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Semester Project

-

Map Fusion for Collaborative UAV SLAM

-

ETH zürich
V4RL VISION FOR ROBOTICS LAB
Autonomous Systems Lab

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SLAM	Simultaneous Localisation and Mapping.
UAV	Unmanned Aerial Vehicle.
KF	KeyFrame.
KFM	KeyFrame Match.
BA	Bundle Adjustment.
PGO	Pose Graph Optimization.
LM	Levenberg-Marquardt.
DL	Powell's dog leg.

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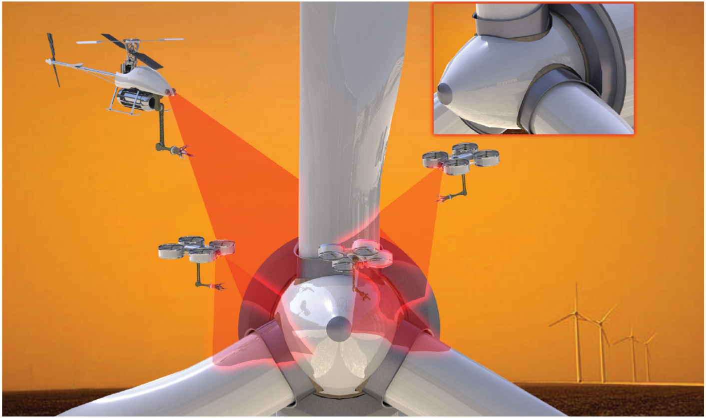

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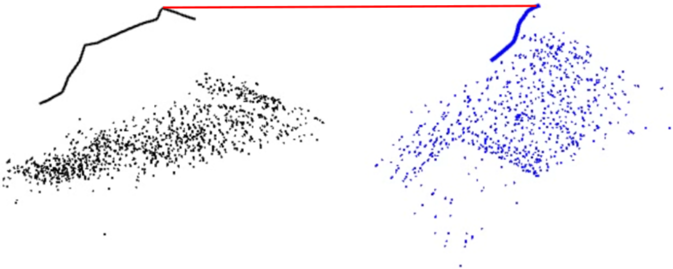

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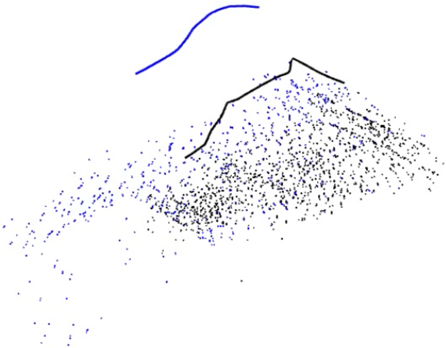

Introduction - What is a KeyFrame Match (KFM)?

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KeyFrames (KFs): The most “representative” poses

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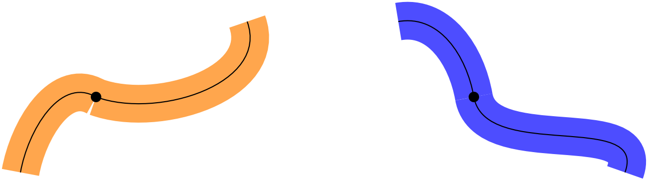
KeyFrames (KFs): The most “representative” poses

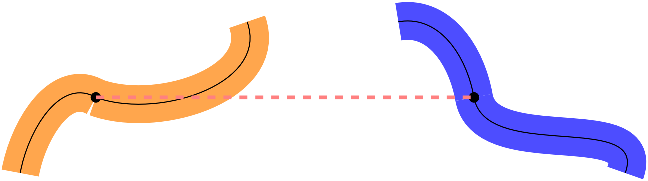
Two clients each with own landmarks and KeyFrames (KFs)



Introduction - What is a KeyFrame Match (KFM)?

