Vision Algorithms for Mobile Robotics

Lecture 02
Image Formation

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Lab Exercise 1 - Today

Implement an augmented reality wireframe cube and practice the perspective projection
Today’s Outline

• Image Formation
• Other camera parameters
• Digital camera
• Perspective camera model
• Lens distortion
Historical context

• **Pinhole model**: Mozi (470-390 BCE), Aristotle (384-322 BCE)
• **Principles of optics (including lenses)**: Alhacen (965-1039)
• **Camera obscura**: Leonardo da Vinci (1452-1519), Johann Zahn (1631-1707)
• **First photo (heliography)**: Joseph Nicephore Niepce (1827)
• **Daguerréotypes** (1839)
• **Photographic film** (Eastman, 1888, founder of Kodak)
• **Cinema** (Lumière Brothers, 1895)
• **Color Photography** (Lumière Brothers, 1908)
• **Television** (Baird, Farnsworth, Zworykin, 1920s)
• **First consumer camera with CCD**: Sony Mavica (1981)
• **First fully digital camera**: Kodak DCS100 (1990)

First surviving photo ever: “View from the Window at Le Gras”, by Niepce, 1827
How to form an image

• Would this work?
Camera obscura

• Add a barrier to block off most of the rays
  • This reduces blurring
  • The opening is known as the aperture
Home-made camera obscura

- Image is **inverted**
- **Depth of the room** is the **focal length**
- How can we **reduce the blur**?

How to build a camera obscura at home ([link](#))
Effects of the Aperture Size

• A large aperture makes the image blurry because a cone of light is let through from each world point
Effects of the Aperture Size

- **Shrinking the** aperture makes the **image sharper**
- The ideal aperture is a **pinhole** that only lets through one ray of light from each world point
Why not making the aperture as small as possible?

- With small apertures, less light gets through → must increase exposure time

- If aperture gets too small, diffraction effects start to appear
Image formation using a converging lens

- A thin converging lens focuses light onto the film satisfying two properties:
Image formation using a converging lens

• A thin converging lens focuses light onto the film satisfying two properties:
  1. Rays passing through the **Optical Center** are not deviated
Image formation using a converging lens

- A thin converging lens focuses light onto the film satisfying two properties:
  1. Rays passing through the **Optical Center** are not deviated
  2. All rays parallel to the **Optical Axis** converge at the **Focal Point**

![Diagram of light passing through a lens](attachment:image.png)
Thin lens equation

- Find a relationship between $f$, $Z$, and $e$
Thin lens equation

- Find a relationship between $f$, $Z$, and $e$

![Diagram of thin lens equation](image)

Similar Triangles:

\[
\frac{B}{A} = \frac{e}{Z}
\]
Thin lens equation

• Find a relationship between $f$, $Z$, and $e$

Any object point satisfying this equation is in focus
Can I use this to measure distances?
“In focus”

- For a given point on the object, there is a specific distance between the lens and the film, at which the object appears **in focus** in the image.
- Other points project to a **blur circle** in the image.
The blur circle has radius: \( R = L\delta/(2e) \)

- Observe how both small aperture \( L \) and \( \delta \) yield a small blur circle \( R \)
- To capture a sharp image, we must adjust the camera settings such that \( R \) remains smaller than the 1 pixel
The Pin-hole approximation

- What happens if $z \gg f$ and $z \gg L$?
The Pin-hole approximation

- What happens if \( z \gg f \) and \( z \gg L \)?
The Pin-hole approximation

- What happens if $z \gg f$ and $z \gg L$?

- We observe that

$$\frac{1}{f} = \frac{1}{z} + \frac{1}{e} \Rightarrow \frac{1}{f} \approx \frac{1}{e} \Rightarrow f \approx e \Rightarrow \text{focal plane approaches the focal point}$$

\[ \approx 0 \]
The Pin-hole approximation

• This is known as **Pinhole Approximation**
• The relation between the image and object becomes:

\[
\frac{x}{X} = \frac{f}{Z} \implies x = -f \frac{X}{Z}
\]

• This is called **Perspective Projection**
Perspective effects

Far away objects appear smaller, with size inversely proportional to distance.
Perspective can be used as a prior

Perspective gives us very strong depth cues and, thanks to experience (e.g., Manhattan world assumption), we can perceive a 3D scene by viewing its 2D representation (i.e. the image)
Playing with Perspective: the Ames room

• However, our perception of a 3D scene can be fooled. An example is the Ames room (btw, check out the Ames room in the Technorama science museum in Winterthur)

Ames room documentary by neuroscientist Dr. V.S. Ramachandran:
https://youtu.be/Ttd0YjXF0no
Perspective Projection: what is preserved or lost?

