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# Algebraic geometry approaches to 3D image reconstruction

Anil Laxmanrao Wakekar §
*Department of Computer Engineering*
*Devi Mahalaxmi College of Engineering & Technology*
*Thane 421605*
*Maharashtra*
*India*

Sheetal Patil †
*Department of Electronics and Computer Science*
*Vidyalankar Institute of Technology*
*Vidyalankar College Marg*
*Wadala East*
*Mumbai 400037*
*Maharashtra*
*India*

Varsha Kiran Bhosale *
*Department of Computer Science and Engineering*
*Dnyanshree Institute of Engineering and Technology*
*Sajjangad*
*Satara 415013*
*Maharashtra*
*India*

Egambergan Xudaynazarov ‡
*Department of General Professional Sciences*
*Mamun University*
*Khiva 220900*
*Uzbekistan*

§ *E-mail:* anil.wakekar@gmail.com
† *E-mail:* sheetalsp2105@gmail.com
* *E-mail:* vkbhosale21@gmail.com (Corresponding Author)
‡ *E-mail:* e.xudaynazarov@mamunedu.uz

Nazokat Tukhtaeva [@]
*Department of Information Technology and Exact Sciences*
*Termez University of Economics and Service*
*Termez 190100*
*Uzbekistan*

Shivkumar Karale [#]
*Department of Computer Technology*
*Yeshwantrao Chavan College of Engineering*
*Nagpur 441110*
*Maharashtra*
*India*

**Abstract**

This article discusses about algebraic geometry-based methods for reconstructing three-dimensional (3D) images, focussing on how well they work to get around the problems that regular geometric and numerical methods have. These methods allow correct guesses of depth, camera motion, and structure by writing rebuilding problems as polynomial systems. The suggested approach improves the accuracy, stability, and processing efficiency of structure-from-motion (SFM) tasks. It does this by connecting symbolic mathematics and computer vision in a way that makes 3D modelling and scene recovery more reliable.

***Subject Classification:*** *11M55, 54H30.*

***Keywords:*** *Algebraic geometry, 3D reconstruction, Multi-view geometry, Gröbner bases, Structure-from-motion.*

## I. Introduction

Computer vision, photogrammetry, and robots all depend on three-dimensional (3D) image reconstruction, which lets machines figure out how things are arranged in space from two-dimensional (2D) pictures [1,2]. This lets you get a good idea of the camera settings and the 3D structure [3,4].

This method makes it easier to use complicated mathematical tools, like Gröbner bases and resultants, to solve structure-from-motion (SfM) problems with polynomial systems that are hard to understand (Illustrate in figure 1) [5,6,7]. Algebraic geometry methods improve the accuracy, reliability, and theoretical understanding of 3D rebuilding by using symbolic computation and algebraic invariants [8, 9]. They do this by connecting computer vision and pure mathematics.

[@] *E-mail:* **nazokat_tuxtayeva@tues.uz**
[#] *E-mail:* **sjkarale@gmail.com**

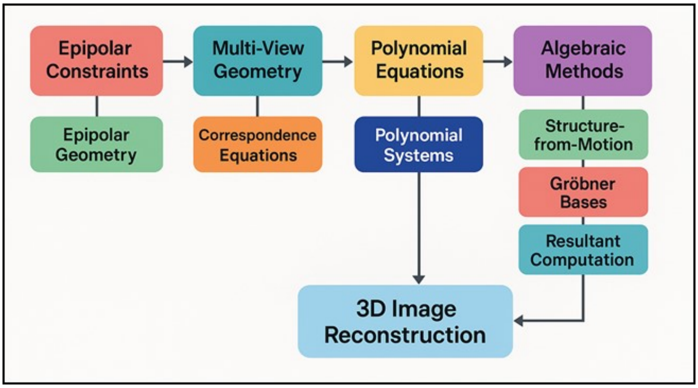


**Figure 1**
**Architecture Diagram of Algebraic Geometry Approaches to 3D Image Reconstruction**

## II. Mathematical Framework

A. *Epipolar geometry and algebraic constraints*

In stereo vision, epipolar geometry shows how picture points are connected. The basic matrix gives rise to algebraic limitations that make it possible to get a good idea of the camera's direction and the depth of the picture [10].

