Augmented reality on your knees

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Seminar by Nikita Ligostaev

What a heck why AR?

Web-camera is a sensor by construction, image formation is crucial for any kind of visualization.
We will consider very basic principles of linear algebra used in computer vision without going into details.
AR is just a straightforward application for today's seminar.
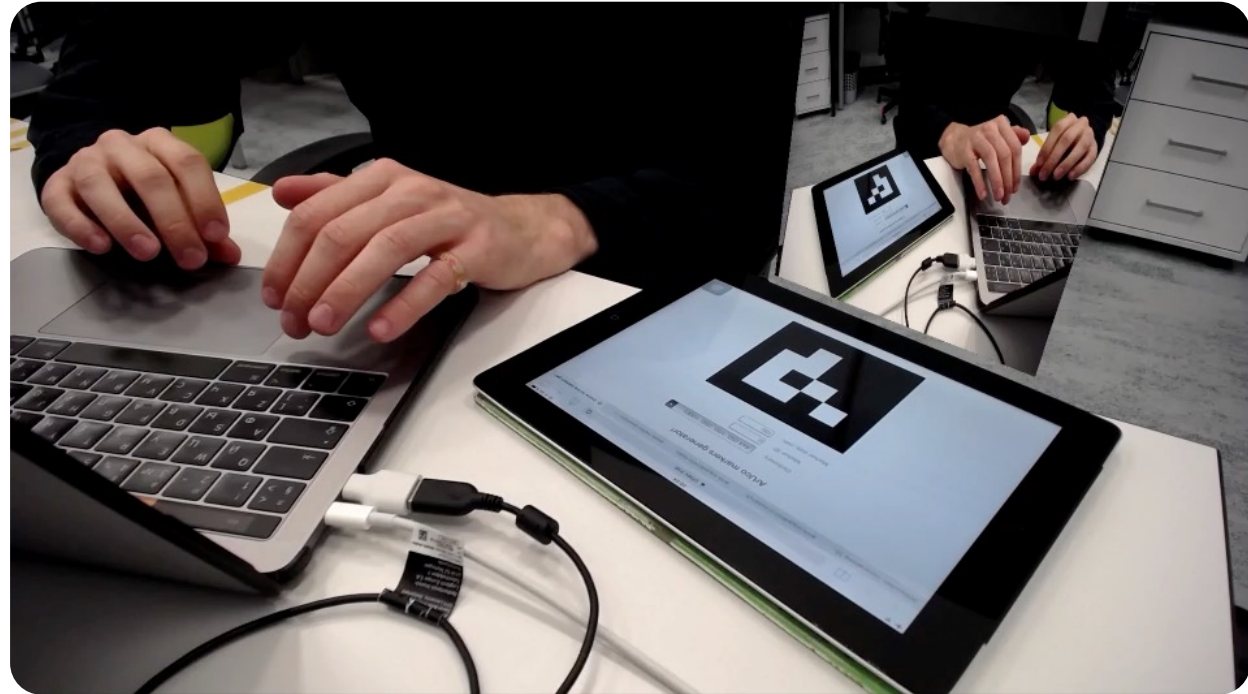
⚠️