KeyFrames (KFs): The most “representative” poses

KeyFrame Match (KFM): Two KeyFrames (KFs) observing the same location



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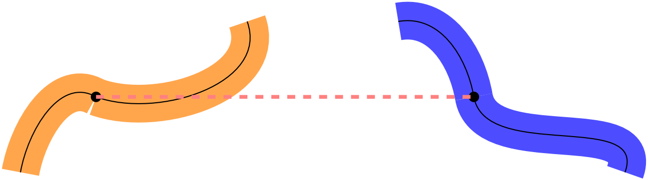
KeyFrames (KFs): The most “representative” poses

KeyFrame Match (KFM): Two KeyFrames (KFs) observing the same location $\rightarrow$ Can obtain transformation

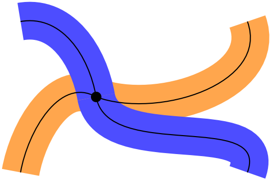


Introduction - What is a KeyFrame Match (KFM)?

KeyFrames (KFs): The most "representative" poses

KeyFrame Match (KFM): Two KeyFrames (KFs) observing the same location

With the transformation $\rightarrow$ maps can be aligned

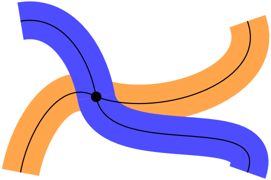


Introduction - What is a KeyFrame Match (KFM)?

KeyFrames (KFs): The most "representative" poses

A KeyFrame Match (KFM) contains:

- Two KeyFrames (KFs) (One per map)
- The transformation ($T \in \mathrm{Sim}(3)$) between them



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- A multi agent SLAM system based on ORB-SLAM2 should be extended

[Mur-Artal and Tardos, 2016]

Motivation

- A multi agent SLAM system based on ORB-SLAM2 should be extended
- So far, as soon as a KeyFrame Match (KFM) was detected, maps were merged

[Mur-Artal and Tardos, 2016]

Motivation

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- A multi agent SLAM system based on ORB-SLAM2 should be extended
- So far, as soon as a KeyFrame Match (KFM) was detected, maps were merged
- Using multiple KFMs to guarantee no false map merging

[Mur-Artal and Tardos, 2016]

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- A multi agent SLAM system based on ORB-SLAM2 should be extended
- So far, as soon as a KeyFrame Match (KFM) was detected, maps were merged
- Using multiple KFMs to guarantee no false map merging
- Using multiple KFMs to obtain an optimal map alignment

[Mur-Artal and Tardos, 2016]

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Map merging - Old approach

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Old approach:

- As soon as a KFM was detected, maps were merged

Map merging - New approach

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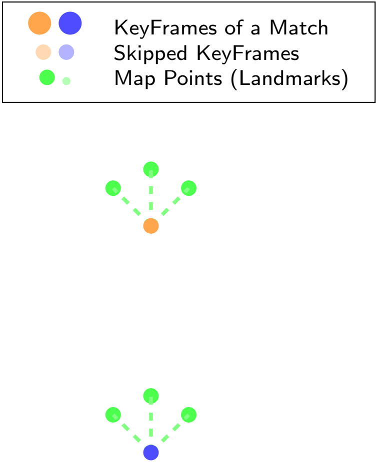
Find $n(=3)$ KeyFrame Matches (KFMs)



