Index

C^n-continuous, 738
L_1-norm minimization, 150
    ML-type estimation as L_1., 148
L_{12}-norm minimization, **148**, 755, 764
S^1, 214, 215
S^2, 199, 200, 242, 243
S^3, 242, 333
S^5, 243
$\mathsf{\Pi}$, **300**
$\mathsf{\Pi}(\mathbf{x})$, independent rows and columns, 319
$\overline{\mathsf{\Pi}}$, **301**
$\mathsf{\Gamma}$, 219
$\mathsf{\Gamma}(\mathbf{x})$, independent rows, 319
$\overline{\mathsf{\Gamma}}$, 233
Ω, **84**
χ distribution, 34
χ^2-square distribution, 33
δ_0, 131
    for multi-dimensional test, 68, 130
    for one-dimensional test, 66, 128
$\ell(\ell'', \ell''')$, **625**
D, 227
$\mathbb{P}$, 231
$\mathbb{P}^0$, 215, 216, 231
$\mathbb{P}^1$, 214
$\mathbb{P}^2$, 200, 203, **206**, 207, 211, 215, 231
$\mathbb{P}^3$, **210**, 231
$\mathbb{P}^5$, 231
$\mathbb{P}^n$, **215**
$\mathbb{P}^{*2}$, **209**, 209
$\mathbb{P}^{*3}$, **212**, 231
$\mathbb{T}^n$, **345**
$\mathbb{T}^{*2}$, 346
$\mathbb{T}^{*3}$, 347
$\mathsf{S}(\mathbf{x})$, independent rows, 318
ρ-function, 144
    table of ρ., 149
$\wp_2(\mathcal{X}', \ell'''))$, **631**
$\wp_3(\mathcal{X}', \ell''))$, **631**
x-parallax, 566, **589**, 601–604
y-parallax, 561, 566, **589**, 590, 592, 602
$2^1/_2$D surface, 729
1D homography, 257
    fixed entities of h., 276
1D point, 214
    at infinity, 214
    homogeneous coordinates of p., 214
2D affinity, 252
    fixed line of a., 274
2D autocollineation, perspective a., 277
2D block adjustment
    free b., 663
    functional model of b., 651
    gauge constraints in b., 665
    gauge transformation in b., 668
    inner precision of b., 666
    mathematical model of b., 651
    sparsity of matrices, 655
    stochastical model of b., 652
    theoretical quality of b., 670–674
2D circle, 237
2D homography, 250, **253**
    algebraic solution for h., 389
    closed form solution of h., 406
    degrees of freedom of h., 321
    fixed entities of h., 274
    from uncertain point pairs, 425
    minimal parametrization of h., 385
    minimal solution of h., 321
    orientedness of transformed entities, 355
    uncertainty of points mapped with h., 387
2D line, 207
    at infinity, **207**
    centroid representation of l., 374
    direction of l., 294, 348
    distinct points of l., 318
    from two points, 292
    from uncertain centroid to Hessian form of l., 374
    Hessian normal form of l., **207**, 374
    Hessian normal form of uncertain l., 374
    homogeneous coordinates of l., 207
    null space of covariance matrix of l., 375, 392
    optimal closed form solution for l., 397
    oriented l., 346
    Plücker coordinates of l., 223
    point at infinity of l., 209, 294
    point-direction form of l., 209
    through two points, 221
    transformation of l., 258
    uncertain Hessian form to homogeneous coordinates of l., 375
    uncertain Hessian parameters of l., 376
    uncertain homogeneous coordinates to Hessian form, 377
    uncertain l., 373–377
2D model block adjustment, 650–674
2D motion, 251
    fixed entities of m, 274
2D point, 206
    at infinity, 206
    closest to conic, 295
    covariance matrix of spherically normalized p., 393
    degrees of freedom of p., 207
    direct least squares solution of intersection p., 401
    direct solution for intersection p., 401
    distinct lines of p., 318
    dual of p., 204
    homogeneous coordinates of p., 206
    null space of covariance matrix of p., 368, 393
    oriented p., 345
    Plücker coordinates of p., 223
    reduced coordinates of p., 370
    sign of intersection p., 353
    spherical normalization of uncertain p., 368
    uncertain p., 366–372
2D rotation, 251
    fixed entities of r., 274
2D scaling, 251
2D shear, 252
2D similarity, 252
2D translation, 251
    fixed entities of t., 274
3D affinity, 255
3D autocollineation, 280
3D circle, 241
3D conics, 241

3D homography, 256
closed form solution of h., 406
fixed entities of h., 275
minimal solution of h., 322
3D line
and spatial triangle, 351
approximating 6-vector of l., 381
at infinity, 219
coplanarity of two l., 304
covariance matrix of reduced coordinates of l., 381
degrees of freedom of l., 216, 227
direct solution of l., 412
directed l., 606
direction of l., 348, 353
distinct planes of l., 319
distinct points of l., 319
dual l., 233
from two planes, 220
moment vector of l., **218**, 219, 220, 227
oriented l., 348
parameters of l., 216
Plücker coordinates of l., **218**, 226
point at infinity of l., 220
point-direction form of l., 220
projection, 480
reconstruction from two images, 605
reduced coordinates of l., 380–381
spherical projection of l., 481
through four 3D lines, 302
through two points, 300
transformation, 259
two-point form of l., 220
uncertain l., 379–381
3D model block adjustment, 649
3D motion, 255
fixed entities of m., 276
3D point, 210
at infinity, 210
degrees of freedom of p., 211
direct least squares solution of intersection p., 402
direct solution for line intersection p., 401
distinct planes of p., 319
from several images, 602
from two rays, normal case of image pair, 601
homogeneous coordinates of p., 210
oriented p., 346
Plücker coordinates of p., 225
quality of p., 526
triangulation of p. from several images, 602
uncertain p., 372–373
3D points, collinearity of p., 306
3D rotation, *see* rotation
3D similarity, 255
3D translation, 255
fixed entities of t., 275

a posteriori probability density, 77
a priori probability density, 76
absolute orientation, 549, **552**, 607, 609
direct solution of a. with three points, 515
of calibrated cameras, 552
of uncalibrated cameras, 552
redundancy of a., 613
within two-step procedure, 612
absolute points, 241
acceptability
of a covariance matrix, 120
of bundle adjustment result, 688
of configuration, 495, 516
of precision, 117, 120
accuracy, **116**, 490
empirical a., 117
identification a., 117, **490**, 706
of the mean, 116
adaptive least Kth order squares, 146
additional parameters, 123, 464
choice of a., 509, 684
elimination, 695
evaluation, 693
evaluation of a., 699
adjacency graph, 654, 660
adjugate matrix, 770
adjustment, *see* estimation
adjustment, block a., 643
ADS 80, Leica, 443, 445, 446
aerotriangulation, 707, **718**, 721
affinity
2D a., 252
3D a., 255
chirality of transformed configurations, 357
minimal solution of a., 320
sign of entities transformed with a., 357
algebraic solution, 178
covariance matrix of a., 180
for 2D homography, 389
for 2D line, 396
for 2D line intersection, 401
for 3D line intersection, 401
for plane, 396
for projection matrix, 494
with eigenvalue decomposition, 179
with SVD, 179
algorithm
$\mathsf{K}, R, \boldsymbol{Z}$ from P, 500
$\mathbf{b}, R$ from essential matrix, 583
3D circle from its image, 536
direct LSE 2D line from points, 401
direct LSE 3D line from points, 414
direct LSE 3D similarity from point pairs, 411
direct LSE mean axis, 405
direct LSE mean direction, 404
direct LSE point from lines, 403
direct LSE rotation from point pairs, 408
DLT for projection matrix, 496
Gauss–Helmert model with reduced coordinates, 416
Gauss–Markov model with constraints, 108
Gauss–Markov model, linear, 91
homography from point pairs, 389
model with constraints between the observations only, 171
optimal P from image points, 498
RANSAC, 156
reweighing constraints, 169
robust a. for Gauss–Helmert model with constraints, 168
sequential similarity transformations, 710
sequential spatial resection, 709
triangulation, 600
algorithmic complexity, 452
analysis model, 7, 448
angle
between 2D direction and coordinate axes, 206
between 3D direction and coordinate axes, 210
between two 2D lines, 298
direction a, 298
parallactic a., 420, 421
tilt a. of plane, 212
zenith a., 210
antiparallel, 343
antipodal
line, 348
plane, 347
point, 344–346
approximate residuals, 164
approximate values, 145, 452
for bundle adjustment, 707–715
for bundle adjustment, direct solutions, 711
for bundle adjustment, sequential solutions, 708
for relative orientation, 583
for relative orientation, normal case, 589
AR-process
AR(P), 52
AR(1), 53
AR(2), 53
for modelling profiles, 748
integrated A., 54, 752
observed A., 749
area camera, 444
area of triangle, 222
astigmatism, 379
asymmetric weight function, 756
attitude of camera, 456
autocollineation, 248, 256
2D a., 277
fixed elements of a., 272
perspective a., **277**
automatic image matching, 563
autoregressive process, *see* AR process
axis and angle
from rotation matrix, 331
axis, closed form solution of mean a., 405