By the end of the seminar you will be able to use monocular camera for projection of anything in the camera frame.
Hopefully, it will be useful for common understanding and your research (in ideal case).
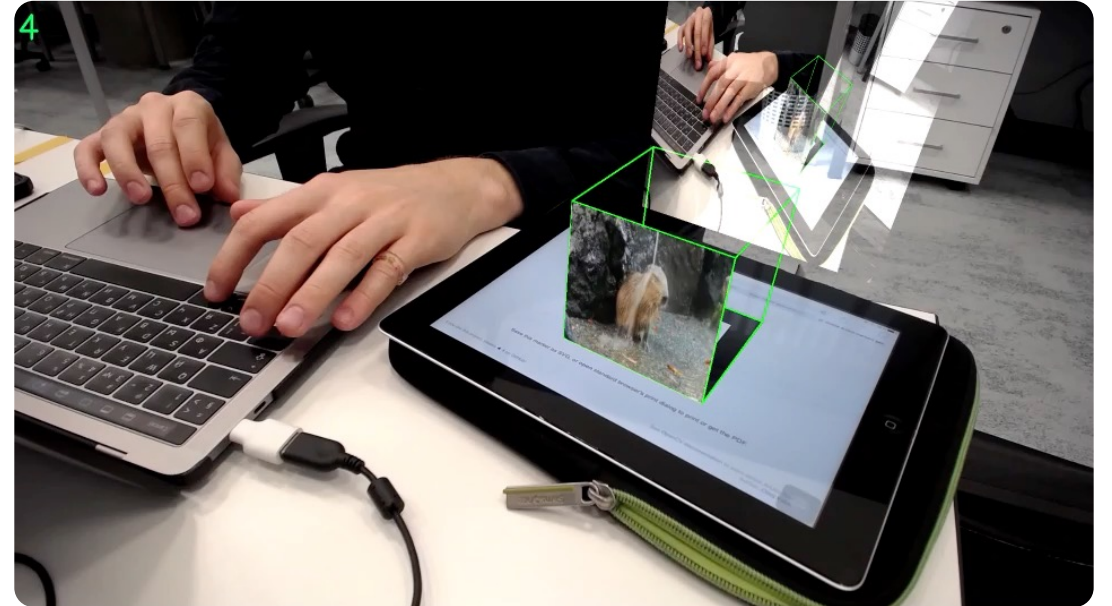
⚠️ Spoilers for seminar

numero uno

Web-camera feed projection on the plane
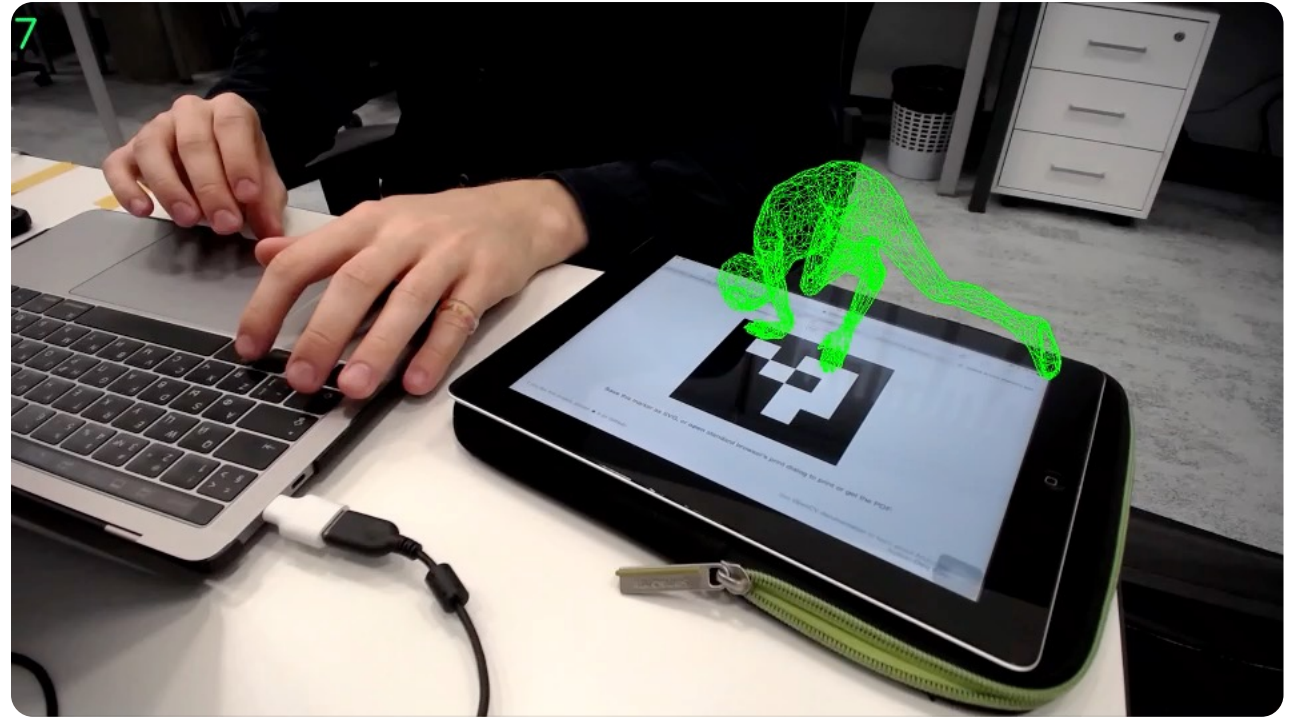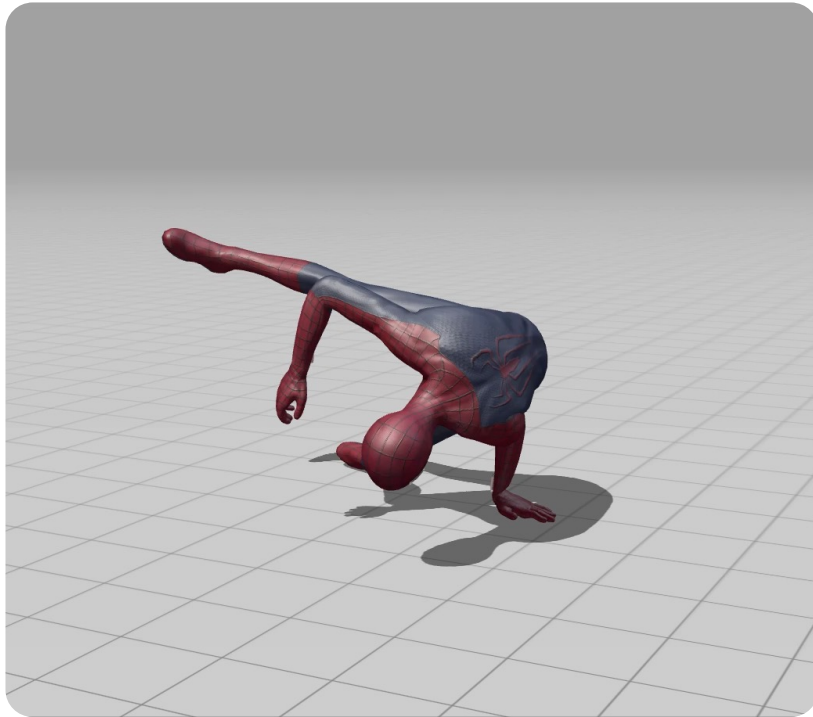
⚠️ Spoilers for homework

