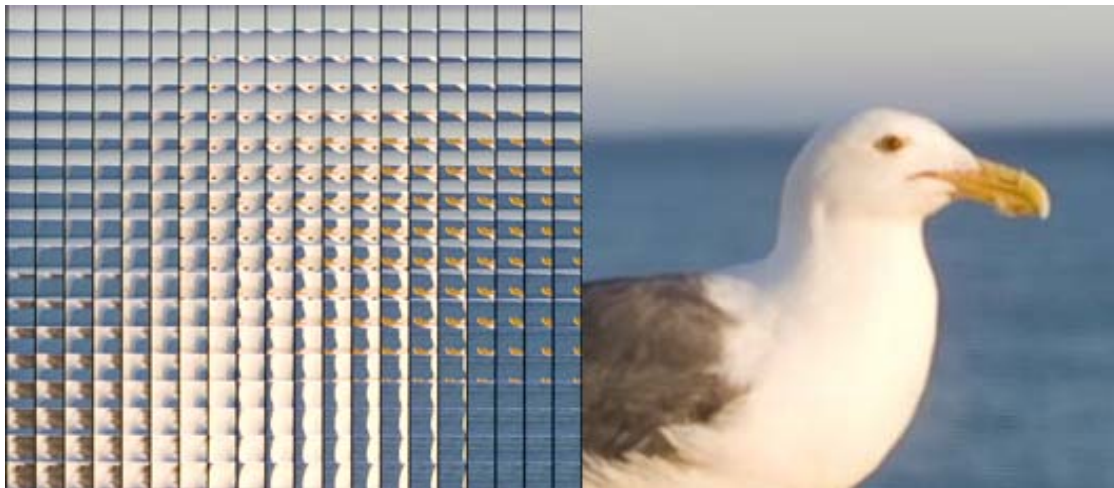
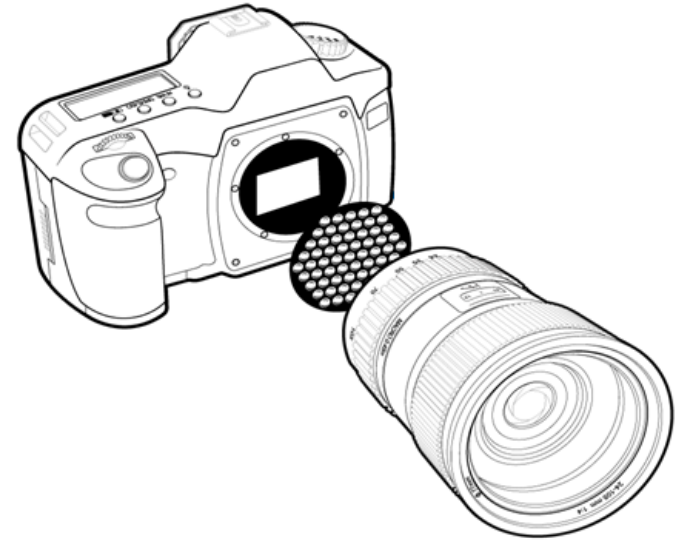


Plenoptic Principal Planes

Todor Georgiev, Andrew Lumsdaine, and Sergio Goma

Plenoptic Cameras

Plenoptic cameras are the future of photography because of the completeness of captured data





3D camera solutions
one camera - one lens - one shot



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R5 – Low cost 3D-focus cameras.

Raytrix presents the new economic 4D lightfield camera series.

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R11 – Highend 3D-focus cameras.

Raytrix presents the new state-of-the-art 4D lightfield camera series with incredi

