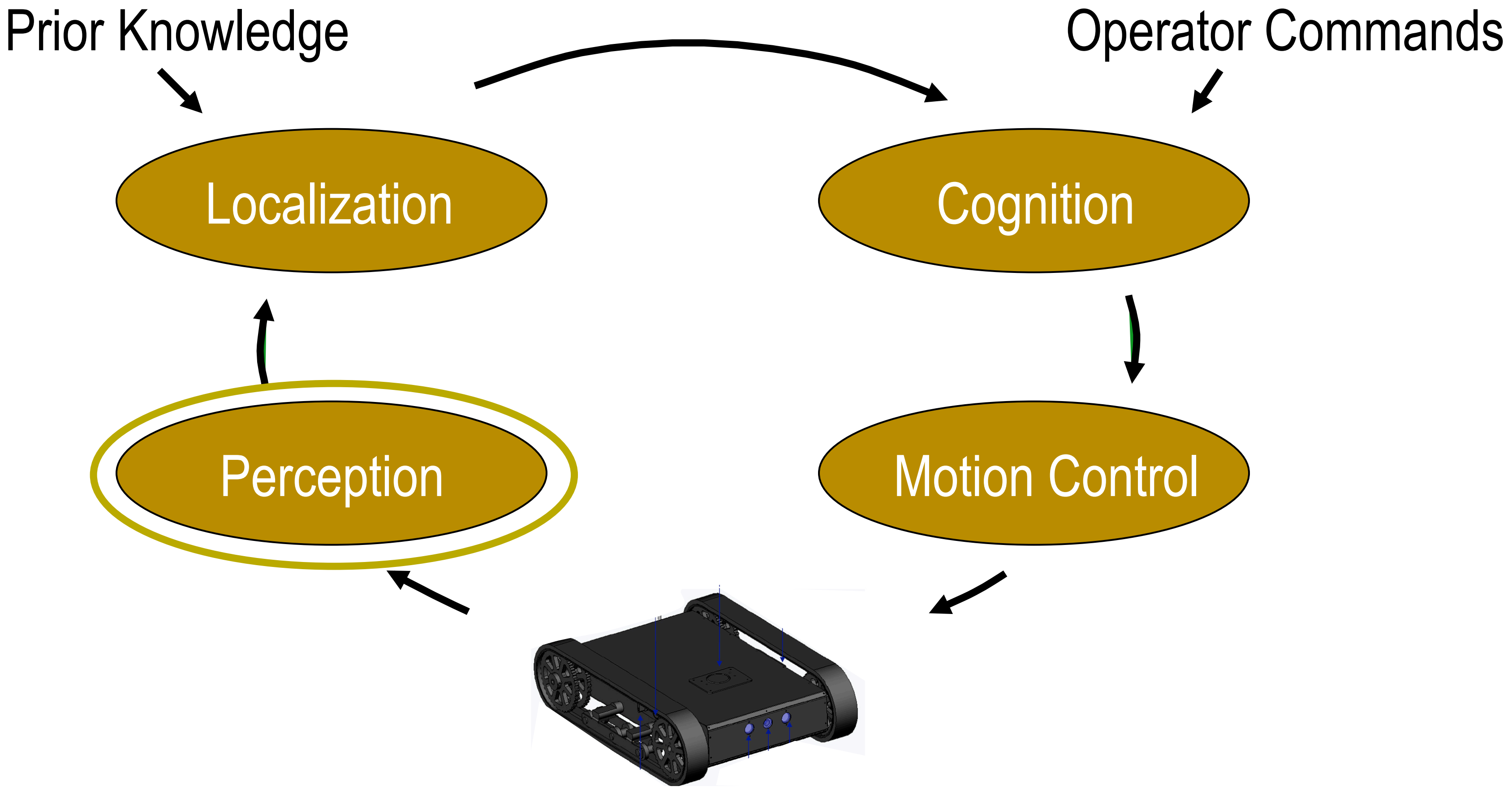
E160 – Lecture 7
Autonomous Robot Navigation

Instructor: Chris Clark

Semester: Spring 2016

Figures courtesy of Siegwart & Nourbakhsh

Control Structures
Planning Based Control

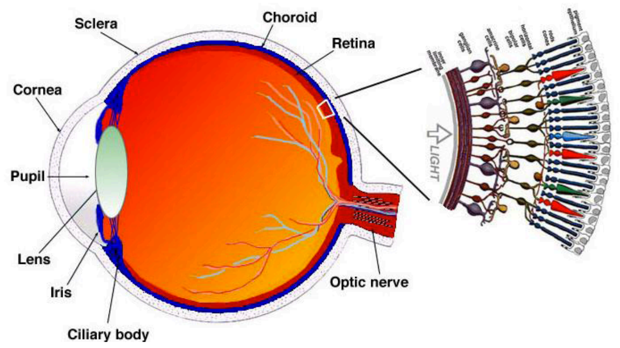


Outline – Vision Systems

1. Introduction
2. Features
3. Stereo Vision
4. Optical Flow
5. Color Tracking

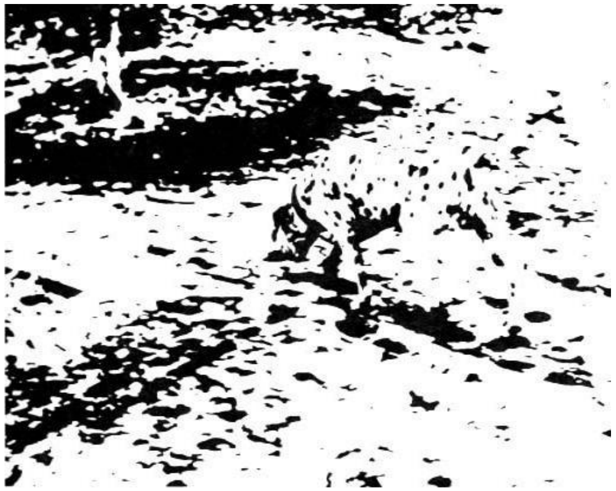
Introduction to Vision Systems

- Vision is our most powerful sense. It provides us with an enormous amount of information about the environment without direct contact.
  - Millions photoreceptors
  - Sample rate of 3 Gbytes/s
  - 60 Billion neurons used to process an image



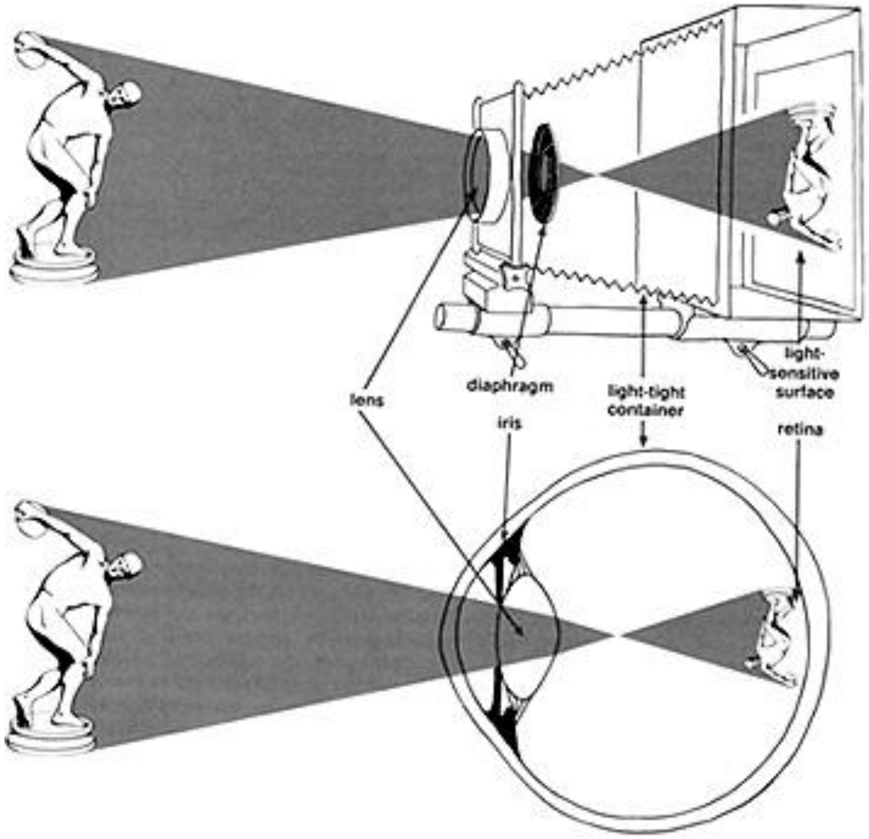
Introduction to Vision Systems

- Our visual system is very sophisticated
  - Humans can interpret images successfully under a wide range of conditions – even in the presence of very limited cues



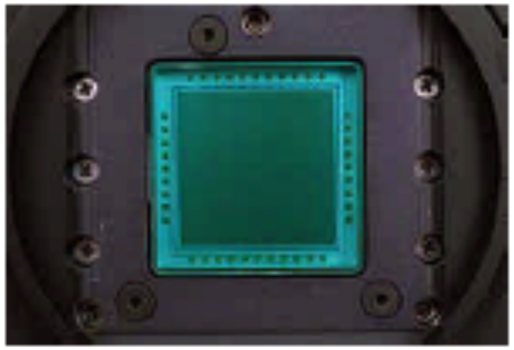
Introduction to Vision Systems

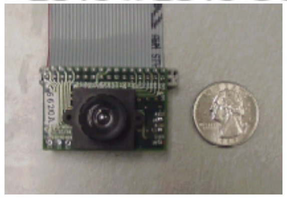
- Not sensible to copy the biology, but learn from it
    - Capture light
    - Convert to digital image
    - Process to get ”salient" information



