

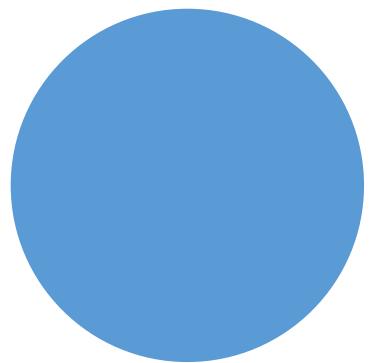
Introduction: Sensing Visual Data in ROS

Human-Centred Robotics

Dr Tobias Fischer

2019-11-07





Computer Vision |
The very basics |

Computer Vision: The very basics

First encounter

088 084 161 169 152 053 123 221 119 121 144 138 152 164 158 103 215 192 098 232 183 161 178 177 071 072 151 188 175 065 139 237 118 084 116 089 168 119 118 085 218 210 114 246 168 143 169 168 025 036 106 153 166 055 123 226 098 038 044 027 039 042 046 049 215 209 107 232 128 084 116 124
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What do you see ?

Slide: Vittorio Ferrari

Computer Vision: The very basics

First encounter

Computer vision is the field of study that aims at enabling computers to interpret and understand the visual world. It is a multidisciplinary field that involves computer science, mathematics, physics, and engineering. Computer vision has many applications, such as image processing, object recognition, scene understanding, and robotics.

The first step in computer vision is to capture an image. This can be done using a camera or a scanner. Once an image is captured, it needs to be processed. This involves several steps:

- Image acquisition: The image is captured by a camera or a scanner.
- Image pre-processing: The image is converted into a digital format and noise is removed.
- Feature extraction: The image is analyzed to extract features, such as edges, corners, and shapes.
- Object detection: The image is analyzed to detect objects, such as cars, people, and buildings.
- Scene understanding: The image is analyzed to understand the scene, such as the location, the time, and the weather.

Computer vision is a complex field that requires a deep understanding of mathematics, physics, and computer science. It is a rapidly growing field with many exciting applications.

And now?

Computer Vision: The very basics

First encounter

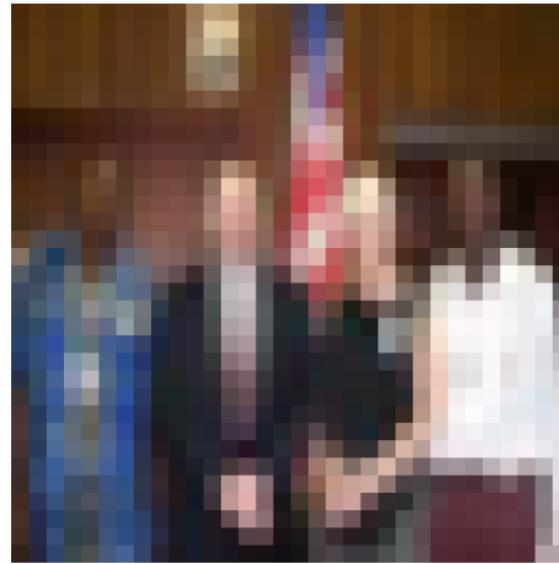


Rapid visual recognition is important !

Computer Vision: The very basics

The goal of computer vision

To extract “meaning” from pixels



Humans are remarkably good at this...

Source: “80 million tiny images” by Torralba et al.

