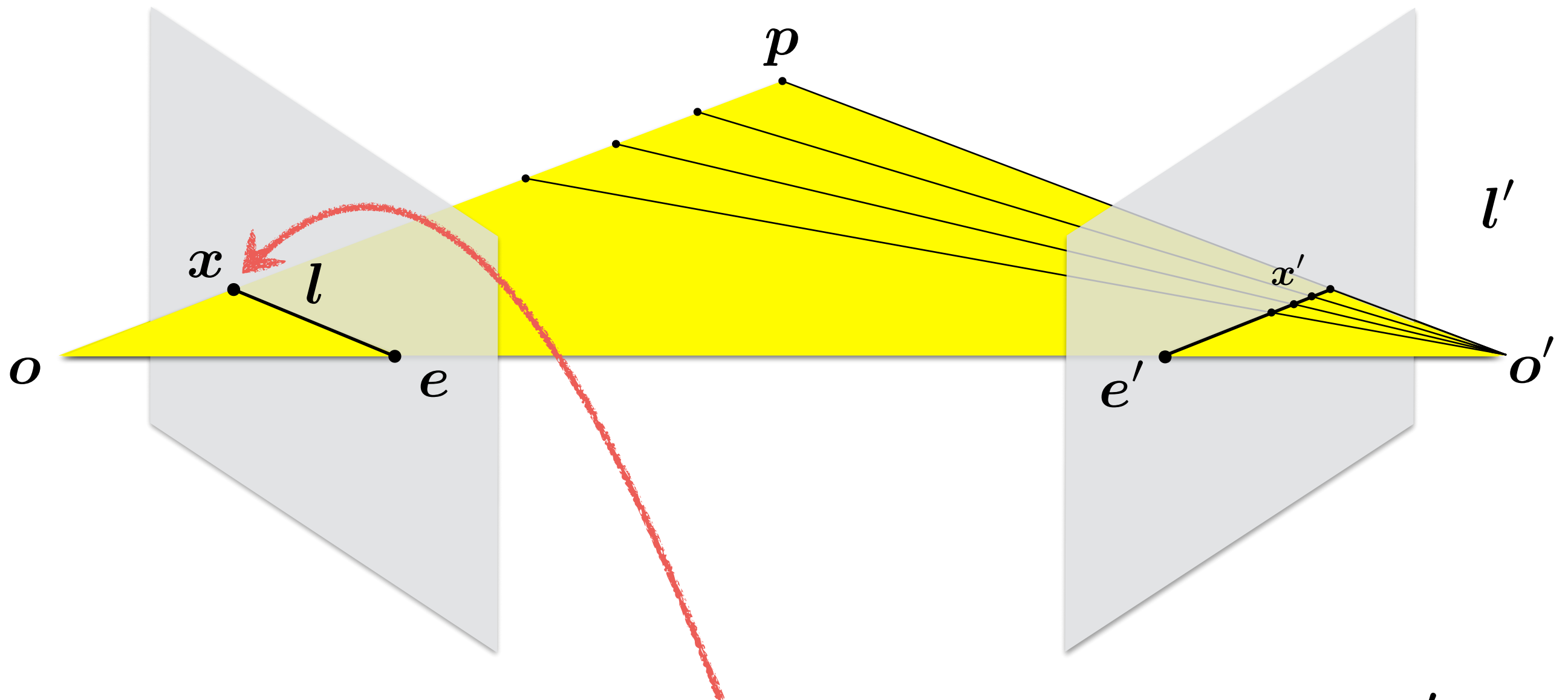


# Epipolar constraint



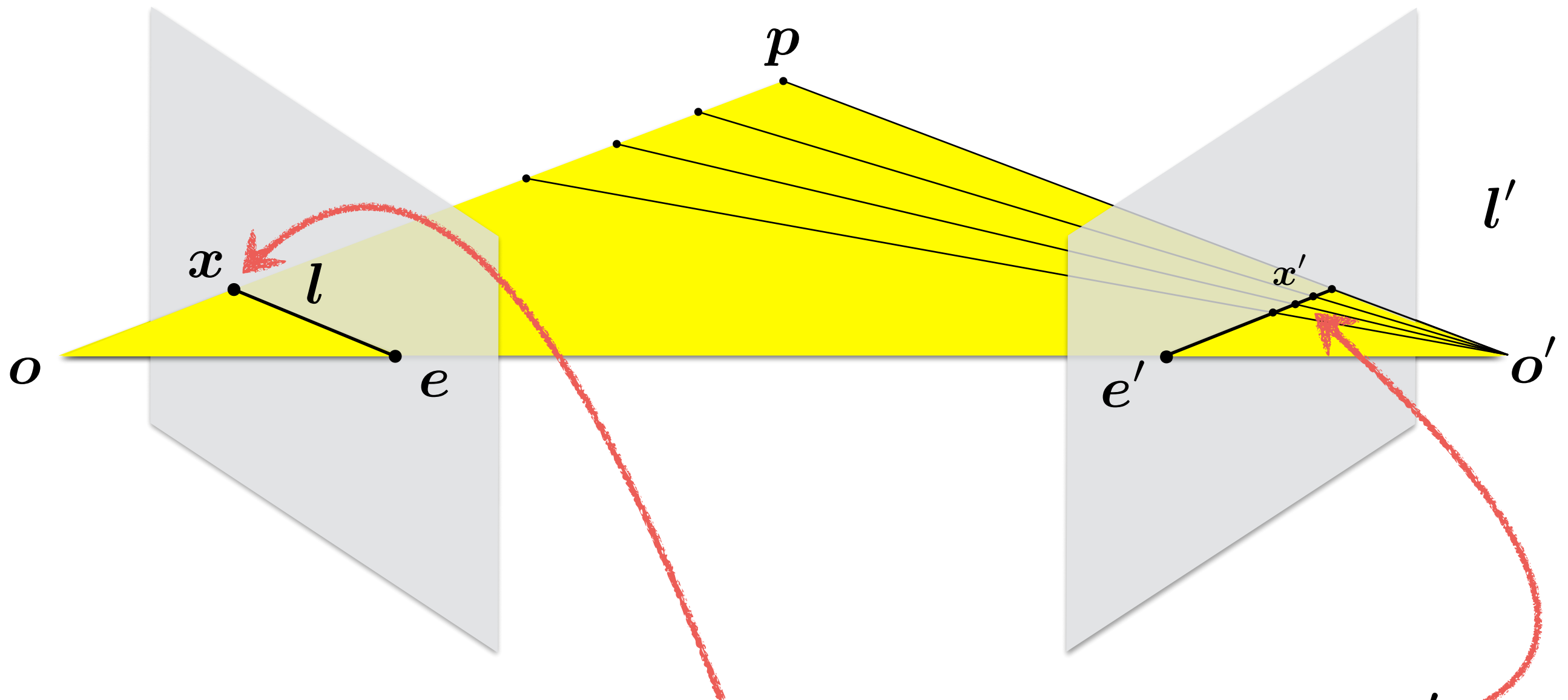
Potential matches for  $x$  lie on the epipolar line  $l'$