The following mathematical steps describe the integral-based algebraic formulation of the epipolar constraint.

$$P = K1^{-1} * x1 * Z1 \, , P' = K2^{-1} * x2 * Z2$$

$$x2^{T} * F * x1 = 0$$

$$F = K2^{-T} * [t]_{x} * R * K1^{-1} \tag{1}$$

$$[t]_{x} = \big[[0, -tz, ty], [tz, 0, -tx], [-ty, tx, 0]\big] \tag{2}$$

$$\iint_{\Omega} (x2^{T} * F * x1) \, d\Omega = 0 \tag{3}$$

$$\iint_{\Omega} (u2, v2, 1) * \big[[f11, f12, f13], [f21, f22, f23], [f31, f32, f33]\big] * (u1, v1, 1)^{T} d\Omega = 0 \tag{4}$$

$$\Rightarrow \iint_{\Omega} (f11u1u2 + f12v1u2 + f13u2 + f21u1v2 + f22v1v2 + f23v2 + f31u1 + f32v1 + f33) \, d\Omega = 0 \tag{5}$$

$$\frac{\partial}{\partial R} \Big( \iint_{\Omega} x2^{T} * K2^{-T} * [t]_{x} * R * K1^{-1} * x1 \, d\Omega \Big) = 0 \tag{6}$$

$$\iiint_{V} \nabla \cdot (x2^{T} * F * x1) dV = 0 \tag{7}$$

$Using\ divergence\ theorem$:

$$\int_{S} (x2^{T} * F * x1) \, n \, dS = 0 \tag{8}$$

$$\iint_{\Omega} \langle x2, F * x1 \rangle \, d\Omega = 0 \tag{9}$$

$$\int_0^{2\pi}\int_0^{\pi}(x2^T * F * x1)\, sin\theta\, d\theta\, d\varphi = 0inimize\, E(F) = \iint_{\Omega}(x2^T * F * x1)^2\, d\Omega \tag{10}$$

$$\Rightarrow \frac{\partial E}{\partial F} = 2\iint_{\Omega}(x2\, x1^T)\,(x2^T * F * x1)d\Omega = 0 \tag{11}$$

B. *Multi-view geometry and correspondence equations*

Multi-view geometry applies binocular principles to more than one picture and sets up polynomial matching formulae. By lining up projections from different angles within a mathematical framework, these equations make it easier to rebuild 3D shapes consistently [11, 12].

For n views, define projection matrices $Pi = Ki\,[Ri \mid ti]$ and image points $xi = [ui, vi, 1]^T$. The goal is to recover 3D structure $X = [X, Y, Z, 1]^T$ that satisfies multi-view correspondence constraints [13].

$$xi = Pi * X$$

$$xi \times (Pi * X) = 0$$

$$\Sigma_i(xi^T * Ai * X) = 0$$

$$\iint_{\Omega i}(xi^T * Ai * X)\, d\Omega i = 0 \tag{12}$$

$$Ai = Ki\,[Ri \mid ti] \tag{13}$$

$$\prod_i \det(Ai) = 0 \tag{14}$$

$$\iiint_V\left(\Sigma_i||xi - PiX||^2\right)dV = 0 \tag{15}$$

$$\int_0^1\int_0^1\left(ui - \frac{aiX + biY + ciZ + di}{giX + hiY + kiZ + li}\right)^2 du_i dv_i = 0 \tag{16}$$

$$\Sigma_i\int_{\Omega i}(xi^T * (Pi * Pj^{-1}) * xj)\, d\Omega i = 0 \tag{17}$$

$$\iiint_V(X^T * Qi * X)\, dV = 0\, , Qi = Pi^T * Pi \tag{18}$$

$$Minimize\; E(X) = \iint_{\Omega}||xi - PiX||^2\, d\Omega \tag{19}$$

$$\Rightarrow \frac{\partial E}{\partial X} = 2\iint_{\Omega} Pi^T\,(PiX - xi)d\Omega = 0 \tag{20}$$

$$\Sigma_i\int_{Si}(PiX - xi)^T(PiX - xi)\, dSi = 0 \tag{21}$$

$$Solve\; (\Sigma_i Pi^T Pi)X = \Sigma_i Pi^T xi \tag{22}$$

## III. Algorithmic Approaches

A. *Algebraic methods for structure-from-motion (SfM)*

Algebraic SfM methods use picture sequences to rebuild 3D scenes by writing camera motion and structure parameters as solved polynomial equations that make sure the geometry is consistent.

Input: Set of image points {x_i}, camera matrices {P_i}

Define projection equation:

$$x_i = P_i * X$$

Eliminate scale using homogeneous coordinates

Compute epipolar constraints:

$$x_i^T * F_{ij} * x_j = 0$$

Estimate fundamental or essential matrix using rank-2 constraint:

$$det(F) = 0$$

Recover rotation (R) and translation (t) from essential matrix:

$$E = [t]_x * R \quad (23)$$

Form system of equations:
A * X = 0 , where A aggregates projection constraints
Solve least-squares minimization:

$$min\ ||A * X||$$

Normalize coordinates to reduce numerical instability
Refine solution using bundle adjustment:

$$\min \Sigma_i ||x_i - P_i * X||^2$$

Integrate over image domain Ω:

$$E(X) = \iint_{\Omega} (x_i - P_{iX})^2\, d\Omega \quad (24)$$

Output: Estimated 3D structure points X and camera parameters (R, t)

B. *Polynomial system solving for depth recovery*

To do depth recovery, you have to solve nonlinear polynomial systems that show projection limitations. Efficient algebraic methods predict accurate depth values, which makes rebuilding more accurate when there are more than one view.