back projection, 482

bandwith of matrix, 662
barycentric coordinates, 213, 349
base line, 551, 563
base vector, 553, 578, 582
  estimation from 2 points, given rotation, 578
base-to-height ratio, 604
basis functions
  monomials as b., 733
  of collocation, 735
  radial b., 735
  splines as b., 736
  trigonometric b., 734
Bayer pattern, 444
Bayesian estimation, 76–78
  in Gauss–Markov model, 93
  surface reconstruction as B., 742
Bayesian factor, 64
Bayesian information criterion, 139, 686
Bertrand's paradox, 22
best linear unbiased estimate, 79
best unbiased estimate, 79
bi-partite graph, 646
bias, **116**
  induced by linearization, 44
  of estimated variance factor, 137
  of estimates, 79, 141
  of normalization, 45
  of product, 44
  of the mean, 45
  of the variance, 45
  of variance of image points and lines, 493
bicubic interpolation, 738
bilinear interpolation, 738
bilinearity of coplanarity constraint, 553
binomial distribution, 28
bivector, 235
block, 643
block adjustment, 643
  2D model b., 651
  adjacency graph in b., 660
  bundle adjustment as b., 648
  free b., 663
  linear planar b., 711–714
  mathematical model of b., 647
  model b., 645
block matrix, inverse of b., 769
blunder, *see* outlier
boundary of region, 442
break down point, 145
bundle adjustment, 450, 609, **648**
  acceptability of accuracy of b., 692
  acceptability of design of b., 691
  acceptance criteria for results of b., 688
  approximate values, 707–715
  as block adjustment, 648
  Cramer–Rao bound of b., 683
  empirical accuracy of b., 682
  Euclidean b., 649
  evaluation of b., 687
  factorization method for b., 714
  for camera calibration, 696
  for image pair, 610
  for image triplet, 638
  for relative orientation, 585
  functional model of b., 675
  gauge constraints in b., 665
  linear estimation of rotations in b., 713
  linearized model of b., 676
  MAP estimate for b., 648
  nonlinear model of b., 675
  outlier detection, 707–715
  projective, 676
  projective b., 649
  redundancy of image pair, 611
  self-calibrating b., 450, 674–696
  sensitivity of b., 701
  spherical camera b., 686
  variance component estimation in b., 679
  view planning for b., 715–722
  with lines, 676
  with points, 610, 649
bundle of rays, 461, 559

calibrated camera, **460**, 555–557, 607, 622
  for the image pair, 556
calibration
  laboratory c., 697
  of camera, 449
  self-c., 697
  stability of c., 702
  test field c., 697
  with unknown testfield, 698
calibration matrix, 471
  differential c., 501
  from projection matrix, 499
camera, 460
  absolute orientation of calibrated c., 552
  absolute orientation of uncalibrated c., 552
  affine c., **464**
  area c., 444
  calibrated c., 452, **460**, 607, 622
  calibrated perspective c., 555–557
  calibration, 449
  calibration, bundle adjustment for c., 696
  calibration, laboratory c., 697
  calibration, test field c., 697
  catadioptric c., 487
  central c., **446**, 456, 465, 622
  computational c., 444
  coordinate system, **463**, 465, 602
  coplanarity constraint for images of calibrated c., 555–557
  coplanarity constraint for images of spherical c., 556–557
  digital c., 465
  distortions of perspective c., 505
  essential matrix of normalized c. , 559
  Euclidean c., **464**
  fish-eye c., 485
  generic c., **446**, 460
  geometric c. model, 443
  ideal c., **465**, 561
  ideal perspective c., 468
  ideal unit c., 465
  line c., 444
  matrix, 281
  metric c., **460**, 460
  model, 441, **445**, 479
  model of central c., 468
  model of perspective c., 462, 464, 470
  model of real c., 461
  model of spherical c., 462, 468
  moving c., 568
  normalized c., **465**, 472, 713
  orientation, 449
  partially calibrated c., **460**
  perspective c., 248, **446**, 456, 460, 464, 607
  perspective c. for the image pair, 550
  perspective c. for the image triplet, 622
  perspective c. with distortions, **464**
  pinhole c., 253, 281, 464, 465
  planes, 554
  point c., 444
  pose, 456
  principal planes of c., 474
  ray, 469
  real c., 456
  relative orientation, 552
  spherical, 582
  spherical c., **446**
  spherical c. for the image pair, 555, 556
  spherical c. for the image triplet, 622
  stellar calibration of perspective c., 496
  systems, 488
  uncalibrated, **461**
  uncalibrated c., 452, 490, 550, 622
  with affine sensor, 470
  with distortion, 462
  with Euclidean sensor, 531
Canon PowerShot A630, 443, 445
catadioptric camera, 487
catadioptric optics, 446
caustic, 445, 446
Cayley representation of rotation, 336
central camera, **446**, 456, 465
  model of, 468
central limit theorem, 30
central projection, **456**, 467, 481, 485, 487, 490
centroid representation, 490, 492
  of 2D line, 374
  of plane, 377
Chasles' theorem, 272
check of linearization, 104
check points, 683, 700
checkability, 117, 453
  of coordinates in absolute orientation, 411
  of parameters, 133

checking the implementation, 139
chirality, 357
  effect of affinity, 357
  effect of homography on c., 356
  of 2D line and point, 349
  of four 3D points, 350
  of plane and point, 350
  of three 2D points, 349
  of two 3D lines, 350, 355
choice of additional parameters, 509, 684
Cholesky decomposition, 86, 661, 776
circle, 237
  2D, 237
  3D, 241
circle fitting, 177
close range applications, 452
closed form estimation, 176–183
closed form solution, *see* direct solution
clustering, 157
cofactor matrix, 369, 556, **769**
  as dual transformation matrix, 259
  for line conic, 239
  for plane quadric, 240
  for polarity, 238
  for transformation of hyperplanes, 258
collinearity
  equations, 470
  of 3D points, 306, 602
  of projection centres, 622
  of three 2D points, 296
  projective c. equations, 472
collineation, 247, **277**
  1D c., 257
  perspective c., 248, 277, 278
  projective c., 248
collocation, 174–176
  basis functions of c., 735
colour image, 569
complanarity, *see* coplanarity
complete search, 151
complete space U, 231
complex numbers, 651
computational camera, 444
concatenation
  of displacements, 262
  of homographies, 261
  of transformations, 261
concurrence
  of planes, 307
  of three 2D lines, 296
condition number, **118**, 286, 537, 574, 659
conditional probability, 23
conditioning, **286**
  effect of c. on normal equations, 657
  of point coordinates, 321, 465, 494, 571, 603, 606
  of projection matrix, 537
confidence
  ellipse, 32, 369
  hyperbola, 374
conformal geometric algebra, 236
conic, 236
  central form of c., 237
  closed form solution for c., 182
  dual c., 239
  general form of c., 236
  orientation of c., 348
  parametric form of c., 237
  point closest to c., 295
  point of symmetry of c., 237
  tangent at c., 238
  transformation of c., 260
conjugate
  rotation, 281–282, 321
  transformation, 278
  translation, 279
consensus set maximization, 143, 157
constraints
  between corresponding image features, 451
  coplanarity c. for image of calibrated cameras, 555
  coplanarity c. for images from uncalibrated cameras, 552
  coplanarity c. for normal case, 562
  crisp c., 96
  epipolar c. for image triplet, 639
  for essential matrix, 557
  for fundamental matrix, 553
  for groups of observations, 167
  for three image points, 623
  gauge c., 110
  weak c., 102
constructions
  in 2D, 292–295
  in 3D, 300–304
continuous random variables, 26
continuous, C^n-c., 738
control
  feature, 647
  full c. point, 608
  horizontal c. point, 609
  line, 493, 548, 609
  plane, 609
  planimetric c. point, 609
  point, 450, 493, 527, 548
  points of image pair, 608
  stochastic c. point, 610
convolution, 42
Cook's distance, 127
coordinate axes, 244
coordinate system
  camera c., 461, **463**, 465, 602
  elements of c., 243
  image c., 463
  normalized camera c., 466
  object c., **462**, 465
  of photogrammetric model, 559
  scene c., 462
  sensor c., 463
coordinate transformation, 109, 262–266
  interpretation of c., 249
coordinates
  barycentric c., 213, **349**
  homogeneous c., 45, **195**, 205
  image c., 469
coplanarity
  condition, 228
  of 3D points, 602
  of four 3D points, 307
  of two 3D lines, 304
coplanarity constraint, **550**, 564
  for normal case, 561, 562
  from projection rays, 554
  of images of calibrated cameras, 555–557
  of images of spherical cameras, 556–557
  of images of uncalibrated cameras, 552, 553
  table, 562
corrections, 82
correctness, 116
  of covariance matrix, 140
  of variance factor, 140
correlation, 248
  coefficient, 31, 37
  function, 50
  matrix, 38
  of parameters of spatial, 522
  projective c., 282
  singular, 564
correspondence, 548
correspondence problem, 9
corresponding
  image lines, 568
  image points, 561, 563, 568, 569
  points and lines, 621
covariance, 37
  function, **49**, 121, 736, 739, 741
  intersection, 98
  operator, 38
covariance matrix, 37
  acceptability of c., 120
  correctness of c., 140
  effect of wrong c., 135
  eigenvalue decomposition of c., 667
  empirical c., 118
  evaluation of c., 669
  metric for c., 121
  of algebraic solution, 180
  of centroid, 410
  of estimated observations, 86
  of estimated parameters, 86, 96
  of estimated residuals, 87
  of five-point solution, 588
  of homography from four points, 388
  of image coordinates, 569
  of matrix, 32
  of mean direction, 403
  of parallaxes, 569
  of parameters, relative orientation, 591
  of projection matrix, 495
  of quaternion, 383
  of quaternion from directions, 408
  of reduced 2D line coordinates, 376
  of reduced coordinates $\boldsymbol{x}_r$, 371