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The only **camera**
that captures life
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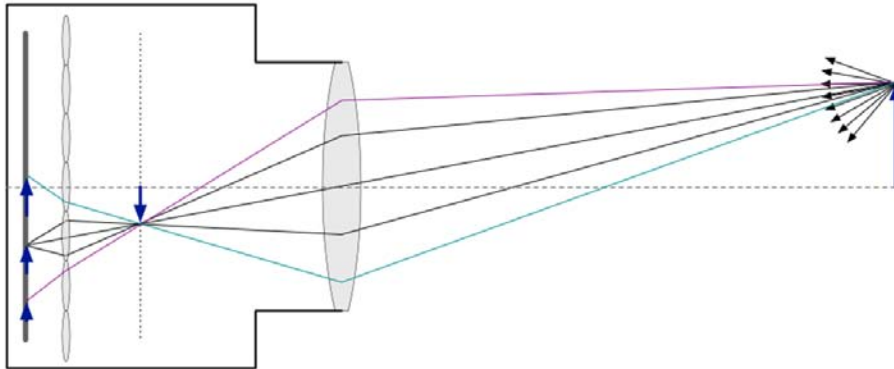
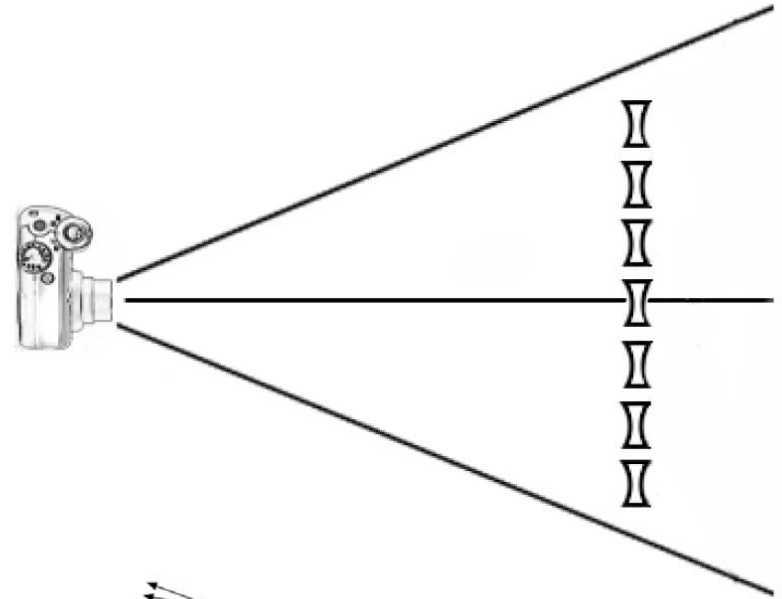
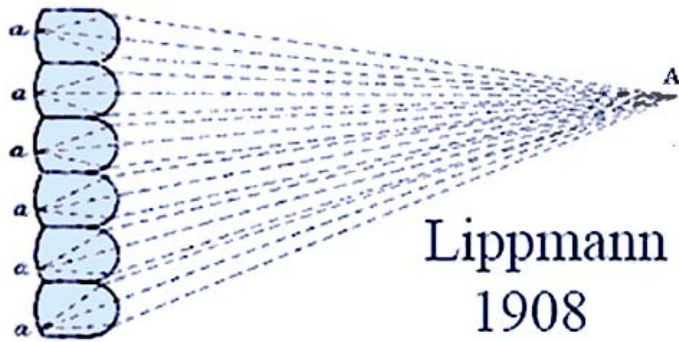
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Integral (Plenoptic) Cameras