- **Straight lines** are still **straight**
- **Lengths and angles** are **not preserved**
Vanishing points and lines

• Parallel lines intersect at a “vanishing point” in the image
• Parallel planes intersect at a “vanishing line” in the image
• Notice that vanishing points can fall both inside or outside the image
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Focus and Depth of Field

- **Depth of Field** is the distance between the nearest and farthest objects in a scene that appear **acceptably sharp** in an image.
Focus and Depth of Field

- A smaller aperture increases the depth of field but reduces the amount of light into the camera: recall the definition of blur circle (it reduces with aperture)

What is the depth of field of an ideal pinhole camera?
Field of View (FOV)

• The FOV is the angular portion of 3D scene seen by the camera
Field of View (FOV)

- As focal length $f$ gets smaller, image becomes more wide angle
- As focal length $f$ gets larger, image becomes more narrow angle
- Relation between field of view, $\theta$, image size, $W$, and focal length, $f$:

\[
\tan \frac{\theta}{2} = \frac{W}{2f} \rightarrow f = \frac{W}{2} \left[ \tan \frac{\theta}{2} \right]^{-1}
\]
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Digital camera

• In a digital camera the **film** is an array of photodiodes (CCD or CMOS) that convert photons (light energy) into electrons
Digital images

Pixel Intensity with 8 bits ranges between [0, 255]

im[176][201] has value 164
im[194][203] has value 37

NB. Matlab coordinates: [rows, cols]; C/C++ [cols, rows]
Color sensing in digital cameras

• The **Bayer pattern** (invented by Bayer in 1976, who worked at Kodak) places interleaved RGB filters over the pixel array.

• The reason why the number of green filters is twice as that of red and blue ones is because the **luminance** signal is mostly **determined by green** values and the **human visual system** is much more **sensitive** to **spatial differences in luminance** than in chrominance.

For each pixel, the missing color components can be estimated from neighboring values by interpolation (**demosaicing**).
Color sensing in digital cameras

RGB color space

... but there are also many other color spaces... (e.g., YUV)
Rolling vs Global Shutter Camera

Rolling Shutter

- Rows of pixels are exposed and read at different times, one after the other
- May distort (skew) moving objects
- Cheap

Global Shutter

- All pixels are exposed simultaneously
- No distortion of moving objects
- More costly
Rolling vs Global Shutter Camera

- Rolling Shutter cameras may distort (skew) moving objects
- Global Shutter cameras do not have this problem
Cool application of rolling shutter cameras

• High speed wave-form capturing from a guitar

Recorded from an iPhone 4 (rolling shutter): [https://youtu.be/TKF6nFzpHBU](https://youtu.be/TKF6nFzpHBU)
An example camera datasheet

Nano-drone of my lab equipped with this camera
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Perspective Camera

Nomenclature:
• $C = \text{optical center}$
  = center of the lens
  = center of projection
• $X_c, Y_c, Z_c = \text{axes of the camera reference frame}$
• $Z_c = \text{optical axis}$
• $O = \text{principal point}$
  = intersection of optical axis and image plane
Perspective Camera

• Note that a camera does not measure distances but angles.
• So, we call it a “bearing sensor” or “angle sensor”
Perspective Camera

• For convenience, the image plane is usually represented in front of the lens, $C$, such that the image preserves the same orientation (i.e. not flipped)
From World to Pixel coordinates

Goal: Find pixel coordinates \((u, v)\) of the projection of world point \(P_W\) onto the image plane:

- Convert world point \(P_W\) to camera point \(P_C\) through rigid body transformation \([R, T]\)
- Convert \(P_C\) to image-plane coordinates \((x, y)\)
- Convert \((x, y)\) to (discretized) pixel coordinates \((u, v)\)
Perspective Projection – 1/4