numero due

Video projection on the cube plane
and web-camera feed projection functionality

03

⚠️ Spoilers for bonus

numero tre

Animated .obj model projection

Instructions

All tasks and their description are available in Github repository (the same repository you used for conda setup)

- ✗ solve all tasks from **seminar.ipynb**
- ✗ solve homework from **hw.ipynb**
- ✗ solve **bonus.ipynb** for additional points
- ✗ in case you are done with tasks you are free and can go home
- ✗ **do not forget to submit report in Canvas for homework or/and bonus** (make video recordings of your solution, archive copy of repository, include your videos in **./data folder**, put your name in the beginning of **hw.ipynb** or/and **bonus.ipynb**)

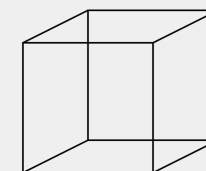# Plan for today
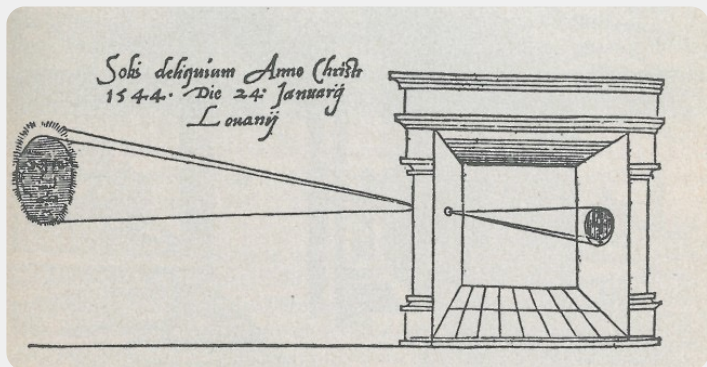
Pinhole camera model
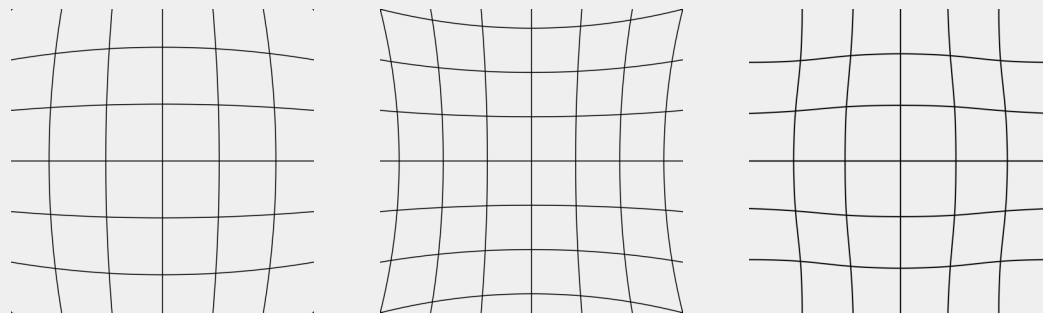
Lens/camera distortion

$$\begin{bmatrix} \hat{x_s} \\ \hat{y_s} \\ \hat{z_s} \end{bmatrix} = \mathbf{K} \begin{bmatrix} \mathbf{R}|t \end{bmatrix} \begin{bmatrix} x_w \\ y_w \\ z_w \\ 1 \end{bmatrix}$$
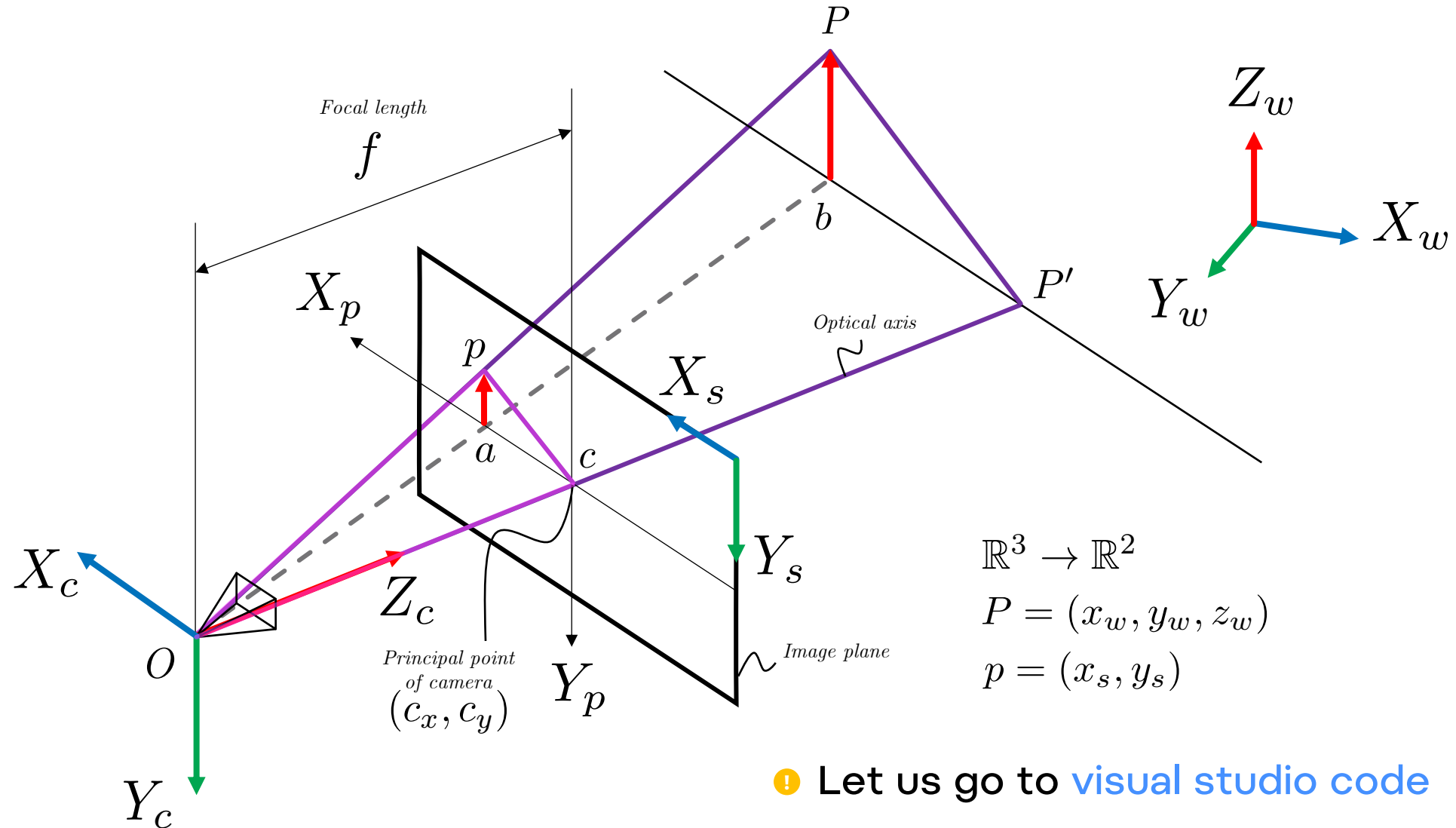
Projective transformation