of reduced coordinates of 3D line, 381
of rotation, 435
of rotation from directions, 407
of rotation matrix, 435
of the residuals, relative orientation, 591
reference c., 517
singular c., 33
sparsity of c., 663
specification of c., 121
theoretical c., 517
Cramer–Rao bound, **86**, 118, 648
of bundle adjustment, 683
crisp constraints, 96
criterion matrix, 120
critical configuration, **452**, 452
DLT with points, 495
estimation of trifocal tensor, 636
image pair, 614
line prediction, 626
prediction in image triplet, 635
spatial resection, 515, 521
critical cylinder of spatial resection, 515, 517
critical surface
estimation of essential matrix, 588
estimation of fundamental matrix, 571
relative orientation, 588
cross ratio
of collinear points, 268
of concurrent lines, 270
cumulative distribution, 26
cumulative distribution, inverse c., 40
curvature
as fictitious observations, 747
as prior, 745
for regularization, 747
curve, flatness of c., 739
Cuthill–McKee algorithm, 662

d.o.f., *see* degrees of freedom
datum, *see* gauge
decision theory tasks, 19
decomposition
Cholesky d., 661, 776
LU d., 661
of projection matrix, 498
QR d., 776
definition accuracy, 117
degenerate configuration, 517
degrees of freedom
of 2D point, 207
degrees of freedom, 360
3D rotation, **327**
in χ^2-distribution, 33
in t-distribution, 35
in Fisher distribution, 35
in noncentral χ^2 distribution, 34
in Wishart distribution, 34
of 2D elation, 278
of 2D homography, **251**, 253, 321
of 2D line, 375
of 2D perspectivity, 278
of 2D point, 368
of 3D elation, 281
of 3D homography, 255
of 3D homology, 281
of 3D line, **216**, 227, 264
of 3D point, 211, 373
of 3D rotation, 327, 382
of collineations, 285
of essential matrix, 556
of fundamental matrix, 553
of general homography, 249
of general rotation, 326
of image pair, 550
of plane, 212
of projection matrices from fundamental matrix, 594
of projection matrix, 472
of test w.r.t. ground truth, 119
of test on bias, 141
of test on correctness of covariance matrix, 141
of test on groups of outliers, **129**, 129, 131
of test on noise level, 140
of test on systematic errors, 134
of tests on geometric relations, 393, 395
of transformations, 253
of trifocal tensor, 622
of variance factor, 90, 98
Delaunay triangulation, 732
delta function, 26
Denavit–Hartenberg parameters, 264
density
a posteriori d., 77
function, 26
dependent images, 558, 595
general parametrization, 558
design matrix, 82
reduced d., 95
detectability
ellipse, 130
factor, 125, 129, 131
of gross errors, relative orientation, 591
of groups of gross errors, 129
of single gross errors, 125
detectable gross error, 125
detectable outliers during relative orientation, 592
diagnostics, 142
external d., **115**, 119
internal d., **115**, 115, 117, 118
differential
angles, 337, 338
calibration matrix, 501
rotation, 336
rotation vector, 337
similarity transformation, 111
differential GPS, 683, 721
DigiCAMx4, IGI, 683
digital elevation model, 728
digital surface model, 728
direct linear transformation (DLT), 247, **249**
direct LS estimation
2D lines from points, 401
3D line from points, 414
3D similarity from point pairs, 411
mean axis, 405
mean direction, 404
point from lines, 403
rotation from point pairs, 408
direct solution, 176, 178, 452
minimal d., 178
minimum norm solution, 179
of 2D intersection point, 401
of 3D homography, 406
of 3D intersection point, 401, 402
of 3D line, 411
of absolute orientation with three points, 515
of algebraic surface, 183
of best fitting 2D line, 397
of best fitting mean axis, 405
of best fitting mean direction, 403
of best fitting plane, 400
of best fitting rotation from directions, 406
of best fitting similarity, 408
of bundle adjustment, 711
of circle fitting, 177
of conic, 182
of ellipse fitting, 182
of estimation a 3D line, 412
of homography, 406
of quadric fitting, 183
of spatial resection, 513
of spatial resection with > 3 points, 518
of trifocal tensor, 636
directed
3D line, 606
prediction of d. image lines in image triplet, 627
direction
angle, 298
angle between 2D d. and coordinate axes, 206
angle between 3D d. and coordinate axes, 210
closed form solution for mean d., 403
cosine matrix for rotation, 328
interpolation of d., 341
of 2D line, 294
of camera ray, 467, **469**
of intersection of two planes, 353
of join of two points, 352
of line segment, 352
of lines and planes, 346–348
vector of image point, **469**, 553, 556
discrete random variables, 26
dispersion operator, 38
displacements, 262
concatenation of d., 262
distance
between two 2D points, 298
between two 3D lines, 310
between two 3D points, 309
from origin in 2D, 297
Mahalanobis d., 84

of 2D entities, 297–298, 310
of 2D point from 2D line, 298
of 2D point from line, 298
of 3D entities, 308
of 3D line from origin, 308
of 3D line to origin, 218
of 3D point from line, 309
of 3D point from origin, 308
of 3D point from plane, 310
of plane from origin, 308
of two covariance matrices, 121
signed d., 354
distinct entities defining
2D line, 318
2D point, 318
3D line, 319
3D point, 319
plane, 319
distortion
lens d., 464, 507
nonlinear d., 452, 477
of perspective mapping, 479
radial, 506
radial d., 506–508
tangential d., 506
distortion model, 476
phenomenological d., 508
physical d., 506
distribution, 24, 28–35
χ d., 34
χ^2-square d., 33
t-d., 35
binomial d., 28
cumulative d., 26
exponential d., 29
Fisher d., 35
Gaussian d., 29
inverse cumulative d., 40
Laplace d., 29
mixed d., 143
multi-dimensional normal d., 31
normal d., 29
quantiles of d., 40
Rayleigh d., 29
Student's t-d., 35
uniform d., 28
Wishart d., 34
DLT, 247, **249**, 480, 622
algebraic solution for d., 494
direct estimation of d., 494
explicit form of D., 472
for uncalibrated cameras, 472
from 3D lines, 504
precision of d. compared to spatial resection, 523
theoretical precision of d., 522
two d. for image pair, 611
DMC, Intergraph, 683
double points, 523, 590, 592
doubly integrated white noise process, 53
driving process, 52, 749
dual
3D line, 233
conic, 239
entities, 231
of 2D point, 204
oriented projective plane, 346
oriented projective space, 347
Plücker coordinates, 233
Plücker matrix, 233
projective plane $\mathbb{P}^{*2}$, **209**, 209
projective space $\mathbb{P}^{*3}$, **212**, 231
transformation, 259
duality, 203, 229–236, 283
of 2D point and 2D line, 234
of 3D lines, 235
of 3D point and plane, 234
of transformations, 259
dualizing matrix, 227

effect
of intrinsics and extrinsics on image coordinates, 502
of random errors on estimation, 117
of wrong covariance matrix, 135
ego-motion determination, 644
eigenvalue
decomposition of covariance matrix, 667
generalized e. problem, 517
eigenvalues, 773–774
elation
definition of e., 278
elementary rotation, 328
angles from rotation matrix, 330
concatenation of e., 329
ellipse, 237
confidence e., 32
detectability e., 130
fitting, 182
sensitivity e., 130
standard e., **31**, 366, 369
empirical
accuracy, 117, **118**
accuracy of bundle adjustment, 682
covariance matrix, 118
precision, 117, **118**
sensitivity, 126, 130, 134
standard deviation, 118
empty projective space $\mathbb{P}^0$, 231
endlap, 700, **718**, 721
epipolar
axis, 563, 564
constraints, 639
geometry, 562–565
line, 248, 563–565, 623
line, curved e., 564
line, oriented e., 564
plane, 563
epipolar line, 573–574
epipole, 563, 565, 594
equidistant projection, 487
equisolid projection, 487
equivalence of uncertain homogeneous vectors, 390
equivariant function, 267
error in variables model, 161
error propagation, *see* variance propagation
error, quasi-systematic, 667
essential matrix, 556–557, 562, 575–583, 613, 623
degrees of freedom of e., 556
dependent images, 558
from ≥ 7 points, 575
from 2 points, given rotation, 578
from 4 coplanar points, 577
from 5 points, 575
normalized cameras, 559
parametrizations of e., 557
projection matrices from e., 595
singular values of e., 557
estimable quantities, 109, 666
estimate
Bayesian e., 76–78, 93
best linear unbiased e., 79
best unbiased e., 79
least squares e., 79
maximum a posteriori e., 77
maximum likelihood e., 78
estimated
covariance matrix of e. observations, 86
covariance matrix of e. parameters, 86
covariance matrix of e. residuals, 87
observations, 86
parameters, 84
residuals, 84
size of gross errors, 131
size of group of gross errors, 128
size of single gross error, 124
variance factor, 89
estimation
Bayesian e., 93
Bayesian e. in Gauss–Markov model, 93
bias of e., 141
evaluation of e., 117
in Gauss–Helmert model with constraints, 163–170
in Gauss–Markov model with constraints, 99–102
in linear Gauss–Markov model, 81–102
in model with constraints between observations only, 170
in nonlinear Gauss–Markov model, 102–107
of 2D intersection point, 417
of 3D similarity transformation, 607
of variance components, 91–93, 493
on curved manifolds, 415
robust e., 141
sequential e., 96
statistically optimal e., 452
stochastical model of e., 76, 83
with implicit functions, 160
with reduced coordinates, 415
with two group, 96
estimation theory, 75–81
tasks, 19

