Lecture 9:
2D Transformation & Alignment

COMP 590/776: Computer Vision

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Course Website:
Scan Me!

Steps of creating a Panorama

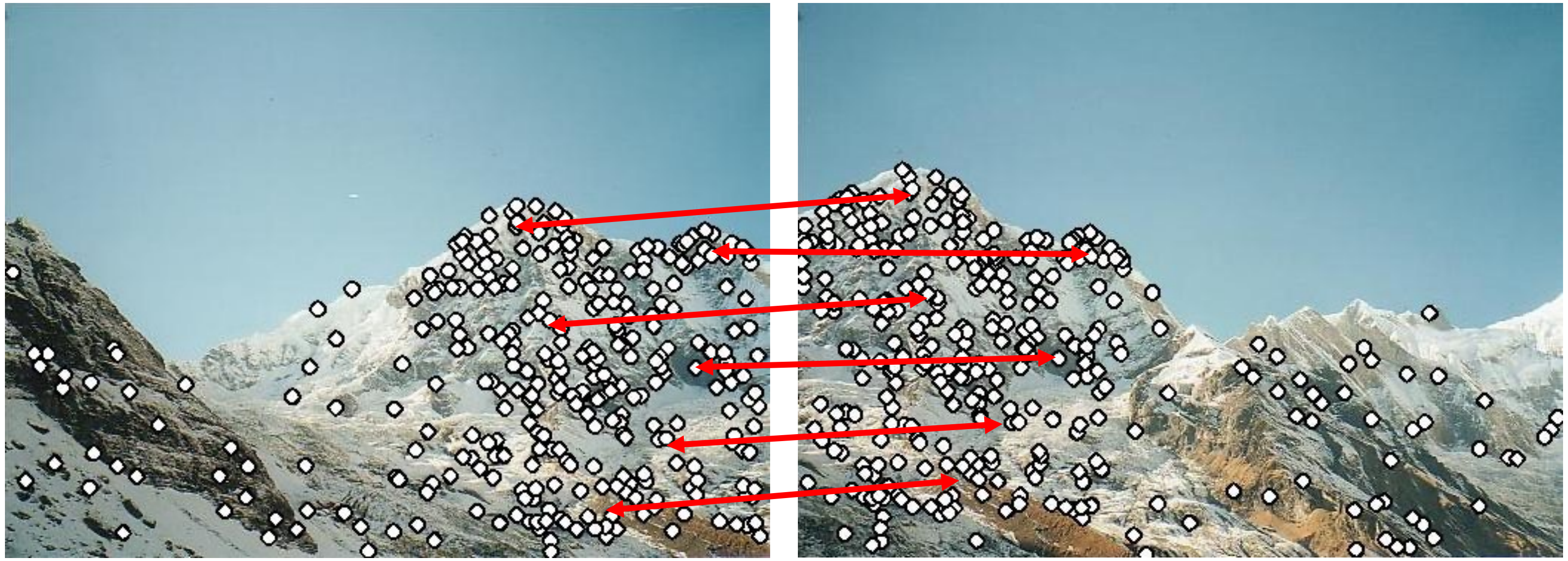
This is your next homework assignment!

Why extract features? (last week)

- Motivation: panorama stitching
  - We have two images – how do we combine them?

Why extract features? (last week)

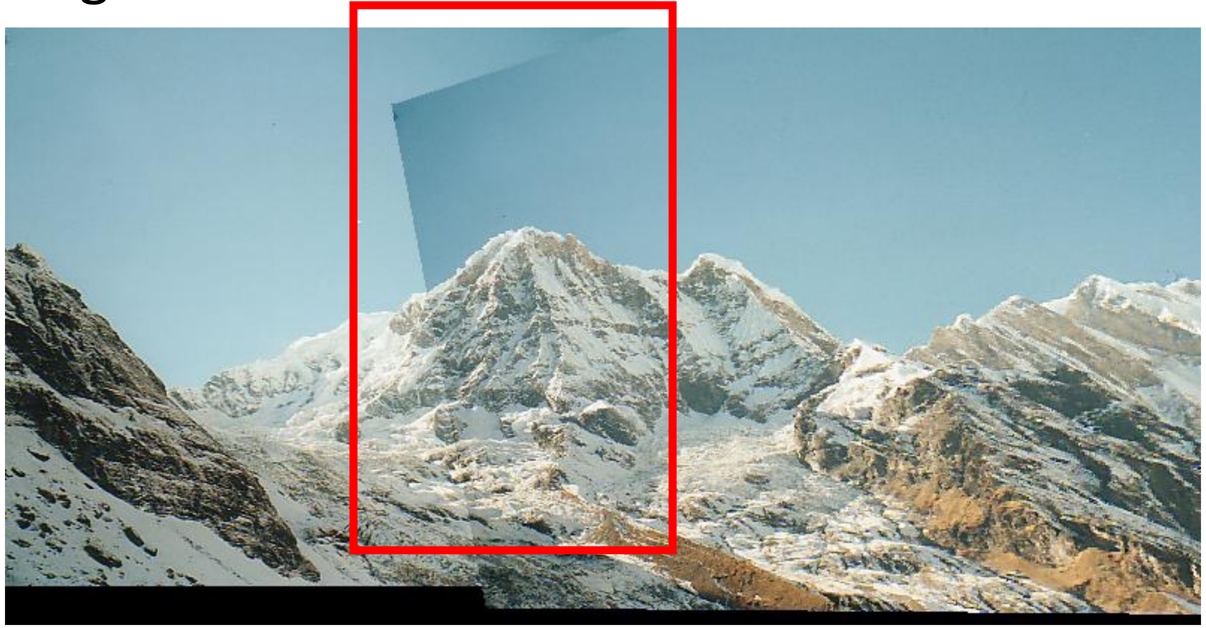
- Motivation: panorama stitching
  - We have two images – how do we combine them?



Step 1: extract features
Step 2: match features

How to align and combine two images?

- Motivation: panorama stitching
  - We have two images – how do we combine them?



Step 1: extract features
Step 2: match features
Step 3: align images
Step 4: blending images

Last Week

This Week

What is the geometric relationship between these two images?

?

What is the geometric relationship between these two images?

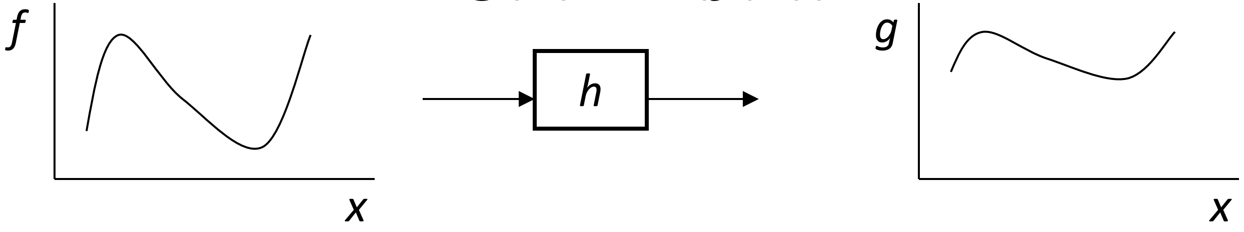
Very important for creating mosaics!

First, we need to know what this transformation is.

Second, we need to figure out how to compute it using feature matches.

Image Warping

- image filtering: change *range* of image
  - $g(x) = h(f(x))$



- image warping: change *domain* of image
  - $g(x) = f(h(x))$

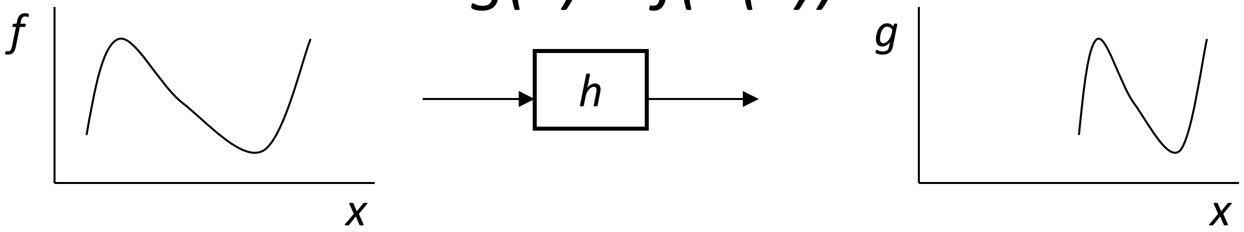


Image Warping

- image filtering: change *range* of image

f 

- $g(x) = h(f(x))$

$\longrightarrow \boxed{h} \longrightarrow$

g 

- image warping: change *domain* of image

f 

- $g(x) = f(h(x))$

$\longrightarrow \boxed{h} \longrightarrow$

g 

Today’s class

- Types of 2D Transformations
  - Linear
  - Affine
  - Perspective (Homography)

- Computing 2D Transformations
  - Linear
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Parametric (global) warping

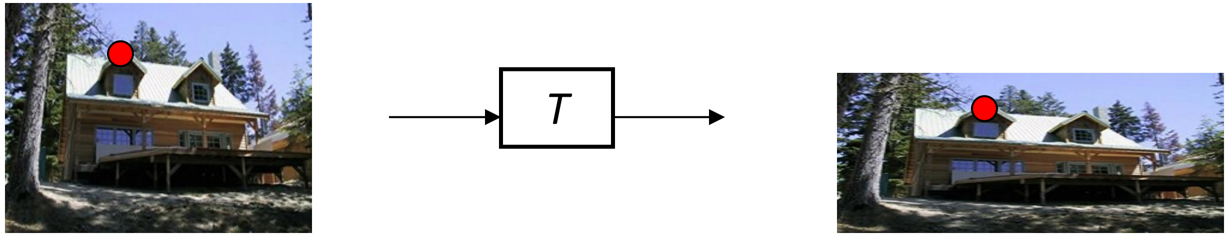
- Examples of parametric warps:

translation

rotation

aspect

Parametric (global) warping



p = (x,y) **p'** = (x',y')

- Transformation T is a coordinate-changing machine:

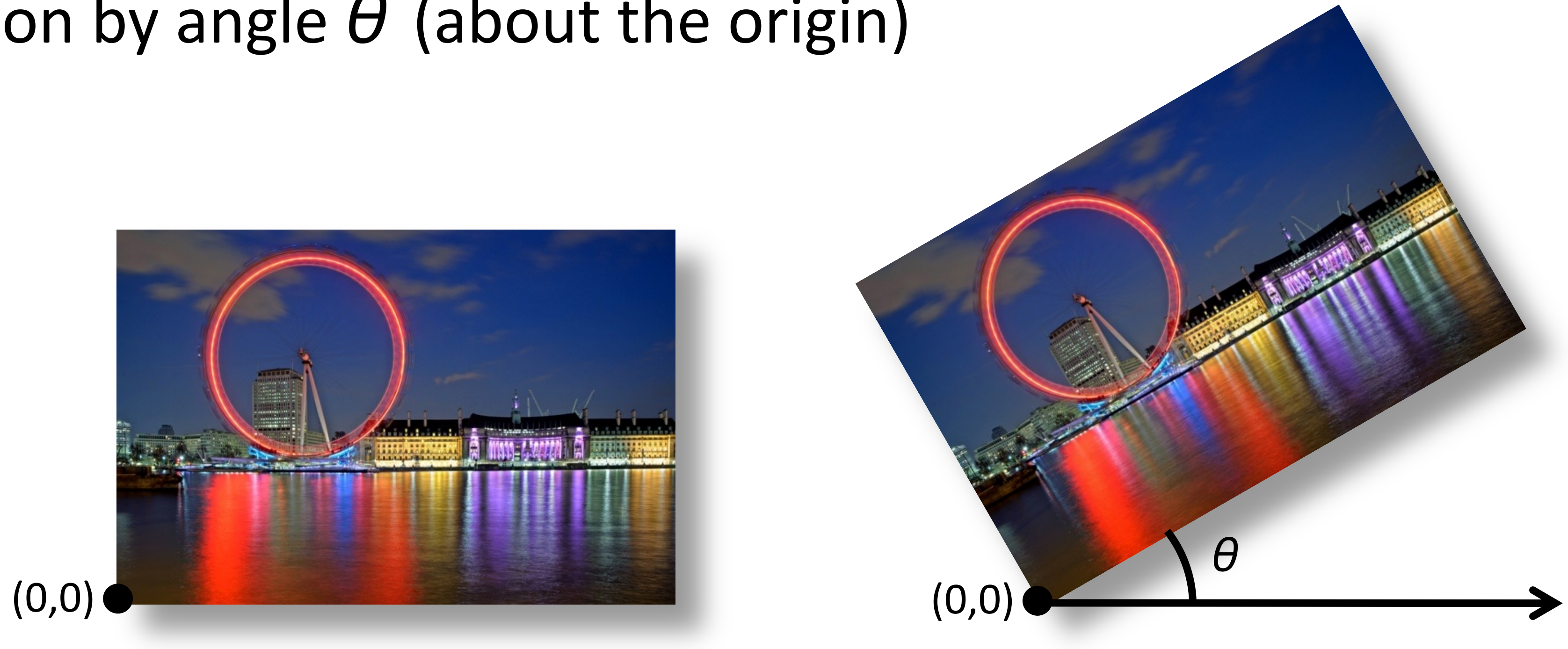
$$\mathbf{p}' = T(\mathbf{p})$$

- What does it mean that *T* is global?
  - Is the same for any point **p**
  - can be described by just a few numbers (parameters)
- Let's consider *linear* transforms (can be represented by a 2x2 matrix):

$$\mathbf{p}' = \mathbf{T}\mathbf{p} \qquad \begin{bmatrix} x' \\ y' \end{bmatrix} = \mathbf{T} \begin{bmatrix} x \\ y \end{bmatrix}$$

Common linear transformations

- Rotation by angle θ (about the origin)



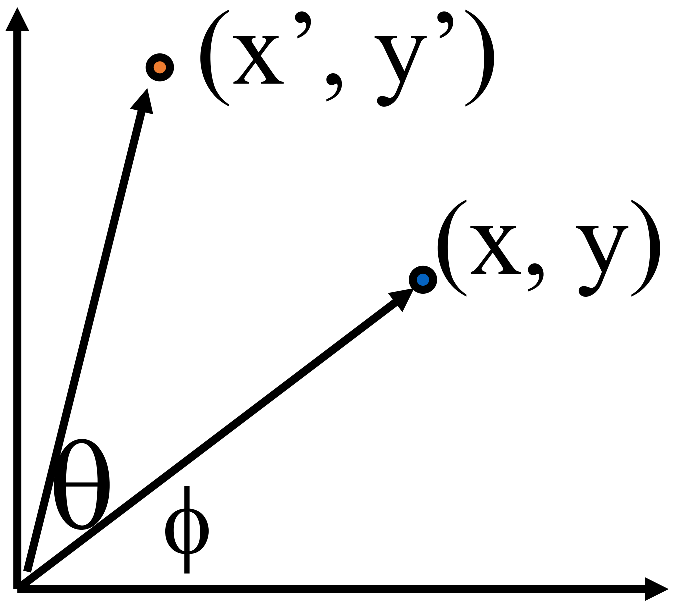
$$\mathbf{R} = \left[\begin{array}{cc} \cos\theta & -\sin\theta \\ \sin\theta & \cos\theta \end{array} \right]$$

What is the inverse?

For rotations:

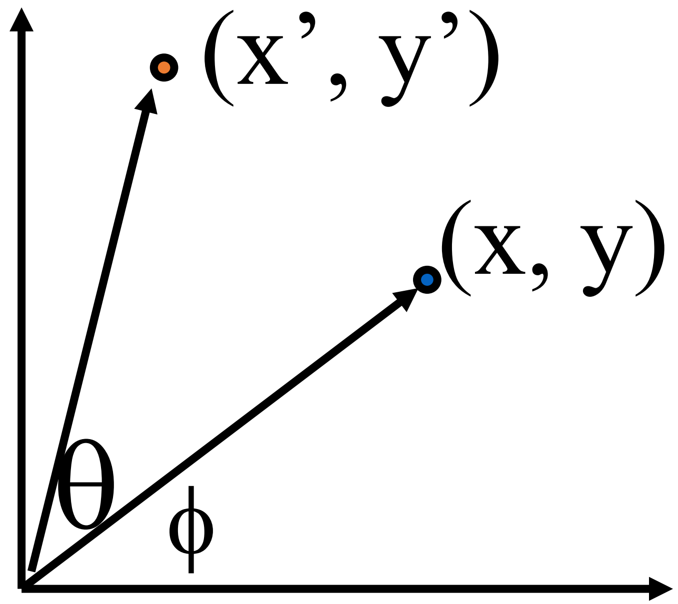
$$\mathbf{R}^{-1} = \mathbf{R}^{T}$$

2-D Rotation



$x = r \cos(\phi)$
$y = r \sin(\phi)$
$x' = r \cos(\phi + \theta)$
$y' = r \sin(\phi + \theta)$

2-D Rotation

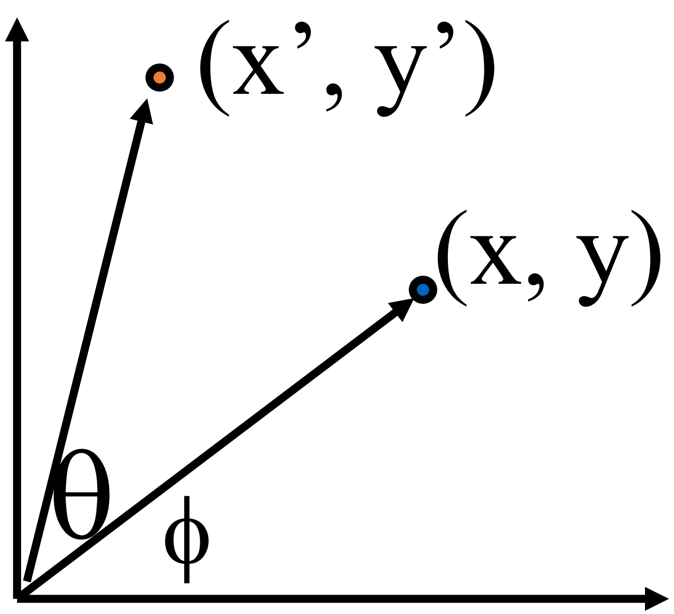


$x = r \cos(\phi)$
$y = r \sin(\phi)$
$x' = r \cos(\phi + \theta)$
$y' = r \sin(\phi + \theta)$

Trig Identity…

$x' = r \cos(\phi) \cos(\theta) - r \sin(\phi) \sin(\theta)$
$y' = r \sin(\phi) \cos(\theta) + r \cos(\phi) \sin(\theta)$

2-D Rotation



$x = r \cos(\phi)$
$y = r \sin(\phi)$
$x' = r \cos(\phi + \theta)$
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Trig Identity…

$x' = r \cos(\phi) \cos(\theta) - r \sin(\phi) \sin(\theta)$
$y' = r \sin(\phi) \cos(\theta) + r \cos(\phi) \sin(\theta)$

Substitute…

$x' = x\, \mathbf{cos}(\theta) - y\, \mathbf{sin}(\theta)$
$y' = x\, \mathbf{sin}(\theta) + y\, \mathbf{cos}(\theta)$

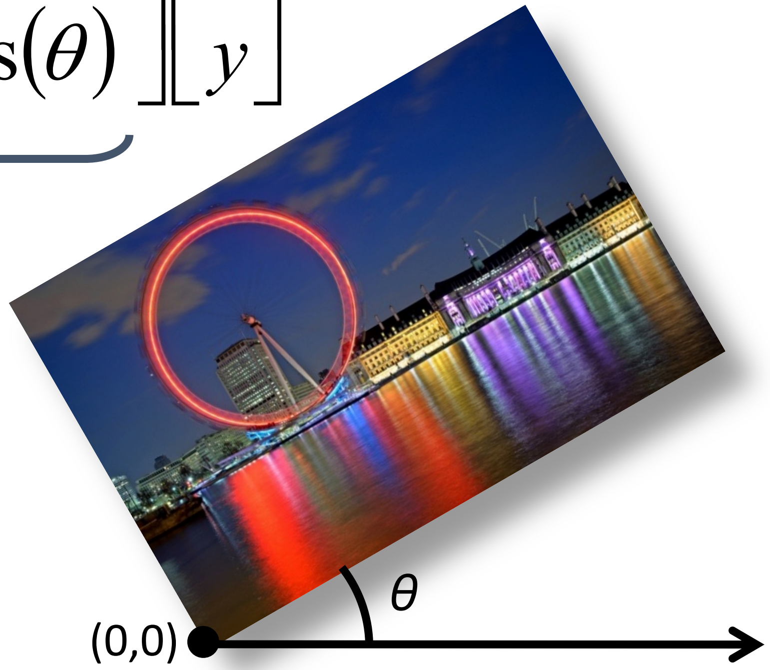
2-D Rotation

- This is easy to capture in matrix form:

$$\begin{bmatrix} x' \\ y' \end{bmatrix} = \underbrace{\begin{bmatrix} \cos(\theta) & -\sin(\theta) \\ \sin(\theta) & \cos(\theta) \end{bmatrix}}_{\mathbf{R}} \begin{bmatrix} x \\ y \end{bmatrix}$$

(0,0)

(0,0)



2x2 Matrices

- What types of transformations can be represented with a 2x2 matrix?