Introduction to Vision Systems

- There exist a large number of cameras capable of getting these images…


2048 x 2048 CCD array



Orangemicro iBOT Firewire

Sony DFW-X700

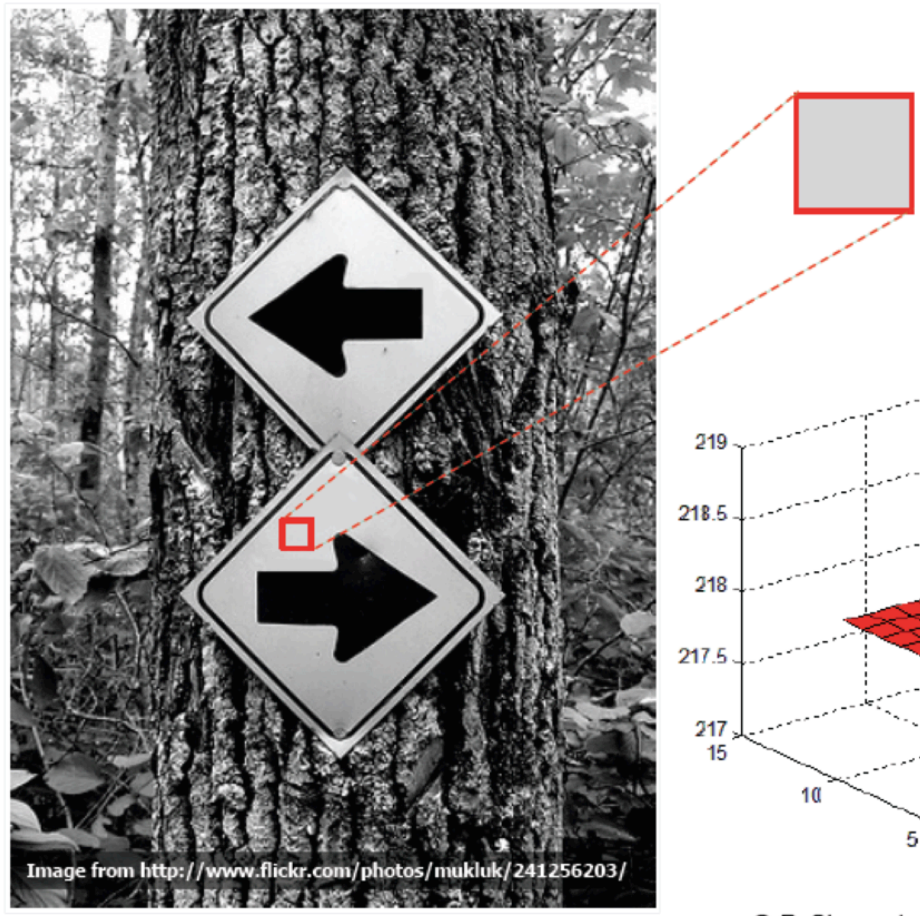
Cannon IXUS 300

Outline – Vision Systems

Filtering

- The image is represented as an array of intensity values.
- What useful information can we extract from these intensities?

Filtering



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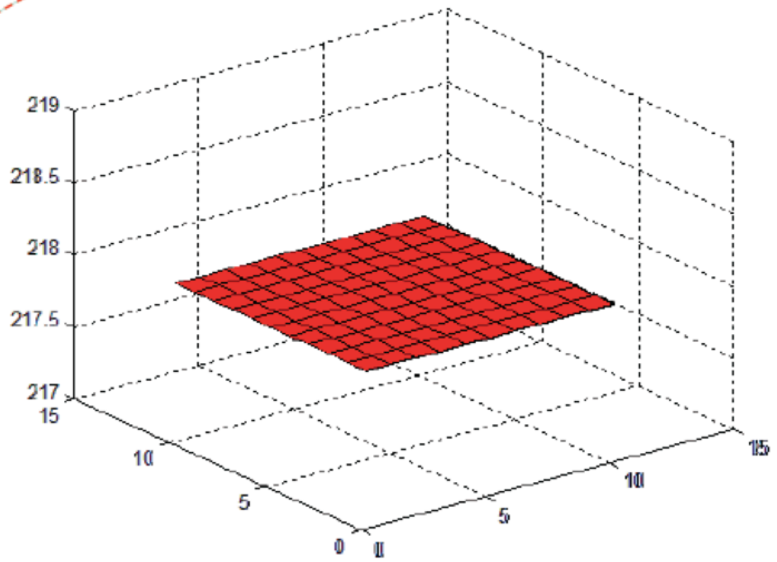

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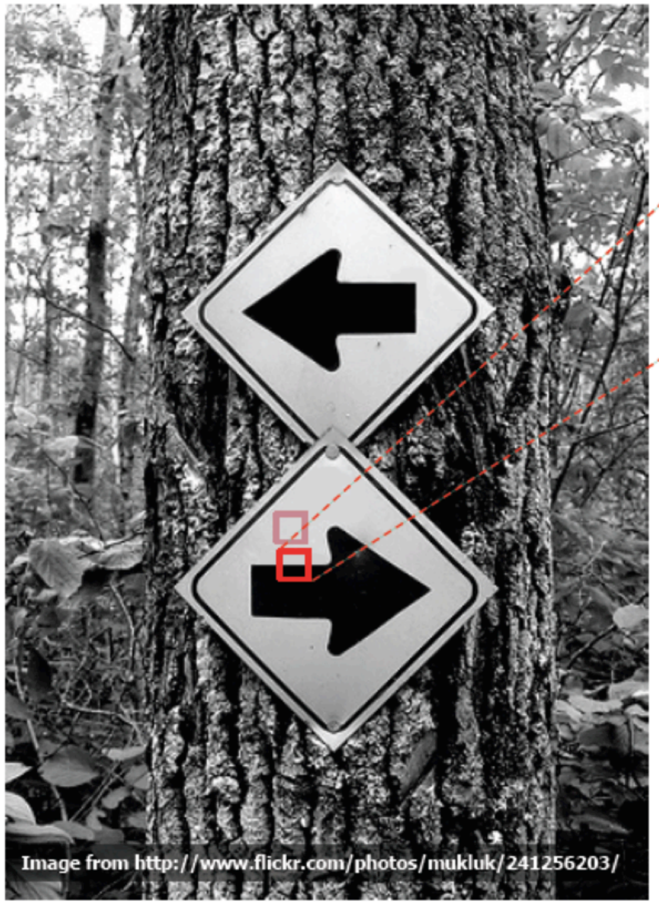
Filtering



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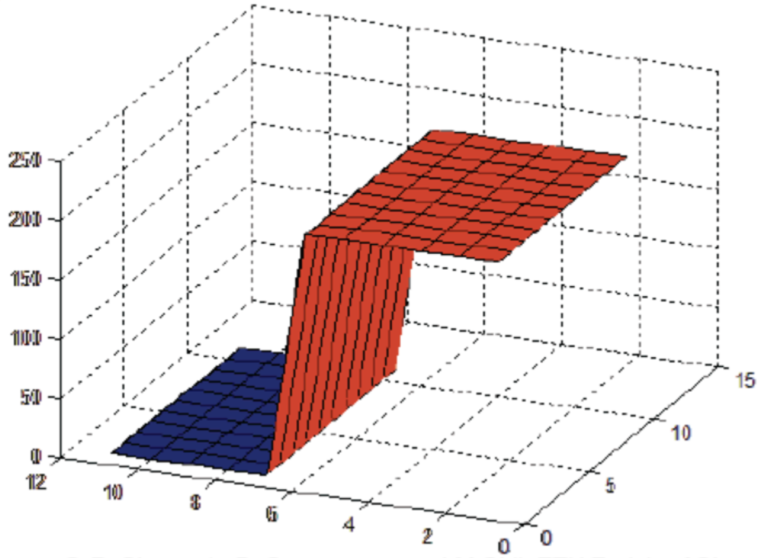

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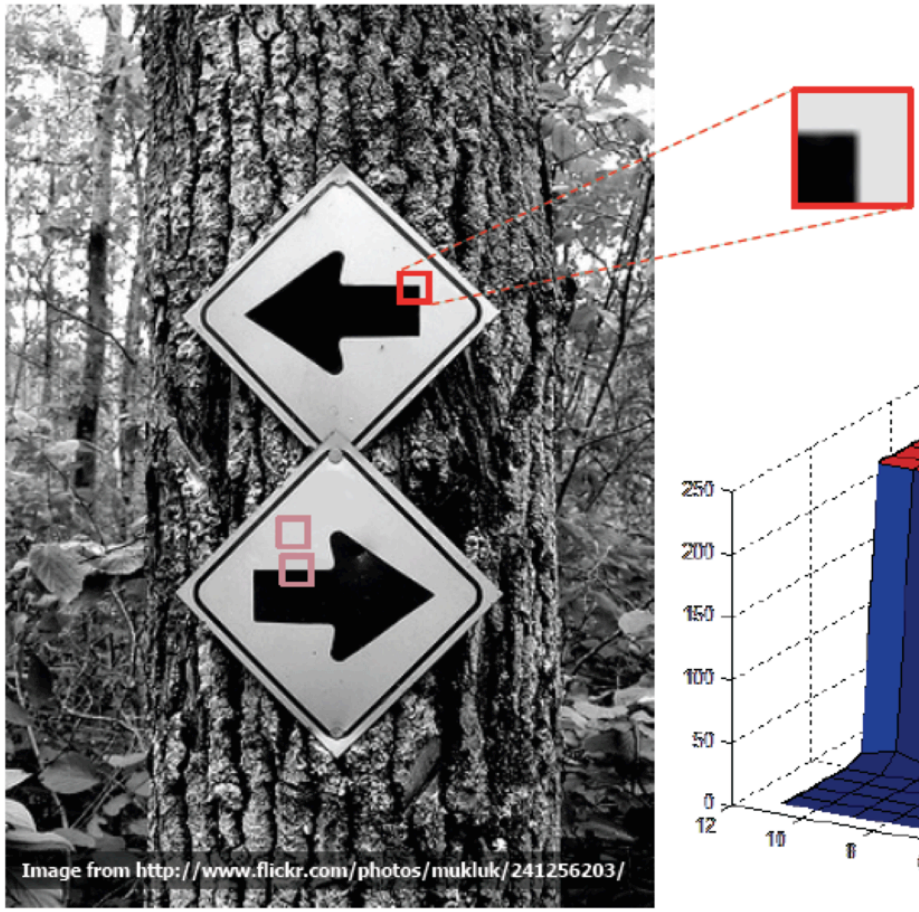
Filtering