Computer Vision: The very basics

Vision as a source of semantic information



slide credit: Fei-Fei, Fergus & Torralba

Computer Vision: The very basics

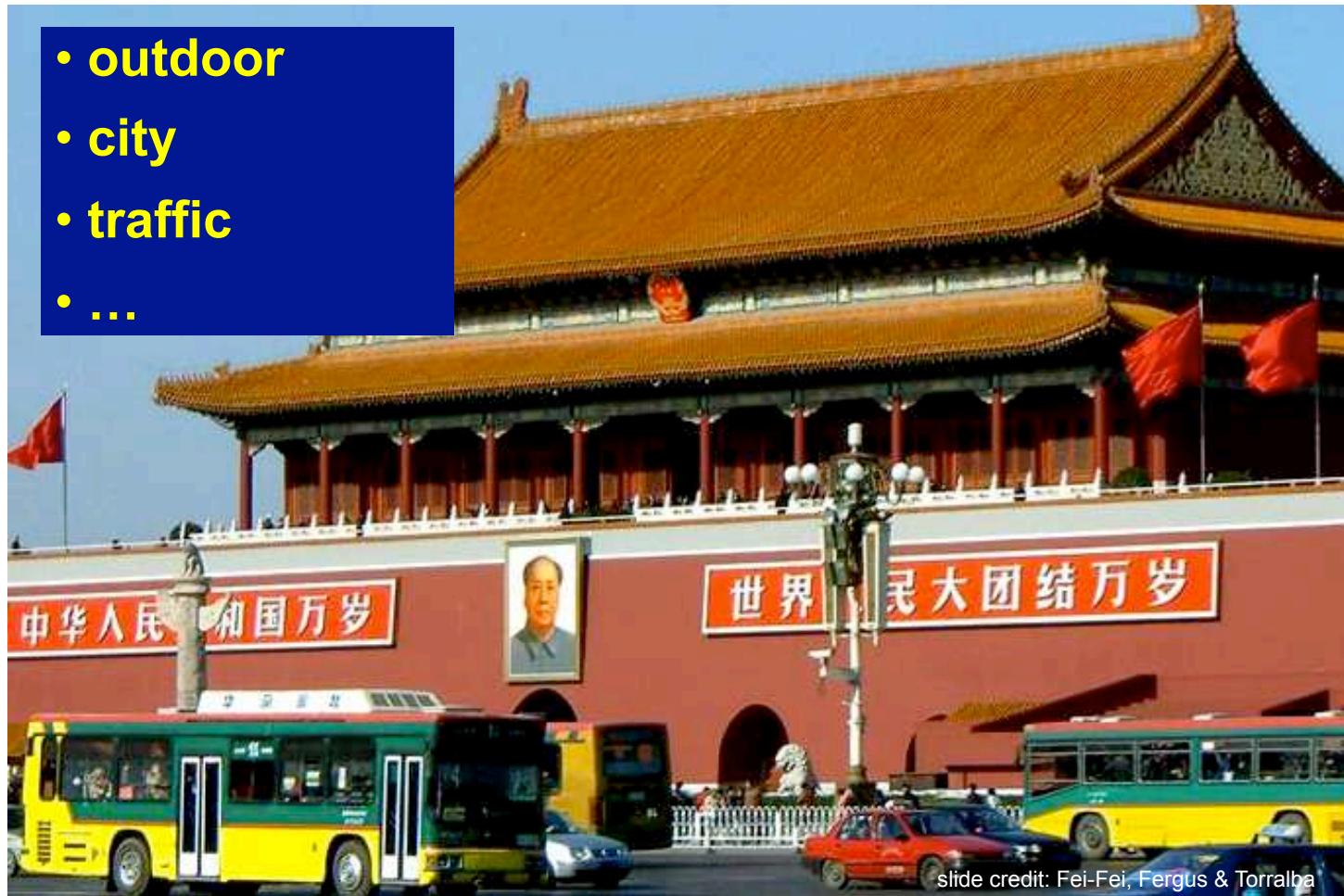
Object categorization



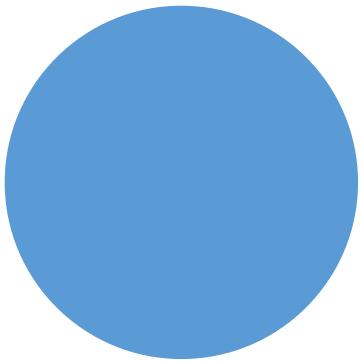
Computer Vision: The very basics

Scene and context categorization

- **outdoor**
- **city**
- **traffic**
- ...



slide credit: Fei-Fei, Fergus & Torralba



Why is Computer
Vision hard? |

Why is Computer Vision hard?

