Multiple View Geometry: Exercise Sheet 2

Exercise: 19 May 2010

Part I: Theory

The following exercises should be **solved at home**. You do not have to hand in your solutions, however, writing it down will help you present your answer during the tutorials.

1. Indicate the $SE(3)$ matrices for the following transformations:
   (a) Translation by the vector $T = (t_x \; t_y \; t_z)^\top$.
   (b) Rotation by the rotation matrix R.
   (c) Rotation by R followed by the translation T.
   (d) Translation by T followed by the rotation R.

2. Let $M_1, M_2 \in \mathbb{R}^{3\times 3}$. Please prove the following:
   $\mathbf{x}^T M_1 \mathbf{x} = \mathbf{x}^T M_2 \mathbf{x}$ for all $\mathbf{x} \in \mathbb{R}^3$ iff $M_1 - M_2$ is skew-symmetric (i.e. $M_1 - M_2 \in so(3)$).

3. Let $A \in \mathbb{R}^{m\times n}$. Prove that kern$(A^\top A) =$ kern(A).
   Hint: Consider for $x \in \mathbb{R}^m$: $A^\top x = \begin{pmatrix} a_1 x \\ \vdots \\ a_n x \end{pmatrix}$, where $a_1, \dots, a_n$ are the columns of A. How does this relate to kern$(A^\top)$?

Part II: Practical Exercises

This exercise is to be solved **during the tutorial**.

1. Download the package mvg_ex02.tgz and use `openOFF.m` to load the 3D model `model.off`.

2. Write a function that rotates the model around its center (i.e. the mean of its vertices) for given rotation angles α, β and γ around the x-, y- and z-axis. Use homogeneous coordinates and describe the overall transformation by a single matrix. The rotation matrices around the respective axes are as follows:

   rotation matrix (x-axis) rotation matrix (y-axis) rotation matrix (z-axis)
   $$\begin{pmatrix} 1 & 0 & 0 \\ 0 & \cos\alpha & -\sin\alpha \\ 0 & \sin\alpha & \cos\alpha \end{pmatrix} \quad \begin{pmatrix} \cos\beta & 0 & \sin\beta \\ 0 & 1 & 0 \\ -\sin\beta & 0 & \cos\beta \end{pmatrix} \quad \begin{pmatrix} \cos\gamma & -\sin\gamma & 0 \\ \sin\gamma & \cos\gamma & 0 \\ 0 & 0 & 1 \end{pmatrix}$$

3. Rotate the model first 5 degrees around the x-axis and then 25 degrees around the z-axis. Now start again by doing the same rotation around the z-axis first followed by the x-axis rotation. What do you observe?

4. Perform a translation in addition to the rotation. Find a suitable matrix from $SE(3)$ for this purpose and add it to your function from 2. Translate the model by the vector $(0.5 \;\; 0.2 \;\; 0.1)^\top$.

Matlab-Tutorials:
http://www.math.utah.edu/lab/ms/matlab/matlab.html
http://www.math.ufl.edu/help/matlab-tutorial/
http://www.glue.umd.edu/~nsw/ench250/matlab.htm