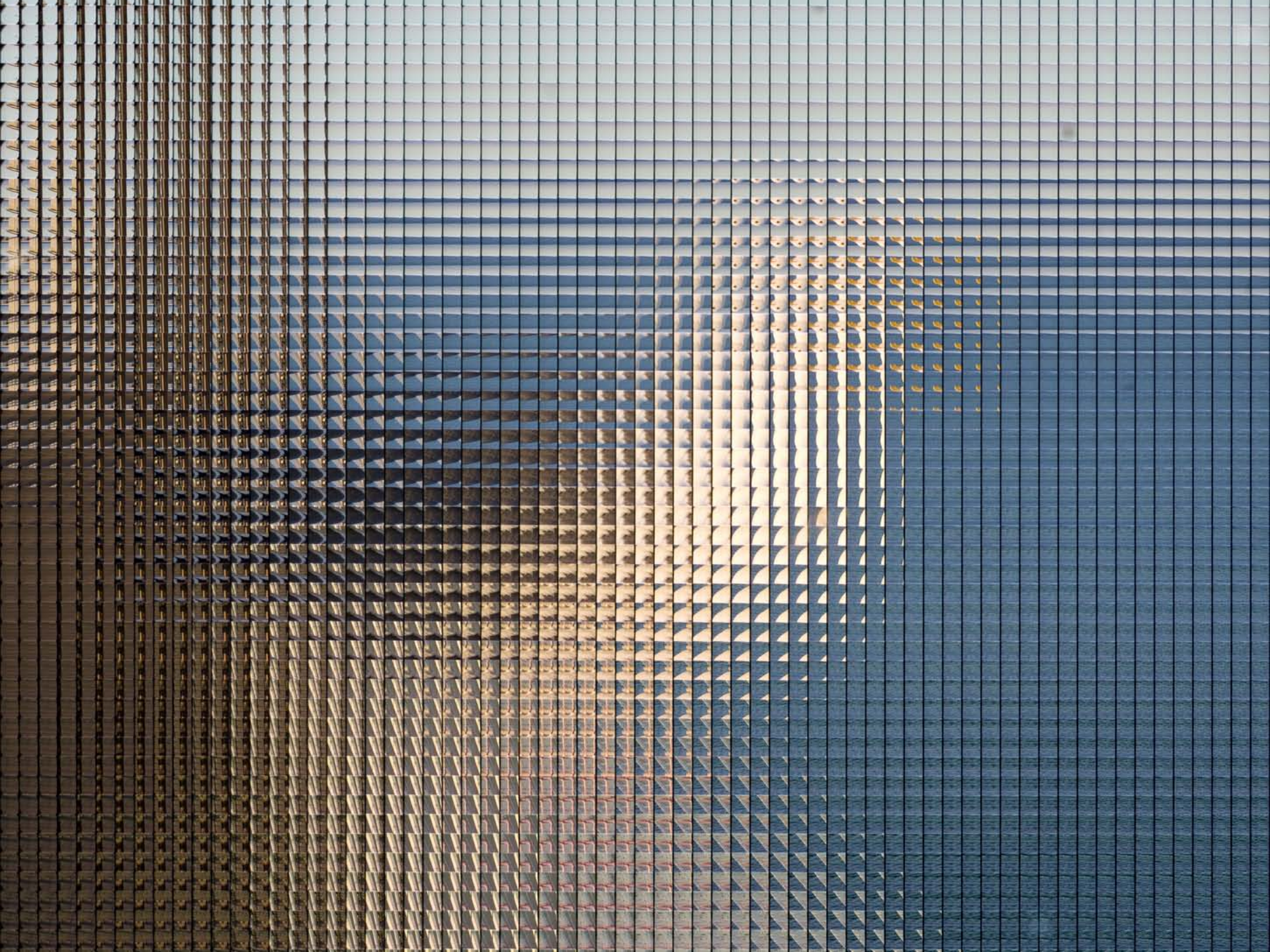


Integral (Plenoptic) Images



Integral (Plenoptic) Images





Integral (Plenoptic) Images

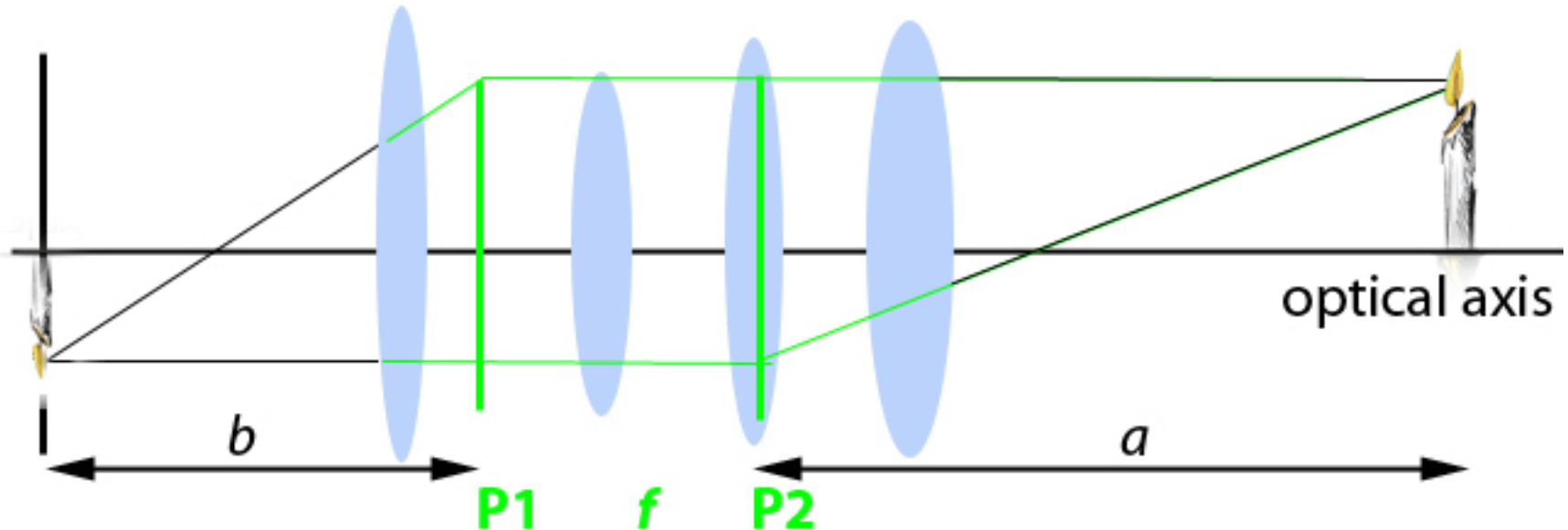


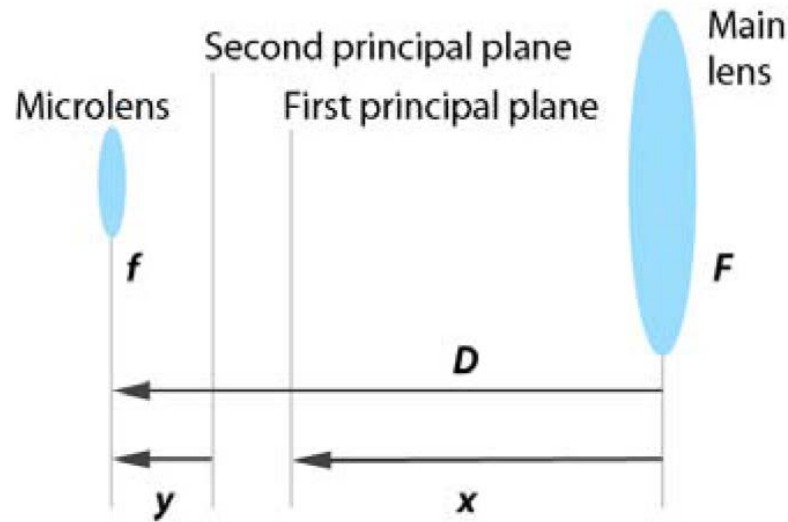
Integral (Plenoptic) Images



Principal Planes

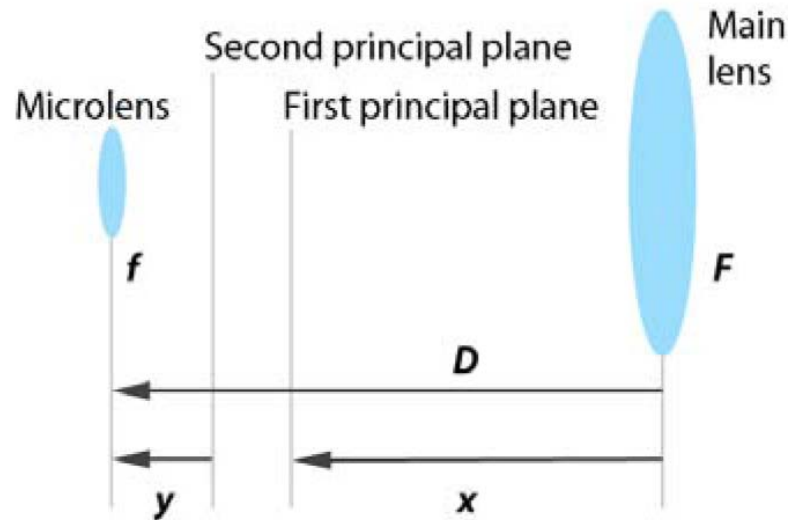
Gauss discovered that the matrix for **any** optical transform can be written as a product of some appropriate **translation, lens, and translation** again.