Euclidean
bundle adjustment, 649
camera, 464
normalization, 196, 198
normalization of matrix, 285
normalization of vector, 199
Euclidean part
of 1D point, 214
of 2D line, 207
of 2D point, 206
of 3D line coordinates, 218
of 3D point, 210
of plane, 211
Euler's rotation theorem, 326
evaluation
w.r.t. groups of gross errors, 128
w.r.t. single gross errors, 124
w.r.t. systematic errors, 133
of acceptability of precision, 120
of additional parameters, 699
of block adjustment, 662
of bundle adjustment, 687
of calibration model, 684
of checkability of parameters, 133
of covariance matrix of block adjustment, 669
of detectability of groups of gross errors, 129
of detectability of single gross errors, 125
of effect of errors, 122
of empirical accuracy, 118
of empirical precision, 118
of estimation, 115
of theoretical precision, 117
of uncertain relations, 393
expectation, 36, 38
of function of stochastic vector, 44
operator, 38
exponential ρ-function, 149
exponential distribution, 29
exterior orientation, **460**, 460, 629, 634
model of e., 465
of camera systems, 488
of image pair, 550, 610
of image triplet, 622, 623
exterior parameters, 460
external diagnostics, **115**, 119
external precision, 116
extrapolation during transformation, 389
extrinsic parameters, *see* exterior parameters
from spatial resection, 513

factor graph, **654**, 659, 661
factorization
of matrix, *see* decomposition
factorization for bundle adjustment, 714
feature
control f., 647
image f., 646
scene f., 646
fictitious observations, 78, 750
for profile reconstruction, 746
field of view, 445, 446, **458**, 459, 468, 484
field-based representation, 8
field-based scene description, 442
fill-in, 662–665
filtering, 730, 736, 762
Kalman f., 96, 98
Wiener f., 93
FinePix REAL 3D W1, Fuji, 443, 445
fish-eye, 444
camera, 485
lens, 459, 485
optics, 478
Fisher
distribution, 35
information matrix, 86
fitted observations, 86
fixed entities, 272–277
of 1D homography, 276
of 2D affinity, 274
of 2D homography, 274
of 2D motion, 274
of 2D rotation, 274
of 2D translations, 274
of 3D affinity, 276
of 3D homography, 275
of 3D motion, 276, 282
of 3D translation, 275
of planar motion, 275
of spatial motion, 276
flatness
of a curve, 739
of a surface, 739–741
flight direction, 558
flight plan, 452
flying height, 605
focal length, 256, 461
focal point, 461
foot point
of 2D origin on line, 295
of origin on 3D line, 323
forward motion, 589
image pair, quality, 593
free adjustment, 109
inner precision of f., 666
minimum trace solution of f., 111
of block, 663
reduced normal equations of f., 114
free network, 109
Fuji FinePix REAL 3D W1, 443, 445
function
ρ-f., 144
delta f., 26
density f., 26
multi-dimensional probability f., 27
of a random variable, 40
of two random variables, 42
separable f., 28
step f., 25
functional model, 75, 490
algebraic structure of f., 161
invertibility of f., 144
nonlinear – linear f., 161
of 2D block adjustment, 651
of block adjustment, 647
of bundle adjustment, 675
table with f., 171
fundamental matrices of image triplet, 623
fundamental matrix, 553–555, 570–574, 612, 622, 629
as singular correlation, 564
degrees of freedom of f., 553
from ≥ 7 points, 571
from ≥ 8 points, 570
from camera planes, 554
from projection matrices, 554
from projection matrix for lines, 564
singular values of f., 554

Gamma-matrix, 219
dual G., 233
gauge, **108**, 703
constraints, 110
constraints in bundle adjustment, 665
definition of g. of coordinate system, 109
definition of g. of covariance matrix, 109
in bundle block, 645
linear g. constraints, 112
minimal control in block adjustment for g., 664
nonlinear g. constraints, 111
transformation, 108–114
transformation in block adjustment, 668
transformation, regular g., **112**, 121
transformation, singular g., 112
unspecified g., 669
Gauss–Helmert model, 160, **162**, 162, 163, 174, 414, 415
for 2D intersection point, 418
for homography estimation, 424, 425
for relative orientation, 586
for total least squares, 161
Gauss–Helmert model with constraints, **163**, 174
estimation in G., 163–170
linear G., 163
nonlinear G., 163
normal equations of G., 165
redundancy of G., 165
robust algorithm for G., 168
Gauss–Markov model, 162, 173, 414, 415, 497
Bayesian estimation in G., 93
for homography estimation, 424, 427
for image triplet, 638
for self-calibrating bundle adjustment, 675, 678
for surface reconstruction, 743, 746
linear G., 81–102
nonlinear G., 102–107
nonlinear G. with constraints, 104

Gauss–Markov model with constraints, 99–102, 162, 173
estimation in G., 100
linear G., 162
nonlinear G., 162
Gauss–Newton method, 103, 105
Gaussian distribution, 29
general weighted least squares, 80
generative model, 83
generic camera, **446**, 460
relative pose, 581
geometric algebra, 236
geometric image model, 447
geometric relations
in 2D, 295–299
in 3D, 304–308
geometry
epipolar g., 562–565
image pair, 549–568
image triplet, 622–632
of single image, 456
single image, 488
global test, 90
bundle adjustment, 689
GPS, 450, 452, 493, 647, 653
differential G., 683, 721
Gram–Schmidt orthogonalization, 511
graph
adjacency g., 654, 660
bi-partite g., 646
factor g., **654**, 659, 661
graph surface, **729**, 739
Grassmann–Cayley algebra, 234
gross error, *see* outlier
detection, 452
estimated size of g., 124, 131
lower bound for detectable g., 125, 131
model of g., 123
test statistic for g., 131
gross errors, 452
ground sampling distance, **457**, 590, 683, 716, 720
ground truth, 115, 119, 429, 683
groups of observations, 86
constraints for g., 167
detectable gross errors of g., 129
diagnostics of g., 130
evaluation of g., 128
in sequential estimation, 96
in variance component estimation, 91, 92
normal equations for g., 96
outlier model of g., 123
sensitivity factor of g., 130
Gruber
points, 590
position, 590
GSD, *see* ground sampling distance

Hadamard product, 137, **776**
harmonic homology, 280
harmonic points, 270
hat function, 736
hat matrix, 86
Helmert point error, 366
Hessian matrix, 44, 106
of log-likelihood function, 78
of surface function, 741
Hessian normal form, 207
uncertain, 374
hierarchy of transformations, 285
homogeneous
uncertainty, 396
homogeneous entities, notation of h., 196
homogeneous coordinates, 45, **195**, 490
of 1D point, 214
of 2D line, 207
of 2D point, 206
of 3D point, 210
of plane, 211
homogeneous part
of 1D point coordinates, 214
of 2D line coordinates, 207
of 2D point coordinates, 206
of 3D line coordinates, 218
of 3D point coordinates, 210
of plane coordinates, 211
homogeneous representation, 195
homogeneous stochastic process, 51
homogeneous uncertain vectors, equivalence of h., 390
homogeneous uncertainty, 121, 371
homogeneous vectors, normalization of h., 198, 241
homography, **249**, 247–249, 253, 254, 256
1D h., 257
2D h., 250, **253**
2D h. between images, 567, 578
3D h., 255, 256, 613, 622
concatenation of h., 261
constraint of two 3D lines, 316
cross ratio, 268
depth and parallax map, 602
effect of h. on chirality , 356
fixed entities of 1D h., 276
fixed entities of 2D h., 274
fixed entities of 3D h., 275
from point pairs, 389
from uncertain point pairs, 425
general h., 248
image to map plane, 526
image to scene plane, 524, 525
invariants of h., 268
minimal parametrization of uncertain h., **384**, 426
quasi-affine h., 357
table of constraints with h., 316
uncertain h., 384–386
uncertainty of h. from uncertain points, 387
uncertainty of points mapped with h., 387
vector form of h., 315
homologeous, *see* corresponding
homology, **277**, 280, 284, 568
between images, 567
harmonic h., 280
singular values of h., 568
homology, see also perspective autocollineation, 277
horizon, 208, **458**, 468, 474, 482
as 3D control line, 494, 504
horizon line, 458, 459
horizontal view, 456
horopter, 521
Hough transformation, 158, **283**
Huber estimator, **148**, 150
human stereo vision system, 561
hyperbola, 237
standard h., 374
hyperplane, 221, 224, 226, 283
at infinity, 215
transformation of h., 258

ideal
camera, 465
image point, 463
lens, 256
perspective camera, 468
unit camera, 465
ideal point, *see* point at infinity
identification accuracy, 117, 706
of features, 490
identity
of two 2D entities, 296
of two 3D entities, 306
IGI DigiCAMx4, 683
ill-posed, 82
image
coordinate system, 463
coordinates, 469
coplanarity constraint of i. from uncalibrated cameras, 552
distortion model, 476
distortions, 505
feature, 646
geometry, 456
geometry of nadir i., 459
geometry of slanted i., 459
matching, 402, 563
model, 7, 441
orientation of single image, 489
oriented i. line, 482
pair, *see* image pair
perspective i., 456
point, *see* image point
pyramid, 491
rectified i., 477
reduced i. coordinates, **468**, 470
relative orientation, 552
scale, 457
sequence, 647, *see* image strip
straight line-perturbing i. errors, 464
theoretical precision of i. block, 673
theoretical precision of i. strip, 670–673
triplet, *see* image triplet
two-step procedure of i. orientation, 549
image pair
bundle solution for i., 610
comparison of procedures for i., 614