From Camera frame to image plane coordinates \((x, y)\)

• The Camera point \(P_c = [X_c, Y_c, Z_c]^T\) projects to \(p = (x, y)\) onto the image plane

• From similar triangles:
  \[
  \frac{x}{f} = \frac{X_c}{Z_c} \Rightarrow x = \frac{fX_c}{Z_c}
  \]

• Similarly, for \(y\):
  \[
  \frac{y}{f} = \frac{Y_c}{Z_c} \Rightarrow y = \frac{fY_c}{Z_c}
  \]
Perspective Projection – 2/4

From image plane coordinates \((x, y)\) to pixel coordinates \((u, v)\)

- Let \(O = (u_0, v_0)\) be the pixel coordinates of the camera optical center
- Let \(k_u, k_v\) be the pixel conversion factors (inverse of the pixel-size along \(x\) and \(y\))

\[
\begin{align*}
u &= u_0 + k_u x \quad \rightarrow \quad u = u_0 + \frac{k_u f x_C}{Z_C} \\
v &= v_0 + k_v y \quad \rightarrow \quad v = v_0 + \frac{k_v f y_C}{Z_C}
\end{align*}
\]
Perspective Projection – 2/4

From image plane coordinates \((x, y)\) to pixel coordinates \((u, v)\)

- Let \(O = (u_0, v_0)\) be the pixel coordinates of the camera optical center
- Let \(k_u, k_v\) be the pixel conversion factors (inverse of the pixel-size along \(x\) and \(y\))

\[
\begin{align*}
  u &= u_0 + k_u x \\
  v &= v_0 + k_v y
\end{align*}
\]

\(\alpha_u x_C \frac{x_C}{Z_C} \quad \text{Focal lengths (expressed in pixels)}\)

\(\alpha_v y_C \frac{y_C}{Z_C}\)
Perspective Projection – 3/4

• Use **Homogeneous Coordinates** for linear mapping from 3D to 2D:

\[
p = \begin{pmatrix} u \\ v \end{pmatrix} \quad \tilde{p} = \begin{pmatrix} \tilde{u} \\ \tilde{v} \\ \tilde{w} \end{pmatrix} = \lambda \begin{pmatrix} u \\ v \\ 1 \end{pmatrix}
\]

• Using matrix form and homogeneous coordinates, the perspective projection becomes:

\[
\lambda \begin{bmatrix} u \\ v \\ 1 \end{bmatrix} = \begin{bmatrix} \alpha_u & 0 & u_0 \\ 0 & \alpha_v & v_0 \\ 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} X_c \\ Y_c \\ Z_c \end{bmatrix}
\]

This matrix is called **"Calibration matrix"** or **"Intrinsic Parameter Matrix"** and is often denoted as \( K \)

In the past it was common to assume a skew factor \( K_{12} \neq 0 \) to account for possible skew in the pixel manufacturing process. However, the camera manufacturing process today is so good that we can safely assume \( K_{12} = 0 \) and \( \alpha_u = \alpha_v \) (i.e., square pixels).
Perspective Projection – 3/4

- Use **Homogeneous Coordinates** for linear mapping from 3D to 2D:

\[
p = \begin{pmatrix} u \\ v \end{pmatrix} \quad \tilde{p} = \begin{pmatrix} \tilde{u} \\ \tilde{v} \\ \tilde{w} \end{pmatrix} = \lambda \begin{pmatrix} u \\ v \\ 1 \end{pmatrix}
\]

- Using matrix form and homogeneous coordinates, the perspective projection becomes:

\[
\lambda \begin{bmatrix} u \\ v \\ 1 \end{bmatrix} = K \begin{bmatrix} X_c \\ Y_c \\ Z_c \end{bmatrix}
\]

Compact form
Exercise 1

• Determine the Intrinsic Parameter Matrix ($K$) of a digital camera with an image size $640 \times 480$ pixels and a horizontal field of view of $90^\circ$

• Assume square pixels and the principal point as the center of the diagonals

• What is the vertical field of view?