2D Identity?

$$x' = x$$
$$y' = y$$

$$\begin{bmatrix} x' \\ y' \end{bmatrix} = \begin{bmatrix} 1 & 0 \\ 0 & 1 \end{bmatrix} \begin{bmatrix} x \\ y \end{bmatrix}$$

2D Scale around (0,0)?

$$\boldsymbol{x}' = \boldsymbol{s}_x * \boldsymbol{x}$$
$$\boldsymbol{y}' = \boldsymbol{s}_y * \boldsymbol{y}$$

$$\begin{bmatrix} \boldsymbol{x}' \\ \boldsymbol{y}' \end{bmatrix} = \begin{bmatrix} \boldsymbol{s}_x & 0 \\ 0 & \boldsymbol{s}_y \end{bmatrix} \begin{bmatrix} \boldsymbol{x} \\ \boldsymbol{y} \end{bmatrix}$$

2x2 Matrices

- What types of transformations can be represented with a 2x2 matrix?

2D Rotate around (0,0)?

$$x' = \cos\Theta * x - \sin\Theta * y$$
$$y' = \sin\Theta * x + \cos\Theta * y$$

$$\begin{bmatrix} x' \\ y' \end{bmatrix} = \begin{bmatrix} \cos\Theta & -\sin\Theta \\ \sin\Theta & \cos\Theta \end{bmatrix} \begin{bmatrix} x \\ y \end{bmatrix}$$

2D Shear?

$$x' = x + sh_x * y$$
$$y' = sh_y * x + y$$

$$\begin{bmatrix} x' \\ y' \end{bmatrix} = \begin{bmatrix} 1 & sh_x \\ sh_y & 1 \end{bmatrix} \begin{bmatrix} x \\ y \end{bmatrix}$$

2x2 Matrices

- What types of transformations can be represented with a 2x2 matrix?

2D Mirror about Y axis?

$$x' = -x$$
$$y' = y$$

$$\begin{bmatrix} x' \\ y' \end{bmatrix} = \begin{bmatrix} -1 & 0 \\ 0 & 1 \end{bmatrix} \begin{bmatrix} x \\ y \end{bmatrix}$$

2D Mirror over (0,0)?

$$x' = -x$$
$$y' = -y$$

$$\begin{bmatrix} x' \\ y' \end{bmatrix} = \begin{bmatrix} -1 & 0 \\ 0 & -1 \end{bmatrix} \begin{bmatrix} x \\ y \end{bmatrix}$$

2x2 Matrices

- What types of transformations can be represented with a 2x2 matrix?

2D Translation?

$$\begin{aligned} x' &= x + t_x \\ y' &= y + t_y \end{aligned}$$

NO!

Translation is not a linear operation on 2D coordinates

Only linear 2D transformations can be represented with a 2x2 matrix

All 2D Linear Transformations

- Linear transformations are combinations of …
  - Scale,
  - Rotation,
  - Shear, and
  - Mirror

$$\begin{bmatrix} x' \\ y' \end{bmatrix} = \begin{bmatrix} a & b \\ c & d \end{bmatrix} \begin{bmatrix} x \\ y \end{bmatrix}$$

- Properties of linear transformations:
  - Origin maps to origin
  - Lines map to lines
  - Parallel lines remain parallel
  - Ratios are preserved
  - Closed under composition

$$\begin{bmatrix} x' \\ y' \end{bmatrix} = \begin{bmatrix} a & b \\ c & d \end{bmatrix} \begin{bmatrix} e & f \\ g & h \end{bmatrix} \begin{bmatrix} i & j \\ k & l \end{bmatrix} \begin{bmatrix} x \\ y \end{bmatrix}$$

Today's class

- Types of 2D Transformations
  - Linear
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- Computing 2D Transformations
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Homogeneous Coordinates

- **Q: How can we represent translation as a 3x3 matrix?**

$$x' = x + t_x$$

$$y' = y + t_y$$

- ***Homogeneous coordinates***
  - represent coordinates in 2 dimensions with a 3-vector

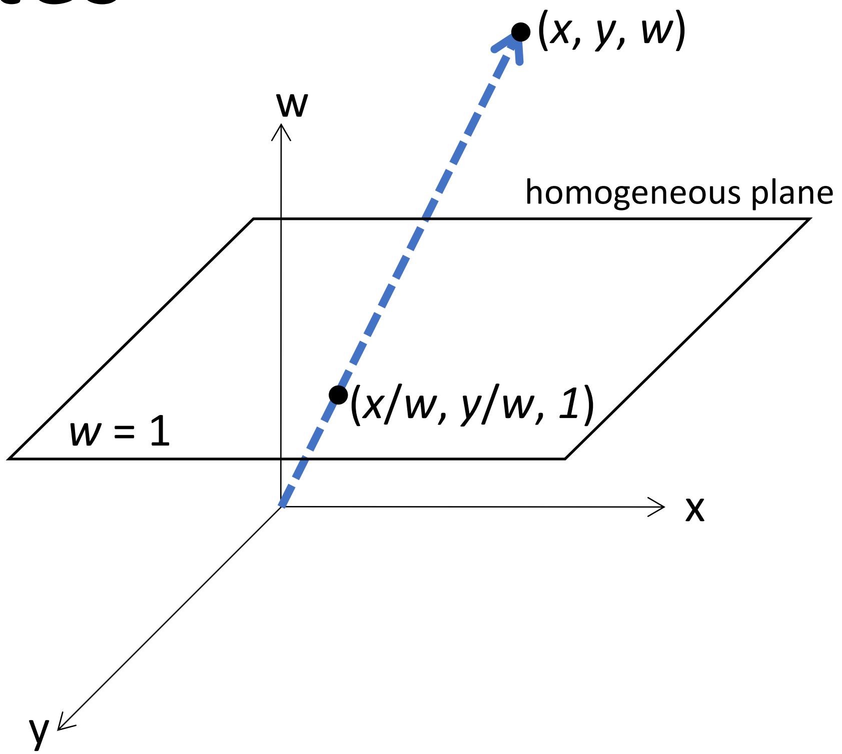
$$\begin{bmatrix} x \\ y \end{bmatrix} \xrightarrow{\text{homogeneous coords}} \begin{bmatrix} x \\ y \\ 1 \end{bmatrix}$$

Homogeneous coordinates

Trick: add one more coordinate:

$$(x, y) \Rightarrow \begin{bmatrix} x \\ y \\ 1 \end{bmatrix}$$

homogeneous image coordinates

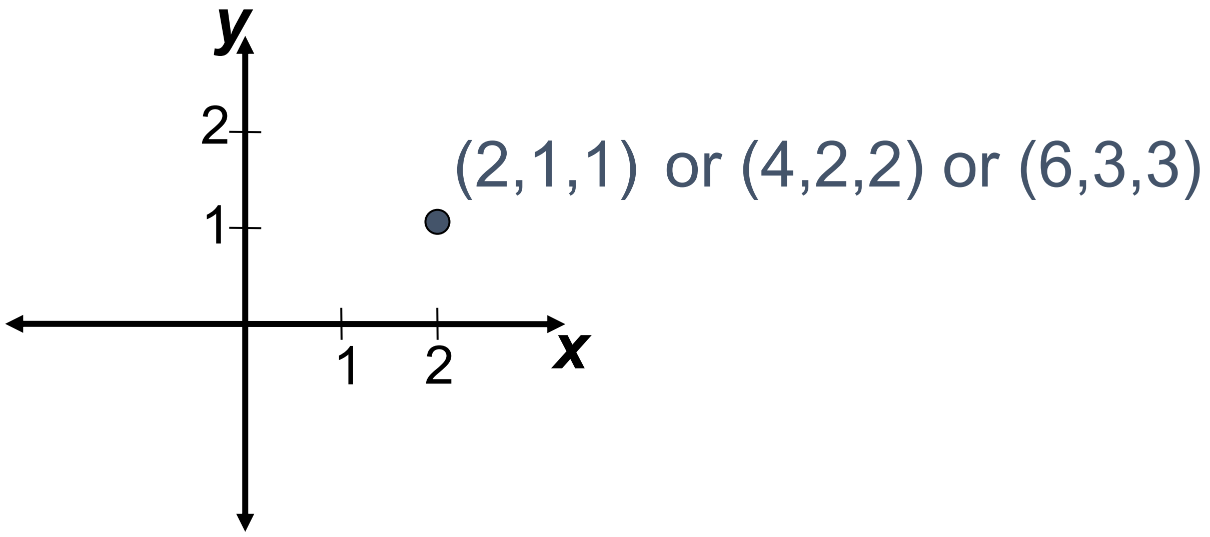


Converting *from* homogeneous coordinates

$$\begin{bmatrix} x \\ y \\ w \end{bmatrix} \Rightarrow (x/w, y/w)$$

Homogeneous Coordinates

- Add a 3rd coordinate to every 2D point
  - (x, y, w) represents a point at location (x/w, y/w)
  - (x, y, 0) represents a point at infinity
  - (0, 0, 0) is not allowed



Convenient coordinate system to represent many useful transformations

Homogeneous Coordinates

- **Q: How can we represent translation as a 3x3 matrix?**

$$x' = x + t_x$$
$$y' = y + t_y$$

- A: Using the rightmost column:

$$\mathbf{T}\boldsymbol{ranslation} = \begin{bmatrix} 1 & 0 & \boldsymbol{t_x} \\ 0 & 1 & \boldsymbol{t_y} \\ 0 & 0 & 1 \end{bmatrix}$$

$$\begin{bmatrix} 1 & 0 & t_x \\ 0 & 1 & t_y \\ 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} x \\ y \\ 1 \end{bmatrix} = \begin{bmatrix} x + t_x \\ y + t_y \\ 1 \end{bmatrix}$$

Affine transformations

$$\mathbf{T} = \begin{bmatrix} 1 & 0 & t_x \\ 0 & 1 & t_y \\ 0 & 0 & 1 \end{bmatrix}$$

any transformation represented by
a 3x3 matrix with last row [0 0 1]
we call an *affine* transformation

$$\begin{bmatrix} a & b & c \\ d & e & f \\ 0 & 0 & 1 \end{bmatrix}$$

Basic affine transformations

$$\begin{bmatrix} x' \\ y' \\ 1 \end{bmatrix} = \begin{bmatrix} 1 & 0 & t_x \\ 0 & 1 & t_y \\ 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} x \\ y \\ 1 \end{bmatrix}$$

Translate

$$\begin{bmatrix} \boldsymbol{x}' \\ \boldsymbol{y}' \\ 1 \end{bmatrix} = \begin{bmatrix} \boldsymbol{s}_{\boldsymbol{x}} & 0 & 0 \\ 0 & \boldsymbol{s}_{\boldsymbol{y}} & 0 \\ 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} \boldsymbol{x} \\ \boldsymbol{y} \\ 1 \end{bmatrix}$$

Scale

$$\begin{bmatrix} x' \\ y' \\ 1 \end{bmatrix} = \begin{bmatrix} \cos\theta & -\sin\theta & 0 \\ \sin\theta & \cos\theta & 0 \\ 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} x \\ y \\ 1 \end{bmatrix}$$

2D *in-plane* rotation

$$\begin{bmatrix} \boldsymbol{x}' \\ \boldsymbol{y}' \\ 1 \end{bmatrix} = \begin{bmatrix} 1 & \boldsymbol{sh}_{\boldsymbol{x}} & 0 \\ \boldsymbol{sh}_{\boldsymbol{y}} & 1 & 0 \\ 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} \boldsymbol{x} \\ \boldsymbol{y} \\ 1 \end{bmatrix}$$

Shear

Matrix Composition

- Transformations can be combined by matrix multiplication

$$\begin{bmatrix} x' \\ y' \\ w' \end{bmatrix} = \left(\begin{bmatrix} 1 & 0 & tx \\ 0 & 1 & ty \\ 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} \cos\Theta & -\sin\Theta & 0 \\ \sin\Theta & \cos\Theta & 0 \\ 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} sx & 0 & 0 \\ 0 & sy & 0 \\ 0 & 0 & 1 \end{bmatrix} \right) \begin{bmatrix} x \\ y \\ w \end{bmatrix}$$

$$\mathbf{p}' \quad = \quad T(t_x,t_y) \qquad R(\Theta) \qquad S(s_x,s_y) \qquad \mathbf{p}$$

Does the order of multiplication matter?