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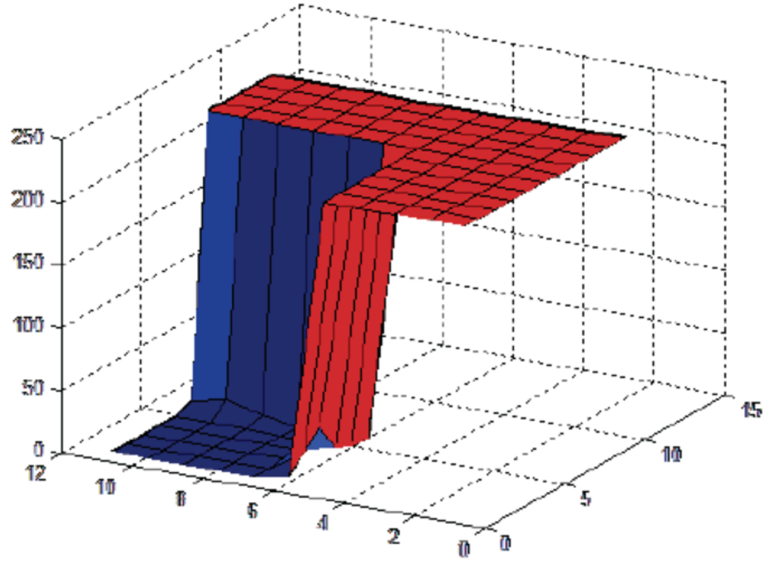

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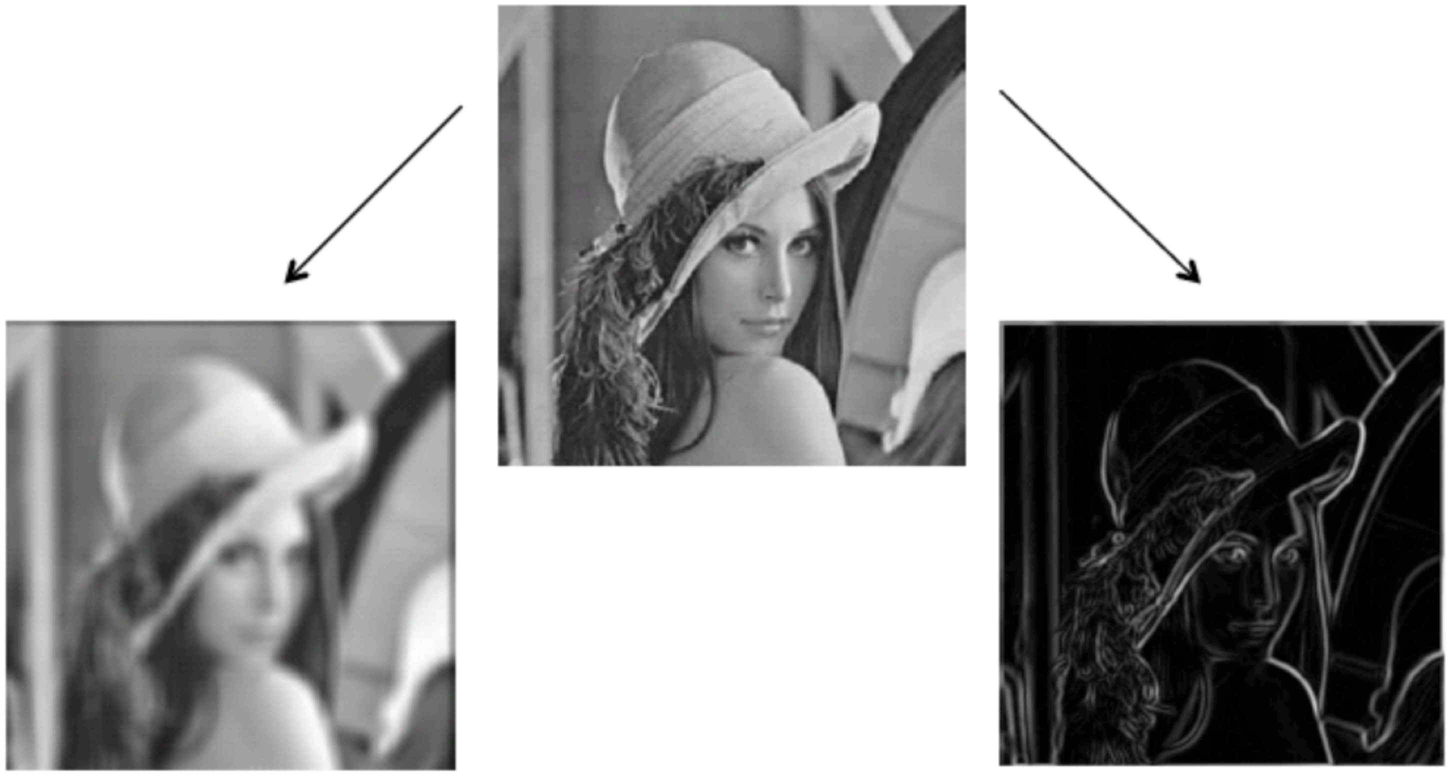
Filtering

- In other courses, we construct **frequency filters** based on frequency, e.g. lowpass/ highpass filters
- In Image processing, we construct **spatial filters**

Filtering



Lowpass filtered image

Highpass filtered image

Filtering

- Spatial Filters
  - Given an Intensity Image $I(x,y)$
  - Let $S_{x,y}$ be the neighborhood of pixels around the pixel at (x,y)
  - We can create a filtered image $J=F(I(x,y))$
    - Each pixel (x,y) in J is calculated based on a function of S_{xy}

Filtering

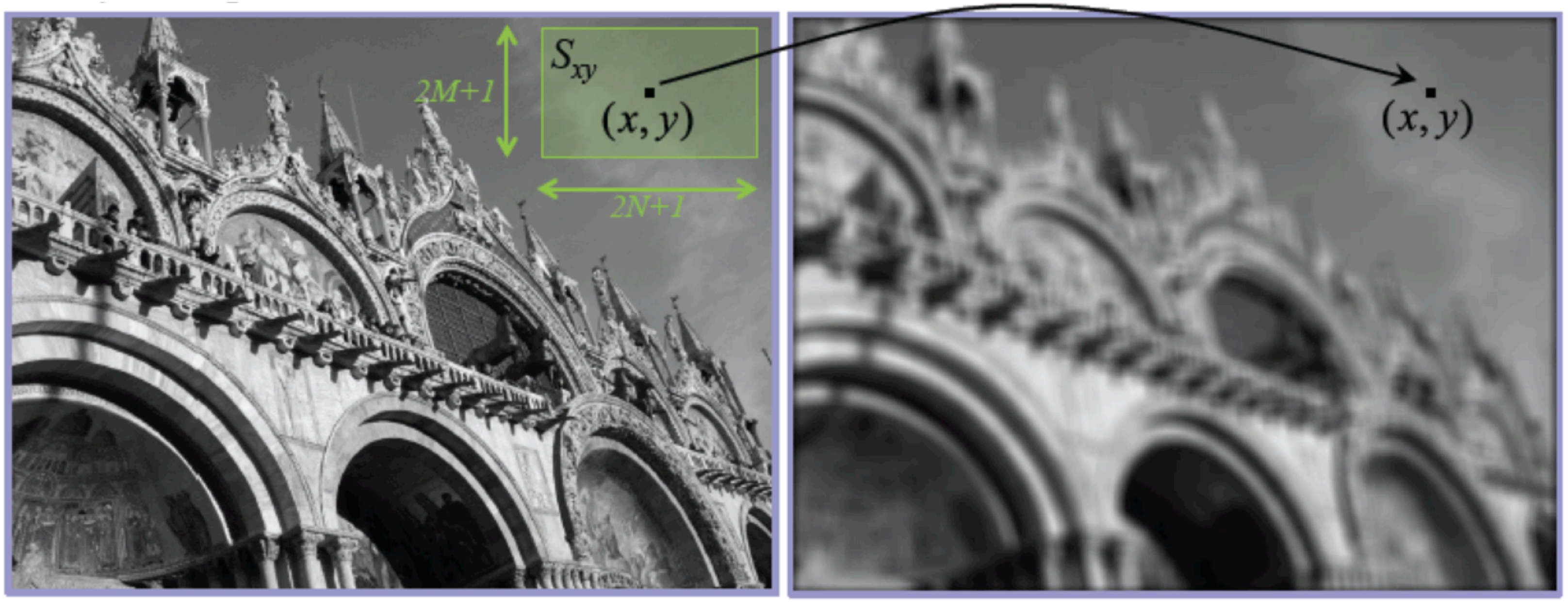


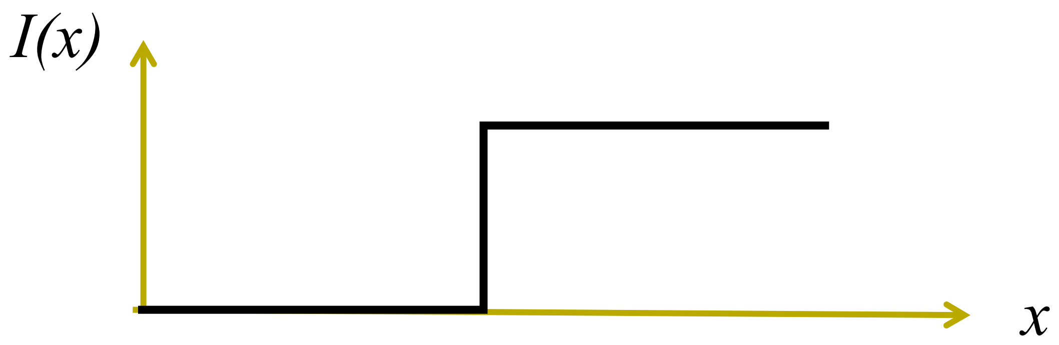
Image I

Filtered Image $J = F(I)$

$$J(x,y) = \frac{\sum_{(r,c)\in S_{xy}} I(r,c)}{(2M+1)(2N+1)}$$

Filtering

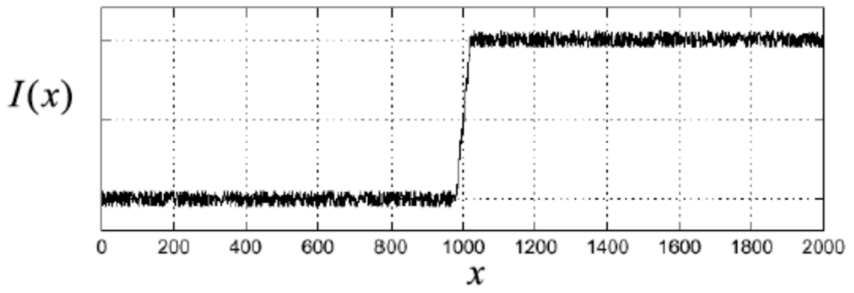
- Edge Detection
  - Edge = intensity discontinuity in one direction