• What’s the projection on the image plane of $P_c = [1, 1, 2]^T$
Exercise 1 - Solution

• Recall:

\[ \tan \frac{\theta}{2} = \frac{W}{2\alpha} \rightarrow \alpha = \frac{W}{2} \left[ \tan \frac{\theta}{2} \right]^{-1} = \frac{640}{2\tan \frac{\pi/2}{2}} = 320 [\text{pixels}] \]

\[ \rightarrow \alpha_u = \alpha_v = \alpha = 320 \text{ pixels} \text{ (because pixels are square)} \]

• Because the Principal Point is center of the diagonals \( \rightarrow O = (u_0, v_0) = \left( \frac{640}{2}, \frac{480}{2} \right) = (320, 240) \)

\[ \rightarrow K = \begin{bmatrix} 320 & 0 & 320 \\ 0 & 320 & 240 \\ 0 & 0 & 1 \end{bmatrix} \]

• Vertical FOV: \( \theta_V = 2 \tan^{-1} \frac{H}{2\alpha} = 2 \tan^{-1} \frac{480}{2 \cdot 320} = 73.74^\circ \)
Exercise 1 - Solution

• What’s the projection on the image plane of $P_c = [1, 1, 2]^T$

• Solution 1 (using Perspective Projection Equation in plane form)

\[
\begin{align*}
    u &= u_0 + \frac{\alpha x_c}{z_c} = 320 + \frac{320 \cdot 1}{2} = 480 \text{ [pixels]} \\
    v &= v_0 + \frac{\alpha y_c}{z_c} = 240 + \frac{320 \cdot 1}{2} = 400 \text{ [pixels]}
\end{align*}
\]

• Solution 2 (using Perspective Projection Equation in matrix form)

\[
\begin{bmatrix}
\lambda u \\
\lambda v \\
\lambda
\end{bmatrix} =
\begin{bmatrix}
320 & 0 & 320 \\
0 & 320 & 240 \\
0 & 0 & 1
\end{bmatrix}
\begin{bmatrix}
1 \\
1 \\
2
\end{bmatrix} =
\begin{bmatrix}
960 \\
800 \\
2
\end{bmatrix}
\]

\[
\begin{align*}
    u &= \frac{960}{2} = 480 \text{ [pixels]} \\
    v &= \frac{800}{2} = 400 \text{ [pixels]}
\end{align*}
\]
Exercise 2

• Prove that world’s parallel lines intersect at a vanishing point in the camera image

Vertical vanishing point (at infinity)
Exercise 2 - Solution

• World’s parallel lines with direction \((l, m, n)\), passing through \((X_0, Y_0, Z_0)\), are described by these equations:

\[
X = X_0 + sl \\
Y = Y_0 + sm \\
Z = Z_0 + sn
\]

• Let’s consider the perspective projection equation in plane form:

\[
u = u_0 + \alpha \frac{X}{Z} , \quad v = v_0 + \alpha \frac{Y}{Z} \]

• Substitute line equations into the perspective projection equation and compute limit for \(s \to \infty\)

\[
limit_{s \to \infty} u_0 + \alpha \frac{X_0 + sl}{Z_0 + sn} = u_0 + \alpha \frac{l}{n} , \quad limit_{s \to \infty} v_0 + \alpha \frac{Y_0 + sm}{Z_0 + sn} = v_0 + \alpha \frac{m}{n} \]

• These are the image coordinates of the vanishing point. **Notice that they only depend on the line direction** (indeed, they do not depend on \((X_0, Y_0, Z_0))\).
Exercise 2 - Solution

• You can verify that the solution satisfies this matrix equation. Can you show it geometrically?

\[
\begin{bmatrix}
\lambda u \\
\lambda v \\
\lambda \\
\end{bmatrix}
= \begin{bmatrix}
\alpha & 0 & u_0 \\
0 & \alpha & v_0 \\
0 & 0 & 1 \\
\end{bmatrix}
\begin{bmatrix}
l \\
m \\
n \\
\end{bmatrix}
\]
Perspective Projection – 4/4

From the World frame to the Camera frame

\[
\begin{bmatrix}
X_c \\ Y_c \\ Z_c
\end{bmatrix} =
\begin{bmatrix}
r_{11} & r_{12} & r_{13} \\ r_{21} & r_{22} & r_{23} \\ r_{31} & r_{32} & r_{33}
\end{bmatrix}
\begin{bmatrix}
X_w \\ Y_w \\ Z_w
\end{bmatrix} +
\begin{bmatrix}
t_1 \\ t_2 \\ t_3
\end{bmatrix}
\]