Map merging - New approach

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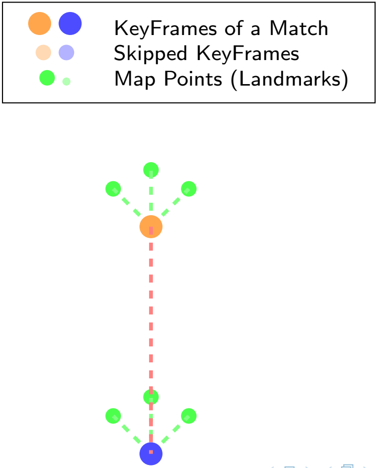
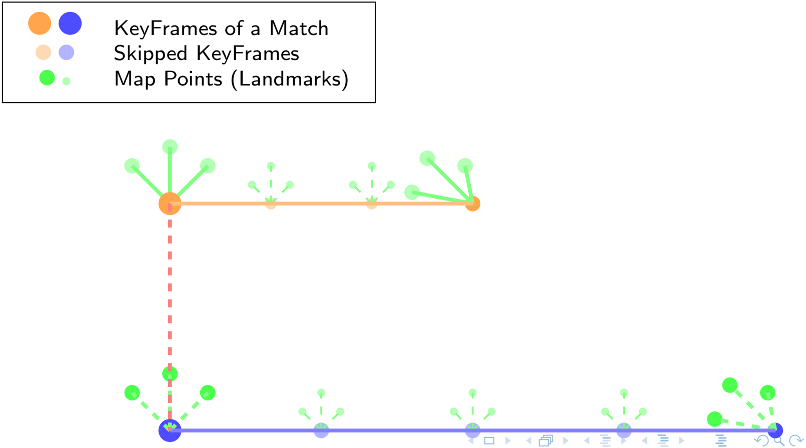
Find $n(=3)$ KeyFrame Matches (KFMs),
Skip $m(=5)$ KeyFrames (KFs)



Map merging - New approach

Find $n(=3)$ KeyFrame Matches (KFMs),
Skip $m(=5)$ KeyFrames (KFs)



Map merging - New approach

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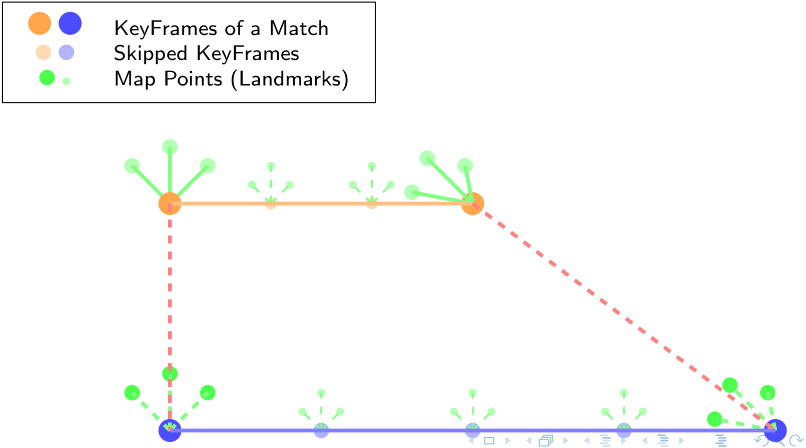

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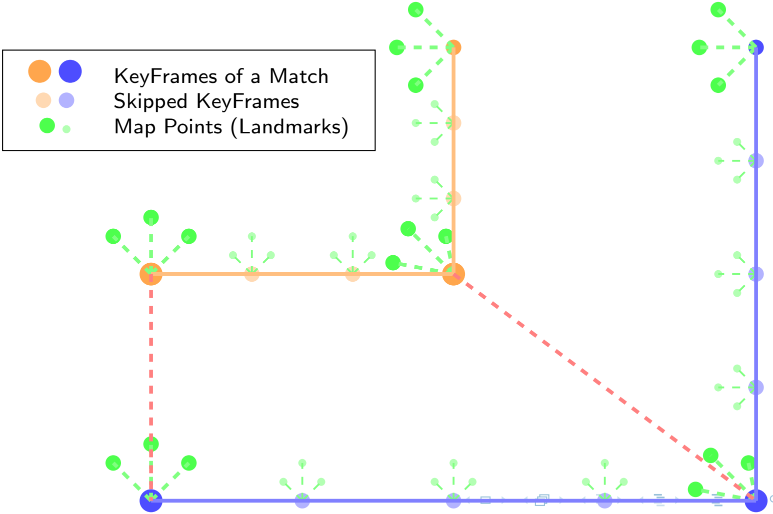
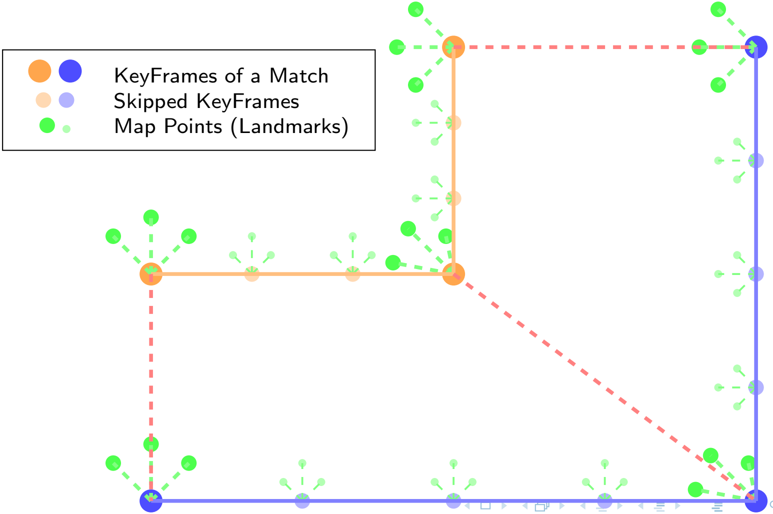


