

Index

- 3D reconstruction, 123
- 5+1-point algorithm, 274
- 5-point algorithm, 260
- 7-point algorithm, 255
- 8-point algorithm, 253
- affine point, 43
- affine transformation, 55
- affine transformation group, 55
- affine vector, 43
- algebraic constraint, 181
- algebraic distance, 38
- algebraic error, 38, 180
- algebraic representation, 147
- algebraic representation of $SO(3)$, 149
- algebraically independent, 117
- aperture, 93, 282
- associative operation, 332
- automatic camera calibration, 280
- auxiliary variables, 193, 218, 258, 293
- axis-angle representation, 150
- backward interpolation, 301
- barrel distortion, 285
- barycentric coordinates, 236
- baseline, 123
- blending, 302
- block diagonal matrix, 340
- block matrix, 339
- bounding box, 108, 296
- Brown-Conrady distortion, 287
- bundle adjustment, 317, 318
- C-normalized image coordinates, 98
- calibrated epipolar geometry, 121, 252
- calibration device, 290
- camera, 93
- camera calibration, 107, 212, 279
- camera center, 92
- camera centered coordinate systems, 94
- camera matrices from F , 131
- camera matrix, 92
- camera normalized image coordinates, 98
- camera obscura, 93
- camera projection matrix, 92
- camera resectioning, 106
- canonical form, 28, 30, 63, 64, 68, 71
- canonical homogeneous coordinates, 88
- Cardano angles, 162
- Cartesian representation, 18
- Cayley transform, 156
- central perspective, 91
- central projection, 91
- centroid, 175
- Closed form concatenation of rotations, 150
- Closed form inverse of a rotation, 150
- co-linear planes, 22
- co-linear points, 18, 22
- co-planar lines, 22
- co-planar points, 21
- collineation, 83
- column compression, 344
- commutative operation, 332
- complete representation, 149
- consensus set, 265
- consistent parameterization, 218
- consistent Plücker coordinates of 3D line, 70
- constraint enforcement, 219
 - fundamental matrix, 253
 - normalized camera matrix, 242
 - rotation matrix, 233
- corner points, 186
- correspondence, 121
- correspondence problem, 194, 195
- corresponding points, 121, 191
- cost function, 174
- cross product, 335
- cross product matrix, 335
- cross product operator, 335
- cross-correlation, 175
- D-normalization, 32
- data degeneracy, 197
- data error, 187
- data matrix, 34, 179
- decentering distortion, 287
- degeneracy
 - epipolar geometry estimation, 255
 - homography estimation, 197
- degenerate configuration, 50
- degenerate data, 33
- degrees of freedom, 49, 217

depth, 97
 depth-of-field, 282
 descent direction, 360
 direct linear transformation, 117, 193
 directed line, 39
 direction, 43
 distributive operation, 332
 distortion center, 288
 DL-normalization, 71
 DLT, 193
 double embedding of $SO(3)$, 159
 dual homogeneous coordinates, 30, 65
 dual line normalization, 32, 71
 dual Plücker coordinates, 47, 69
 dual transformation, 60
 duality mapping, 70
 duality principle, 47
 Eckart-Young (-Mirsky) theorem, 347
 ego-motion estimation, 318
 energy function, 174
 epipolar constraint, 117, 121, 127
 epipolar geometry, 121
 degenerate, 255
 epipolar homographies, 126
 epipolar line, 124, 128
 epipolar plane, 124
 epipolar points, 123
 epipoles, 123
 equation of the line, 18
 equation of the plane, 21
 equilibrating transformation, 207
 equivalent cameras, 113
 error function, 174
 essential matrix, 121, 139, 140
 estimation
 robust, 274
 internal constraint, 140
 estimation
 camera matrix, 210
 epipolar geometry, 245
 fundamental matrix, 252
 homography, 191
 introduction, 173
 rigid transformation, 235
 rotations, 231
 transformations, 191
 Euclidean reconstruction, 135
 Euler angles, 162
 exterior orientation, 104, 235
 external camera parameters, 104
 FET, 286
 field of view, 118
 field of view model, 286
 fish-eye lens, 282
 fish-eye transform, 286
 focal length, 94
 focal point, 92
 forward interpolation, 301
 FOV, 286
 full rank pseudo-inverse, 337
 fundamental matrix, 121, 127
 camera matrices from, 131
 estimation, 252
 robust, 273
 internal constraint, 127
 Gauss-Newton method, 364
 general configuration, 50
 geometric distortion, 282
 geometric objects, 27
 gimbal lock, 169
 gold standard method, 258
 H-normalization, 207
 hand-eye calibration, 235
 Hartley normalization, 207
 homogeneous coordinates, 25, 28, 63
 homogeneous method, 183
 homogeneous representation, 18
 homography, 83
 homography estimation
 degeneracy, 197
 robust, 272
 homography transformation, 83
 hybrid method, 364
 ICP, 237
 ideal data, 187
 ideal point, 43
 identical noise, 188
 identity element, 332
 identity rotation, 150
 image coordinate system, 101
 image coordinates, 92
 image mosaic, 296
 image mosaicking, 296
 image plane, 92
 image point, 92
 incidence relations, 32
 independent noise, 188
 indeterministic estimation method, 265
 inhomogeneous method, 181
 inliers, 262
 inner derivatives, 220
 intercept, 20
 interior orientation, 104
 internal camera parameters, 104
 internal constraint