Extrinsic Parameters
Perspective Projection – 4/4

From the World frame to the Camera frame

\[
\begin{bmatrix}
X_c \\
Y_c \\
Z_c
\end{bmatrix}
= 
\begin{bmatrix}
r_{11} & r_{12} & r_{13} & t_1 \\
r_{21} & r_{22} & r_{23} & t_2 \\
r_{31} & r_{32} & r_{33} & t_3
\end{bmatrix}
\begin{bmatrix}
X_w \\
Y_w \\
Z_w \\
1
\end{bmatrix}
= 
\begin{bmatrix}
R & T
\end{bmatrix}
\begin{bmatrix}
X_w \\
Y_w \\
Z_w \\
1
\end{bmatrix}
\]

By substituting the above one into the Perspective Projection Equation:

\[
\begin{bmatrix}
u \\
v
\end{bmatrix}
= K
\begin{bmatrix}
X_c \\
Y_c \\
Z_c
\end{bmatrix}
\]

\[
\lambda
\begin{bmatrix}
u \\
v \\
1
\end{bmatrix}
= K [R | T]
\begin{bmatrix}
X_w \\
Y_w \\
Z_w \\
1
\end{bmatrix}
\]

Projection Matrix (M)

Perspective Projection Equation

Extrinsic Parameters
• It is often convenient to use normalized image coordinates onto a virtual image plane with focal length equal to 1 unit (adimensional) and origin of the pixel coordinates at the principal point.
• It is often convenient to use normalized image coordinates onto a virtual image plane with focal length equal to 1 unit (adimensional) and origin of the pixel coordinates at the principal point.
Normalized image coordinates

- It is often convenient to use normalized image coordinates onto a virtual image plane with focal length equal to 1 unit (adimensional) and origin of the pixel coordinates at the principal point.
- To do this, we just pre-multiply both terms of the perspective projection equation in camera frame coordinates by $K^{-1}$:

$$
\begin{bmatrix}
    u \\
    v \\
    1
\end{bmatrix}
= K
\begin{bmatrix}
    X_c \\
    Y_c \\
    Z_c
\end{bmatrix}
\Rightarrow
\begin{bmatrix}
    u \\
    v \\
    1
\end{bmatrix}
= K^{-1} \cdot K
\begin{bmatrix}
    X_c \\
    Y_c \\
    Z_c
\end{bmatrix}
\Rightarrow
\begin{bmatrix}
    u \\
    v \\
    1
\end{bmatrix}
= \begin{bmatrix}
    X_c \\
    Y_c \\
    Z_c
\end{bmatrix}
$$

- We define the unit-plane normalized image coordinates $(\bar{u}, \bar{v})$:

$$
\begin{bmatrix}
    \bar{u} \\
    \bar{v} \\
    1
\end{bmatrix}
= K^{-1}
\begin{bmatrix}
    u \\
    v \\
    1
\end{bmatrix}
= \begin{bmatrix}
    \frac{1}{\alpha} & 0 & \frac{u_0}{\alpha} \\
    0 & \frac{1}{\alpha} & \frac{v_0}{\alpha} \\
    0 & 0 & 1
\end{bmatrix}
\begin{bmatrix}
    u \\
    v \\
    1
\end{bmatrix}
\Rightarrow
\begin{bmatrix}
    \bar{u} \\
    \bar{v} \\
    1
\end{bmatrix}
= \begin{bmatrix}
    X_c \\
    Y_c \\
    Z_c
\end{bmatrix}
$$
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Radial Distortion

No distortion

Positive radial distortion (Barrel distortion) $k_1 > 0$

Negative radial distortion (Pincushion distortion) $k_1 < 0$
Radial Distortion in the OpenCV and Matlab Camera Models

- The standard model of radial distortion is a transformation from the ideal (non-distorted) coordinates \((u,v)\) to the real (distorted) coordinates \((u_d,v_d)\)