  - First order derivative in 1D should be large
  - 2nd order derivative can also be used…

Filtering

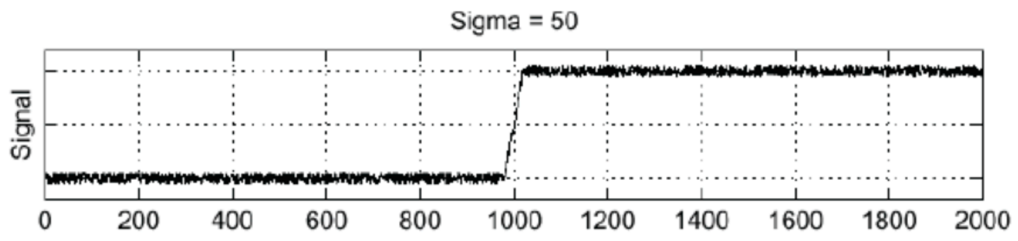
- Edge Detection
  - Actual image intensity might look more like this



Filtering

- Edge Detection

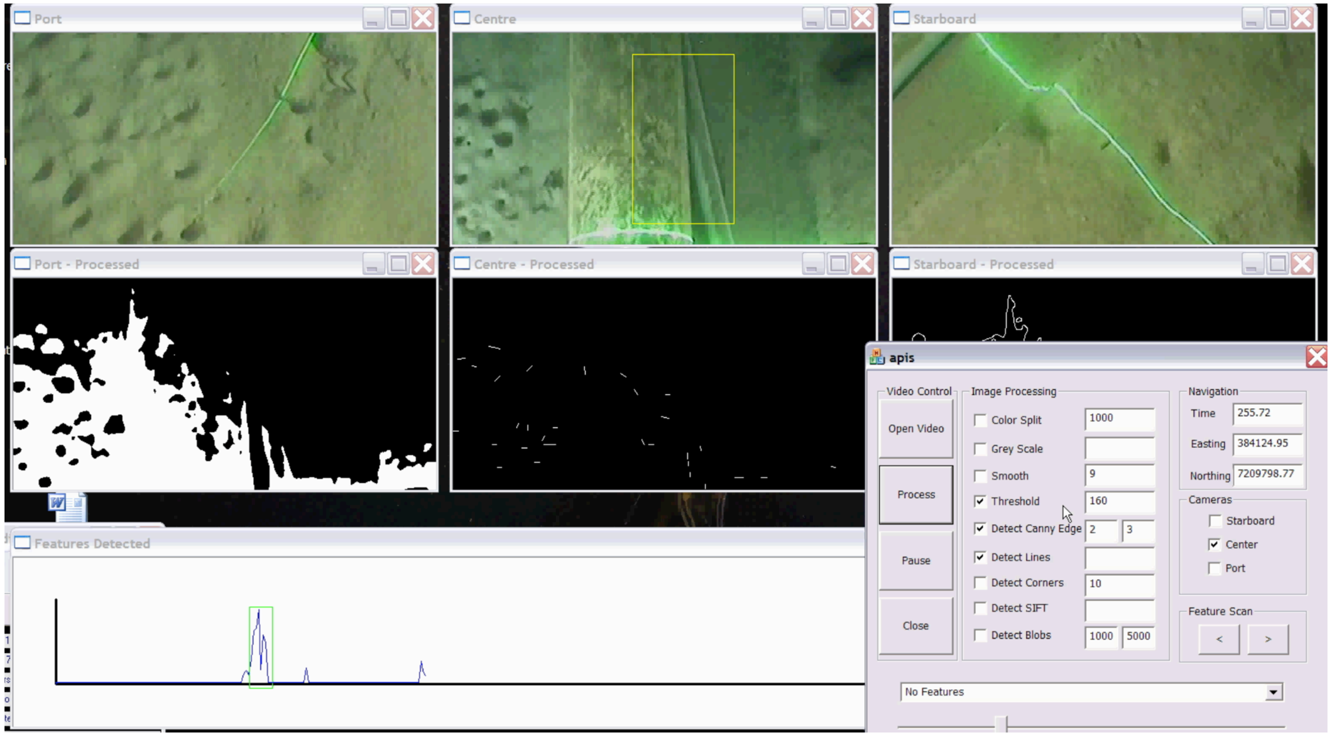
$I(x)$



Peak indicates Edge

Filtering

- Pipe Tracking Example



Video Control: Open Video, Process, Pause, Close

Image Processing

☐ Color Split	1000	
☐ Grey Scale		
☐ Smooth	9	
✓ Threshold	160	
✓ Detect Canny Edge	2	3
✓ Detect Lines		
☐ Detect Corners	10	
☐ Detect SIFT		
☐ Detect Blobs	1000	5000

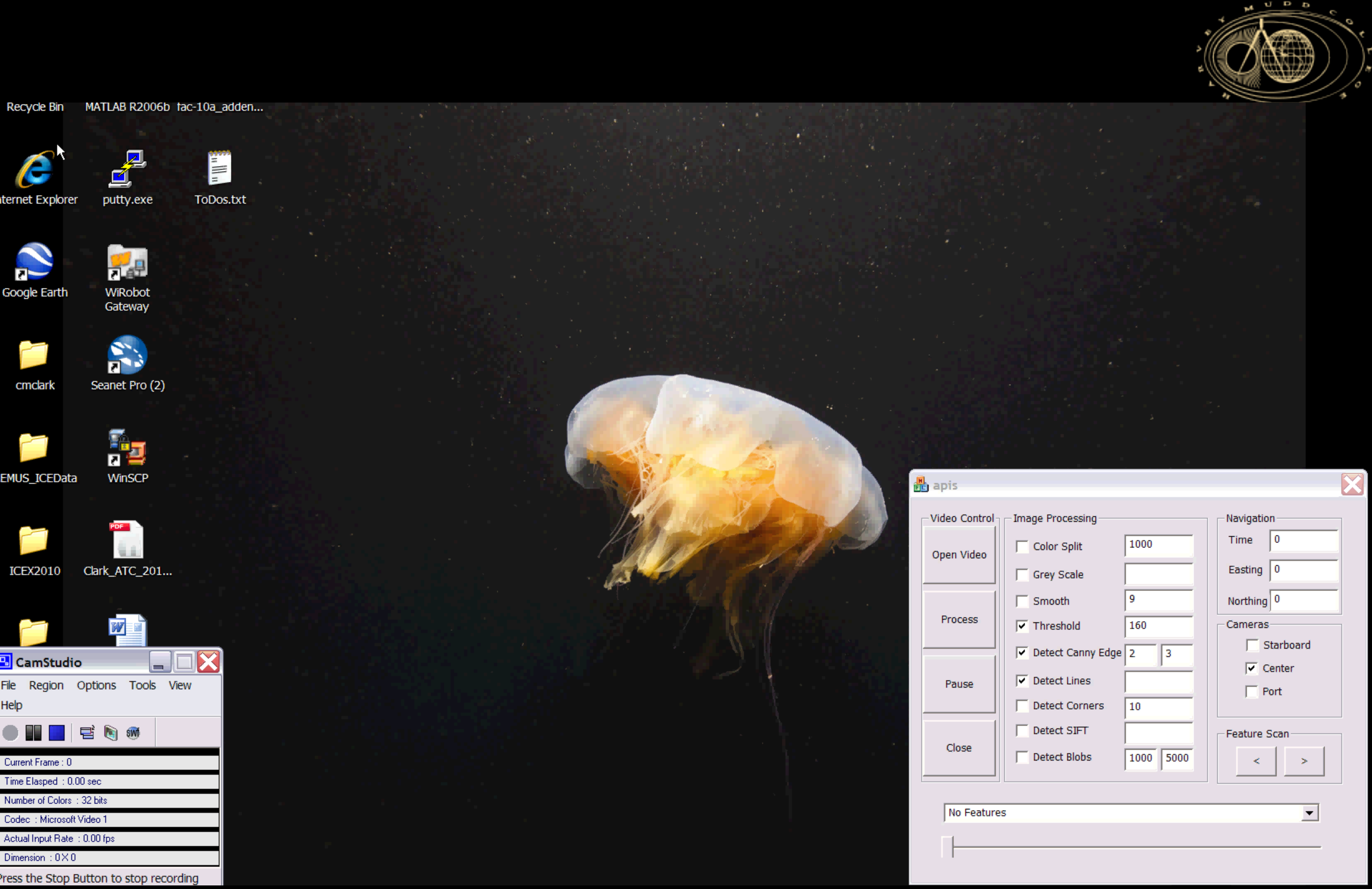
Navigation

Time	255.72
Easting	384124.95
Northing	7209798.77

Cameras: ☐ Starboard, ✓ Center, ☐ Port

Feature Scan: < >

No Features



CamStudio

Current Frame : 0

Time Elasped : 0.00 sec

Number of Colors : 32 bits

Codec : Microsoft Video 1

Actual Input Rate : 0.00 fps

Dimension : 0 X 0

ress the Stop Button to stop recording

apis

Video Control

Image Processing

☐ Color Split	1000
☐ Grey Scale	
☐ Smooth	9
✓ Threshold	160
✓ Detect Canny Edge	2 / 3
✓ Detect Lines	
☐ Detect Corners	10
☐ Detect SIFT	
☐ Detect Blobs	1000 / 5000