# Epipolar constraint

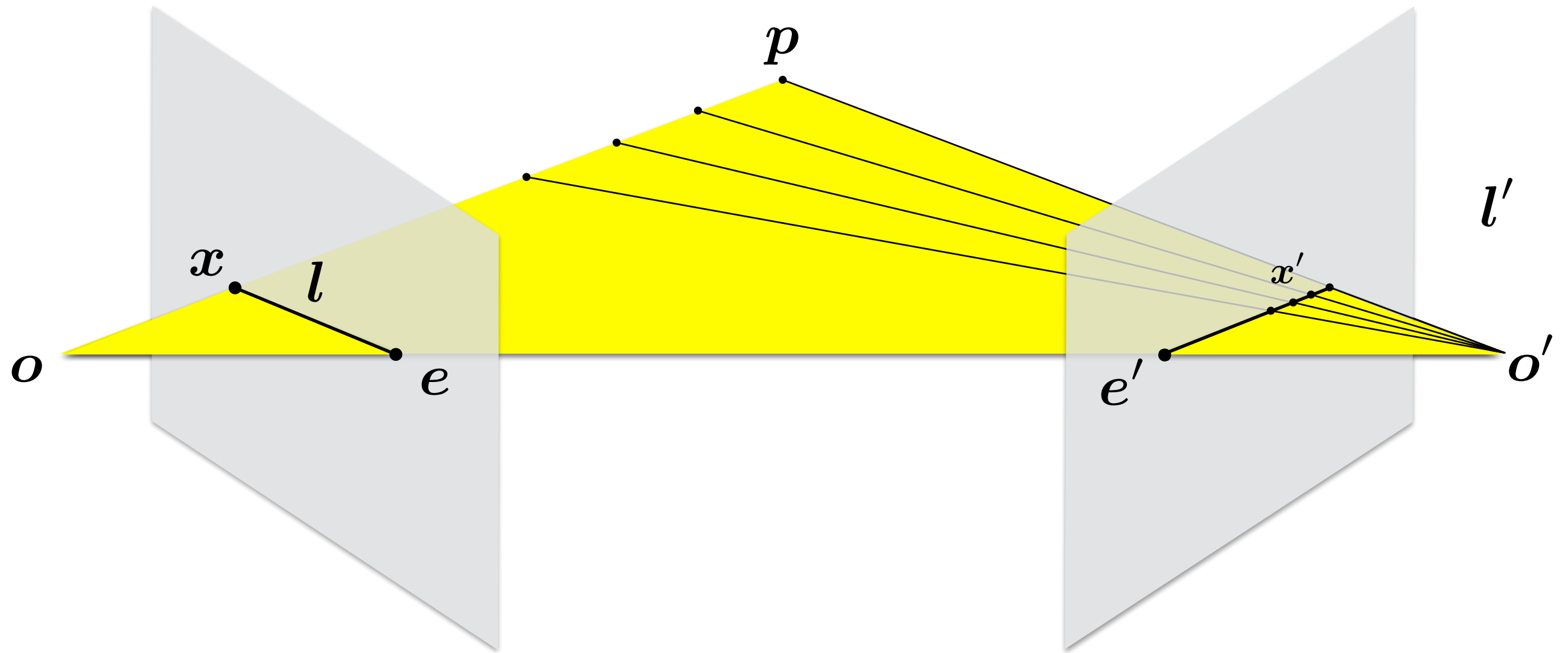


Potential matches for  $x$  lie on the epipolar line  $l'$

# Epipolar constraint



Potential matches for  $x$  lie on the epipolar line  $l'$



The point **x** (left image) maps to a \_\_\_\_\_ in the right image

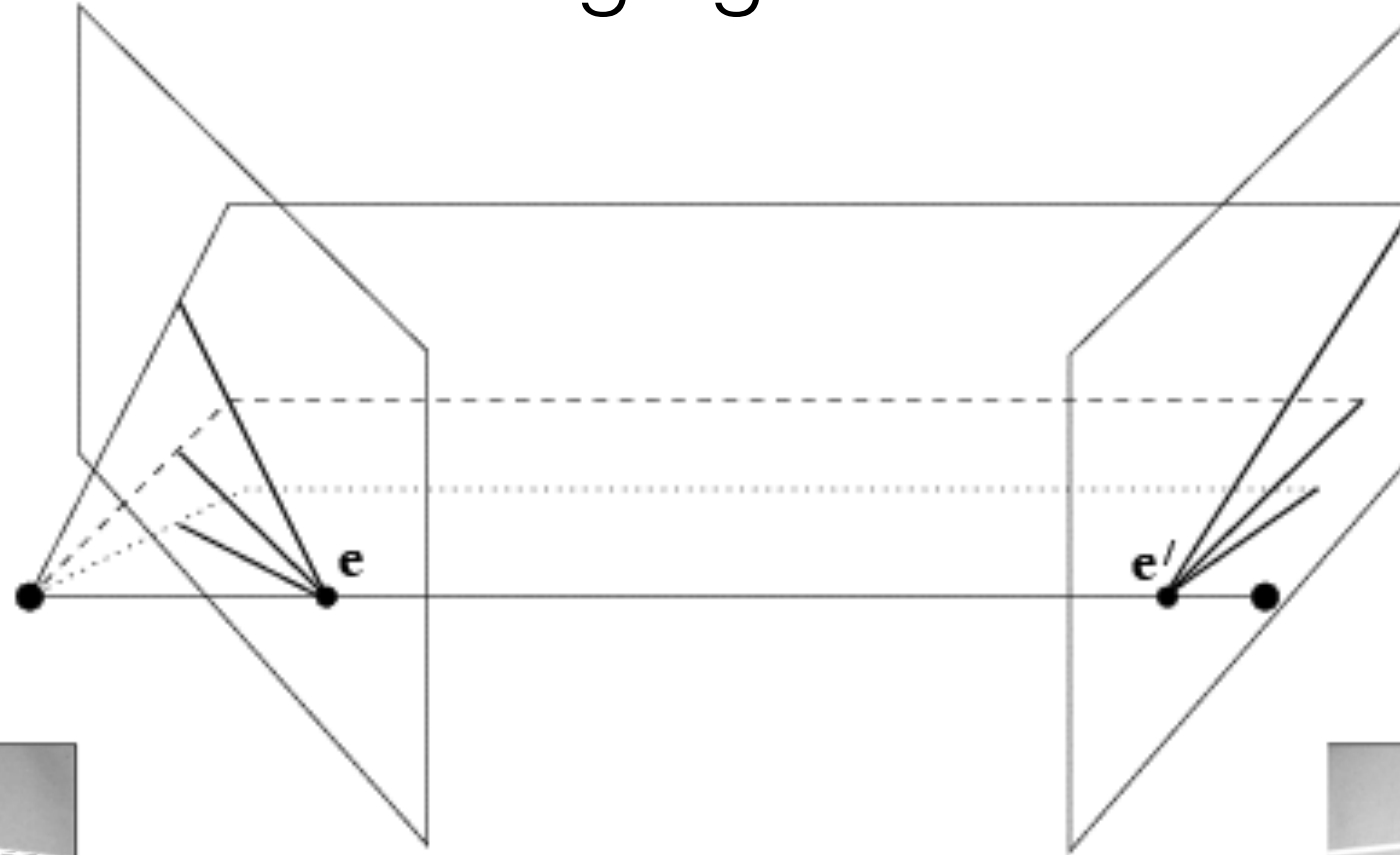
The baseline connects the \_\_\_\_\_ and \_\_\_\_\_