Affine transformations

- Affine transformations are combinations of …
  - Linear transformations, and
  - Translations

$$\begin{bmatrix} x' \\ y' \\ w \end{bmatrix} = \begin{bmatrix} a & b & c \\ d & e & f \\ 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} x \\ y \\ w \end{bmatrix}$$

- Properties of affine transformations:
  - Origin does not necessarily map to origin
  - Lines map to lines
  - Parallel lines remain parallel
  - Ratios are preserved
  - Closed under composition

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- Types of 2D Transformations
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Where do we go from here?

$$\begin{bmatrix} a & b & c \\ d & e & f \\ 0 & 0 & 1 \end{bmatrix}$$

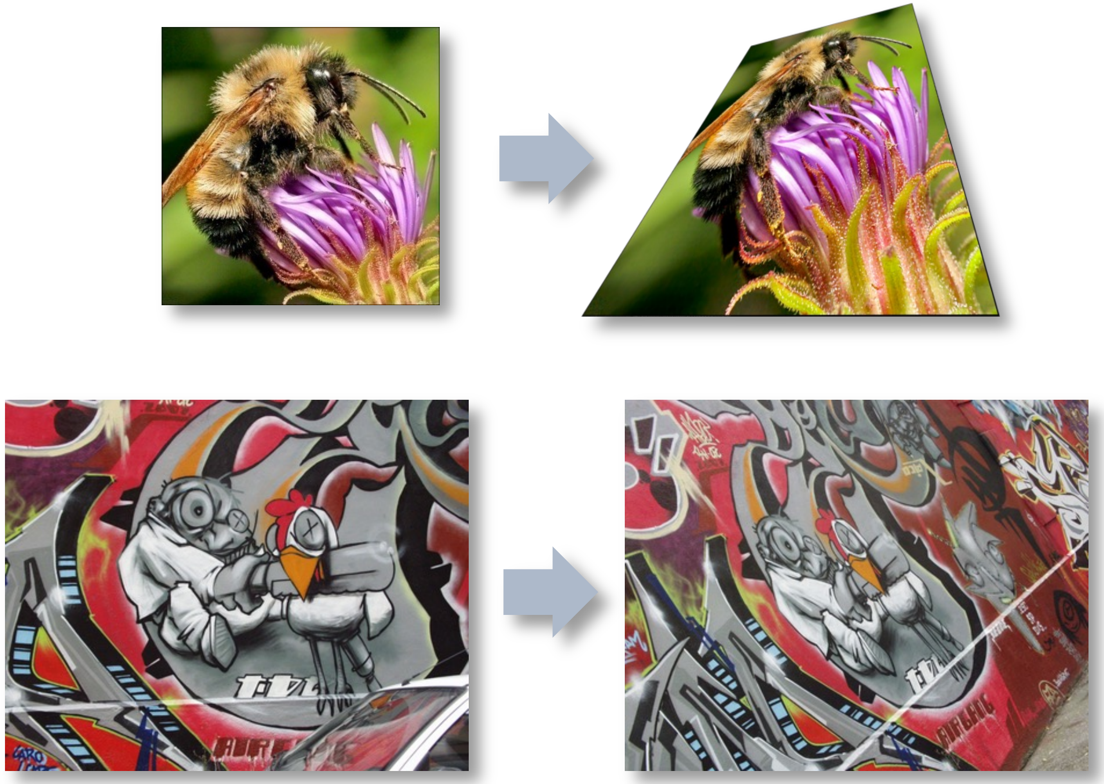
affine transformation

what happens when we mess with this row?

Projective Transformations *aka* Homographies *aka* Planar Perspective Maps

$$\mathbf{H} = \begin{bmatrix} a & b & c \\ d & e & f \\ g & h & 1 \end{bmatrix}$$

Called a *homography*
(or *planar perspective map*)



Any two images of the same planar surface in 3D space are related by a **homography** (assuming a pinhole camera model).

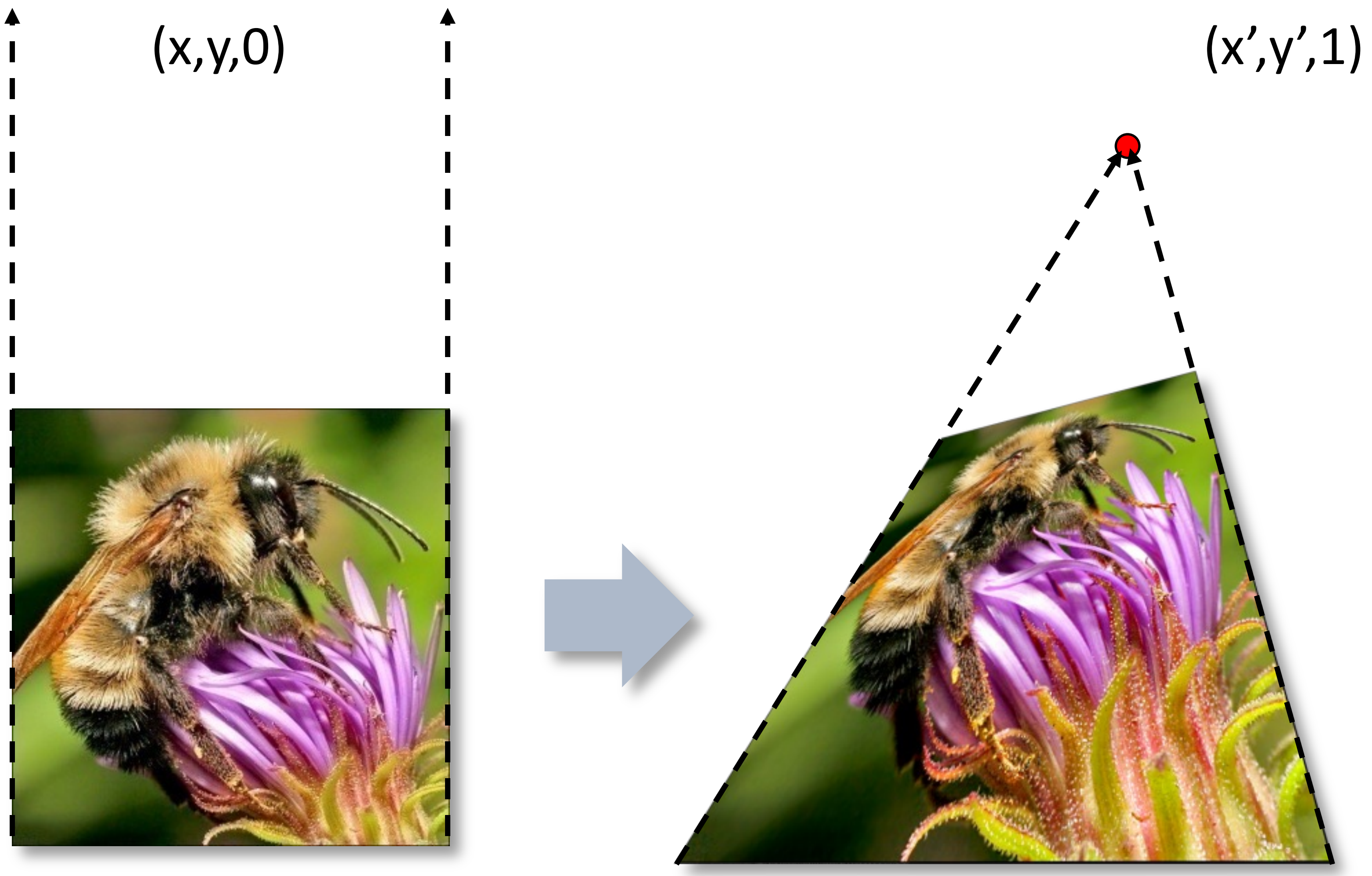
Homographies

$$\begin{bmatrix} x' \\ y' \\ w' \end{bmatrix} = \begin{bmatrix} a & b & c \\ d & e & f \\ g & h & 1 \end{bmatrix} \begin{bmatrix} x \\ y \\ 1 \end{bmatrix} =$$

What happens when the denominator is 0?

$$\sim \begin{bmatrix} \frac{ax+by+c}{gx+hy+1} \\ \frac{dx+ey+f}{gx+hy+1} \\ 1 \end{bmatrix}$$