Challenges: Robustness



Illumination



Object pose



Clutter



Occlusions



Intra-class variation



Viewpoint

Why is Computer Vision hard?

Challenges: Robustness



- **Detection in Crowded Scenes**
 - Learn object variability
 - Changes in appearance, scale, and articulation
 - Compensate for clutter, overlap, and occlusion

Why is Computer Vision hard?

Challenges: object intra-class variation



slide credit: Fei-Fei, Fergus & Torralba

Why is Computer Vision hard?

Inherent ambiguity of the problem

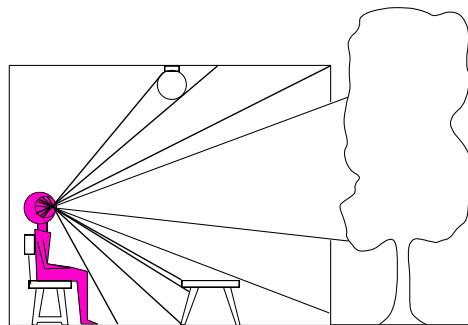
- Many different 3D scenes could have given rise to a particular 2D image



Why is Computer Vision hard?

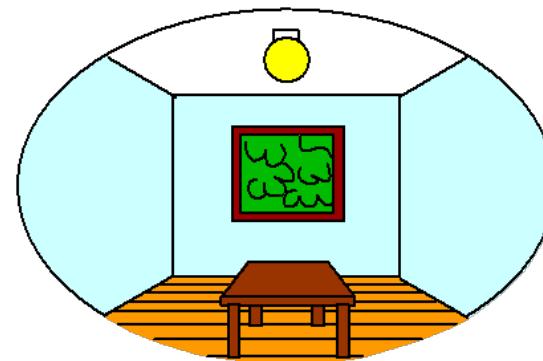
Dimensionality reduction: from 3D to 2D

3D world



Point of observation

2D image

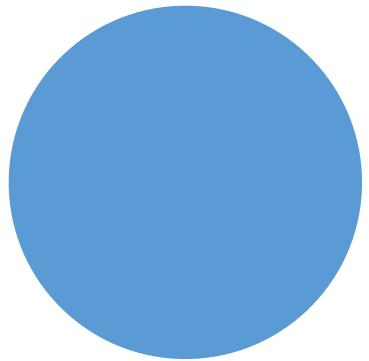


What is preserved?

- Straight lines, incidence

What have we lost?

- Angles, lengths



Computer Vision in the
Personal Robotics Lab

All code available!

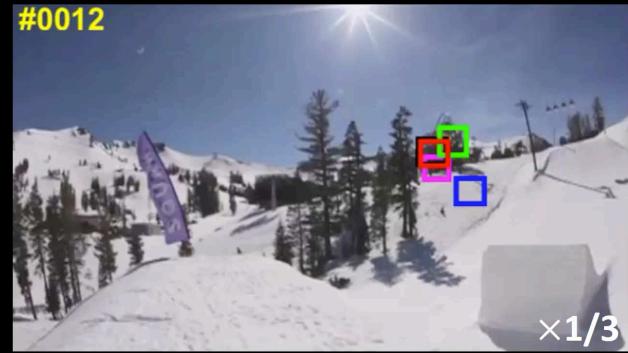
Computer Vision in the Personal Robotics Lab