essential matrix, 140
 fundamental matrix, 127
 normalized camera matrix, 99
 Plücker coordinates, 70
 rotation matrix, 148
 Internal constraint of a representation, 150
 invariances, 49
 inverse Cayley transform, 157
 inverse of a quaternion, 334
 involution, 58
 isotropic noise, 188
 iterative closest point, 237
 Jacobian, 363
 Jacobian mask, 324, 368
 keystone effect, 86
 L-normalization, 68
 L_1 error, 179
 L_2 error, 179
 left inverse, 338
 left singular vectors, 341
 lens distortion, 282
 lens distortion function, 283
 lens effect, 282
 Levenberg-Marquardt method, 364
 line at infinity, 44, 67
 line normalization, 68
 linear transformation, 331
 matrix exponential function, 350
 matrix logarithm, 351
 maximum likelihood estimation, 188
 mean, 175
 measurement error, 187
 measurement noise, 110
 method degeneracies, 251
 method degeneracy, 197
 mid-point method, 246
 minimal case estimation, 196
 minimal parameterization, 104, 130
 ML-estimation, 188
 model error, 184
 Moore-Penrose inverses, 338
 motion stereo, 123
 nearest neighbor interpolation, 111, 301
 Newton's method, 362
 non-linear optimization, 359
 normalized 8-point algorithm, 254
 normalized camera, 97
 normalized camera matrix, 98, 99
 internal constraint, 99
 normalizing transformation, 204, 207
 objective function, 174
 observation, 187
 omni-directional camera, 295
 one-first enumeration, 110
 OPP, 346
 optical axis, 94
 optical center, 92
 optical ray, 112
 optimal triangulation, 247
 orientation of a line, 42
 orthogonal Procrustes problem, 346
 outliers, 262
 over-fitting, 185
 P-normalization, 29
 P3P, 244
 panorama image, 296
 panorama stitching, 296
 parameter space, 149
 parameterization of a transformation, 50
 parametric representation, 19
 perspective n -point problem, 241
 pin-cushion distortion, 285
 pinhole camera, 91, 93
 pinhole perspective, 91
 pixel coordinates, 101
 pixel density, 105
 pixel grid, 108
 pixel value, 109
 pixels, 93
 Plücker coordinates of 2D line, 46
 Plücker coordinates of 3D line, 67
 consistent, 70
 internal constraint, 70
 plumb bob distortion, 287
 PnP, 241
 point at infinity, 42
 point cloud, 322
 point normalization, 29
 points of interest, 186, 195
 pose, 104
 pre-conditioning, 207
 principal axis, 94
 principal line, 94
 principal plane, 94
 principal point, 94
 projection, 83
 projection line, 83, 112
 projection plane, 116
 projection point, 83
 projective elements, 330
 projective reconstruction, 135
 projective space, 330
 projectivity, 83

proper line, 67
 proper lines, 41
 proper points, 41
 pseudo-inverse, 337
 full rank, 337
 pure quaternion, 334
 putative correspondences, 314

 quaternion, 332
 inverse, 334
 pure, 334
 quaternion sandwich product, 158
 quaternionic embedding of \mathbb{R}^3 , 158
 quaternionic embedding of $SO(3)$, 159

 radial distortion function, 284
 Random Sample Consensus, 266
 RANSAC, 266
 re-mapping of the residual vector, 221
 re-normalize, 203
 re-parameterization, 219
 reconstruction, 134
 rectified stereo rig, 123, 136
 rectifying homographies, 138
 reference image, 297
 registration, 237
 representative of a projective element, 329
 reprojection error, 317
 residual, 363
 residual error, 175
 residual vector, 216
 right inverse, 338
 right singular vectors, 341
 rigid transformation, 53
 estimation, 235
 rigid transformation group, 53
 robust errors, 263
 robust estimation, 261, 262
 essential matrix, 274
 fundamental matrix, 273
 homography, 272
 Rodrigues' rotation formula, 151, 152
 rotation, 148
 rotation matrix
 internal constraint, 148
 row compression, 344

 SAD, 179
 sandwich product, 82
 Schur complement, 340
 Schur complement trick, 326
 $SE(2)$, 53
 $SE(3)$, 79
 SfM, 314
 shearing, 58

 signed distance, 37
 similarity reconstruction, 135
 similarity transformations, 54
 singular value decomposition, 340
 singular values, 341
 singularity, 150
 skewing, 58
 slope, 20
 solution space, 197
 SOPP, 233
 special Euclidean transformation group
 in \mathbb{E}^2 , 53
 in \mathbb{E}^3 , 79
 special orthogonal Procrustes problem, 233
 special QR-factorization, 356
 special SVD, 347
 SSD, 179
 SSVD, 347
 standard deviation, 188
 standard Plücker coordinates, 69
 step length, 360
 stereo camera, 121
 stereo rectification, 123
 stereo rig, 121, 123
 structure from motion, 314
 SVD, 340
 SVD profile, 199

 Tait-Bryan angles, 162
 thin-prism distortion, 287
 three-angle representation, 162
 total least squares, 176
 translation group, 52
 trial set, 265
 triangulation, 117, 123, 134, 245
 twisted pair, 166
 twisted rotations, 142, 166

 unbiased estimate, 209
 unbiased noise, 188
 uncalibrated epipolar geometry, 121, 131
 uniform noise, 188
 unique representation, 149
 unit quaternion, 334
 unperturbed data, 187

 variances, 175
 vector product, 335
 vectorization, 194, 211
 virtual image plane, 97
 visibility function, 317
 visual appearance, 270

 Wahba's problem, 232
 world coordinate system, 98

zero-first enumeration, 110