An epipolar line (left image) maps to a \_\_\_\_\_ in the right image

An epipole **e** is a projection of the \_\_\_\_\_ on the image plane

All epipolar lines in an image intersect at the \_\_\_\_\_

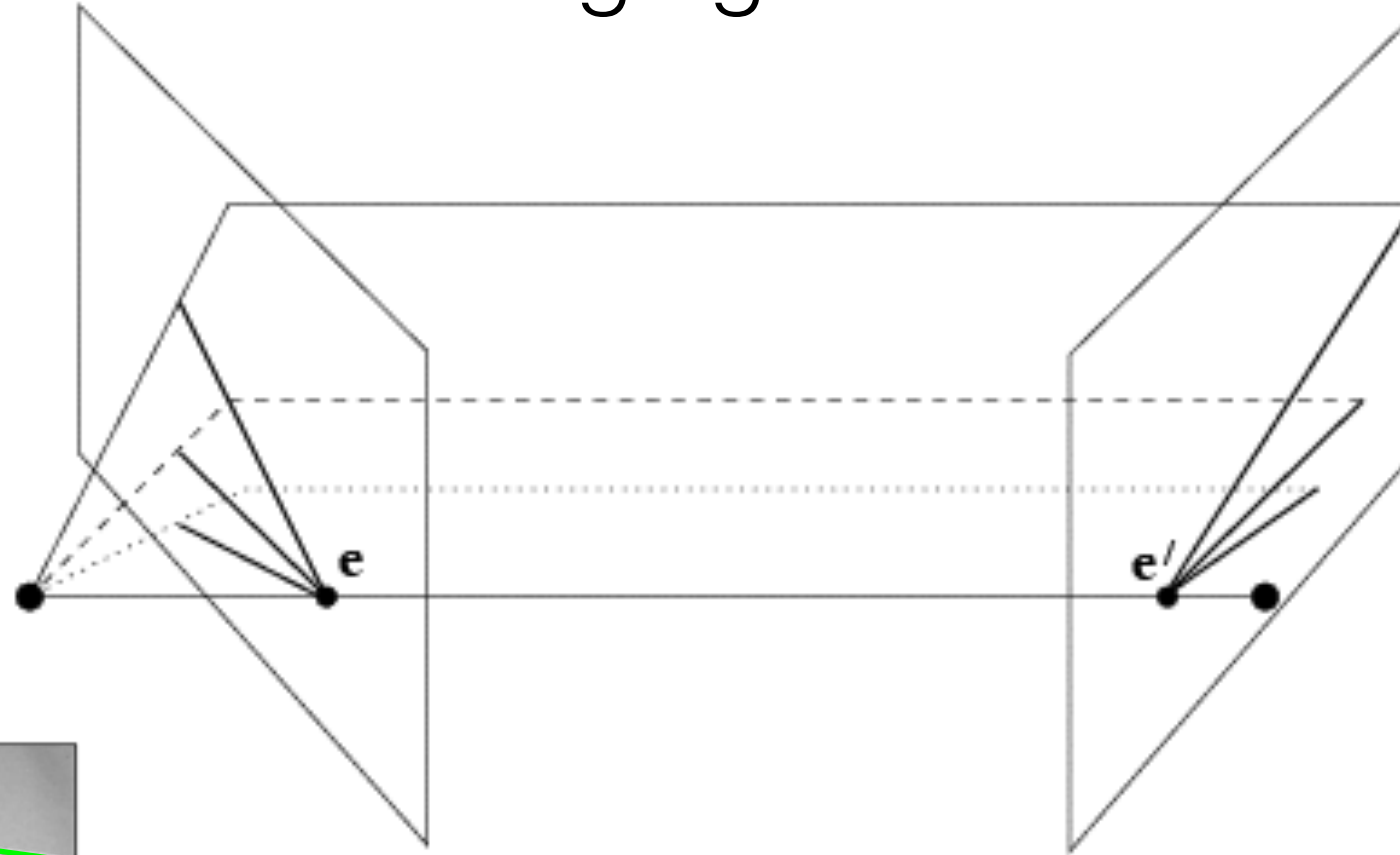
# Converging cameras



*Where is the epipole in this image?*



# Converging cameras



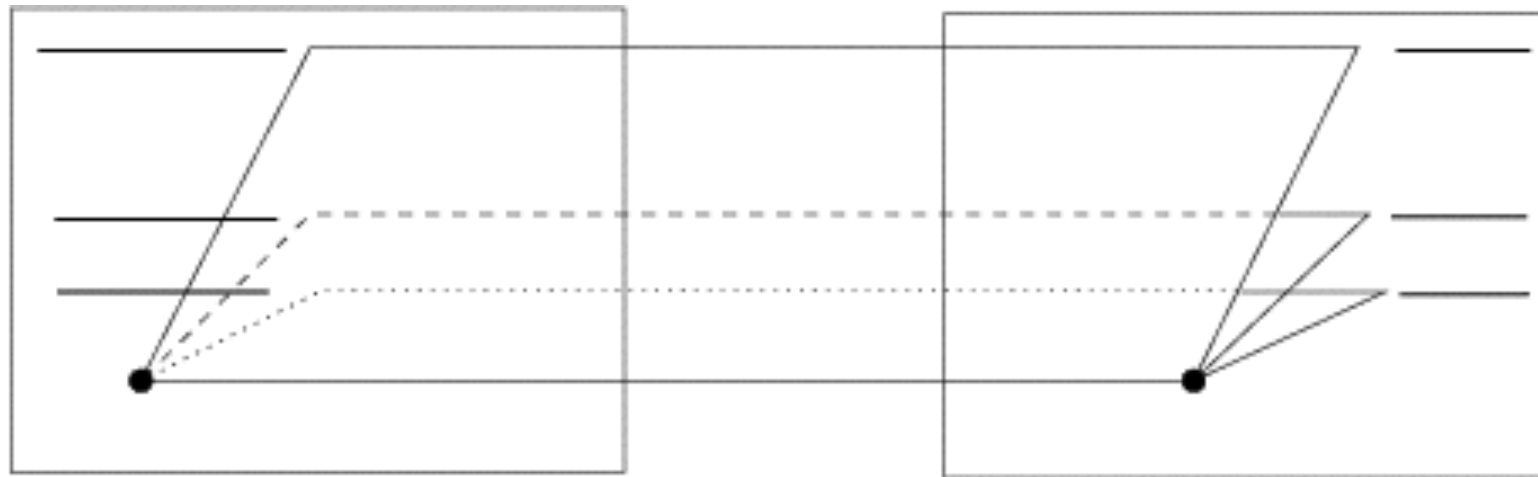
here!