Navigation

Time	0
Easting	0
Northing	0

Cameras

☐ Starboard

✓ Center

☐ Port

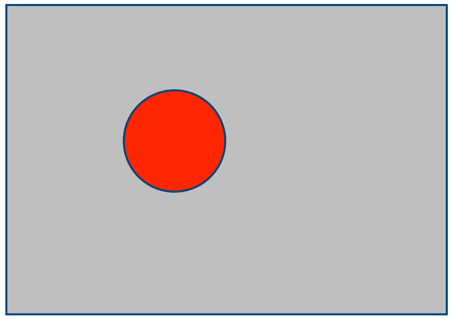
Feature Scan

No Features

Outline – Vision Systems

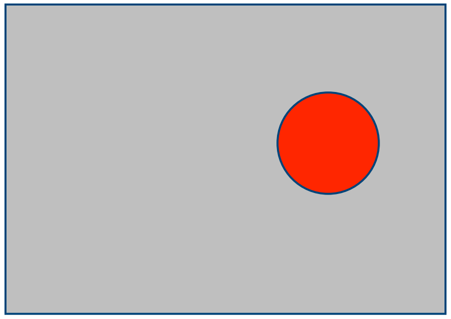
Sensors: Vision Systems

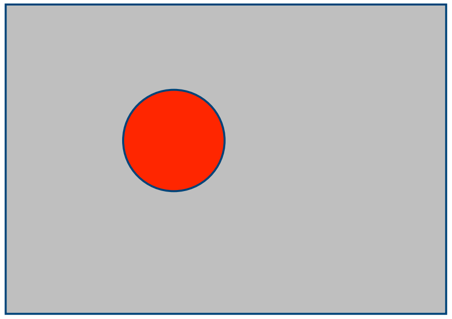
- Monocular Vision:
  - Problem with monocular vision is that you can't tell how far something is from the robot. No Range information!
  - Consider the following image of a red ball:

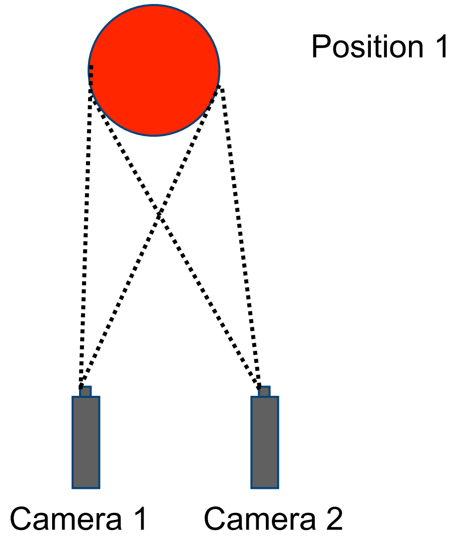


Sensors: Vision Systems

- Stereo Vision:
  - Using two cameras provides enough information to give us the range to the ball
  - The intersection of the two cones must be where the ball lies.

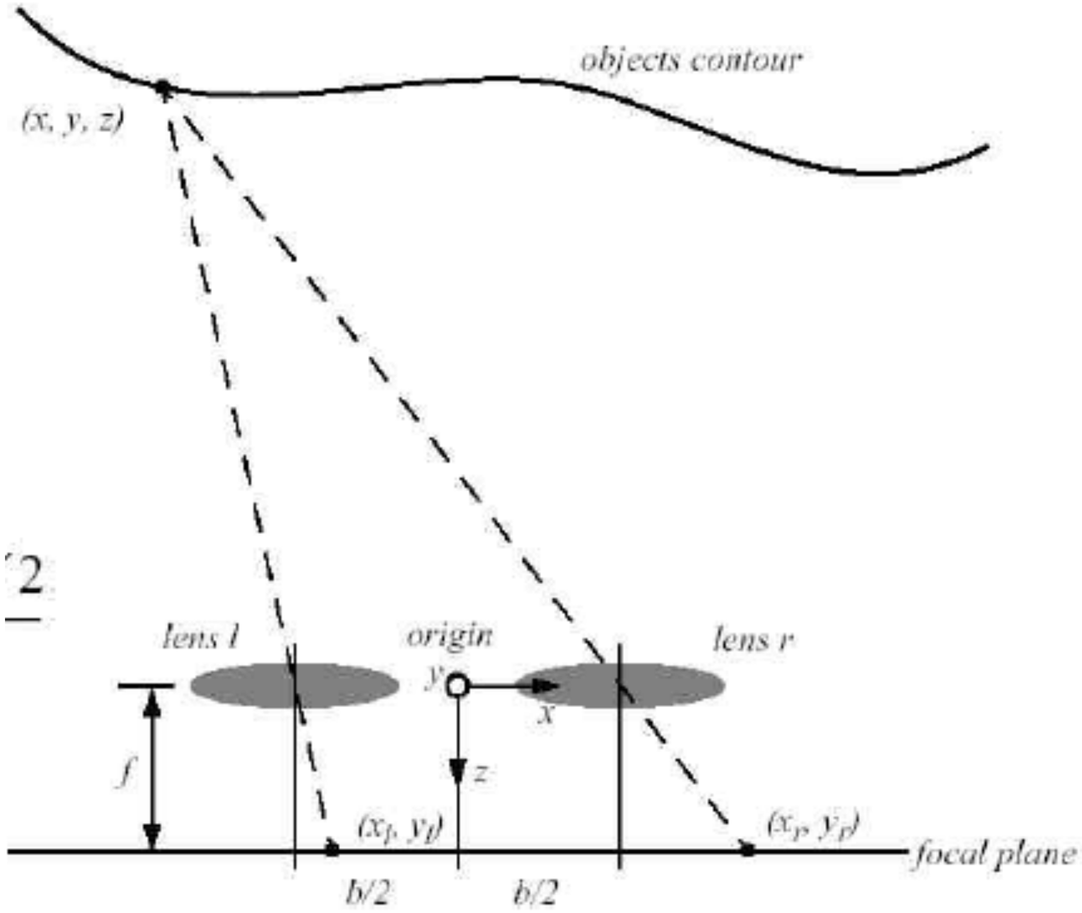

Camera 1 Image


Camera 2 Image



Sensors: Stereo Vision Systems

- Consider idealized camera geometry
- Compare projection of a target on 2 image planes.



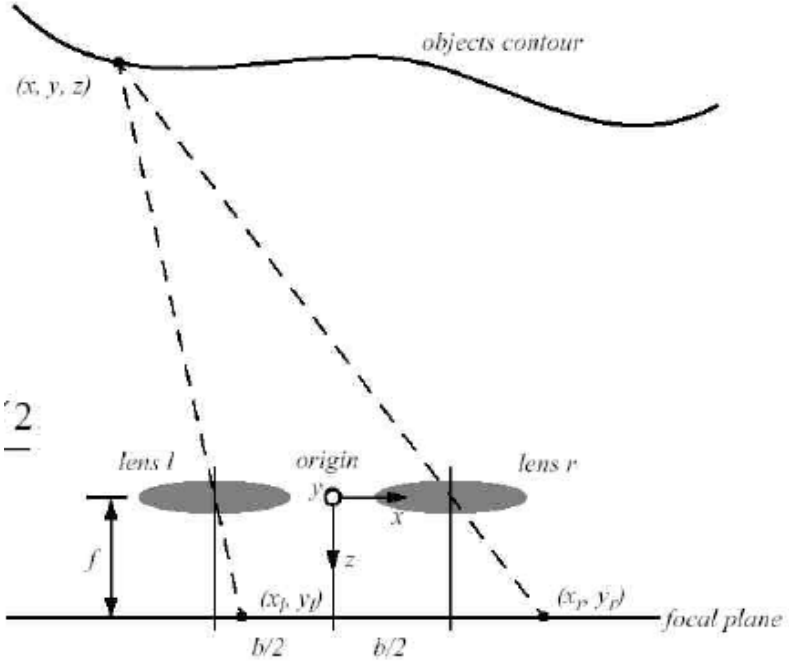
Sensors: Stereo Vision Systems

$$\frac{x_l}{f} = \frac{x+b/2}{z} \text{ and } \frac{x_r}{f} = \frac{x-b/2}{z}$$

$$\frac{x_l - x_r}{f} = \frac{b}{z}$$

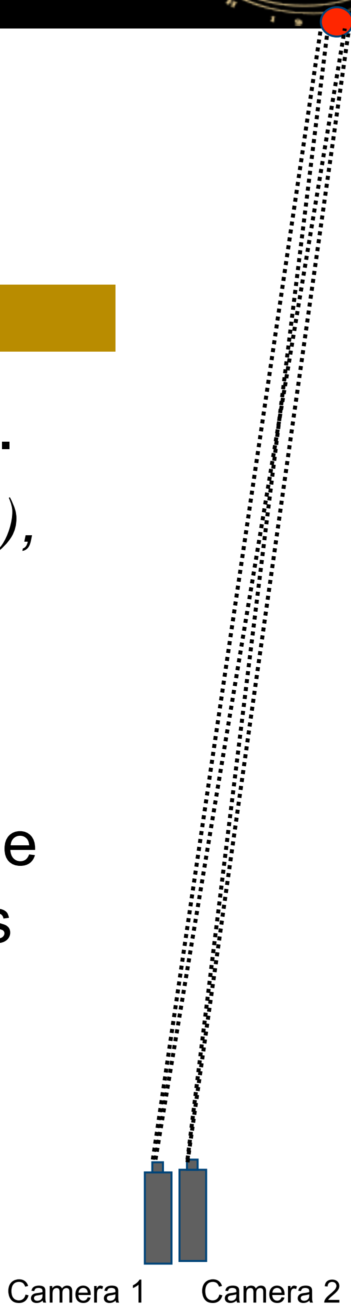
$$x = b\frac{(x_l+x_r)/2}{x_l-x_r} \; ; \; y = b\frac{(y_l+y_r)/2}{x_l-x_r}$$

$$z = b\frac{f}{x_l-x_r}$$



Sensors: Stereo Vision Systems

- There is poor accuracy on far objects.
  - Farther objects have less disparity $(x_l - x_r)$, making it difficult to get accurate depth measurements.
  - This is similar to having cameras colocated so that the object appears to be at the same position in both images. This ends up working like monocular vision



Sensors: Stereo Vision Systems

- Can we tell the difference between something *100* meters away and *101* meters away given our $f = 0.1m$ and $b = 0.5m$?
  - The disparity for $z = 100$ is $(0.1)(0.5)/100 = 0.0005$
  - The disparity for $z = 101$ is $(0.1)(0.5)/101 = 0.000495$
- How about the difference between something 10 meters away and 11 meters away?
  - The disparity for $z = 10$ is $(0.1)(0.5)/10 = 0.005$
  - The disparity for $z = 11$ is $(0.1)(0.5)/11 = 0.0045$
- We can see there is greater difference between the disparities when the object is close, so…
- Easier to get accurate range when the object is closer!