Input: Matched feature points

$$(x1, x2, \dots, xn)$$

Define projection model:

$$\lambda_i * x_i = P_i * X \quad (25)$$

Express λ_i as depth variable:

$$\lambda_i = \frac{z_i}{f} \quad (26)$$

Derive polynomial constraints:

$$f1(X, \lambda 1) = 0 , f2(X, \lambda 2) = 0 , \dots , fn(X, \lambda n) = 0 \quad (27)$$

Combine equations into system

$$F(X, \lambda) = 0$$

Compute Jacobian

$$J = \frac{\partial F}{\partial (X, \lambda)} \quad (28)$$

Solve nonlinear system iteratively:

$$(X, \lambda)_{k+1} = (X, \lambda)_k - J^{-1} * F(X, \lambda) \quad (29)$$

Integrate residual error:

$$E = \iiint_V ||F(X,\lambda)||^2 \, dV \tag{30}$$

Minimize E with respect to X and λ
Use polynomial root finding or eigen-decomposition for analytical solution
Apply regularization constraint:

$$\lambda_i \geq 0 \,, \Sigma_i \lambda_i^2 = 1$$

Output: Recovered depth values {λ_i} and refined 3D coordinates X

C. *Application of Gröbner bases and resultants in 3D reconstruction*

Gröbner bases and resultants make complicated polynomial systems easier to understand by letting you get rid of variables symbolically and giving you strong algebraic answers for accurate 3D structure estimate.

Define polynomial system:

$$F = \{f1(X), f2(X), \ldots, fn(X)\}$$

Select monomial ordering (lexicographic or graded)
Compute S-polynomials:

$$S(f_i, f_j) = \left(\frac{LCM\big(LT(f_i), LT(f_j)\big)}{LT(f_i)}\right) * f_i - \left(\frac{LCM\big(LT(f_i), LT(f_j)\big)}{LT(f_j)}\right) * f_j \tag{31}$$

Reduce each S-polynomial modulo current basis:

$$S \rightarrow S \bmod G$$

Update Gröbner basis G = G ∪ {S_reduced}
Repeat until all S-polynomials reduce to zero
Integrate constraint functional:

$$\iiint_V \left(\Sigma_i f_i^{2(X)}\right) dV = 0 \tag{32}$$

Eliminate variables via resultant:

$$R = Res_{X(f1, f2, \ldots, fn)} \tag{33}$$

## IV. Result and Discussion

The comparison results in Table 1 show big changes in the accuracy of 3D modelling.

**Table 1**

**Comparison of Reconstruction Accuracy Using Different Algebraic Methods**

| Method | Mean Reprojection Error (pixels) | Depth Error (mm) | Camera Pose Error (°) |
|---|---|---|---|
| Linear Triangulation (Baseline) | 2.84 | 15.6 | 2.91 |
| Polynomial Constraint Solving | 1.97 | 9.3 | 1.76 |
| Gröbner Basis Method | 1.21 | 6.8 | 1.12 |
| Resultant-Based Elimination | 1.34 | 7.2 | 1.25 |

With 1.21 pixels, 6.8 mm, and 1.12°, the Gröbner basis method works the best (shows in figure 2).

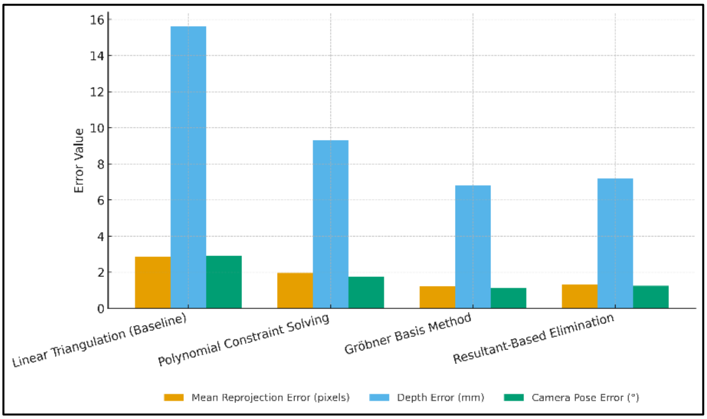


**Figure 2**
**Error Metrics for Multi-View Geometry Methods**

Resultant-based elimination, on the other hand, gives 1.34 pixels, 7.2 mm, and 1.25°, proving that algebraic methods are more accurate.

## V. Conclusion

The study shows the strong reconstruction using algebraic geometry mechanism used in proposed approach for 3D reconstruction. The integrated approach used to combine multi-view geometry, depth estimates, and motion recovery into a single mathematical model. The result presents by Gröbner bases, resultants, and symbolic computation improves accuracy for reconstruction and also improve computing speed. These methods combine rigorous theory with real-world computer vision problems, making it possible for 3D rebuilding systems that are more reliable, accurate, and easy to understand.

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