Map merging - New approach

Find $n(=3)$ KeyFrame Matches (KFMs)



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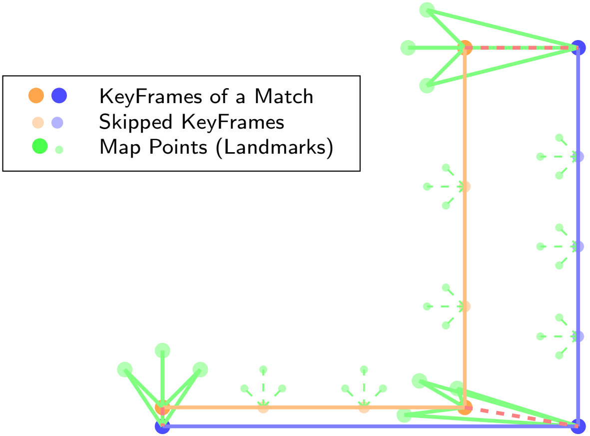
Merge the two maps and fuse map points



Map merging - Results - skipping of KeyFrame (KF)

Co-visibility graph

Connections/Edges between KeyFrames (KFs) which observe the same map points (landmarks)

Map merging - Results - skipping of KF

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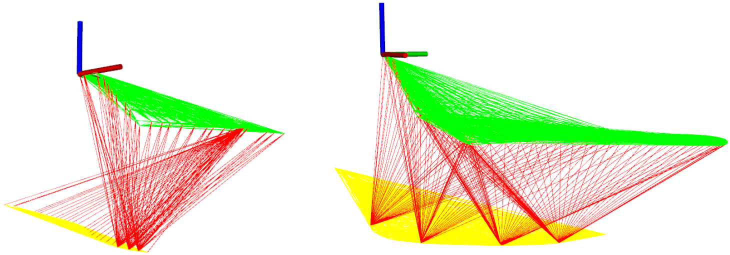
green: Covisibility graph of first map
yellow: Covisibility graph of second map
red: Covisibility between the KFMs



(a) 1 KF skipped after a KFM was found

(b) 10 KF skipped after a KFM was found

Map merging - Results - Reduction of drift

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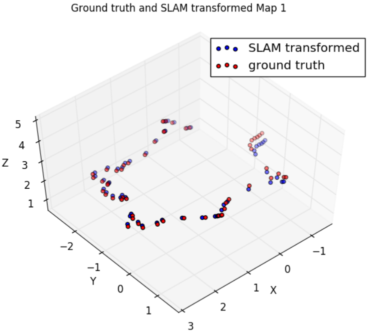
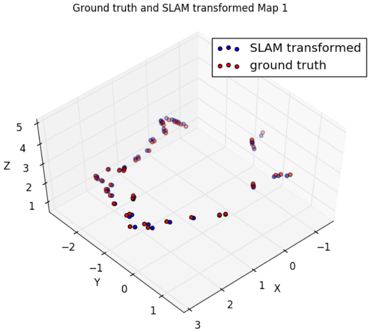