Sensors: Stereo Vision Systems

- Disparity is proportional to b

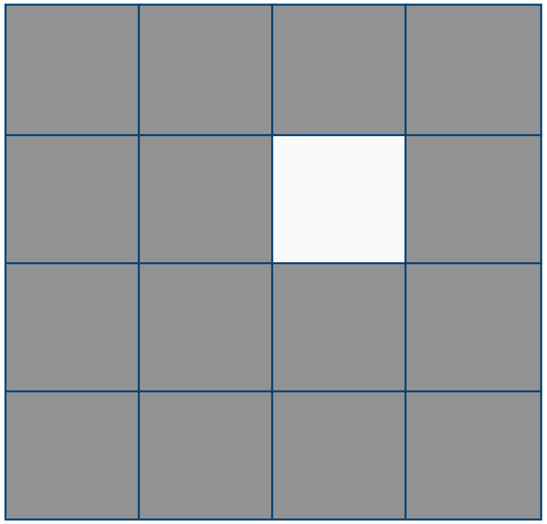
$$\frac{x_l - x_r}{f} = \frac{b}{z}$$

Sensors: Stereo Vision Systems

- We don’t always have red balls on gray backgrounds…
  - “Zero crossing of Laplacian of Gaussian (ZLoG) is widely used method of identifying feature from 2 images”

Sensors: Stereo Vision Systems

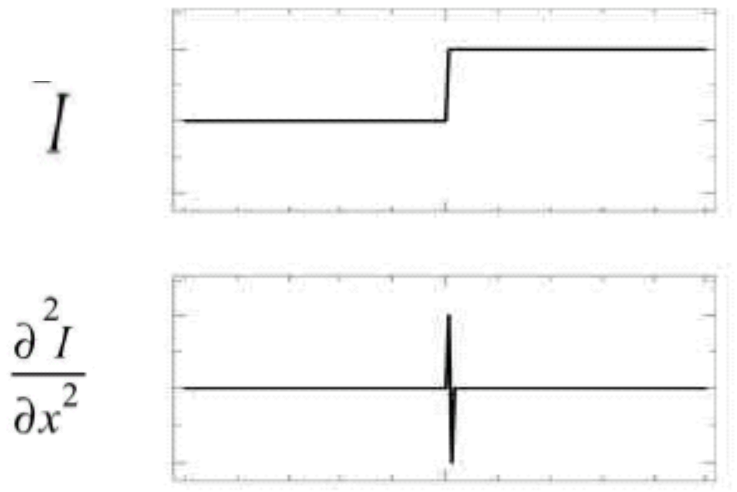
- Consider the 4x4 image:
  - $$I(i,j) = \begin{cases} 0.8 & \text{if } i=3, j=3 \\ 0.1 & \text{else} \end{cases}$$
  - Let's see how we can identify the bright spot



Sensors: Stereo Vision Systems

- ZLOG method finds features with high intensity contrast as measured by Laplacian.

$$L(x, y) = \frac{\partial^2 I}{\partial x^2} + \frac{\partial^2 I}{\partial y^2}$$



- The zero-crossing indicates a feature!

Sensors: Stereo Vision Systems

- To implement the Laplacian, an approximate function is used.
  - The convolution with P:

$$L = P \otimes I \qquad P = \begin{bmatrix} 0 & 1 & 0 \\ 1 & -4 & 1 \\ 0 & 1 & 0 \end{bmatrix}$$

  - That is, each pixel of L is made by summing over adjacent pixels:

$$L(i,j) = I(i-1, j) + I(i+1, j) + I(i, j-1) + I(i, j+1) - 4I(i, j)$$

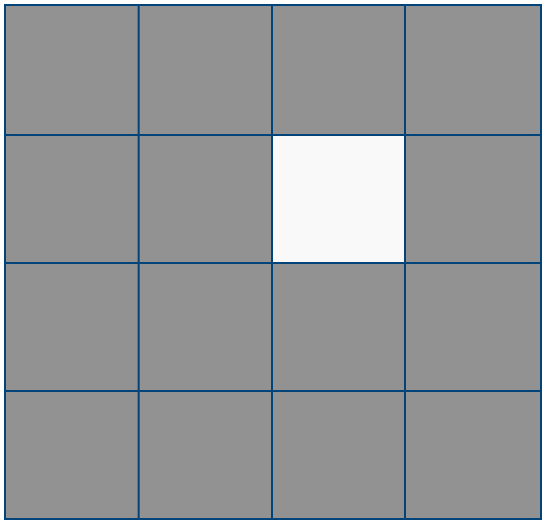
Sensors: Stereo Vision Systems

- Apply the Laplacian to our 4x4 image:

$$L(3,2) \quad = \quad 0.1 + 0.1 + 0.1 + 0.8 - 4\ (0.1) = +0.7$$

$$L(3,3) \quad = \quad 0.1 + 0.1 + 0.1 + 0.1 - 4\ (0.8) = -\ 2.8$$

$$\vdots$$



Sensors: Stereo Vision Systems

- Apply the Laplacian to our 4x4 image:

$$L(3,2) \quad = \quad 0.1 + 0.1 + 0.1 + 0.8 - 4\,(0.1) = +0.7$$

$$L(3,3) \quad = \quad 0.1 + 0.1 + 0.1 + 0.1 - 4\,(0.8) = -\,2.8$$

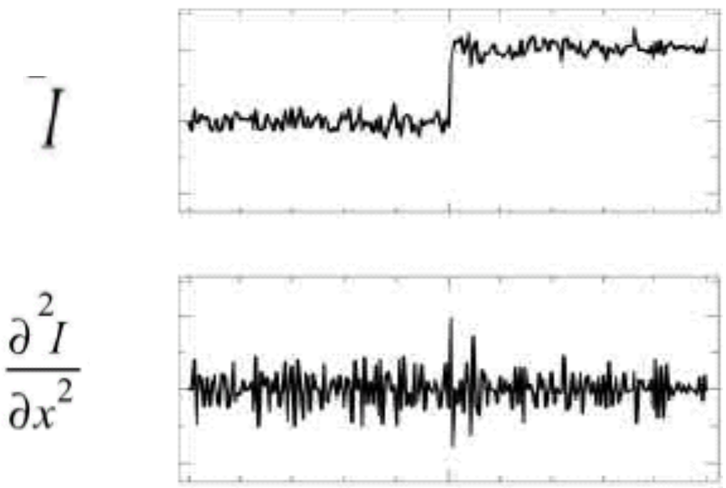
$$\vdots$$

0.0	0.0	0.7	0.0
0.0	0.7	-2.8	0.7
0.0	0.0	0.7	0.0
0.0	0.0	0.0	0.0

Zero crossing

Sensors:
Stereo Vision Systems

- There is a problem that noise makes it difficult to detect zero crossings.



- To deal with this we use a gaussian operator to smooth/blur the image.

Sensors: Stereo Vision Systems

- To deal with noise we use a gaussian operator to smooth/blur the image.

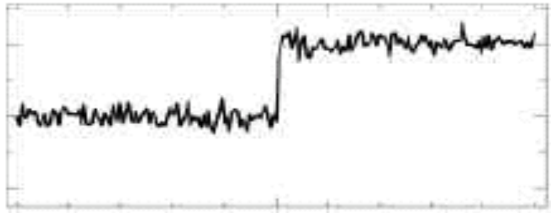
  - *filtering through Gaussian smoothing*

$$G = \begin{bmatrix} \frac{1}{16} & \frac{2}{16} & \frac{1}{16} \\ \frac{2}{16} & \frac{4}{16} & \frac{2}{16} \\ \frac{1}{16} & \frac{2}{16} & \frac{1}{16} \end{bmatrix}$$

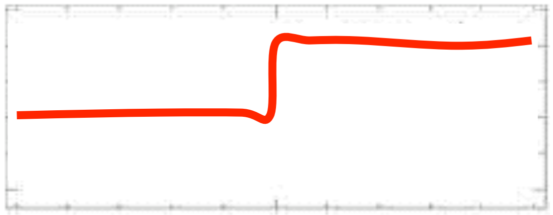
Sensors: Stereo Vision Systems

- The Gaussian operator looks like an operator that averages the pixel values
- This has the effect of smoothing the curve:

$\bar{I}$



$G \otimes I$



Sensors:
Stereo Vision Systems

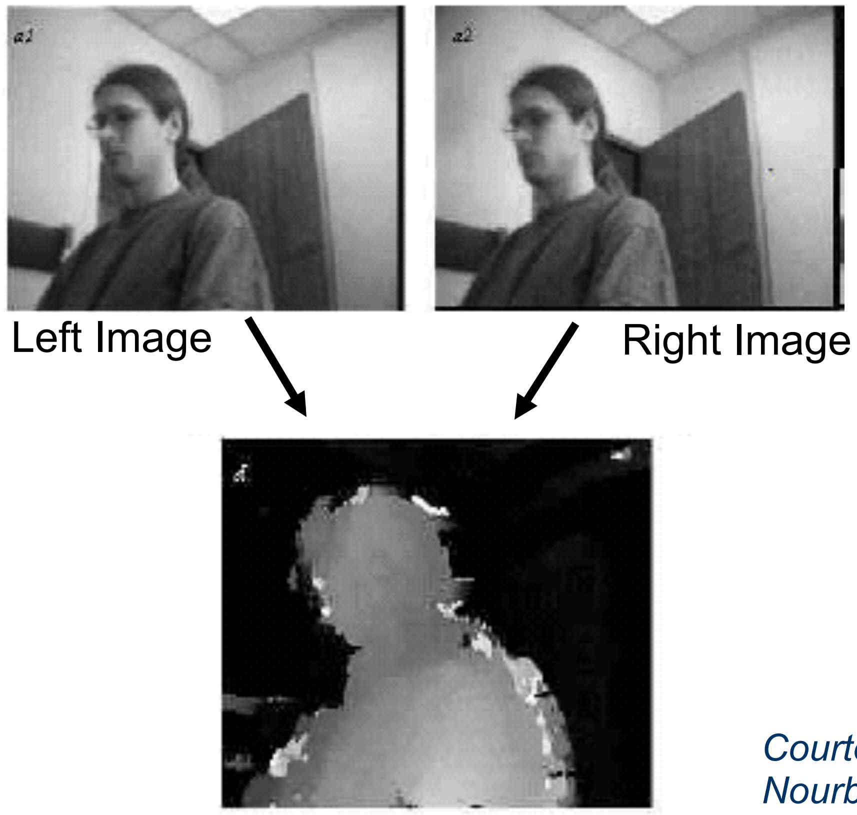
- Apply the Gaussian operator to the image will blur/smooth it so that zero-crossings will not occur simply due to noise.

Sensors: Stereo Vision Systems

- ZLog Method:
  1. Gaussian Filter
  2. Laplacian Filter
  3. Mark features as zero crossing
  4. Match features between images
  5. Use geometry to recover depth map

Sensors: Stereo Vision Systems

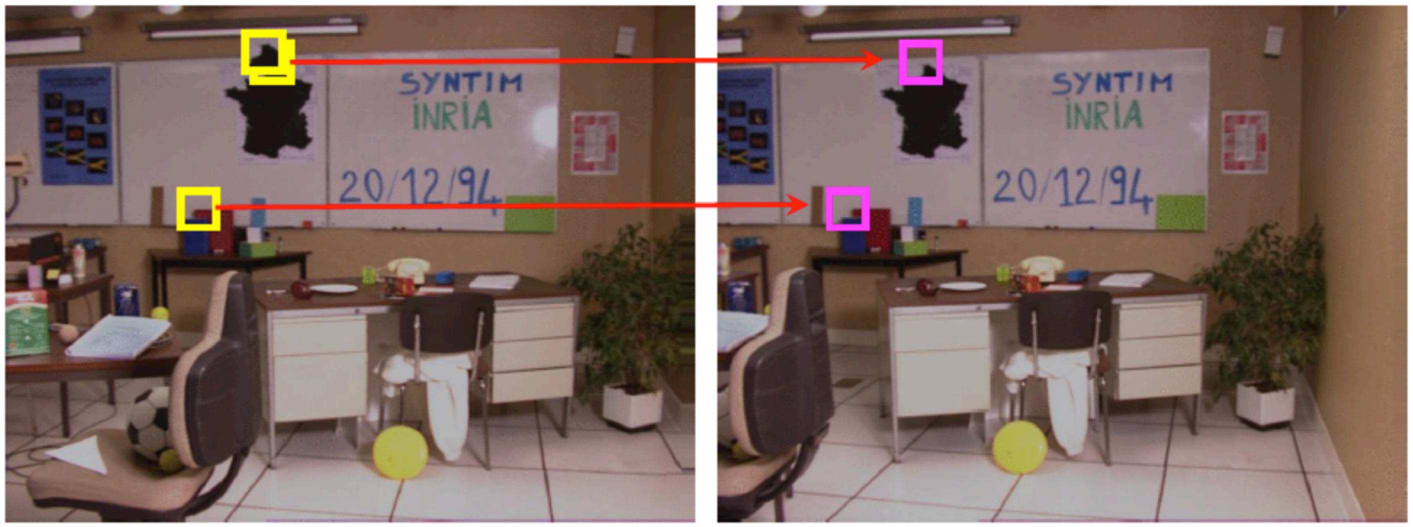
- ZLog Method Example:



Courtesy of Siegwart & Nourbakhsh

Sensors: Stereo Vision Systems

- Key issue is the correspondence problem
  - Identifying same feature from two cameras



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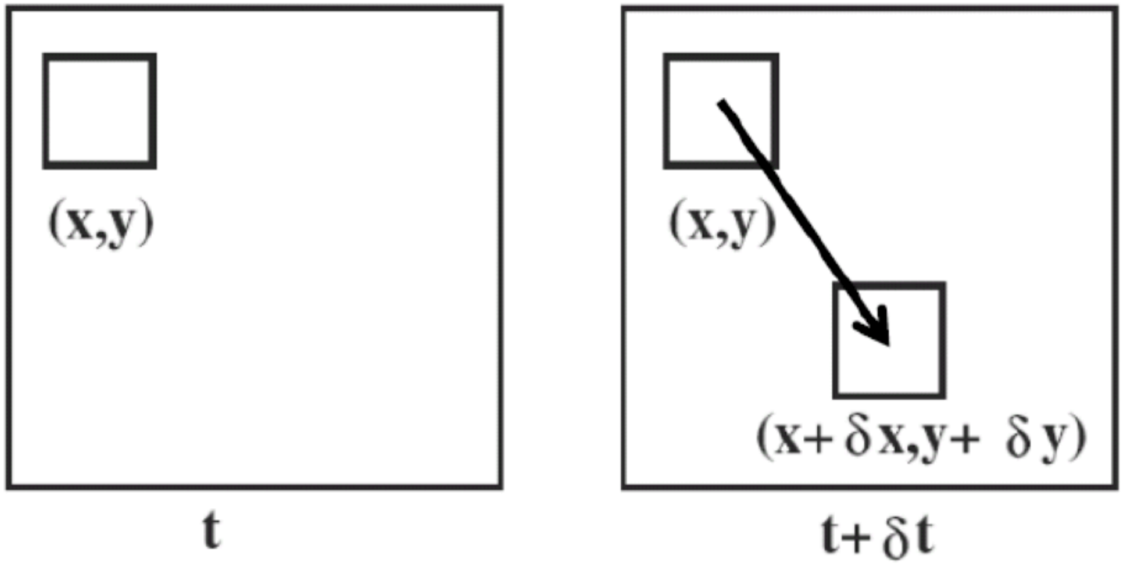
5. Color Tracking

Sensors: Optical Flow

- Motion Field
  - A velocity vector is assigned to every point in an image.
  - Given velocity of point in image, determine velocity of point in the environment.
- Optical Flow
  - Motion of brightness patterns in image.
  - Can be same motion as object motion.

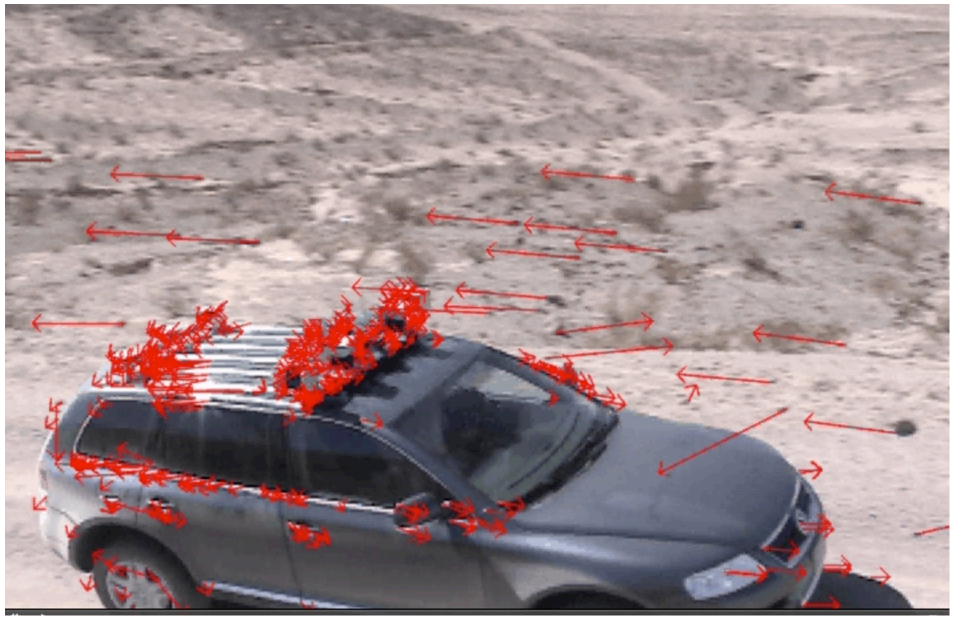
Sensors: Optical Flow

- Optical Flow
  - Computes the motion of all pixels in an image (or subsets of pixels)