*Where is the epipole in this image?*

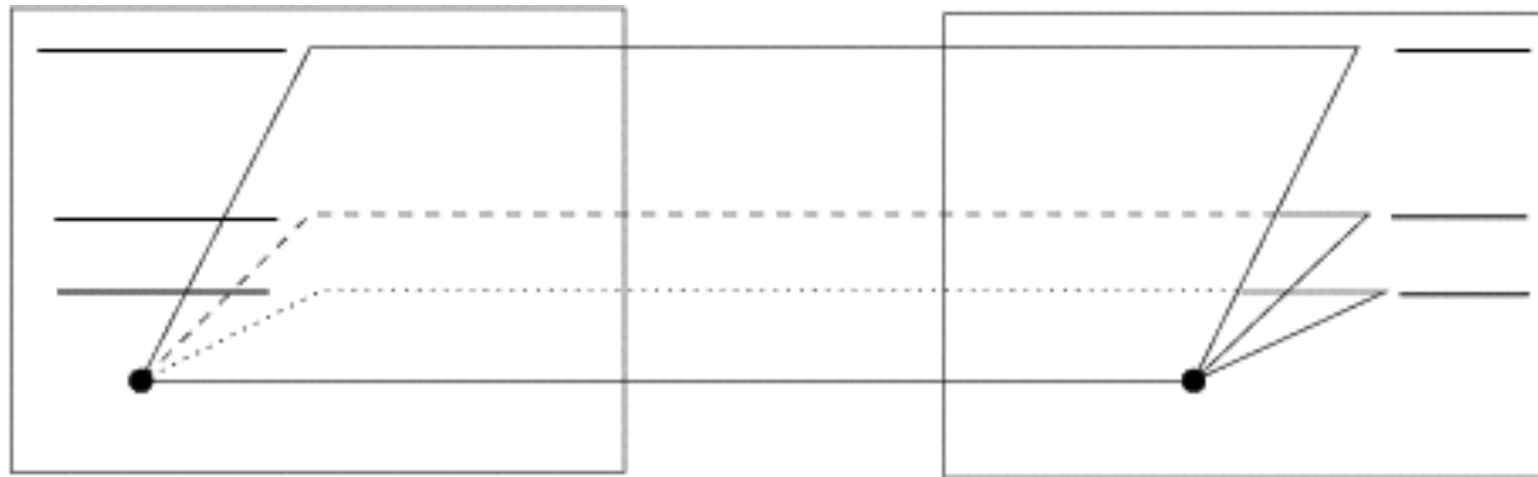
It's not always in the image

# Parallel cameras



*Where is the epipole?*

# Parallel cameras



epipole at infinity