Markers

Hands-on
AR demo

06

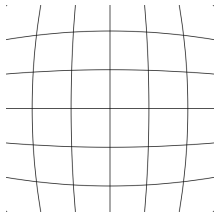# Pinhole camera model

or how camera perceives the world

Pinhole camera model

$$\mathbb{R}^3 \to \mathbb{R}^2$$
$$P = (x_w, y_w, z_w)$$
$$p = (x_s, y_s)$$

⚠ Let us go to visual studio code
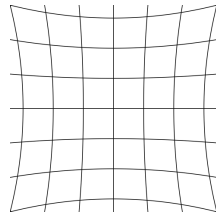
08

Camera/lens distortion

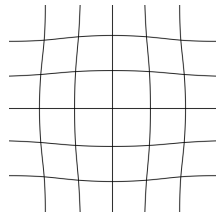and what we can do with it

Barrel
$k_1 < 0$

Pincushion
$k_1 > 0$

Moustache
$k_1 < 0 \quad k_2 > 0$

$$L(x_c, y_c) = L_r(x_c, y_c) + L_t(x_c, y_c)$$

$$r^2 = x_c^2 + y_c^2$$

$$L_r(x_c, y_c) = (1 + k_1 r^2 + k_2 r^4 + k_3 r^6) \begin{bmatrix} x_c \\ y_c \end{bmatrix}$$
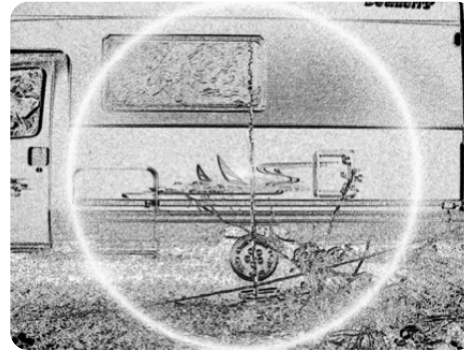
$$L_t(x_c, y_c) = \begin{bmatrix} 2p_1 x_c y_c + p_2(r^2 + 2x_c^2) \\ p_1(r^2 + 2y_c^2) + 2p_2 x_c y_c \end{bmatrix}$$
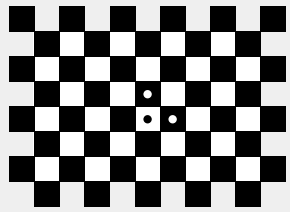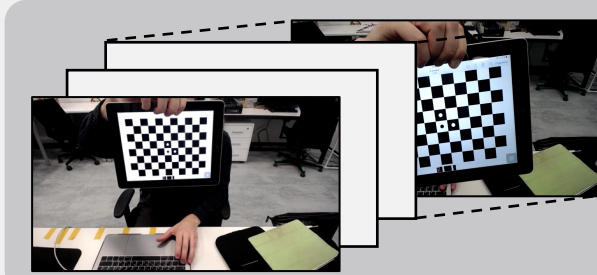
Original

