Lenses

CS 6334 Virtual Reality
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Some slides of this lecture are based on the Virtual Reality textbook by Steven LaValle
Review of VR Systems

**INPUT**
- Head Tracker
- Game Controller
- Keyboard & Mouse

**COMPUTATION**
- Virtual World Generator

**OUTPUT**
- Visual Renderer
- Aural Renderer
- Haptic Renderer

Visual Display
Aural Display
Haptic Display
Aperture Size of Pinhole Camera

What happen if the aperture is too small?
- Less light passes through
- Adding lenses
Figure 4.8: (a) The earliest known artificially constructed lens, which was made between 750 and 710 BC in ancient Assyrian Nimrud. It is not known whether this artifact was purely ornamental or used to produce focused images. Picture from the British Museum. (b) A painting by Conrad con Soest from 1403, which shows the use of reading glasses for an elderly male.
Snell’s Law

• How much rays of light bend when entering and exiting a transparent material

• Refractive index of a material $n = \frac{C}{s}$
  - Air $n = 1.000293$, water $n = 1.33$
  - Crown glass $n = 1.523$

• Snell’s Law

$$n_1 < n_2$$

$$n_1 \sin \theta_1 = n_2 \sin \theta_2$$

$$\theta_2 = \sin^{-1} \left( \frac{n_1 \sin \theta_1}{n_2} \right)$$

Speed of light in a vacuum

Speed of light in the medium
Convex Lenses

- Prisms

- A simple convex lens
Convex Lenses

- Objects in distance
  - Cameras
  \[
  \frac{1}{s_1} + \frac{1}{s_2} = \frac{1}{f}
  \]

- Objects very close
  - Magnification
  - VR headsets
Controllable Aperture

• In the pinhole case, all depths are “in focus”, but there may not enough lights

• When using a convex lens, it focuses objects at a single depth

Figure 4.34: A spectrum of aperture settings, which control the amount of light that enters the lens. The values shown are called the focal ratio or f-stop.
Shutters

• Collecting photons for each pixel

• Rolling shutter vs. Global shutter
Chromatic Aberration

• The speed of light through a medium depends on the wavelength
  • Solution: combining convex and concave lenses of different materials

Figure 4.17: Chromatic aberration is caused by longer wavelengths traveling quickly through the lens. The unfortunate result is a different focal plane for each wavelength or color.

Figure 4.18: The upper image is properly focused whereas the lower image suffers from chromatic aberration. (Figure by Stan Zurek, license CC-BY-SA-2.5.)
Spherical Aberration

• Rays further away from the lens center being refracted more than rays near the center

Aspheric lens
Optical Distortion

• The variation of refractive index towards the outer extremities of a rotational symmetric lens can cause magnification changes in the image space, depending on the distance from the principal axis.
Angular Field of View (AFOV)

\[
AFOV = 2 \times \tan^{-1}\left(\frac{H}{2f}\right)
\]

**Barrel distortion** (wide-angle lenses)

**Pincushion distortion** (telephoto-lenses)

*Figure 1: For a given sensor size, \( H \), shorter focal lengths produce wider AFOVs.*
Barrel Distortion of Fisheye Cameras

Figure 4.21: An image with barrel distortion, taken by a fish-eyed lens. (Image by Wikipedia user Ilveon.)
Tangential Distortion

• Camera sensor mis-alignment during the manufacturing process
Distortion Correction

• The Brown-Conrady distortion model [Wikipedia]

\[
x_u = x_d + (x_d - x_c)(K_1 r^2 + K_2 r^4 + \cdots) + (P_1(r^2 + 2(x_d - x_c)^2) \\
\quad + 2P_2(x_d - x_c)(y_d - y_c))(1 + P_3 r^2 + P_4 r^4 \cdots)
\]

\[
y_u = y_d + (y_d - y_c)(K_1 r^2 + K_2 r^4 + \cdots) + (2P_1(x_d - x_c)(y_d - y_c) \\
\quad + P_2(r^2 + 2(y_d - y_c)^2))(1 + P_3 r^2 + P_4 r^4 \cdots),
\]

where

- \((x_d, y_d)\) is the distorted image point as projected on image plane using specified lens;
- \((x_u, y_u)\) is the undistorted image point as projected by an ideal pinhole camera;
- \((x_c, y_c)\) is the distortion center;
- \(K_n\) is the \(n^{th}\) radial distortion coefficient;
- \(P_n\) is the \(n^{th}\) tangential distortion coefficient; and

\[
r = \sqrt{(x_d - x_c)^2 + (y_d - y_c)^2},\] the Euclidean distance between the distorted image point and the distortion center.[3]

Use calibration tools to estimate these coefficients
Summary: Camera Models

• Camera projection matrix: intrinsics and extrinsics

\[ P = K[R|t] \]

• Lens distortion
  • Radial distortion coefficients \( K_1, K_2, K_3, \ldots \)
  • Tangential distortion coefficients \( P_1, P_2, P_3, \ldots \)
Camera Calibration

• Find the intrinsics, extrinsics and lens distortion coefficients of a camera

• Details will be discussed in CS 6384 Computer Vision

• Chess board camera calibration with OpenCV
  https://docs.opencv.org/3.4/dc/dbb/tutorial_py_calibration.html
Further Reading

• Section 4.2, 4.3, Virtual Reality, Steven LaValle

• Image formation by lenses
  https://courses.lumenlearning.com/physics/chapter/25-6-image-formation-by-lenses/

• Distortion (Wikipedia)