(a) original approach



(b) new approach

Reduction of the error from rmse $= 0.13\text{m}$ to rmse $= 0.10\text{m}$

Map merging - Results

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# KFMs	# KFs skip	rmse
1	0	0.1311
5	20	0.0912
10	5	0.1236
10	10	0.0961

Table: Error (rmse) of different settings (KFMs and KF skipps).

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Culling - Remove redundant KF

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Motivation

Perform KeyFrame (KF) culling to remove redundant information as bundle adjustment complexity grows with the number of KFs
[Mur-Artal et al., 2015]

Culling - Remove redundant KF

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- Remove redundant KFs before map merging

Culling - Remove redundant KF

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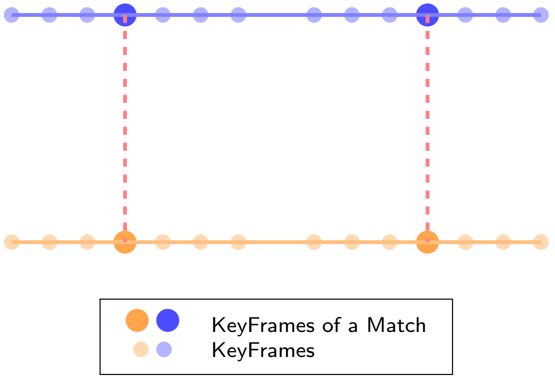
- Remove redundant KFs before map merging
- Performs culling for every KFM separately

Culling - Remove redundant KF

- Remove redundant KFs before map merging
- Performs culling for every KFM separately



Culling - Remove redundant KF

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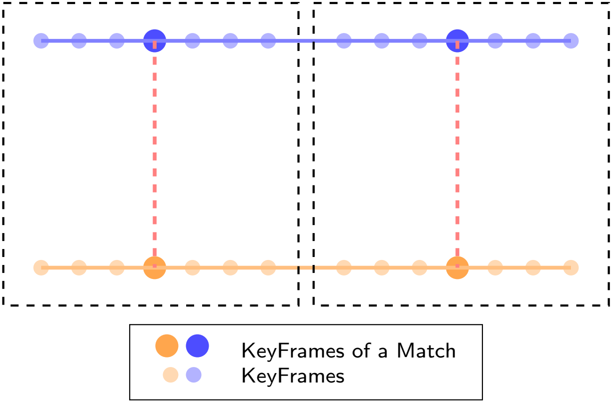

Culling - Remove redundant KF

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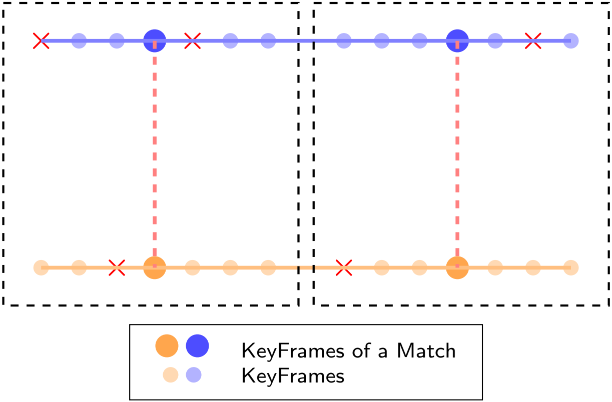

Culling - Results

Pose Graph Optimization (PGO)
Bundle Adjustment (BA)
v / e: numbers of verteces / edges of the graph to optimize

Culling	# KFMs	# KFs skip	PGO v / e	BA v / e
No	1	0	59 / 754	2308 / 22193
Yes	1	0	36 / 283	1893 / 13222
No	10	10	150 / 1949	4806 / 49765
Yes	10	10	93 / 657	4165 / 30453

Table: Time measurements of Pose Graph Optimization (PGO) and Bundle Adjustment (BA) without and with culling.