Sensors: Optical Flow

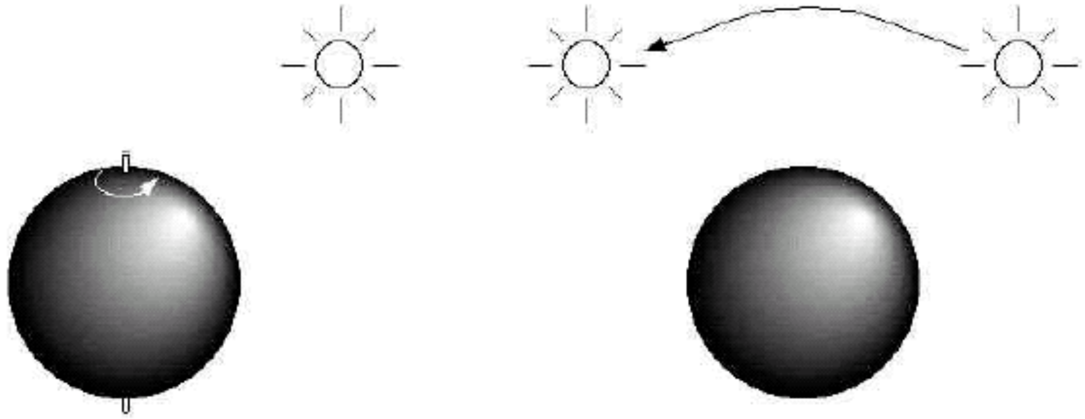
- Optical Flow



https://www.youtube.com/watch?v=ysGM3CfBVpU

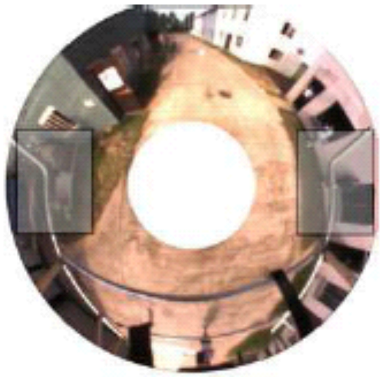
Sensors: Optical Flow

- Problem: with Optical Flow is not always same as motion field.
  - Occlusions lead to discontinuities
  - Moving Light sources
  - Symmetrical Shapes

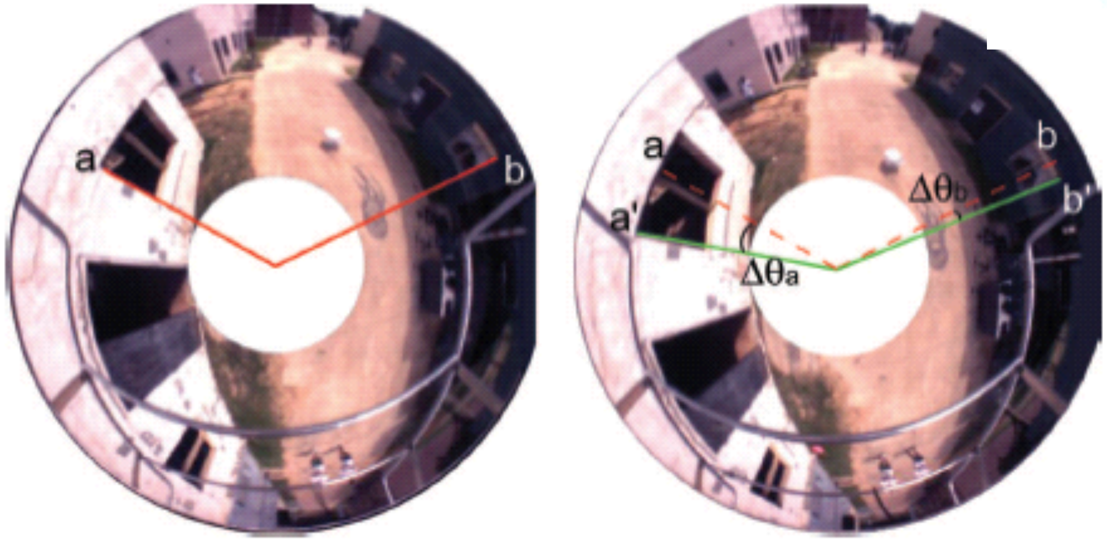


Sensors: Optical Flow for Ravine Navigation

Helicopter equipped with an OmniDirectional Camera



Regions used for optical flow calc's.



Courtesy of S. Hrabar and G. S. Sukhatme, USC

Outline – Vision Systems

1. Introduction
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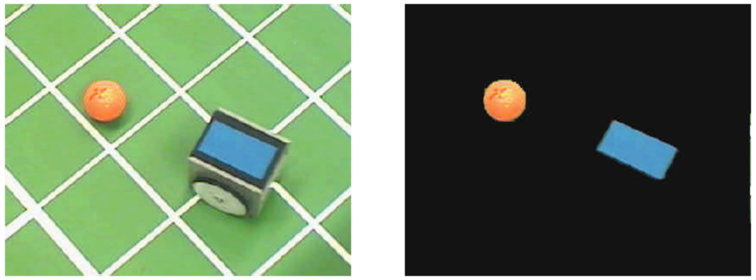
Sensors: Color Tracking

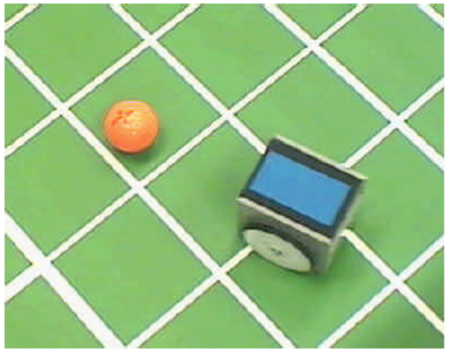
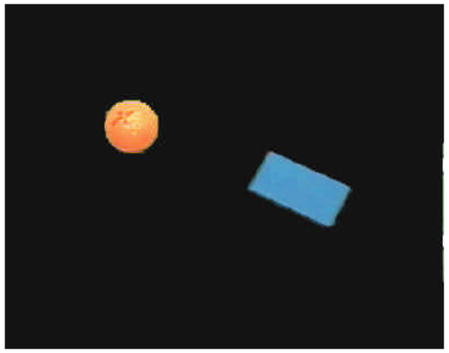
- Goal:
  - Given a color image, extract the pixels that have some specific color of interest.
  - Given the coordinates of these pixels, calculate the coloured object’s position in the robot frame.
  - E.g. How do we extract the ball and robot positions from the image below?



Courtesy of EPFL STeam

Sensors: Color Tracking

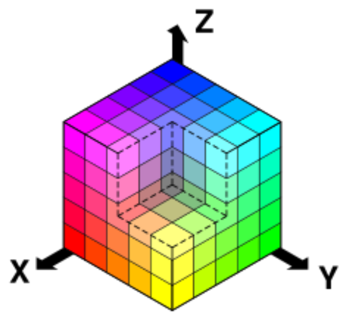
- We are given an R, G, and B value for every pixel in an image…
- Can we match these with some desired RGB values that correspond to the color of the ball and robot?

Courtesy of EPFL STeam

Sensors: Color Tracking

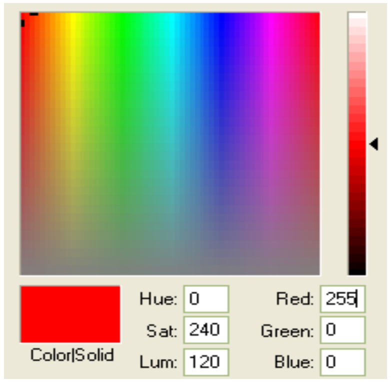
- RGB color representations assign a value from 0 to 255 to each of R, G, and B.
- These colors are additive to form white.
- Examples:
  - [0,0,255] is pure blue
  - [0,255,0] is pure green
  - [0,0,0] is black
  - [255,255,255] is white



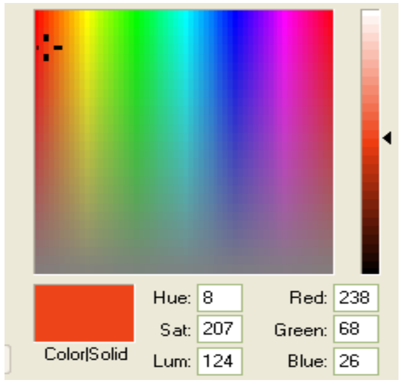
Courtesy of EPFL STeam

Sensors: Color Tracking

- Unfortunately, the RGB representation is not intuitive for measuring the closeness to a desired color.
  - E.g. what if we wanted to track a ball of color pure red - [255,0,0]?
  - We want to find all pixels that have values close to [255,0,0]
  - It is difficult to make good thresholds for any general color from which to accept as being close to our desired color.



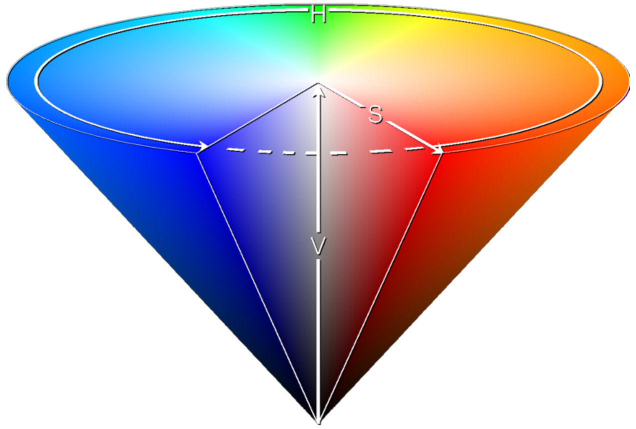
Hue: 0 Sat: 240 Lum: 120 Red: 255 Green: 0 Blue: 0



Hue: 8 Sat: 207 Lum: 124 Red: 238 Green: 68 Blue: 26

Sensors: Color Tracking

- HSV color representations are more intuitive for measuring closeness:
  - Hue
    - The “color type” (such as red, blue, or yellow):
    - Ranges from 0-360 (but normalized to 0-100% in some applications)
  - Saturation
    - The "vibrancy" or “purity”
    - Ranges from 0-100%
  - Value
    - The “brightness”
    - Ranges from 0-100%



Sensors: Color Tracking

- Method, for each pixel:
  - Convert to HSV color space
  - Determine if it is close to color being tracked by passing threshold for each parameter.
- Example:
  - To track pure red, H must belong to range [350, 10], S must belong to range [80,100], and V must belong to range [80,100].
  - Once all pixels that don’t meet threshold are thrown out, the locations of the remaining pixels can used to determine the relative position of the object being tracked.

Sensors:
Color Tracking

- MRS Example:
  - Convoy Search and Track mission

Overhead Vision Systems