control points of i., 608
critical configuration of i., 614
degrees of freedom of i., 550
exterior orientation of i., 550
geometry of i., 549
interior orientation of i., 550
normal case of i., 465, 561
object points, 608
orientation of i., 549, 608
triangulation for normal case of i., 601
triangulation for perspective i., 600
two-step procedure for i., 612
image point
direction, 556
ideal i., **463**, 469
observable i., 461, **463**
uncertainty of i., 491
image triplet
geometry of i., 622
nonlinear observation equations for i., 638
orientation of i., 632
predicting directed lines in i., 627
relative orientation of i., 633, **636**
images, dependent i., 595
implicit functions, estimation with i., 160
implicit variance propagation, **43**, 516
IMU, 653
incidence
of 2D entities, 295
of 2D line and 2D point, 295
of 3D line and plane, 305
of 3D point and line, 306
of 3D point and plane, 304
of two 3D lines, 304
independence
stochastic i., 28
independent events, 23
independent images, **558**, 581, 589
independent random variables, 31
influence function, 147
table of i., 149
information matrix, 86
inner
geometry, 110
precision, 110, 666
precision of free block, 667
inner product, 767
INS, 452, 647
integrated AR-process, 54
integrated white noise process, 53
Intergraph DMC, 683
interior and exterior orientation
from projection matrix, 500
interior orientation, **460**, 464, 610, 629
of image pair, 550
of image triplet, 622
interior parameters of camera, **460**
interior parameters of camera system, 488
internal
diagnostics, **115**, 115, 117, 118
precision, 116
interpolation, 730
bicubic i., 738
bilinear i., 738
linear i., 737
precision of i., 734
interpolation during transformation, 389
interpolation of directions, 341
interpolation of rotations, 341
interpretation, 9
interpretation model, 7, 448
interpretation of line drawings, 523
intersection, 549
of 2D line and conic, 293
of 3D line and plane, 301
of three planes, 302
of two 2D lines, 202, 292
of two planes, 220, 301
intersection of planes, direct LS solution of i., 403
intrinsic parameters, *see* interior parameters
intrinsic parameters of a camera, 463
invariant, 266
number of independent i., 271
of affinities, 268
of five 2D points, 272
of homography, 268
of perspective mappings, 268
of polygon, 267
of projective mapping, 266
of rectangle, 266, 271
inverse cumulative distribution, 40
inverse depth, 257
inverse perspective, 489, 523
inversion of transformation, 261
invertibility of functional model, 144
isocentre, 459
isometric parallel, 459
isotropic stochastic process, 51
isotropic uncertainty, 121
of directions, 367, **371**, 403, 413
of points, **368**, 396, 399, 406, 408, 412
iterative estimation, 92, **103**, 414, 452
of spatial resection, 520
on curved manifolds, 415
iterative solution, 452

Jacobian
of DLT, 501
of DLT for nadir view, 501
of Hessian form to homogeneous 2D line, 375
of homogeneous to Euclidean 3D coordinates, 373
of homogeneous to Euclidean coordinates, 371
of homogeneous to Hessian form of 2D line, 377
of reduction of 3D line coordinates, 380
of reduction of point coordinates, 370
of spherical normalization, 368, 376
of spherical normalization of 3D point, 373
within estimation, 161
within variance propagation, 43
join
of 3D point and line, 302
of three 3D points, 302
of two 2D points, 202, 293
of two 3D points, 300

K-transformation, 109
Kalman filter, 96, 98
keypoint detector
uncertainty, 491
Kronecker product, 137, 555, 775

laboratory calibration, 697
Ladybug 3, Pointgrey, 443–445
lag, 49
Laplace distribution, 29
Laplacian development theorem, 768
law of cosines, 514
least squares
estimate, 79
general weighted l., 80
ordinary l., 80
weighted l., 79
with regularization for profile reconstruction, 747
leave-one-out test, 124, 128
Legoland scene, 529
Leica ADS 80, 443, 445, 446
lens
distortion, 461, 464, **507**
fish-eye l., 459
narrow-angle l., 459
normal l., 459
thin l. projection, 256
ultra-wide angle l., 459
wide-angle l., 459
zoom l., 459
levels of reasoning, 7
leverage point, 127
Lie group, 284
likelihood function, 77
line
antipodal l., 348
at infinity, 203, 345
direction of l. segment, 352
segment, 352
vanishing l., 529
line at infinity, 208
of plane, **208**, 212, 220
line camera, 444
line drawing interpretation, 523
line segment, uncertainty of l., 492
linear substitute model, 103
linearization, check of l. within Gauss–Markov model, 104
linearized model of bundle adjustment, 676
linearized models, table with l., 171
loop closing, 672
lower bound
for detectable deviation, 66
for detectable gross error, 125, 131
LS, *see* least squares

LU-decomposition, 661

M-estimation, 609
MAD, **40**, 146
Mahalanobis distance, **69**, 84, 361
Manhattan scene, 529
MAP estimate, 77
  bundle adjustment, 648
  profile reconstruction, 744
Maple, 522
mapping, 644
  affine m., 357
  as coordinate transformation, 249
  as displacement, 249
  general m. 3D to 2D, 479
  of general lines, 484
  of quadrics, 484
  perspective m., 277
  quasi-affine m., 357
matching, 9
matrix
  block, inverse of b., 769
  correlation m., 38
  covariance m., 37
  Euclidean normalization of m., 285
  exponential, 781
  exponential for homography, 384
  exponential for motion and similarity, 384
  exponential for rotation, **326**, 326, 337, 338, 382
  exponential for transformations, 382
  normally distributed m., 32
  precision m., 83
  product, eigenvalues of m., 773
  random m., 27
  representation of 2D entities, 312
  representation of 3D entities, 313
  skew symmetric m., 336
  sparse m., 86
  sparse structure of m., 655
  spectral normalization of m., 286
  Toeplitz m., 53
  weight coefficient m., 89
  weight m., 83, 89
maximum a posterior estimate, 77
maximum likelihood estimation, 78–79
maximum likelihood type estimation, 147
mean, 36
  accuracy of the m., 116
  bias of m., 45
  of ratios, 46
  operator, 38
  precision of the m., 116
  vector, 38
median, 40
median absolute difference, 40, 146
meta model, 6, 441
method of modified weights, 147
metric camera, **460**, 696
metric for covariance matrices, 121
minimal parametrization
  of 2D homography, 385
  of uncertain homography, 384
  of uncertain motion, 383
  of uncertain quaternions, 383
  of uncertain rotation, 382
  of uncertain similarity, 383
  of uncertain transformations, 381
minimal representation
  of 2D uncertain point, 369
minimal solution, 178
  of 2D affinity, 320
  of 2D homography, 321
  of 3D homography, 322
  of basis of image pair, 578
  of essential matrix, 575
  of fundamental matrix, 571
  of image orientation, 489
  of projection matrix, 494
  of relative orientation from mirror images, 579
  of relative orientation of three images, 636
  of relative orientation, iterative m., 585
  of spatial resection, 513
  of trifocal tensor, 636
  with QR decomposition, 179
minimum norm solution, 179
minimum trace solution, 111
minimum-volume estimate, 146
mirroring
  at y-axis, 251, 279
  at a plane, 281
  transformation in 2D, 279
mixed distribution, 143
ML-type estimation, 147
  L_1-norm minimization as, 148
model
  functional m., 75
  generative m., 83
  geometric m. of camera, 443
  geometric m. of scene, 442
  linear substitute m., 103
  mathematical m., 75
  notion of m., 7
  of analysis, 7
  of camera, 441, **445**
  of constraints between observations only, **162**, 162
  of distortion, 476
  of image, 7, 441
  of interpretation, 7
  of projection, 449
  of scene, 7, 441
  of sensor, 7
  of world, 7
  phenomenological m. of distortion, 505
  photogrammetric, *see* photogrammetric model
  physical m. of distortion, 505
  stochastical m., 76, 83
  thin plate m., 741
  thin rod m., 741
  weak membrane m., 740
  weak string m., 739
  with constraints between the observations only, 173
model block adjustment
  2D, 650
  2D m., 651–674
  3D m., 649
  projective m., 649
modified weights, 147
moment vector of a 3D line, **218**, 219, 220, 227
moments, 36
  central m., 37
  general m., 36
  of normal distribution, 39
mono-plotting, 526
monomials, 733
motion
  2D m., 260
  3D m., 260
  fixed entities of planar m., 275
  fixed entities of spatial m., 276
  forward m., 589
  from object to camera, 466
  from structure, 449
  planar, 251
  rigid body m., 255
  rotational m., 337
  sideward m., 588
  spatial m., 255
  uncertain m., 383
moving object, 568
moving camera, 568
multiple solutions, 452
  of relative orientation, E-matrix, 582
  of relative orientation, F-matrix, 571
  of spatial resection, 515