Points at infinity



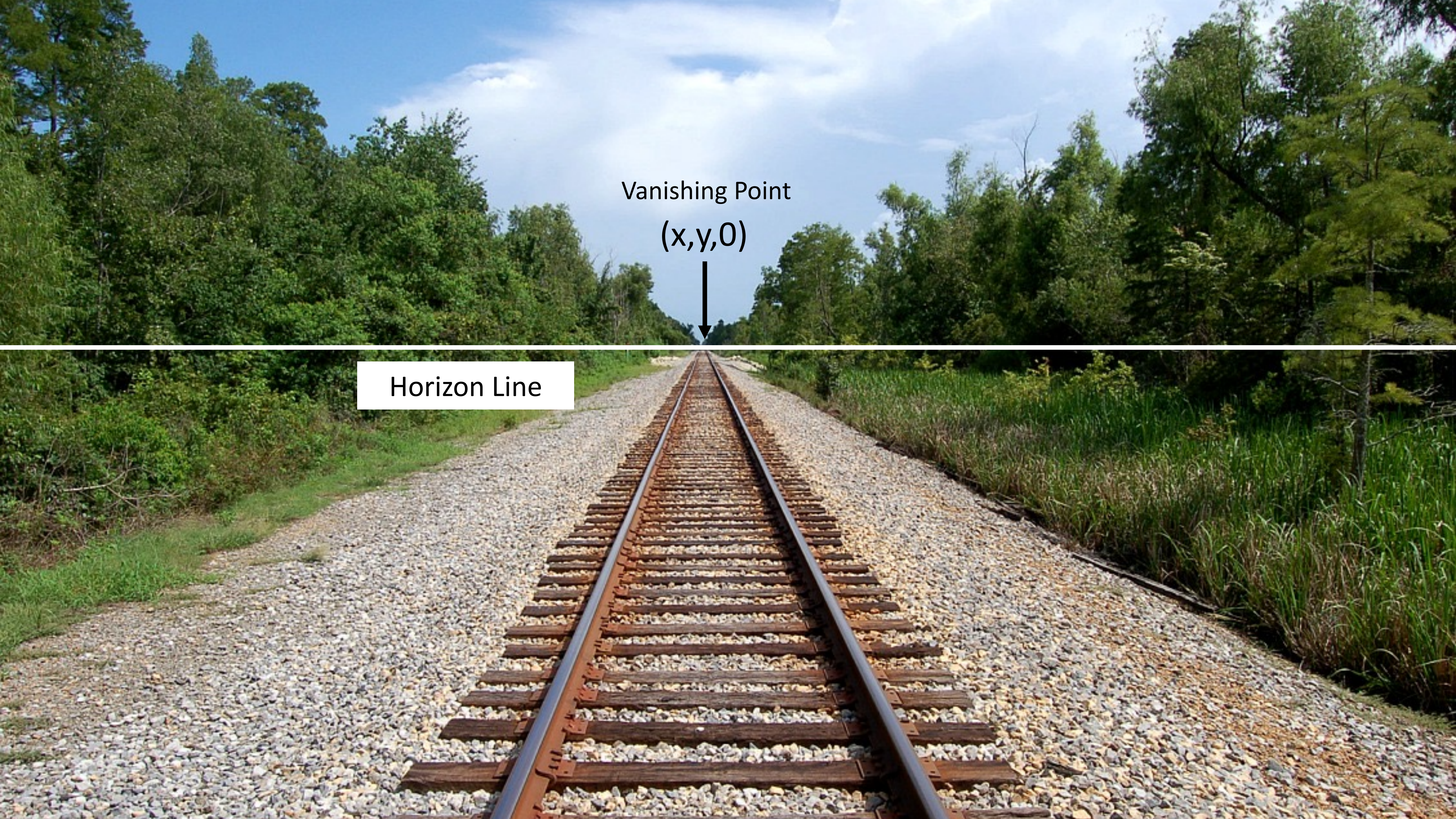
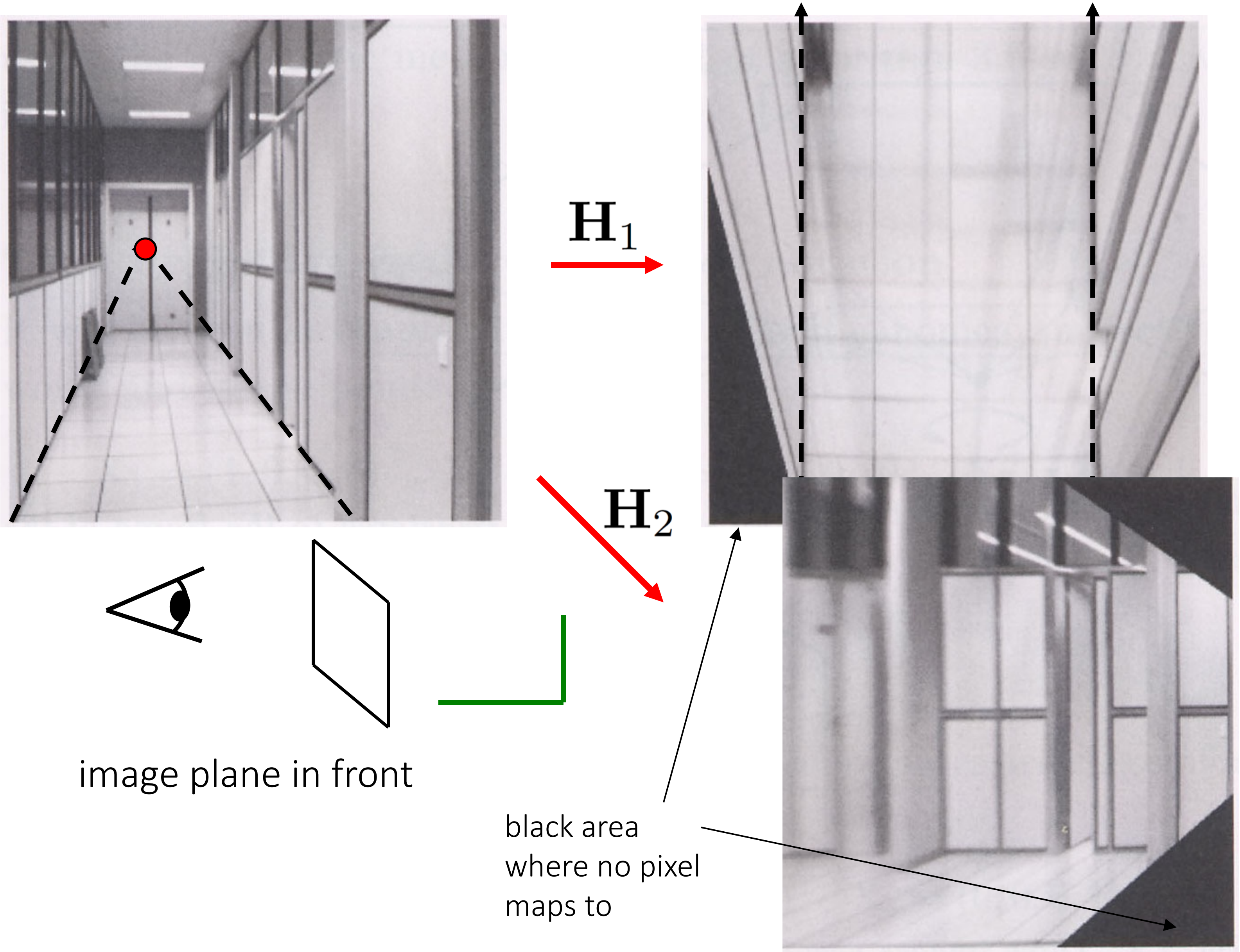

Vanishing Point
(x,y,0)
Horizon Line

Image warping with homographies



Homographies (Projective Transformation)

- Homographies …
  - Affine transformations, and
  - Projective warps

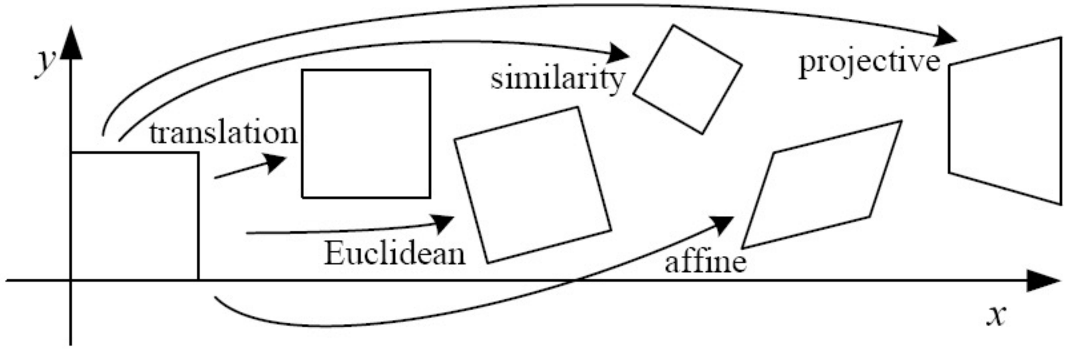
$$\begin{bmatrix} x' \\ y' \\ w' \end{bmatrix} = \begin{bmatrix} a & b & c \\ d & e & f \\ g & h & 1 \end{bmatrix} \begin{bmatrix} x \\ y \\ w \end{bmatrix}$$

$$\begin{bmatrix} x'_i \\ y'_i \\ 1 \end{bmatrix} \cong \begin{bmatrix} h_{00} & h_{01} & h_{02} \\ h_{10} & h_{11} & h_{12} \\ h_{20} & h_{21} & h_{22} \end{bmatrix} \begin{bmatrix} x_i \\ y_i \\ 1 \end{bmatrix}$$

where the length of the vector $[h_{00}\ h_{01}\ \dots\ h_{22}]$ is 1.

- Properties of projective transformations:
  - Origin does not necessarily map to origin
  - Lines map to lines
  - Parallel lines do not necessarily remain parallel
  - Ratios are not preserved
  - Closed under composition

2D image transformations



Name	Matrix	# D.O.F.	Preserves:	Icon
translation	$\begin{bmatrix} \boldsymbol{I} & \vert & \boldsymbol{t} \end{bmatrix}_{2\times 3}$	2	orientation + $\cdots$	
rigid (Euclidean)	$\begin{bmatrix} \boldsymbol{R} & \vert & \boldsymbol{t} \end{bmatrix}_{2\times 3}$	3	lengths + $\cdots$	
similarity	$\begin{bmatrix} s\boldsymbol{R} & \vert & \boldsymbol{t} \end{bmatrix}_{2\times 3}$	4	angles + $\cdots$	
affine	$\begin{bmatrix} \boldsymbol{A} \end{bmatrix}_{2\times 3}$	6	parallelism + $\cdots$	
projective	$\begin{bmatrix} \tilde{\boldsymbol{H}} \end{bmatrix}_{3\times 3}$	8	straight lines	

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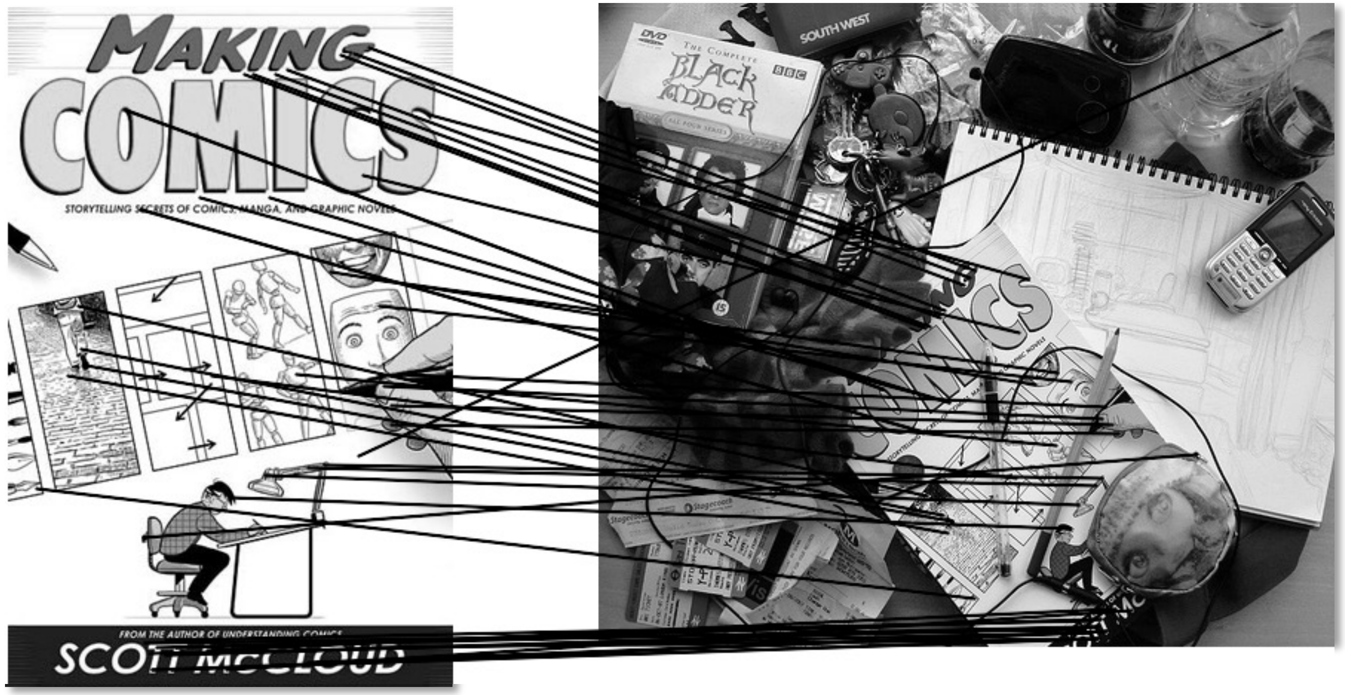
Computing transformations

- Given a set of matches between images A and B
  - How can we compute the transform T from A to B?