Corrected

Difference between
grayscale versions
of original
and corrected images

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Projective transformation

Intrinsic camera matrix
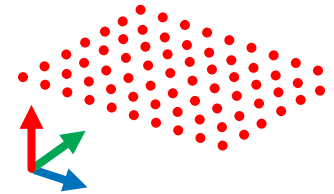

Known-size checkerboard pattern

Set of calibration samples

Camera calibration algorithm
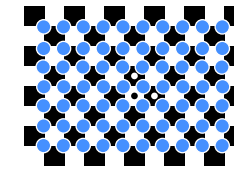
all parameters in px units

$$\mathbf{K} = \begin{bmatrix} f_x & \gamma & c_x \\ 0 & f_x & c_y \\ 0 & 0 & 1 \end{bmatrix} = \begin{bmatrix} 858.212 & 0 & 574.698 \\ 0 & 845.243 & 394.842 \\ 0 & 0 & 1 \end{bmatrix}$$

3D to 2D mapping

$$\mathbf{K} = \begin{bmatrix} f_x & \gamma & c_x \\ 0 & f_y & c_y \\ 0 & 0 & 1 \end{bmatrix}$$

3D model of pattern (3D points in WCS)

2D object points (2D points in CCS)

Intrinsic camera matrix

$$\mathbf{R} = \begin{bmatrix} r_{11} & r_{12} & r_{13} \\ r_{21} & r_{22} & r_{23} \\ r_{31} & r_{32} & r_{33} \end{bmatrix} \quad t = \begin{bmatrix} t_1 \\ t_2 \\ t_3 \end{bmatrix}$$
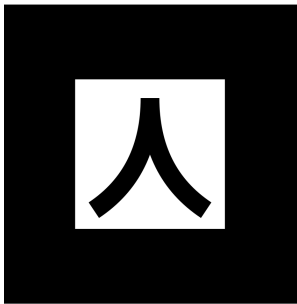
Rotation matrix and translation vector

$$\begin{bmatrix} \hat{x_s} \\ \hat{y_s} \\ \hat{z_s} \end{bmatrix} = \mathbf{K} \left[\mathbf{R} | t \right] \begin{bmatrix} x_w \\ y_w \\ z_w \\ 1 \end{bmatrix}$$
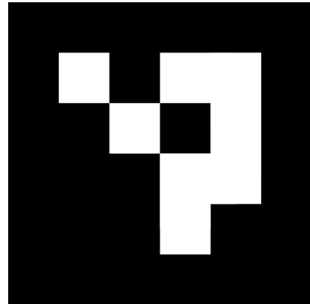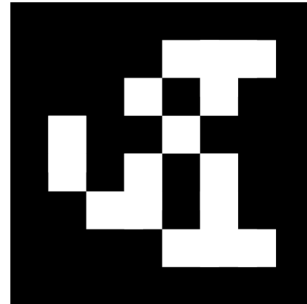
Solution

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Markers

Fiducial markers use the same idea as calibration pattern (known geometry object), but mostly for detection and pose estimation purposes (e.g. in robotics, PCB manufacturing).
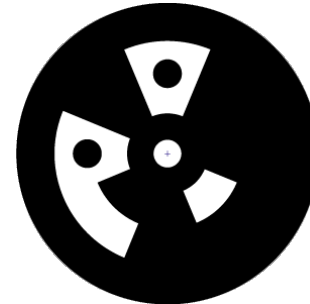

ARToolKit

Aruco

ApriTag

Intersense

reacTIVision

There a lot of them

Hands-on session

is on

⚠️ Let us go to visual studio code

Augmented reality on your knees

Ciao cacao. Thank You.

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