$$L(f)T(D)L(F) = \begin{bmatrix} 1 - \frac{D}{F} & D \\ \frac{D}{fF} - \frac{1}{f} - \frac{1}{F} & 1 - \frac{D}{f} \end{bmatrix}$$

$$T(y)L(\Phi)T(x) = \begin{bmatrix} 1 - \frac{y}{\Phi} & x + y - \frac{xy}{\Phi} \\ -\frac{1}{\Phi} & 1 - \frac{x}{\Phi} \end{bmatrix}$$

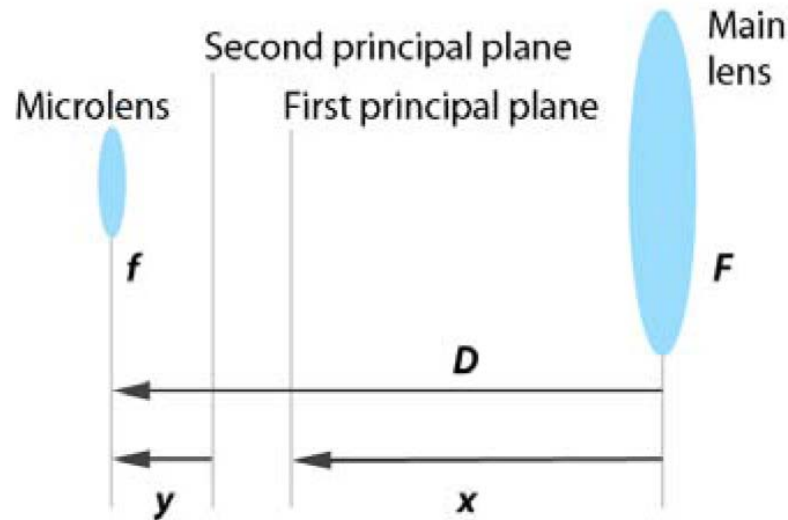


$$L(f)T(D)L(F) = \begin{bmatrix} 1 - \frac{D}{F} & D \\ \frac{D}{fF} - \frac{1}{f} - \frac{1}{F} & 1 - \frac{D}{f} \end{bmatrix}$$