Culling - Results

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Culling removes $\approx 13\%$ of the KeyFrames (KFs)

Pose Graph Optimization (PGO)
Bundle Adjustment (BA)

Culling - Results

Culling removes $\approx 13\%$ of the KeyFrames (KFs)

Culling	# KFMs	# KFs skipped	PGO [ms]	BA [ms]
No	10	10	532.28	3659.48
Yes	10	10	178.83	1098.37

Table: Time measurements of PGO and BA without and with culling.

Pose Graph Optimization (PGO)
Bundle Adjustment (BA)

Culling - Results

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Culling removes $\approx 13\%$ of the KeyFrames (KFs)

Culling	# KFMs	# KFs skipped	PGO [ms]	BA [ms]
No	10	10	532.28	3659.48
Yes	10	10	178.83	1098.37

Table: Time measurements of PGO and BA without and with culling.

Performance increases significantly when culling is enabled

Pose Graph Optimization (PGO)
Bundle Adjustment (BA)

Culling - Results

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Culling	# KFMs	# KFs skipped	*rmse* [m]
No	1	0	0.1311
Yes	1	0	0.2187
No	10	10	0.0961
Yes	10	10	0.0965

Table: *rmse* without and with culling.

Culling - Results

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Culling	# KFMs	# KFs skipped	*rmse* [m]
No	1	0	0.1311
Yes	1	0	0.2187
No	10	10	0.0961
Yes	10	10	0.0965

Table: *rmse* without and with culling.

Accuracy gets worse if not enough information is available.
No problem with multiple KeyFrame Matches (KFMs).

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Optimization - Idea

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Considerable computational benefits can be gained by substituting the Levenberg-Marquardt (LM) algorithm in the implementation of Bundle Adjustment (BA) with a variant of Powell's dog leg (DL) non-linear least squares technique [Lourakis and Argyros, 2005]

Optimization - Idea

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DL optimizer handles trust region differently

Optimization - LM

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The Levenberg-Marquardt (LM) solves iteratively

$$(\mathbf{J}^T\mathbf{J} + \lambda\mathbf{I})\delta = \mathbf{J}^T\boldsymbol{\epsilon}, \text{ where } \boldsymbol{\epsilon} = [\mathbf{y} - \mathbf{f}(\boldsymbol{\beta})]$$

Optimization - LM

The LM solves iteratively

$$(\mathbf{J}^T\mathbf{J} + \lambda\mathbf{I})\delta = \mathbf{J}^T\boldsymbol{\epsilon}, \text{ where } \boldsymbol{\epsilon} = [\mathbf{y} - \mathbf{f}(\boldsymbol{\beta})]$$

- With a small λ LM becomes a Gauss-Newton method

Optimization - LM

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The LM solves iteratively

$$(\mathbf{J}^T\mathbf{J} + \lambda\mathbf{I})\delta = \mathbf{J}^T\boldsymbol{\epsilon}, \text{ where } \boldsymbol{\epsilon} = [\mathbf{y} - \mathbf{f}(\boldsymbol{\beta})]$$

- With a small λ LM becomes a Gauss-Newton method
- With a big λ LM behaves like a Gradient-descent method

Optimization - LM

The LM solves iteratively

$$(\mathbf{J}^T\mathbf{J} + \lambda\mathbf{I})\delta = \mathbf{J}^T\boldsymbol{\epsilon}, \text{ where } \boldsymbol{\epsilon} = [\mathbf{y} - \mathbf{f}(\boldsymbol{\beta})]$$

- With a small λ LM becomes a Gauss-Newton method
- With a big λ LM behaves like a Gradient-descent method
- If an update doesn't reduce the error, λ will be increased and the equation must be solved again