  - Find transform T that best “agrees” with the matches

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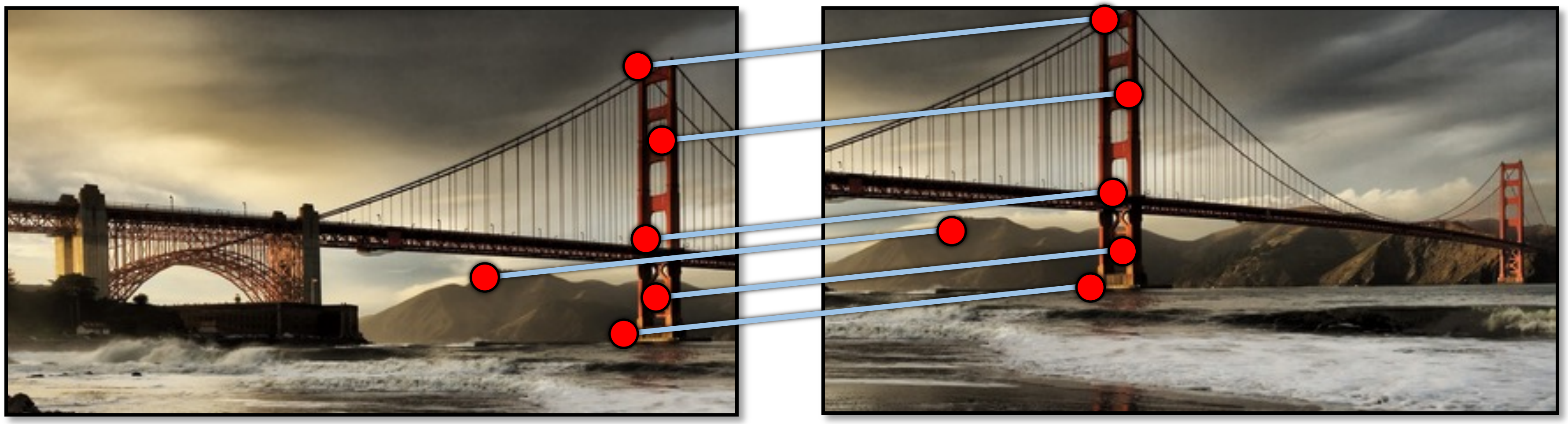
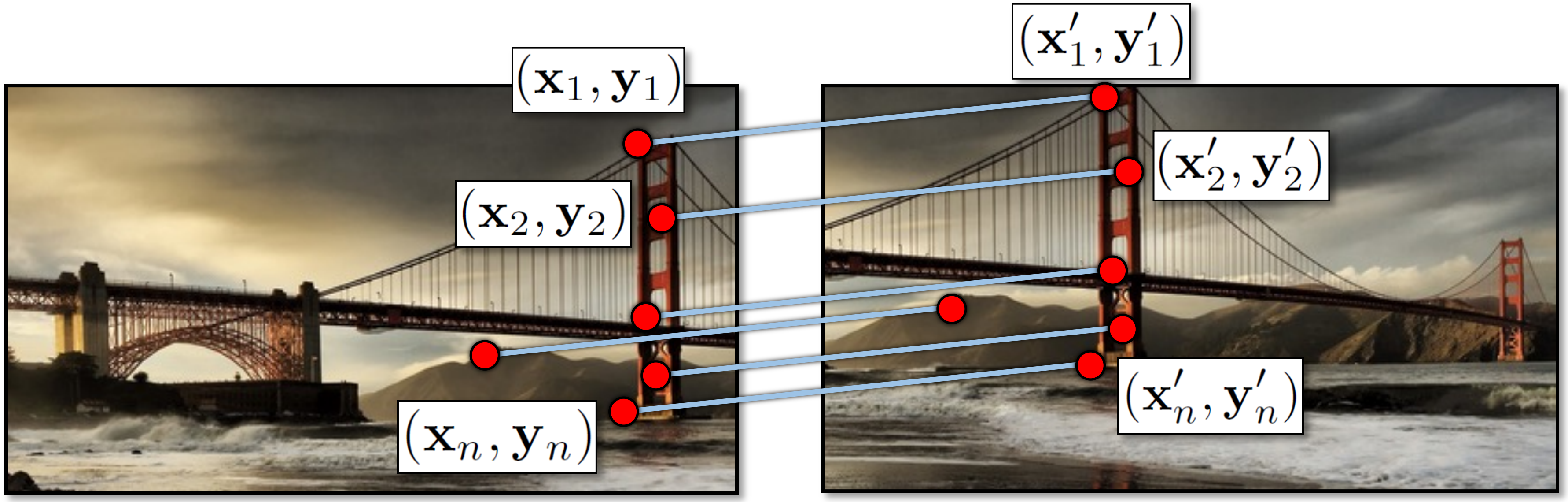
Simple case: translations



$(\mathbf{x}_t, \mathbf{y}_t)$

How do we solve for
$(\mathbf{x}_t, \mathbf{y}_t)$

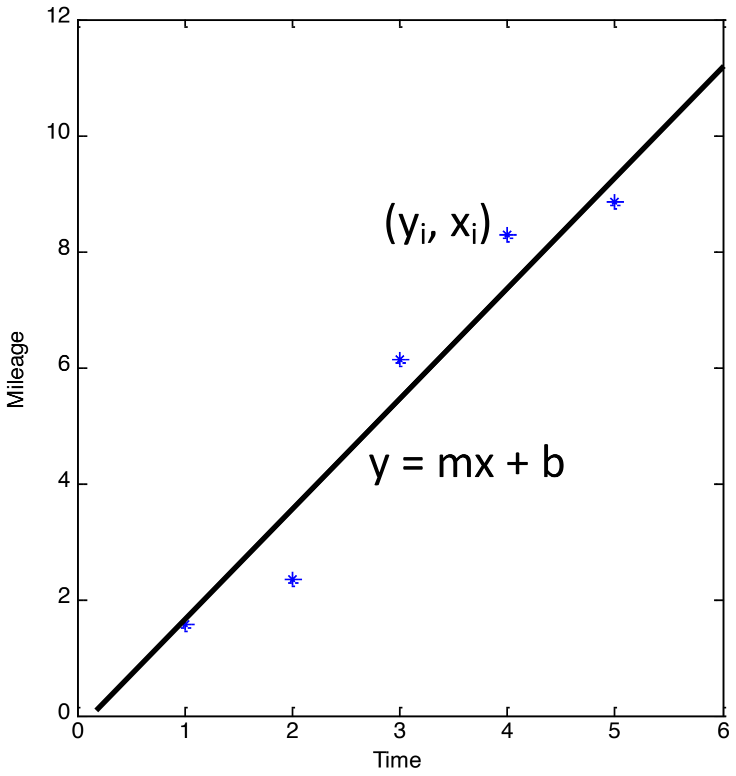
Simple case: translations



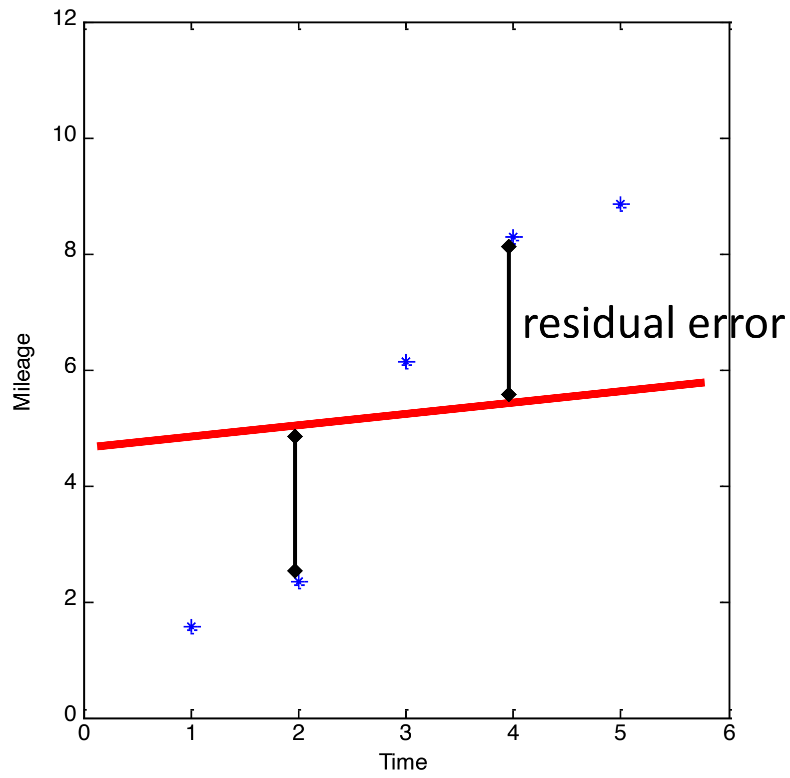
Displacement of match *i* = $(\mathbf{x}'_i - \mathbf{x}_i, \mathbf{y}'_i - \mathbf{y}_i)$

$$(\mathbf{x}_t, \mathbf{y}_t) = \left(\frac{1}{n} \sum_{i=1}^{n} \mathbf{x}'_i - \mathbf{x}_i, \frac{1}{n} \sum_{i=1}^{n} \mathbf{y}'_i - \mathbf{y}_i \right)$$