nadir
  direction, 528
  point, 346, 458
  view, 456, 521
narrow-angle lens, 459
negative point, 344
net area of model, 719
Newton–Raphson method, 105
noncentral χ'^2 distribution, 34
noncentrality parameter, 65, 131
nonlinear
  distortions, 452, 477
  Gauss–Markov model, 102
  Gauss–Markov model with constraints, 104
  model of bundle adjustment, 675
nonmetric camera, uncalibrated n., 697
nonrejection region, 63
normal case
  of image pair, 561
  of image pair, iterative relative orientation, 588
  of single image, 465
  triangulation for n. of image pair, 601
normal cases, 453
normal distribution, 29
  in best unbiased estimation, 81

multi-dimensional n., 31
normal equation
components, 85
for groups, 96
for system for two groups of observations, 96
in Gauss–Helmert model with constraints, 165
in Gauss–Markov model, 84
in Gauss–Markov model with constraints, 100
partitioned n., 94
profile of n. matrix, 662
reduced n., **94**, 660
reduced n. of free adjustment, 114
sparsity of n. matrix, 657–661
table with n., 171
normal lens, 459
normal line
through 2D point, 294
through the 2D origin, 294
normalization
bias of n., 45
Euclidean n., 242
Euclidean n. of matrix, 285
Euclidean n. of vector, 199
of homogeneous matrices, 285
of homogeneous vectors, 198, 241
spectral n. of matrix, 286
spherical n., 45, 199, **242**
spherical n. of matrix, 286
normalized
camera, **465**, 472, 713
camera coordinate system, 466
definition of n. residuals, 144
residuals, 152, 170
trifocal tensor, 628
variance of n. residuals, 145
notation of homogeneous entities, 196
null space
for estimating homography, 389, 496
of covariance matrix of 2D line, 375, 392
of covariance matrix of 2D point, 368, 393
using QR decomposition, 179
numerical differentiation, 453
NURBS, mapping of N., 484

object
coordinate system, **462**, 465
moving o., 568
point, 563
points, image pair, 608
object-based representation, 8
object-based scene description, 442
oblique view, 456
observable image point, 463
observation equations, 82
linearized o. for normal case of relative orientation, 589
nonlinear o., 173
nonlinear o. for image triplet, 638
observation process, 25
observational errors, 83
observations
fictitious o., 78
uncertain o., 490
observed AR-process, 749
One Shot 360, 443, 445, 446
operator
covariance o., 38
dispersion o., 38
mean o., 38
optical axis, 461
optical ray, 528
optics, 456
catadioptric o., 446
optimal estimation
of intrinsics and extrinsics, 501
of projection matrix, 496
oracle, robust estimation as o., **142**, 167
ordinary least squares, 80
orientation
absolute o., 549, **552**, 607
absolute o. within two-step procedure, 612
also see direction, 352
exterior o., **465**, 610
exterior o. of camera systems, 488
exterior o. of image pair, 550
interior o., 610
interior o. of image pair, 550
of cameras, 449
of conics and quadrics, 348
of image pair, 549, 608
of image triplet, 632
of join of 3D line and point, 353
of plane, 354
parameters from essential matrix, 581
quality of o. procedures, 453
relative o., 450, 551
relative o. of image triplet, 633
relative o. within two-step procedure, 612
orientation-preserving transformation, 355
oriented
2D line, 346
2D point, 345
3D line, 348
3D point, 346
epipolar line, 564
image line, 482
plane, 347
point, 344
projective geometry, 343
projective plane, 345
projective space, **345**
orthogonal
projection, 487
orthogonality
of 2D lines, 297
of 3D line and plane, 308
of 3D lines, 307
of planes, 307
outlier, *see* gross error, 609
asymmetric distribution of o., 755
detection, 142
detection in bundle adjustment, 707–715
model, 143

P3P problem, 513–518
panorama, 644
Panoscan Mark III, Rollei, 443, 445, 446
parabola, 237
parallactic angle, 420, 421, **548**, 549, 550, 596, 598, 599, 601, 604, 717
parallax
x-p., 569, **589**, 601–604
y-p., 561, **589**, 590, 592, 602
accuracy of p., 569
covariance matrix, 569
map, 602
vertical p., 561
parallel line
through 2D point, 294
through the 2D origin, 294
parallel projection, 545
parallelepiped, 553
parallelism
of 2D lines, 297
of 3D line and plane, 308
of 3D lines, 307
of planes, 307
parameters
additional p., 123, 464
extrinsic p., 460
interior p. of camera system, 488
intrinsic p. of a camera, 460
parametrization of relative orientation, 557–559
singularity, 559
partially calibrated camera, 460
partitioning of normal equation matrix, 94
PCA of covariance matrix, 667
pencil of planes in epipolar geometry, 563
percentile, 40
perspective
2D autocollineation, 277
3D autocollineation, 280
autocollineation, 277
calibrated p. camera, 555–557
camera, 248, **446**, 456, 460, 464, 607, 622
camera for the image pair, 550
camera model, 462, 470
collineation, 248, **277**, 277, 278
distortion, 503
distortions of p. camera, 505
image, 456
inverse p., 523
mapping with distortions, 479
model of p. camera, 464
projection, 467, **470**, 486
projection of 3D line, 480
perspectivity, 277, 278
phenomenological distortion model, 505, 508
photo collection, 644

photogrammetric model, **549**, 612–613, 708–711, 719
absolute orientation of p., 607
coordinate system definition, 559
coplanarity constraint, 551
net area of p., 719
of image triplet, 622–633
of images of calibrated cameras, 552
of images of uncalibrated cameras, 552
parameters of p. for given projection matrix P', 560
scale of p., 559, 607, 634, 714
photogrammetric models
mutual scale of p., 621
physical distortion model, 505, 506
Pi-matrix, 300
Pi-matrix, dual P., 301
pinhole camera, 253, 257, 281, 464, 465
pixel distance, 465
Plücker
constraint, 218
enforcing P. constraint, 381
matrix, 219
Plücker constraint, 227
Plücker coordinates, 221–229, 768
definition of P., 223
dual P., 233
Euclidean part of P. of 3D line, 218
homogeneous part of P. of 3D line, 218
of 2D line, 223
of 2D points, 223
of 3D line, **218**, 226
of 3D line from points, 217
of 3D points, 225
of plane, 225
Plücker matrix, 227
dual P., 233
planar homography
fixed entities, 274
planar motion, 251
planar object
critical configuration of DLT, 495
plane, 211
antipodal p., 347
at infinity, 212
centroid representation of p., 377
degrees of freedom of p., 212
distinct points of p., 319
homogeneous coordinates of p., 211
horizon of p., 208
intersection, 301
joining 3D point and line, 302
line at infinity of p., **208**, 212, 220
optimal direct solution of p., 400, 436
orientation of p., 348, 354
oriented p., 347
parameters of p. through three points, 225
Plücker coordinates of p., 225
point-direction form of p., 213
quadric, 240
slope of p., 212
three-point representation of p., 213
transformation of p., 258
uncertain p., 377–379, 403
planes, concurrent p., 306
PnP problem, 513–521
point
antipodal p., 344–346
control p. of image pair, 608
in tetrahedron, 351
negative p., 344
of symmetry, 462
oriented p., 344
positive p., 344
tie p. of image pair, 608
uncertainty of transformed p., 387
vanishing p., 210, 529–534
point at infinity, 472, 493, 550
1D p., 214
2D p., 206
3D p., 210
of 2D line, 209, 294
of 3D line, 220
point camera, 444
point of symmetry
of conic, 237
of quadric, 240
Pointgrey Ladybug 3, 443–445
polar of a point, 233
polarity, 233, 283, 285
at conics, 238
at the unit circle, 233
on the sphere, 200
pole of a line, 233
polycamera, 445
pose, 456
of camera, 6, 456, **460**
theoretical precision of p., 522, 523
positive definite function, 50
positive point, 344
power function, 65
power of test, 62
PowerShot A630, Canon, 443, 445
pre-image of line at infinity, 355
precision, **116**, 453
acceptability of p., 117
and accuracy, 116
empirical p., 117
external p., 116
inner p., 110
internal p., 116
matrix, **43**, 83, 367
of interpolation, 734
of the mean, 116
singular p. matrix, 367
theoretical p., 117
prediction, 730
in image pair, image point, 562–565
in image triplet, points and lines, 623–625
of points, lines and planes, 451
prediction errors, 97
prediction operator
$\ell(l'', l''')$, 625
$\wp_2(x', l''')$), 631
$\wp_3(x', l'')$), 631
principal
distance, 457, **462**, 464, 465, 471
distance from two vanishing points, 531
line, 458
plane of optics, 256, **461**
planes of camera, 474
point, 458, **462**, 464, 465, 470, 471
point from projection matrix, 475
point from three vanishing points, 532
prior
for profiles and surfaces, 745–748
variance component estimation of p., 750
prior, see also a priori, 76
probability
a posteriori p. density, 77
a priori p. density, 76
axiomatic definition of p., 22
axioms of p., 23
conditional p., definition, 23
density function, 26
distribution, 24
notion of p., 21
total p., 23
von Mises' definition, 22
process
doubly integrated white noise p., 53
integrated white noise p., 53
stochastic p., 49
profile of normal equation matrix, 662
profile reconstruction
fictitious observations for p., 746
LS with regularization, 747
MAP estimate for p., 744
outlier detection in p., 755
projection
central p., 481, 485, 487
equidistant p., 487
equisolid p., 487
line, **483**, 564
matrix, *see* projection matrix
model, 449
not straight line-preserving p., 564
of 3D lines, 480
of lines, 564
orthogonal p., 487
parallel p., 545
perspective p., 467, **470**, 486
perspective p. of 3D line, 480
plane, 482, 483
ray, 445
spherical p., 467
spherical p. of 3D line, 481
stereographic p., 346, 487
thin lens p., 256
uncertainty of p. ray, 524
projection centre, 248, 254, **457**, 460–466, 474–475, 563
collinear, 622

