

TorquePaper 2016.2: Steps Required to Achieve Autolock Vision Control

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January 29, 2016

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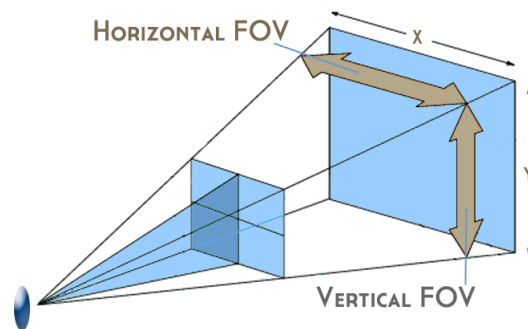
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Chapter 1

Step 1: Match Turn Angle

1.1 Camera FOV

All cameras have a certain amount of degrees that they can see. The figure below shows how a camera's angle of view translates to an image.



The camera used on Sonic was an Axis Camera M1013 which has an angle of view of 67° . This means that if the camera faces the front of the robot, the camera will be able to see 33.5° left and right.

1.2 Simple Solution

OpenCV/GRIP is able to determine the center of the U shape that the reflective tape forms. If the vertical center of the image is treated as 0° , then the proportion from the center

can be used to determine the turn angle. The following equation formalizes this.

$$\theta_{yaw} = \frac{goalCenterX - \frac{imgWidth}{2}}{\frac{imgWidth}{2}} * 33.5^{\circ}$$