Least squares: linear regression



Linear regression

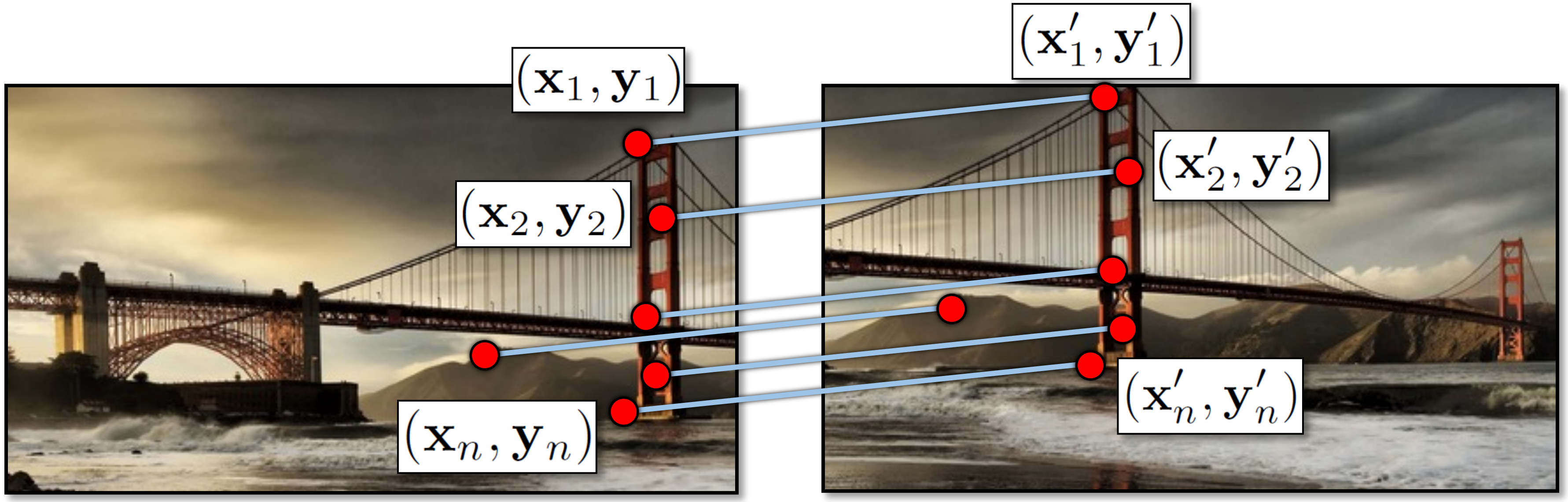


$$\text{Cost}(m, b) = \sum_{i=1}^{n} |y_i - (mx_i + b)|^2$$

Linear regression

$$\begin{bmatrix} x_1 & 1 \\ x_2 & 1 \\ \vdots & \\ x_n & 1 \end{bmatrix} \begin{bmatrix} m \\ b \end{bmatrix} = \begin{bmatrix} y_1 \\ y_2 \\ \vdots \\ y_n \end{bmatrix}$$

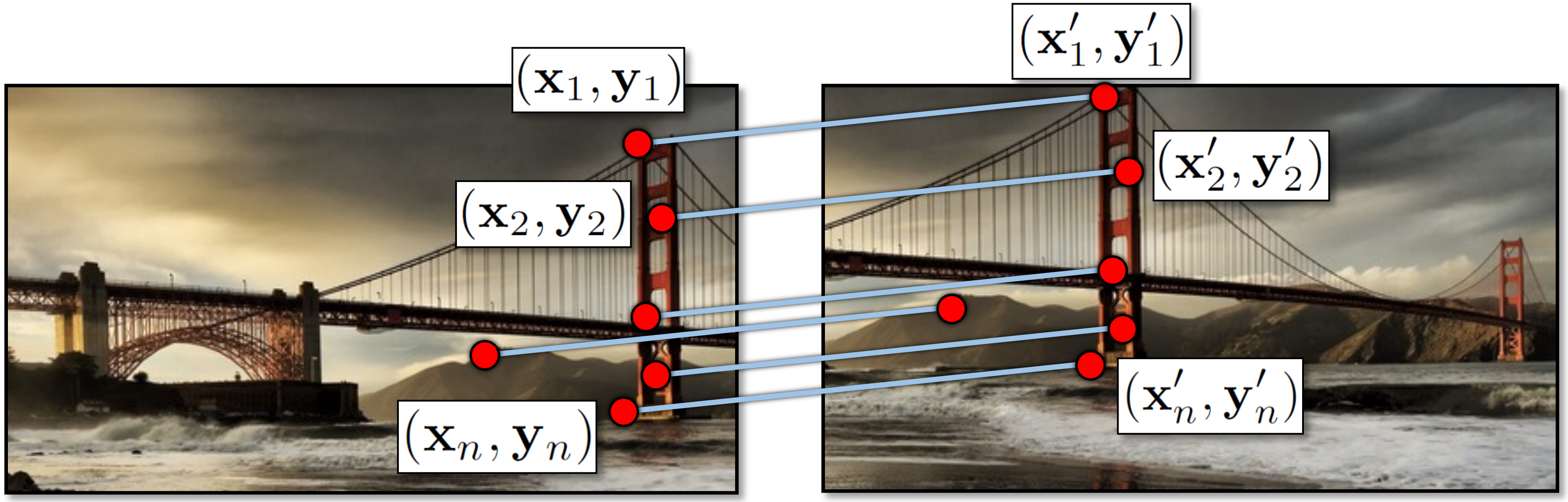
Another view



$$\mathbf{x}_i + \mathbf{x_t} = \mathbf{x}'_i$$
$$\mathbf{y}_i + \mathbf{y_t} = \mathbf{y}'_i$$

- System of linear equations
  - What are the knowns? Unknowns?
  - How many unknowns? How many matches do we need?

Another view



$$\mathbf{x}_i + \mathbf{x_t} = \mathbf{x}'_i$$
$$\mathbf{y}_i + \mathbf{y_t} = \mathbf{y}'_i$$

- Problem: more equations than unknowns
  - “Overdetermined” system of equations
  - We will find the *least squares* solution

Least squares formulation

- For each point $(\mathbf{x}_i, \mathbf{y}_i)$

$$\begin{aligned} \mathbf{x}_i + \mathbf{x_t} &= \mathbf{x}_i' \\ \mathbf{y}_i + \mathbf{y_t} &= \mathbf{y}_i' \end{aligned}$$

- we define the *residuals* as

$$\begin{aligned} r_{\mathbf{x}_i}(\mathbf{x}_t) &= (\mathbf{x}_i + \mathbf{x}_t) - \mathbf{x}_i' \\ r_{\mathbf{y}_i}(\mathbf{y}_t) &= (\mathbf{y}_i + \mathbf{y}_t) - \mathbf{y}_i' \end{aligned}$$

Least squares formulation

- Goal: minimize sum of squared residuals

$$C(\mathbf{x}_t, \mathbf{y}_t) = \sum_{i=1}^{n} \left(r_{\mathbf{x}_i}(\mathbf{x}_t)^2 + r_{\mathbf{y}_i}(\mathbf{y}_t)^2 \right)$$

- "Least squares" solution
- For translations, is equal to mean (average) displacement

Least squares formulation

- Can also write as a matrix equation

$$\begin{bmatrix} 1 & 0 \\ 0 & 1 \\ 1 & 0 \\ 0 & 1 \\ & \vdots & \\ 1 & 0 \\ 0 & 1 \end{bmatrix} \begin{bmatrix} x_t \\ y_t \end{bmatrix} = \begin{bmatrix} x'_1 - x_1 \\ y'_1 - y_1 \\ x'_2 - x_2 \\ y'_2 - y_2 \\ \vdots \\ x'_n - x_n \\ y'_n - y_n \end{bmatrix}$$

$$\underset{2n \times 2}{\mathbf{A}} \quad \underset{2 \times 1}{\mathbf{t}} = \underset{2n \times 1}{\mathbf{b}}$$

Least squares

$$\mathbf{A}\mathbf{t} = \mathbf{b}$$

- Find **t** that minimizes

$$||\mathbf{A}\mathbf{t} - \mathbf{b}||^2$$

- To solve, form the *normal equations*

$$\mathbf{A}^{\mathrm{T}}\mathbf{A}\mathbf{t} = \mathbf{A}^{\mathrm{T}}\mathbf{b}$$

$$\mathbf{t} = \left(\mathbf{A}^{\mathrm{T}}\mathbf{A}\right)^{-1}\mathbf{A}^{\mathrm{T}}\mathbf{b}$$

Today’s class

- Types of 2D Transformations
  - Linear
  - Affine
  - Perspective (Homography)

- Computing 2D Transformations
  - Linear
  - Affine
  - Perspective (Homography)

Affine transformations

$$\begin{bmatrix} x' \\ y' \\ 1 \end{bmatrix} = \begin{bmatrix} a & b & c \\ d & e & f \\ 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} x \\ y \\ 1 \end{bmatrix}$$

- How many unknowns?
- How many equations per match?
- How many matches do we need?

Affine transformations

- Residuals:

$$\begin{aligned} r_{x_i}(a,b,c,d,e,f) &= (ax_i + by_i + c) - x'_i \\ r_{y_i}(a,b,c,d,e,f) &= (dx_i + ey_i + f) - y'_i \end{aligned}$$

- Cost function:

$$C(a,b,c,d,e,f) = \sum_{i=1}^{n} \left(r_{x_i}(a,b,c,d,e,f)^2 + r_{y_i}(a,b,c,d,e,f)^2 \right)$$

Affine transformations

- Matrix form

$$\underbrace{\begin{bmatrix} x_1 & y_1 & 1 & 0 & 0 & 0 \\ 0 & 0 & 0 & x_1 & y_1 & 1 \\ x_2 & y_2 & 1 & 0 & 0 & 0 \\ 0 & 0 & 0 & x_2 & y_2 & 1 \\ & & & \vdots & & \\ x_n & y_n & 1 & 0 & 0 & 0 \\ 0 & 0 & 0 & x_n & y_n & 1 \end{bmatrix}}_{\substack{\mathbf{A} \\ 2n \times 6}} \underbrace{\begin{bmatrix} a \\ b \\ c \\ d \\ e \\ f \end{bmatrix}}_{\substack{\mathbf{t} \\ 6 \times 1}} = \underbrace{\begin{bmatrix} x'_1 \\ y'_1 \\ x'_2 \\ y'_2 \\ \vdots \\ x'_n \\ y'_n \end{bmatrix}}_{\substack{\mathbf{b} \\ 2n \times 1}}$$