from projection matrix, 498
quality of p. from spatial resection, 516, 517
projection matrix, **472**, 607, 629
algebraic solution for p., 494
covariance matrix of p., 495
decomposition of p., 498
direct estimation of p., 494
DLT with p., 494
for 3D lines, 480, 626
for 3D points, 626
from essential matrix, 595
from fundamental matrix, 594
general p., 479
interior and exterior orientation from, 500
optimal estimation of p., 496
proper p., 468, 474, 482, 483
properties of p., 473
properties of p. for 3D lines, 481
uncertainty of p., 475
projective
bundle adjustment, 649
collination, 248
correlation, 282
line $\mathbb{P}$, 231
model, 480
model block adjustment, 649
oriented dual p. plane, 346
oriented p. plane, 345
oriented p. space, 345
plane $\mathbb{P}^2$, 200, 203, **206**, 231
3D points at infinity, 211
partioning of p., 215
representation as unit sphere, 215
point $\mathbb{P}^0$, 215, 216, 231
space $\mathbb{P}^1$, 214
space $\mathbb{P}^3$, **210**, 231
space $\mathbb{P}^n$, 215
transformation, 611
projective bundle adjustment, 676
projectivity
2D p., 253
3D p., 256
pure p., 254
singular p., 473
propagation of uncertainty, 386
proper
projection matrix, 468, 474, 482, 483
rotation matrix, 499
pseudo-inverse, 101, 779
rectangular matrix, 779
symmetric matrix, 779
pseudo-likelihood function, 144

QR decomposition, 776
for minimal solution, 179
for null space, 179
quadratic variation, **741**, 760
quadric, 239
fitting, 183
mapping of q., 484
orientation of q., 348
point of symmetry of q., 240
tangent plane at q., 240
transformation of q., 260
quality
checkability of the observations, 609
criteria, 609
of 3D point from two images, 603
of 3D points, 526
of parameters, 452
of relative orientation, 590
precision, 609
quantile, 40
quasi-affine projective mapping, 357
quasi-systematic errors, 667
quaternion, 332–335
as hyper-complex numbers, 333
covariance matrix of q., 383
uncertain q., 383

R (software package), 115
radial basis function, 735
radial distortion, 506–508
random
matrix, 27
number generation, 55
vector, 27
random perturbations, 452
random sample consensus, *see* RANSAC
random variables, 24–28
continuous r., 26
discrete r., 26
independent r., 31
transformation of r., 41
uncorrelated r., 31
RANSAC, 153–157, 609
ray direction, 467, **469**, 514
sign of r., 492
uncertainty of r., 492
Rayleigh distribution, 29
reasoning levels, 7
reconstruction
of point on plane, 524
of points and lines, 596–606
quality of r. procedures, 453
rectangle, invariants of r., 271
reduced
design matrix, 95
normal equations, 660
reduced coordinates, 393
covariance matrix of r., 371
of 2D point, 370
of 3D line, 380–381
redundancy, **82**, 609
matrix, **87**, 669
numbers, **88**, 145
numbers, relative orientation, 592
of absolute orientation, 613
of bundle adjustment image pair, 611
of Gauss–Helmert model with constraints, 165
of Gauss–Markov model, 82
of Gauss–Markov model with constraints, 100
of two DLTs, 611
of two spatial resections, 612
relative r., 145
table with r., 171
reference covariance matrix, 517
refraction, 477
regression model, 81
regularization, 82, 747
regularizing observations, 746
rejection region, 63
relative orientation, 450, 551, 634
epipolar geometry of r., 562
iterative r., 585–594
iterative r. for ideal forward motion, 593
iterative r. for normal case, 588
of image pair, 622
of image triplet, 636
of images of calibrated cameras, 552
of images of generic cameras, 581
of images of uncalibrated cameras, 552
planar object, 567
quality of r., 590
theoretical precision of r., 590
theoretical reliability of r., 590
with known plumb line, 581
within two-step procedure, 612
relative redundancy, 145
relief displacement, 459
representation of uncertain points and lines, minimal r., 369–371
residual of coplanarity constraint, 555, 562
residuals, 82
approximate r., 164
covariance matrix of r., 87
normalized r., 144, 152, 170
standardized r., 125
variance of normalized r., 145
resolution, 442
reverse Cuthill–McKee algorithm, 662
rho-function, *see* ρ-function
rigid body motion, 255
RMSE, 119
robust estimate
of standard deviation of normalized residuals, 146
of variance factor, 146
robust estimation, 141–185
as oracle, 142
maximum likelihood-type estimation, 147
of variance factor, 145–146
strategies, 158
with L_1-norm minimization, 150
with clustering, 157
with complete search, 151
with RANSAC, 153
robustness, 142
evaluation of r. with influence function, 147
Rollei Panoscan Mark III, 443, 445, 446
root mean square error, 119
rotating slit camera, 485
rotation, 325, 460
2D r., 251

3D r., 255
averaging, 713
axis and angle from r. matrix, 331
axis angle representation of r., 331
Cayley representation of r., 336
closed form solution for r. from directions, 406
concatenation of elementary r., 329
concatenation of r. with quaternions, 337
conjugate r., 281, 321
differential equation for r., 337
differential r. vector, 337
direction between planes, 353
direction cosine matrix for r., 328
eigenvalues of r. matrix, 327
elementary r., 328
Euler's theorem for r., 326
interpolation, 341
matrix, *see* rotation matrix
minimal r. between two vectors, 340
quaternion representation of r., 332, 335
relations between representations for r., 338
representations in 3D: overview, 326
Rodriguez representation of r., 335
singularity of r., 330
skew-symmetric matrix representation of r., 336
uncertain r., 382–383
vector, 336–338
with Euler angles, 328
rotation matrix, 326, 466
as local coordinate system, 378
direction cosine r., 328
exponential form of r., 326, 337
from corresponding vectors, 339
from projection matrix, 499
from three image lines, 531
representation, 327
rotational motion, 337
rounding error, 26, 29, 39

S-matrix, 112
S-transformation, 109, 113
in block adjustment, 668
regular S-, **112**, 121
singular S-, 112
sampling
in RANSAC, 154
of distributions, 56
scale
factor, 604
mutual s. of photogrammetric models, 621, 639
number, **457**, 591, 604, 720
of photogrammetric model, 551, **559**, 607
scale difference, 464
of image coordinate system, 471
scale transfer, 634, 639
scaling in 2D, 251
scene
coordinate system, 462
feature, 646
field-based s. description, 442
geometric model of s., 442
model, 7, 441
object-based s. description, 442
reconstruction, 450
Schur complement, 660
search, complete s., 151
segment, line s., 352
selecting independent constraints, 317
self-calibrating bundle adjustment, 450, 674–696
self-calibration, 492, 697–699
self-diagnosis, 452
sensitivity, 115
w.r.t. groups of outliers, 130
w.r.t. single outliers, 126–128
w.r.t. systematic errors, 134–135
analysis, 592, 609, 695, 699
ellipse, 130
factor, 126–128, 130, 132, 692–694, 701, 705–706
of bundle adjustment, 691, 693, 701
of relative orientation, 589
sensor coordinate system, 463
sensor model, 7
separable function, 28
sequential estimation, 96
shear, 464, 470, 471
shear in 2D, 252
sidelap, **718**, 721
sideward motion, 588
sign
constraints for points in image triplet, 624
effect of affinity on s. of entity, 357
of distance, 354
of intersection of 3D line and plane, 353
of intersection point of two 2D lines, 353
of ray direction, 492
significance level, 62
significance number, 62
similarity
2D s., 252
3D s., 255, 613, 622
closed form solution of s., 408
minimal solution of s., 320
transformation, 611
uncertain s., 383
simulating data, 55
single image, normal case of, 465
single viewpoint, 445
singular
correlation, 564
dual conic, 241
line conic, 241
precision matrix, 367
projectivity, 473
value decomposition, 777
values of essential matrix, 557
values of fundamental matrix, 554
values of homology, 568
vector, right s., 571
skew matrix, 336, **770**
product with matrix, 772
properties, 770
SLERP, *see* spherical linear interpolation
slope of curve, 739
slope of plane, 212
smoothness
of a function, 740
of a surface, 740–742
SO(n), 326
solution
direct s., 452
iterative s., 452
minimal direct s., 178
space
complete s., 231
empty s., 231
sparse
covariance matrix, 86, 663
design matrix, 656, 657
matrix, 86
normal equation matrix, 657–661
reduced normal equation matrix, 660
structure of matrices, 655
spatial resection, 513–521, 533, 623
critical configuration of s., 515
direct solution of s., 513
direct solution with > 3 points, 518
iterative solution, 520
quality of projection centre from s., 516
theoretical precision of s., 523
two s. for image pair, 612
with observed scene lines, 521
spectral normalization
of matrix, 286
variance propagation, 783
spherical
linear interpolation, 341
normalization, 45, 198, 199, **242**
normalization of matrix, 286
normalization of uncertain 2D point, 368
projection, 467
projection of 3D line, 481
spherical camera, **446**, 456, 462, 468, 555, 582
bundle adjustment, 686
calibrated s. for the image pair, 556
triangulation for s., 597
spherically normalized homogeneous coordinates, 490
spline, 736
one-dimensional s., 736
two-dimensional s., 737
SPSS (software package), 115
stable configuration, 452
standard deviation, 37
empirical s., 118