- For a given non distorted image point \((u,v)\), the amount of distortion is a nonlinear function of its distance \(r\) from the principal point. For most lenses, this simple quadratic model of radial distortion is sufficient:

\[
\begin{bmatrix}
u_d \\
v_d
\end{bmatrix} = (1 + k_1 r^2) \begin{bmatrix}u - u_0 \\v - v_0\end{bmatrix} + \begin{bmatrix}u_0 \\
v_0\end{bmatrix}
\]

where

\[r^2 = (u - u_0)^2 + (v - v_0)^2\]
Radial & Tangential Distortion in the OpenCV and Matlab Camera Models

- **Radial Distortion**: Depending on the amount of distortion (and thus on the camera field of view), higher order terms can be introduced for the radial distortion.

- **Tangential Distortion**: if the lens is misaligned (not perfectly parallel to the image sensor), a non-radial (tangential) distortion is introduced.

\[
\begin{bmatrix}
u_d \\
v_d
\end{bmatrix} = (1 + k_1 r^2 + k_2 r^4 + k_3 r^6) \begin{bmatrix} u - u_0 \\ v - v_0 \end{bmatrix} + \begin{bmatrix} 2k_4(u - u_0)(v - v_0) + k_5(r^2 + 2(u - u_0)^2) \\ k_4(r^2 + 2(v - v_0)^2 + 2k_5(u - u_0)(v - v_0) \end{bmatrix} + \begin{bmatrix} u_0 \\ v_0 \end{bmatrix}
\]

This formula won’t be asked at the exam 😊

The left figure shows the impact of the complete distortion model (radial + tangential) on each pixel of the image. Each arrow represents the effective displacement of a pixel induced by the lens distortion. Observe that points at the corners of the image are displaced by as much as 25 pixels. The center figure shows the impact of the tangential component of distortion. On this plot, the maximum induced displacement is 0.14 pixel (at the upper left corner of the image). Finally, the right figure shows the impact of the radial component of distortion. This plot is very similar to the full distortion plot, showing that the tangential component could very well be discarded in the complete distortion model. On the three figures, the cross indicates the center of the image (i.e., the center of the two diagonals), and the circle the location of the principal point.
Summary: Perspective projection equations

- A world’s 3D point \( P_w = (X_w, Y_w, Z_w) \) projects into the image point \( p = (u, v) \)

\[
\lambda \begin{bmatrix} u \\ v \\ 1 \end{bmatrix} = K[R | T] \cdot \begin{bmatrix} X_w \\ Y_w \\ Z_w \\ 1 \end{bmatrix}
\]

where

\[
K = \begin{bmatrix}
\alpha & 0 & u_0 \\
0 & \alpha & v_0 \\
0 & 0 & 1
\end{bmatrix}
\]

- To account for radial distortion, distorted pixel coordinates \((u_d, v_d)\) can be obtained as:

\[
\begin{bmatrix} u_d \\ v_d \end{bmatrix} = (1 + k_1 r^2) \begin{bmatrix} u - u_0 \\ v - v_0 \end{bmatrix} + \begin{bmatrix} u_0 \\ v_0 \end{bmatrix}
\]

where \( r^2 = (u - u_0)^2 + (v - v_0)^2 \)

- For convenience, the projection of \( P_w \) into pixel coordinates, including lens distortion, is usually denoted:

\[
\begin{bmatrix} u_d \\ v_d \end{bmatrix} = \pi(P_w, K, R, T)
\]

See also the OpenCV documentation (link)
Summary (things to remember)

- This-lens equation
- From the thin lens to the pinhole camera
- Perspective Projection Equation
- Vanishing points and lines
- Intrinsic and extrinsic parameters \((K, R, T)\)
- Homogeneous coordinates
- Normalized image coordinates
- Radial distortion
Readings

• Chapter 4 of Autonomous Mobile Robots book: [link]
Understanding Check

Are you able to:

• Explain what a blur circle is?
• Derive the thin lens equation and perform the pinhole approximation?
• Explain how to build an Ames room?
• Derive a relation between the field of view and the focal length?
• Proof the perspective projection equation, including lens distortion and world-to-camera projection?
• Explain normalized image coordinates and their geometric explanation?
• Define vanishing points and lines?
• Prove that parallel lines intersect at vanishing points?