

given a pinhole model

$$p \rightarrow p_{\text{rect}}$$

$$\begin{aligned} p &= R_p \cdot t \\ p_{\text{rect}} &= \begin{bmatrix} b_1 f_1 \\ b_2 f_2 \\ 1 \end{bmatrix} \end{aligned}$$

Schur Trick

$$\begin{aligned} v_i &= v_i + v_i (m_1 m_2 + k_1 k_2) \\ v_i &= v_i + v_i (m_1 m_2 + k_1 k_2) \\ v_i &= f_i v_i \\ v_i &= f_i v_i + c_i \end{aligned}$$

$$\begin{aligned} e &= \delta - h(x, y) \\ e &= \delta - h(T, p) \\ \therefore \text{error: } & \text{overall error:} \\ & \frac{1}{2} \sum_{i=1}^m \sum_{j=1}^n \|e_{ij}\|^2 \\ & = \frac{1}{2} \sum_{i=1}^m \sum_{j=1}^n \|v_{ij} - h(T, p_j)\|^2 \end{aligned}$$

→ we are adjusting the pose T & the camera P at the same time

→ Bundle Adjustment

∴ in the dual problem:

$$x = [T_1, \dots, T_m, p_1, \dots, p_n]^T$$

∴ when  $x \leftarrow x + \Delta x$

$$\begin{aligned} & \frac{1}{2} \|f(x + \Delta x)\|^2 \\ & \approx \frac{1}{2} \sum_{i=1}^m \sum_{j=1}^n \|v_{ij} + p_{ij} \Delta s_i + E_{ij} \Delta p_j\|^2 \end{aligned}$$

↓  
partial derivative  
w.r.t.  $T_i$  w.r.t.  $p_j$

we then stack all variables altogether:

$$\begin{aligned} x_c &= [f_1, f_2, \dots, f_m]^T \in \mathbb{R}^{3m} \\ x_p &= [p_1, p_2, \dots, p_n]^T \in \mathbb{R}^{3n} \end{aligned}$$

$$\rightarrow \frac{1}{2} \|f(x + \Delta x)\|^2 = \frac{1}{2} \|e + E x_c + E x_p\|^2$$

$$\rightarrow H \Delta x = g$$

- $H = J^T J$  or  $J^T J + \lambda I$

- $J = [F \ E]$

- $J^T J = \begin{bmatrix} F^T F & F^T E \\ E^T F & E^T E \end{bmatrix}$