of exterior orientation with spatial resection, 523
of height, 604
of image coordinates, 527
of parameters
relative orientation, 591
robust estimator of s. of normalized residuals, 146
standard ellipse, **31**, 366, 369
standard hyperbola, 374
standardized residuals, 125
stationary, 49
statistically best fitting
2D line, 397
mean axis, 405
mean direction, 403
plane, 400
rotation from directions, 406
similarity, 408
Steiner's theorem, **37**, 116
stellar calibration, **496**, 533
step function, 25
stereo vision, human s., 561
stereographic projection, **243**, 346, 487
stitching, 644
stochastic independence, 28
stochastic process, 48–55
homogeneous s., 51
isotropic s., 51
stationary s., 49
stochastical model, 76
for surface reconstruction, 743
of 2D block adjustment, 652
of block adjustment, 647
of estimation, 83
straight line segments, 480
straight line-preserving, 249, 470
structure from motion, 450, 568
structure tensor, 402, 569
Student's t-distribution, 35
suboptimal test for gross errors, 126
substitute model, 103
substitute parameters, 177
subsymbolic level of real world, 7
surface, 442
$2^1/_2$D s., 729, 733–742
flatness of s., 739–741
graph s., **729**, 739
reconstruction, 727, 730
reconstruction as Bayesian estimation, 742
reconstruction, outlier detection in s., 755
smoothness of s., 740–742
surfel, 442
SVD
for algebraic solution, 179
for consistency of essential matrix, 575
for consistency of rotation matrix, 531
for estimation of 3D line, 606
for estimation of 3D point, 603
for estimation of base vector, 579
for estimation of fundamental matrix, 571
for estimation of projection matrix, 495
for partitioning of essential matrix, 581
for partitioning of fundamental matrix, 595
of essential matrix, 557
of fundamental matrix, 553
swing angle, 459
symbolic image description, 448
symbolic level of world model, 7
systematic error, 116
in bundle adjustment, 683
model of s., 123
quasi-s., 667
systems of cameras, 488

taking position, **457**, 469, 550, 563
tangent
line at conic, 238
plane at quadric, 240
tangent space, 370
tangential distortion, 485, 506
telelens, 459
tensor notation, 782
test
for 3D line through triangle, 351
for coplanarity constraint, 555
for estimated parameters, 133
for gross error, 131
for point in tetrahedron, 351
of point in triangle, 349
of prediction errors, 98
one-sided t., 67
suboptimal t. for gross errors, 126
two-sided t., 65
within sequential estimation, 98
test field calibration, 697, 698
testability, 66
of mean, 65
of mean vector, 67
of observations, relative orientation, 592
testing, 393
approximate t., 393
geometric relations in 2D and 3D, 393
uncertain relations, 393
tetrahedron
chirality of t., 350
point in t., 351
sign of volume of t., 225
volume of t., 225
theoretical
precision, 117
sensitivity, 127, 135
theoretical covariance matrix, 517
theoretical precision
of 3D point, 526
from two images, 603
of bundle adjustment, 683
of DLT, 522
of image blocks, 673
of image strips, 671
of point on horizontal plane, 527
of pose estimation, 521
of relative orientation, 590
of spatial resection, 523
of strips and blocks, 670–674
of surface interpolation, 761
theoretical reliability
of absolute orientation, 411
of relative orientation, 590
thin plate model, 741
thin rod model, 741
tie points of image pair, 608
tilt angle, 459
tilt angle of a plane, 212
Toeplitz matrix, 53
torsion, 741
total least squares, 161
total probability, 23
traffic light decision, 63
transformation, 247
1D t., 257
2D affinity, 252
2D homography, 253
2D mirroring at y-axis, 251
2D projectivity, 253
2D rotation, 251
2D scaling, 251
2D shear, 252
2D translation, 251
3D affinity, 255
3D homography, 256, 552, 613
3D homography, image pair, 611
3D projectivity, 256
3D rotation, 255
3D similarity, 255, 551, 613, 622
3D similarity, image pair, 611
3D translation, 255
concatenation of t., 261
conjugate t., 278
coordinate t., 262
direct solution of similarity t., 408
dual t., 259
extrapolation during t., 389
group, 284
hierarchy, 285
interpolation during t., 389
inversion of t., 261
of 2D line, 258
of 2D point, 250
of 3D line, 259
of 3D point, 255
of conic, 260
of coordinates w.r.t. fixed reference, 263
of coordinates w.r.t. transformed reference, 264
of hyperplane, 258
of object w.r.t. fixed reference, 262
of object w.r.t. transformed reference, 263
of oriented entities, 355
of plane, 258
of quadric, 260
of random variable, 41
orientation-preserving t., 355
planar motion, 251
similarity t., 252
spatial motion, 255

translation
2D t., 251
3D t., 255
conjugate t., 279
triangle
area of t., 222
chirality of t., 349
spatial t. and 3D line, 351
triangular irregular network, 732
triangulation, 549, 552, 595, **596**
algebraic t. from multiple images, 602
Delaunay t., 732
for normal case of image pair, 601
for perspective image pair, 600
for spherical camera, 597
trifocal matrices, 625–626
trifocal plane, 623
trifocal tensor, 622, **625**, 625, 629
degrees of freedom of t., 622
direct estimation for t., 636
from projection matrices, efficient computation, 626
iterative solution for t., 637
minimal solution of t., 636
normalized t., 628
trigonometric basis functions, 734
true value, 79
truncated L_2-norm minimization, 148
Tschebyscheff polynomials, 510
twisted cubic, 495

ultra-wide lens, 459
Ultracam, Vexcel, 443–445, 683
uncalibrated camera, **461**, 490, 622
uncertain
2D line, 373–377
2D point, 366–372
3D line, 379–381
3D point, 372–373
Euclidean coordinates, 371
geometric entities, 359
geometric relations, 359
Hessian parameters of 2D line, 376
homogeneous coordinates, 367, 375
homography, 384–386
matrix, 32
minimal representation of u. 2D point, 369
motion, 383
observations, 490
plane, 377–379, 403
quaternion, 383
rotation, 382–383
rotation matrices, 382
scene points and lines, 493
similarity, 383
spherical normalization of u. 2D point, 368
uncertainty
homogeneous u., 121, 371, 396
isotropic u., 121, 396
isotropic u. of directions, 367, **371**, 403, 413
isotropic u. of points, **368**, 369, 399, 406, 408, 412
of directions in the camera, 492
of estimated 3D line, 413
of extrinsics and intrinsics from projection matrix, 500
of feature identification, 490
of image points, 491
of key point, 491
of line segments, 492
of projection matrix, 475
of projection ray, 524
of ray direction, 492
of transformed points, 387
propagation, 386
uncorrelated random variables, 31
uniform distribution, 28
unit camera, 465
unit circle
S^1 in $\mathbb{R}^2$, 214, 215
unit sphere
S^2 in $\mathbb{R}^3$, 199, 200, 242, 243
S^3 in $\mathbb{R}^4$, 242
S^5 in $\mathbb{R}^6$, 243
unscented transformation for variance propagation, 47

vanishing line, 529
vanishing point, 208, 210, 459, 529–534
estimation, 417
variance, 37
bias of v., 45
of normalized residuals, 145
of ratio, 46
of residual of coplanarity constraint, 555
of scale of similarity from points, 410
variance component estimation, 91–93, 493
bundle adjustment, 679
profile reconstruction, 750
variance factor, 716
correctness of v., 140
estimated v., **89**, 680–685, 700–701
initial, 89
interpretation of v., 498
robust estimation of v., 145–146
test of v., 90
variance propagation, **42**, 42–48
implicit v., **43**, 154, 180, 516
nonlinear v., 43
of bilinear forms, 387
of linear functions, 42
of nonlinear functions, 43
of spectral normalization, 783
unscented transformation, 47
with weight matrices, 43
vec operator, 775
vech operator, 775
vector representation
of conics and quadrics, 316
of transformations, 315
vertical parallax, 561
vertical view, 456
Vexcel Ultracam, 443–445, 683
view
horizontal v., 456
nadir v., 456
oblique v., 456
perspective v., 459
vertical v., 456
zenith v., 456
view planning, 715–722
for flat areas, 718
of buildings and rooms, 721
rules of thumb for v., 716
viewing angle, 371, **458**
viewing direction, 458, 462
from projection matrix, 475
normal case of image pair, 561
viewing position, **457**, 469, 550
viewing sphere, 423, 447
viewline, 445
viewpoint of camera, 445
visual odometry, 644
volume of tetrahedron, 225

weak configuration, 698
weak constraints, 102
weak membrane model, 740
weak string model, 739
weight, 83
coefficient matrix, 89
matrix, **43**, 83, 89
table of w. functions, 149
weight function
asymmetric w., 756
weighted
least squares, 79
sum of the squared residuals, 84
weights
in least squares estimation, 81
modified w., 147
whitening, 41
wide-angle lens, 459
Wiener filter, 93
Wishart distribution, 34
Woodbury identity, 769
world model, 7

Yule–Walker equations, 184

zenith
angle, 210
point, 346
view, 456
zoom lens, 459