Optimization - DL

The Powell's dog leg (DL) solves iteratively

$$\min_{\delta} 2(\frac{1}{2}\boldsymbol{\epsilon}^T\boldsymbol{\epsilon} - (\mathbf{J}\boldsymbol{\epsilon})^T\delta + \frac{1}{2}\delta^T\mathbf{J}^T\mathbf{J}\delta), \text{ subjected to } ||\delta|| \leq \Delta$$

For $\kappa \in [0, 2]$, the dog leg trajectory is defined as

$$\delta(\kappa) = \begin{cases} \kappa\delta_{gd} & 0 \leq \kappa \leq 1 \\ \delta_{gd} + (\kappa - 1)(\delta_{gn} - \delta_{gd}) & 1 \leq \kappa \leq 2 \end{cases}$$

Optimization - DL

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With

$$\delta_{gd} = \frac{\mathbf{g}^T\mathbf{g}}{\mathbf{g}^T\mathbf{J}^T\mathbf{J}\mathbf{g}}\mathbf{g}$$

and δ_{gn} the solution of

$$\mathbf{J}^T\mathbf{J}\delta_{gn} = \mathbf{g}$$

the dog leg trajectory looks like

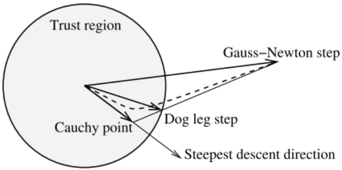

Figure from [Lourakis and Argyros, 2005]

Optimization - DL

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- Once the Gauss-Newton step has been determined, the DL algorithm can solve the subproblem for various Δ without resolving an equation

Optimization - DL

- Once the Gauss-Newton step has been determined, the DL algorithm can solve the subproblem for various Δ without resolving an equation
- Reducing the number of times the Gauss-Newton step has to be determined is crucial for the overall performance of the minimization process

Optimization - DL

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- Once the Gauss-Newton step has been determined, the DL algorithm can solve the subproblem for various Δ without resolving an equation
- Reducing the number of times the Gauss-Newton step has to be determined is crucial for the overall performance of the minimization process
- For the mentioned reasons the DL algorithm requires less computational effort compared to the LM algorithm

Optimization - Approach

- Tried Pose Graph Optimization (PGO) and Bundle Adjustment (BA) with the Powell's dog leg (DL) optimizer

Optimization - Approach

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LM optimizer for PGO and DL optimizer for BA

Optimization - Results

Opt.	# KFMs	# KFs skipped	PGO [ms]	BA [ms]
LM/LM	10	10	178.83	1098.37
LM/DL	10	10	178.70	383.54

Table: Time measurements of LM and DL optimizer.

Pose Graph Optimization (PGO)
Bundle Adjustment (BA)

Optimization - Results

Opt.	# KFMs	# KFs skipped	PGO [ms]	BA [ms]
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Accuracy stays the same while the performance is increased

Pose Graph Optimization (PGO)
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Conclusion

- Multiple KFMs approach increases accuracy

Conclusion

- Multiple KFMs approach increases accuracy
- Skipping of KFs spreads KFMs over a bigger area

Conclusion

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Higher accuracy

The use of KFMs from a bigger area serves PGO and BA with more information $\rightarrow$ higher accuracy

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Higher accuracy

The use of KFMs from a bigger area serves PGO and BA with more information → higher accuracy

- Culling removes redundant KFs → improved timing

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Higher accuracy

The use of KFMs from a bigger area serves PGO and BA with more information → higher accuracy

- Culling removes redundant KFs → improved timing
- Using DL optimizer for the BA also improves timing

Conclusion

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Higher accuracy

The use of KFMs from a bigger area serves PGO and BA with more information $\rightarrow$ higher accuracy

Better timing

Culling and the use of the DL optimizer improves timing

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Outlook & Limitation

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Outlook:

- Heuristic for best map alignment
- Extend area for KF culling

Limitation:

- # of KFMs and # of skips depends on data set

Outlook & Limitation

Outlook:

- Heuristic for best map alignment
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