

8BallPool video analysis

Michele Sprocatti¹, Alberto Pasqualetto², Michela Schibuola³

Department of Information Engineering, University of Padua
Via Gradenigo 6, 35131 Padova, Italy
{michele.sprocatti¹, alberto.pasqualetto.^{2,2}, michela.schibuola³}@studenti.unipd.it

Introduction

This is the report of the final project for the Computer Vision course, which goal is to develop a computer vision system for analyzing video footage of various “Eight Ball” billiard game events.

How the work has been split

The three group members collaborated by dividing the work. Each member was responsible for producing specific files, all of which were annotated with their respective author.

Split of the work

The source code reflects a division of labor across three key areas:

1. Detection and segmentation of balls and the playing table: this area, along with the main program functionality, was handled by Michele.
2. Metrics calculation and tracking: responsibility for this area fell to Alberto.
3. Transformation code and mini-map management: this area was overseen by Michela.

Working hour per member

The approximate number of working hours for each member of the group are these ones:

1. Michele: 40 hours.
2. Michela: 40 hours.
3. Alberto: 40 hours.

Elements of our project

Table detection

A mask-based approach was implemented for table detection, exploiting the consistent central positioning of the table within the dataset. The mask was generated by identifying the most common color in the image’s central columns. Building upon this initial step, Michele exploits the Canny edge detector and OpenCV’s HoughLinesP function. Then the function analyzes intersections and merges nearby points, ensuring the consistent identification of four corner points corresponding to the table’s corners in the processed dataset.

Table segmentation

In order to isolate the table with high precision, Michele employed a two-mask combined with k-means algorithm. The masks involved are:

1. Color-based masking: A mask was created that identified pixels corresponding to the table’s color.
2. Corner detection masking: A separate mask was generated to capture the table’s geometric features starting from the corners already detected.

By combining these two masks with the output of a k-means clustering algorithm with two clusters, the table was effectively isolated from the background.

Balls detection

To detect balls, Michele proposed a multi-step preprocessing approach. Initially, the table region was isolated by constructing a polygon using its corners and a color-based mask is generated. Subsequently, pixels outside the table were nullified, and k-means clustering was applied to the image. The resulting clusters were converted to gray-scale for Hough Circle Transform application. Circle parameters, such as radius and center color, were analyzed to identify potential ball regions. By calculating the mean radius of in-table circles with center not selected by the color mask, a radius range was established. Circles within this radius range were considered for further analysis. Ball classification involved creating a circular mask, computing the gray-scale histogram, and excluding background pixels from the values of the histogram. Peak values in the histogram were used to differentiate between striped and solid balls, while HSV color space analysis is used to distinguish white and black balls. After finding the balls, the team identified an optimization opportunity. Since there’s only one white ball and one black ball, Michele implemented non-maxima suppression for white and black balls independently, in order to improve performance. The result of the detection process is then used to segment the balls.

Attempt of ball radius relative to the distance and perspective of the camera with respect to the table To try to increase the performance of the ball detection, it has been attempted to compute an interval of values for the ball radius relative to the pixels of the image and the position of

the camera with respect to the table; this would have been used in the `HoughCircles()`. For that purpose, the `radiusInterval()` method has been written. This method starts by computing the mean radius value by using a proportion between the diagonal of the table in pixels and the approximate dimensions of the diagonal of the table and the balls in centimeters. Then, a percentage of the slope between the camera direction and the table has been computed, by using one of the angles ($\neq 90^\circ$) that the detected table creates; this angle is compared with the $\pi/2$ angle, and a value between 0 and 1 is computed:

- If the value is 1, then the camera is parallel to the table;
- If the value is 0, then the camera is perpendicular to it;
- If, for example, the value is 0.5, then the camera is about 45° from the table.

To compute the final interval, the minimum and maximum values are computed by subtracting and incrementing a value, which increases with the percentage of slope (more the slope, more the variance) by multiplying the percentage of slope with the mean radius previously computed, and a precision value is added due to some other variables in the images.

The idea of trying this method was from Michela.

Tracking

Mini-map creation

To create the mini-map are needed:

- An image that contains an empty billiard table and some information about it;
- The position of the balls in the current and previous frames;
- A transformation matrix that computes the position of the balls in the mini-map.

Empty mini-map image As a first step, an image of an empty billiard table has been selected, and its corner positions and dimensions have been stored in constant variables.

Computation of the transformation matrix The `computeTransformation()` method has been written to compute the transformation matrix, which allows for the computation of the positions of the balls in the table of the mini-map. To do that, a relationship between the corners of the table in the frame and the corners of the table in the mini-map has been made. This relationship has been made by the OpenCV `getPerspectiveTransform()` method, which “calculates a perspective transform from four pairs of the corresponding points” and returns a transformation matrix. At first, it is supposed that the corners are given in clockwise order and that the first corner is followed by a long table edge. To check this information, `checkHorizontalTable()` has been written.

Check if the corners are in the order needed The `checkHorizontalTable()` method checks, using the image in input and the corners of the table in that image, if the corners are oriented such that the first corner is followed by a long table edge. To check this information, the “percentage of table”

with respect to the pool in a rectangle placed in the center of the edge (with dimensions proportional to the real table and pool dimensions) has been computed for all the edges. This computation has been done in the table image previously transformed and cropped to the table dimensions; in this way, the center between two corners corresponds to the real one (otherwise, if the table has some perspective effect, the center between the two corners may not correspond to the real one). Then, the edges have been ordered by using this percentile. To understand how the corners were oriented, three cases have been considered:

- If the edges with “more pool” are opposite edges, then they are the longest edges;
- If the edge with “more pool” is opposite to the one with “less pool”, then they are not the longest edges;
- Otherwise, there is uncertainty, and then, probably, the one with “more pool” is the longest edge.

If the table is not horizontal as expected, then all the edges have been rotated and the transformation matrix has been re-computed.

Draw the mini-map with tracking lines and balls Given the transformation matrix and the ball positions in the frame, it is possible to compute the positions of the balls in the mini-map. This computation has been done in the `drawMinimap()` method. Every time this method is called, the ball positions and the positions of the balls in the previous frame (if they have been computed by the tracker) are computed by using the `perspectiveTransform()` method. For each ball in the frame, a line between the previous position and the current position is drawn on the mini-map image, passed as a parameter by reference such that all the tracking lines are kept in a single image. Then this image is cloned into a copy, and the current balls are drawn on it. This image is then returned.

The ideas of using `getPerspectiveTransform()` and `perspectiveTransform()`, and how to check the orientation of the table were from Michela; the idea of drawing the balls on a copy of the mini-map image, rather than the one that contains the tracking, was from Alberto.

Video creation

Results

Table detection exhibits very high accuracy, in particular for each initial frame of each video four corner points are consistently identified across the dataset, the assumption that we made is that the camera does not move during a single clip so once the table is detected in the first frame we can use that information for all the frames of the same video. In contrast, ball detection is influenced by k-means clustering. To achieve consistent and satisfactory results, a fixed random seed is incorporated into the code. This method results in an average mAP of 0.72 for the dataset.

Qualitative results

Quantitative results

Conclusions