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- Types of 2D Transformations
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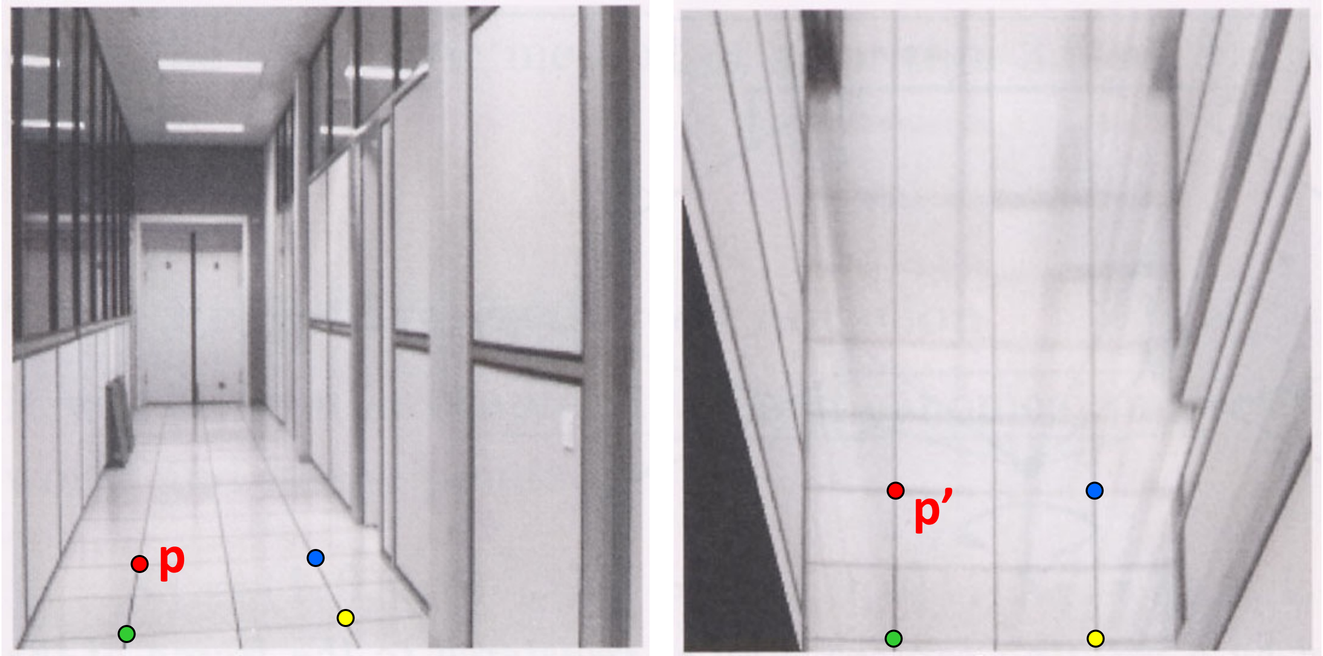
Homographies



To unwarp (rectify) an image

- solve for homography **H** given **p** and **p’**
- solve equations of the form: w**p’** = **Hp**
  - linear in unknowns: w and coefficients of **H**
  - H is defined up to an arbitrary scale factor
  - how many matches are necessary to solve for **H**?

Solving for homographies

$$\begin{bmatrix} x_i' \\ y_i' \\ 1 \end{bmatrix} \cong \begin{bmatrix} h_{00} & h_{01} & h_{02} \\ h_{10} & h_{11} & h_{12} \\ h_{20} & h_{21} & h_{22} \end{bmatrix} \begin{bmatrix} x_i \\ y_i \\ 1 \end{bmatrix}$$

$$x_i' = \frac{h_{00}x_i + h_{01}y_i + h_{02}}{h_{20}x_i + h_{21}y_i + h_{22}}$$

$$y_i' = \frac{h_{10}x_i + h_{11}y_i + h_{12}}{h_{20}x_i + h_{21}y_i + h_{22}}$$

Not linear!

$$\begin{aligned} x_i'(h_{20}x_i + h_{21}y_i + h_{22}) &= h_{00}x_i + h_{01}y_i + h_{02} \\ y_i'(h_{20}x_i + h_{21}y_i + h_{22}) &= h_{10}x_i + h_{11}y_i + h_{12} \end{aligned}$$

Solving for homographies

$$\begin{aligned} x'_i(h_{20}x_i + h_{21}y_i + h_{22}) &= h_{00}x_i + h_{01}y_i + h_{02} \\ y'_i(h_{20}x_i + h_{21}y_i + h_{22}) &= h_{10}x_i + h_{11}y_i + h_{12} \end{aligned}$$

$$\begin{bmatrix} x_i & y_i & 1 & 0 & 0 & 0 & -x'_i x_i & -x'_i y_i & -x'_i \\ 0 & 0 & 0 & x_i & y_i & 1 & -y'_i x_i & -y'_i y_i & -y'_i \end{bmatrix} \begin{bmatrix} h_{00} \\ h_{01} \\ h_{02} \\ h_{10} \\ h_{11} \\ h_{12} \\ h_{20} \\ h_{21} \\ h_{22} \end{bmatrix} = \begin{bmatrix} 0 \\ 0 \end{bmatrix}$$

Solving for homographies

$$\begin{bmatrix} x_1 & y_1 & 1 & 0 & 0 & 0 & -x'_1 x_1 & -x'_1 y_1 & -x'_1 \\ 0 & 0 & 0 & x_1 & y_1 & 1 & -y'_1 x_1 & -y'_1 y_1 & -y'_1 \\ & & & & \vdots & & & & \\ x_n & y_n & 1 & 0 & 0 & 0 & -x'_n x_n & -x'_n y_n & -x'_n \\ 0 & 0 & 0 & x_n & y_n & 1 & -y'_n x_n & -y'_n y_n & -y'_n \end{bmatrix} \begin{bmatrix} h_{00} \\ h_{01} \\ h_{02} \\ h_{10} \\ h_{11} \\ h_{12} \\ h_{20} \\ h_{21} \\ h_{22} \end{bmatrix} = \begin{bmatrix} 0 \\ 0 \\ \vdots \\ 0 \\ 0 \end{bmatrix}$$

$$\underset{2n \times 9}{\mathbf{A}} \qquad \underset{9}{\mathbf{h}} \qquad \underset{2n}{\mathbf{0}}$$

Defines a least squares problem: minimize $\|\mathbf{Ah} - \mathbf{0}\|^2$

- Since *h* is only defined up to scale, solve for unit vector $\hat{\mathbf{h}}$
- Rank(A) = ?

Solving for homographies

$$\underset{2n \times 9}{\mathbf{A}} \times \underset{9}{\mathbf{h}} = \underset{2n}{\mathbf{0}}$$

Rank(A) = 8

- Calculate Singular Value decomposition of A -> $A = UDV^T$
- U is 2n x r ; D is r x r (diagonal matrix with singular values) ; V is 9 x r, where r=rank(A).
- In ideal case r=rank(A)=8, h is in null-space of A.
- In practice rank(A)=9, thus the goal is to find the smallest singular value of A.
- Smallest singular value of A also indicates how well the homography can be estimated.

- Calculate $A^TA = VDU^TUDV^T = V\,D^2\,V^{-1}$ (Since, $U^TU = V^TV = I$)
- This is eigen-decomposition of A^TA
- Smallest singular value of A -> Smallest eigen value of A^TA.
- Solution: optimal h = eigenvector of A^TA with smallest eigenvalue.

Computing transformations

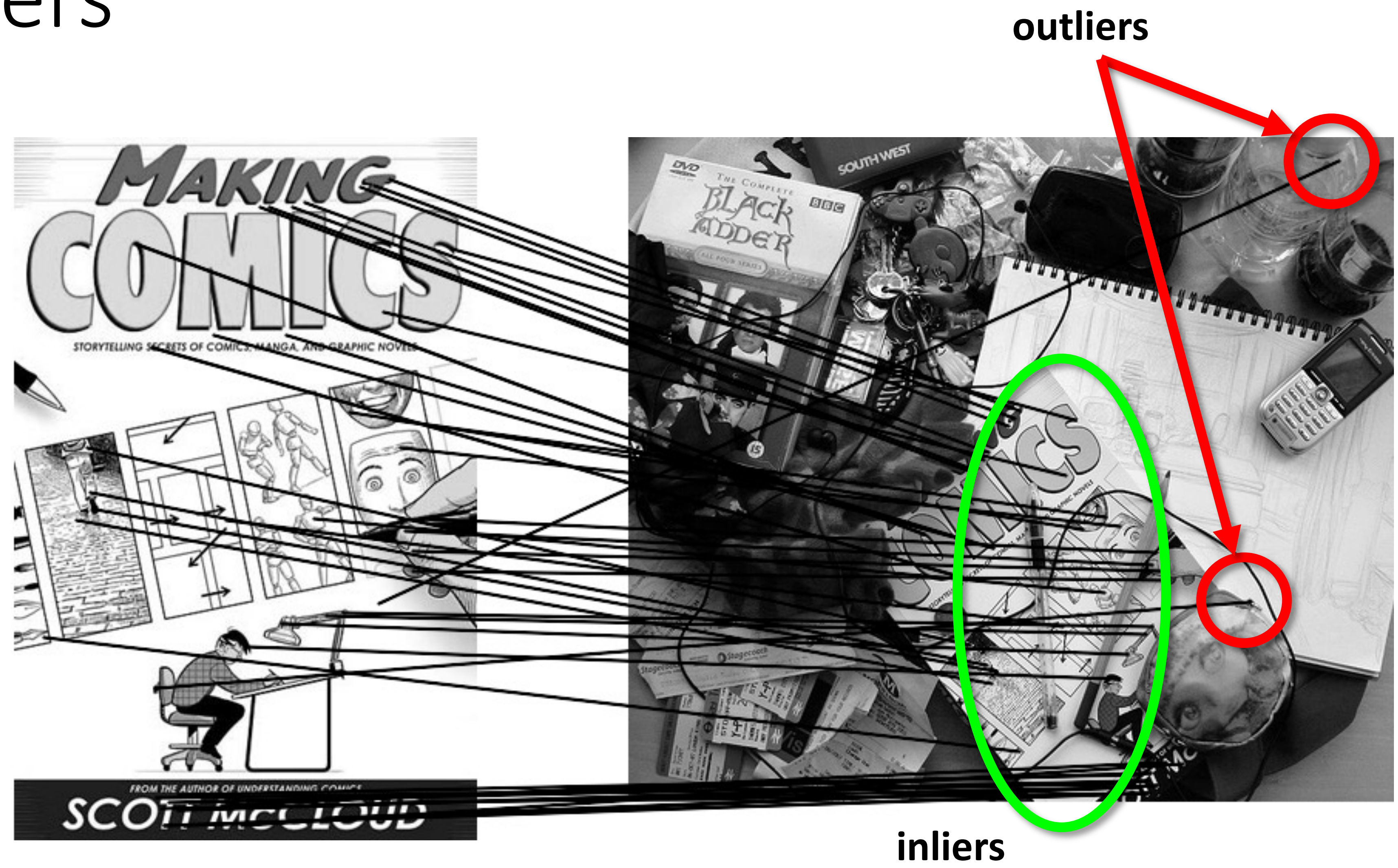
Image alignment algorithm

Given images A and B

1. Compute image features for A and B
2. Match features between A and B
3. Compute homography between A and B using least squares on set of matches

What could go wrong?

Outliers



Lead to next class on RANSAC

Slide Credits

- CS5670, Introduction to Computer Vision**, Cornell Tech, by Noah Snavely.**
- CS 194-26/294-26: Intro to Computer Vision and Computational Photography**, UC Berkeley, by Alyosha Efros.**
- Fall 2022 CS 543/ECE 549: Computer Vision, UIUC, by **Svetlana Lazebnik.**