$$T(y)L(\Phi)T(x) = \begin{bmatrix} 1 - \frac{y}{\Phi} & x + y - \frac{xy}{\Phi} \\ -\frac{1}{\Phi} & 1 - \frac{x}{\Phi} \end{bmatrix}$$

$$\frac{1}{\Phi} = \frac{1}{f} + \frac{1}{F} - \frac{D}{fF}$$

Bottom left matrix element



$$\Phi = \frac{Ff}{F + f - D}$$

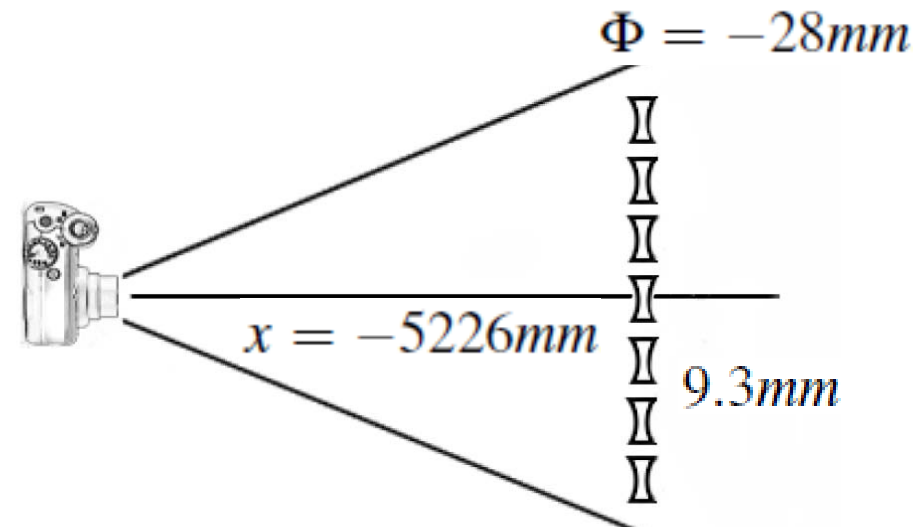
$$x = \frac{DF}{f + F - D}$$

$$y = \frac{Df}{f + F - D}$$

First principal plane can be far in front of the main lens (negative x), establishing optical equivalence between plenoptic cameras.

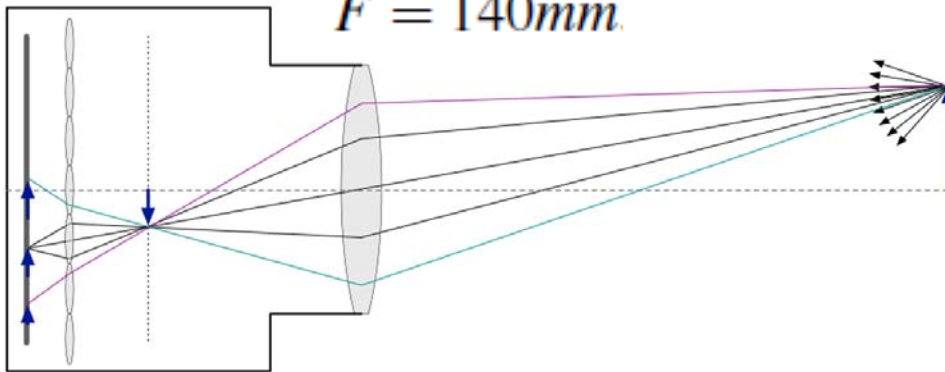
Parameters

Keplerian case:
Microlenses equivalent to negative lenses



$$f = 750\mu m$$

$$F = 140mm$$



$$d = 250\mu m \quad D = 144.5mm$$

Conclusions

Keplerian case:

Microlenses equivalent to negative lenses in front

Galilean case:

Microlenses equivalent to positive lenses behind

Put the camera in physically impossible places

Microlenses are better quality than lenses because they are smaller and have proportionally smaller aberrations.

In aberrations there is no equivalence!