# Forward moving camera



# Forward moving camera

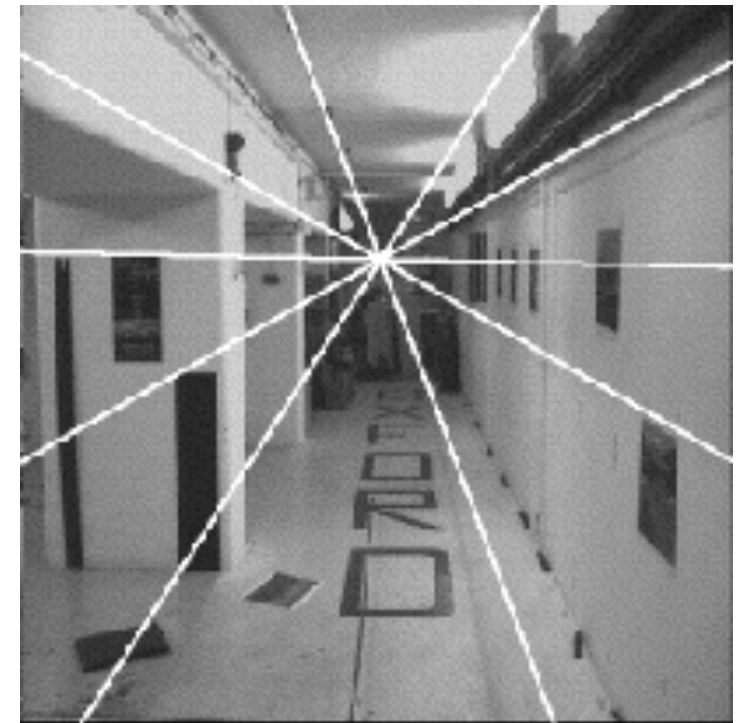
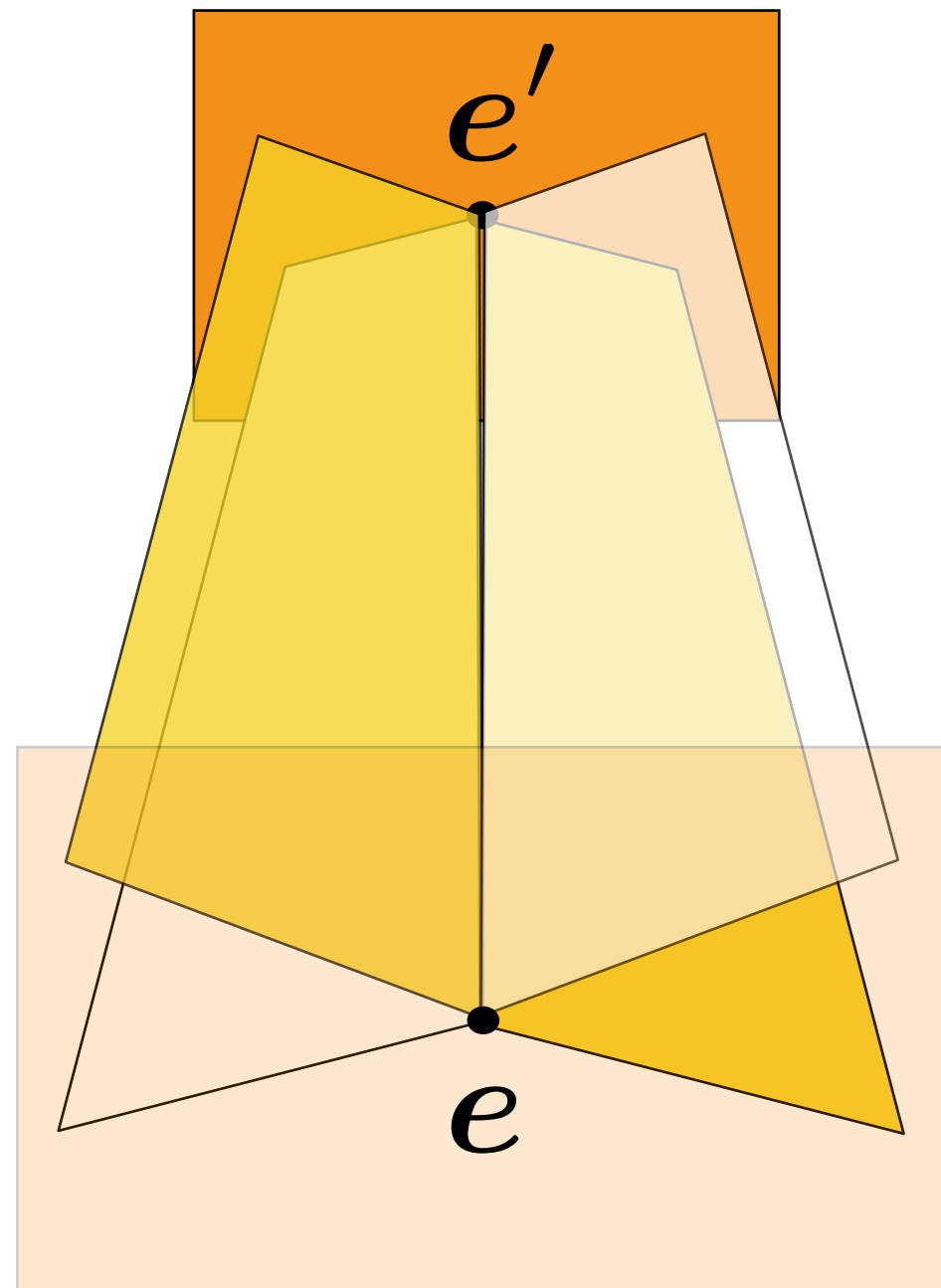
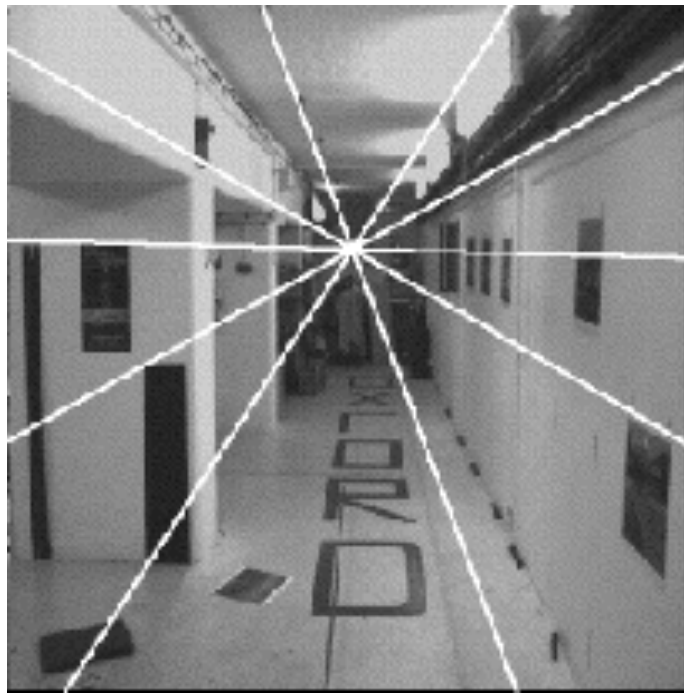




*Where is the epipole?*

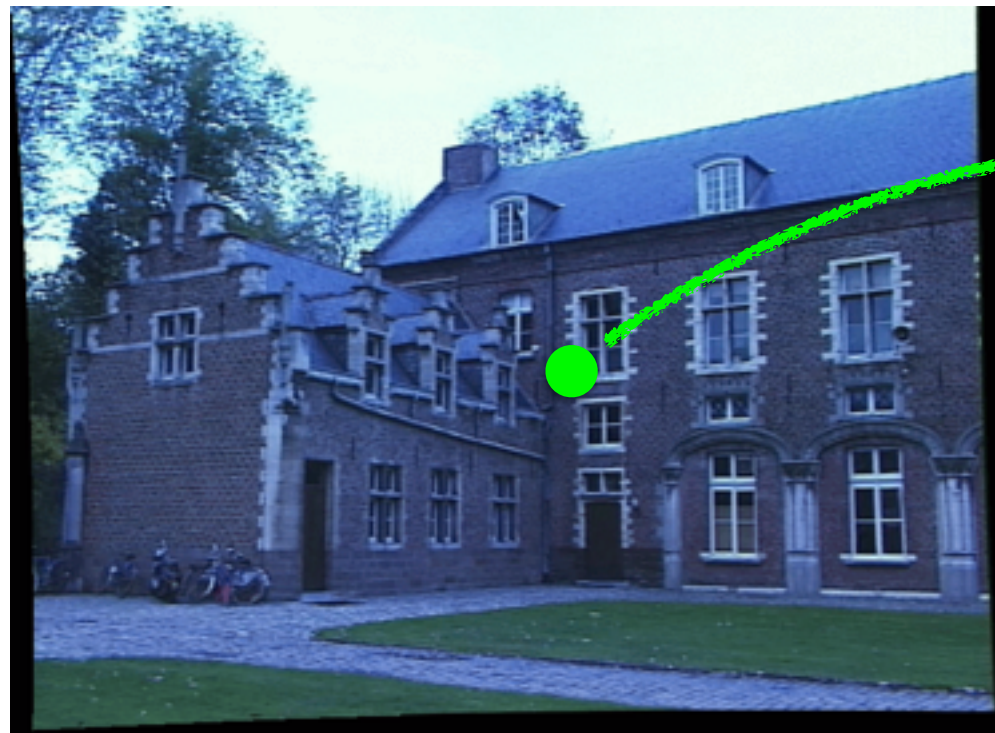
*What do the epipolar lines look like?*

Epipole has same coordinates in both images.  
Points move along lines radiating from “Focus of expansion”

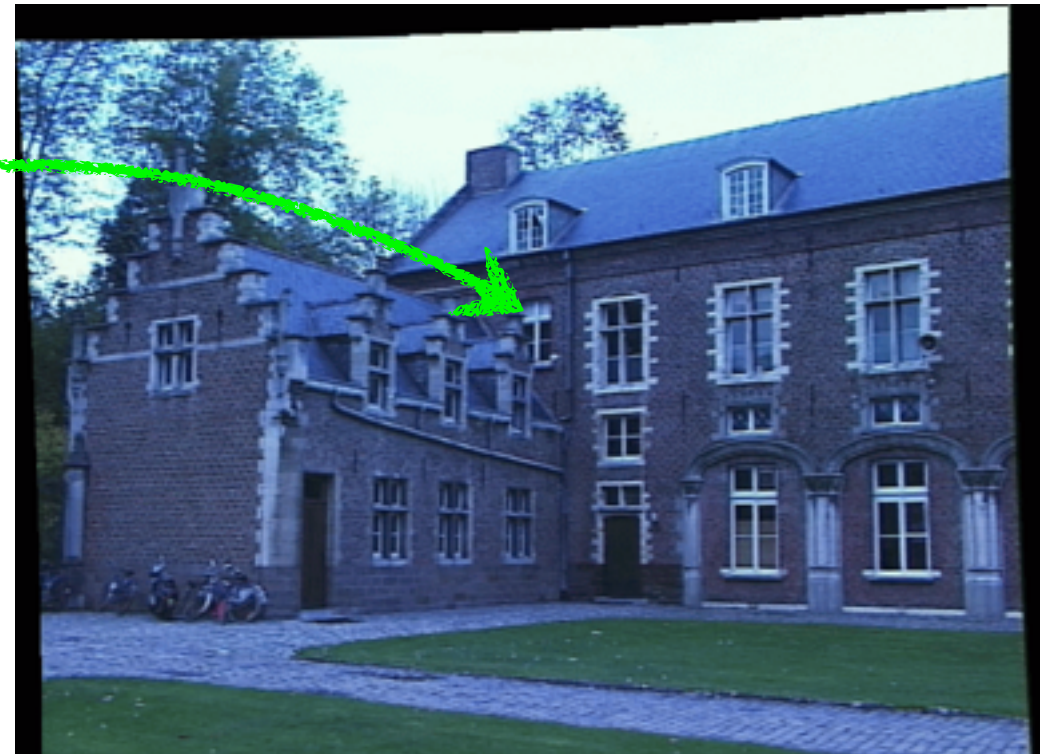


The epipolar constraint is an important concept for stereo vision

**Task:** Match point in left image to point in right image



Left image



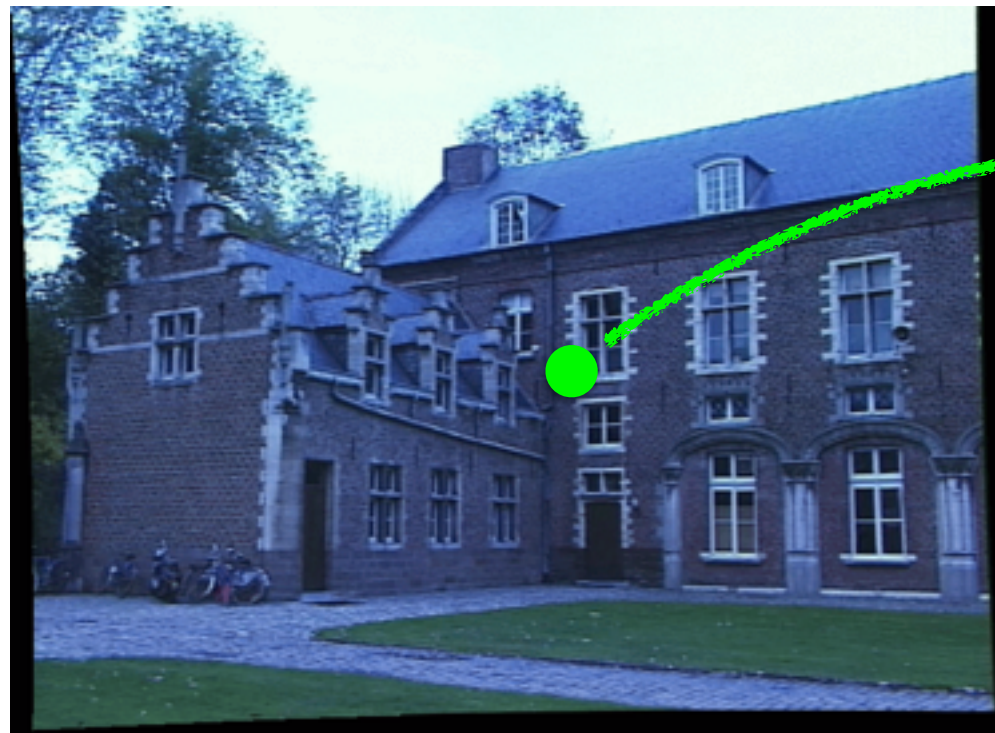
Right image

*How would you do it?*

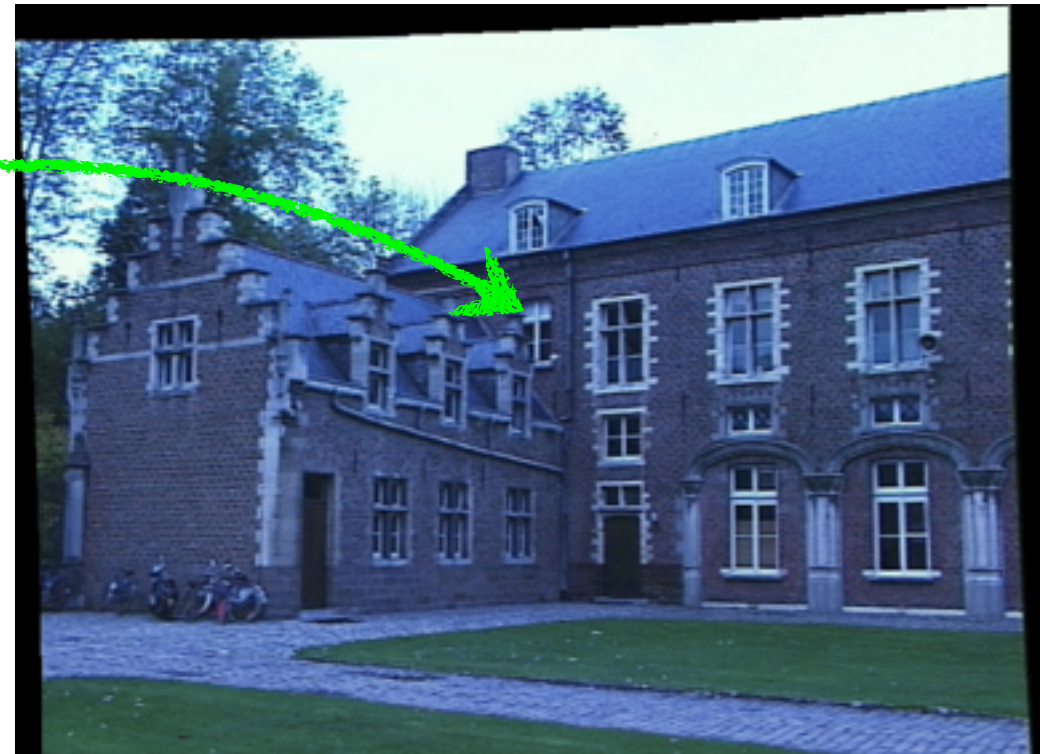


The epipolar constraint is an important concept for stereo vision

**Task:** Match point in left image to point in right image



Left image



Right image

Want to avoid search over entire image

(if the images have been rectified)

Epipolar constrain reduces search to a single line

# iv-tec

imagination and vision