- Ultra-fast visual object tracking

Attentional Correlation Filter Network
for Adaptive Visual Tracking

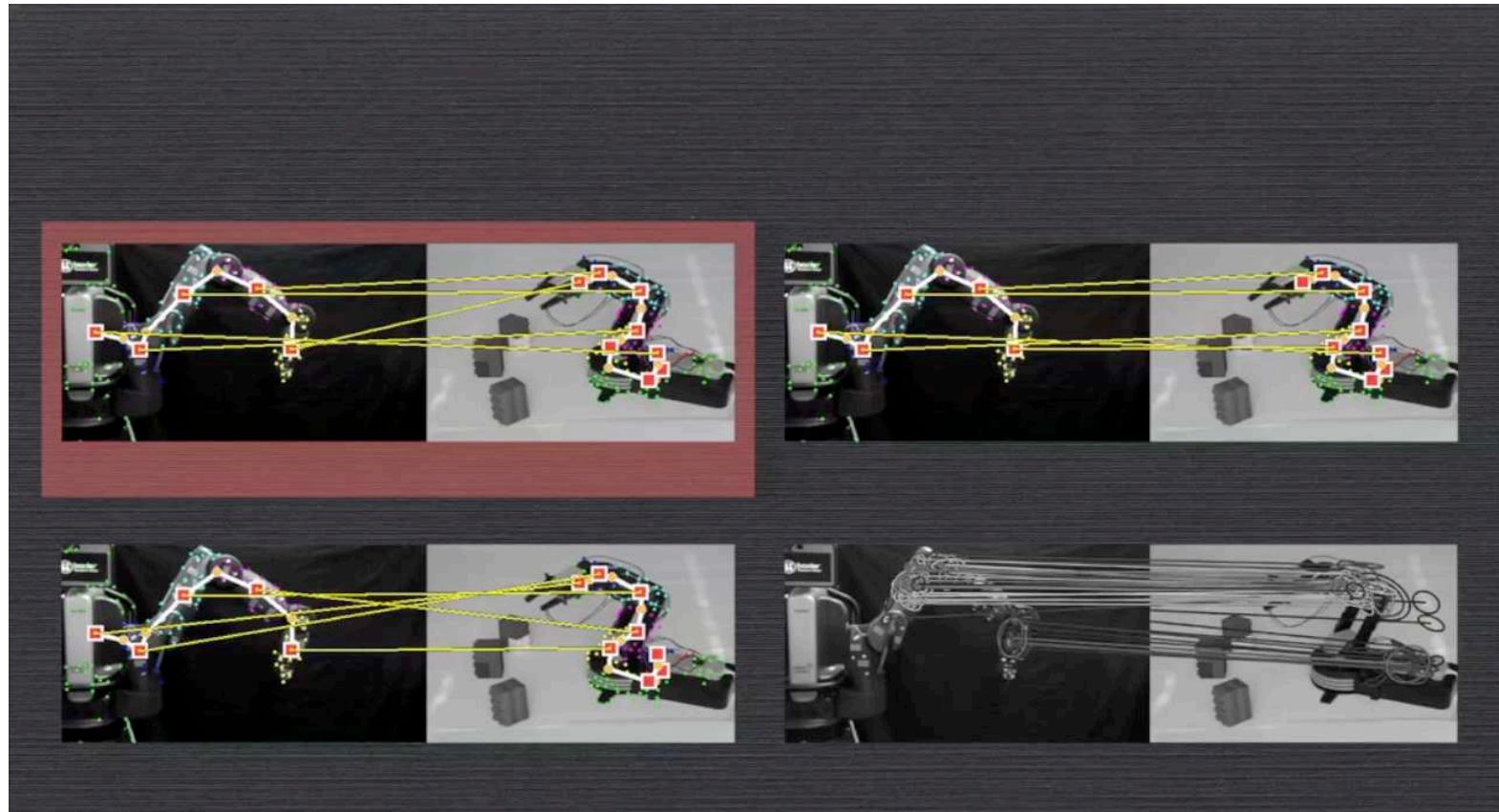
Anonymous #1996

Tracking Result – Skiing



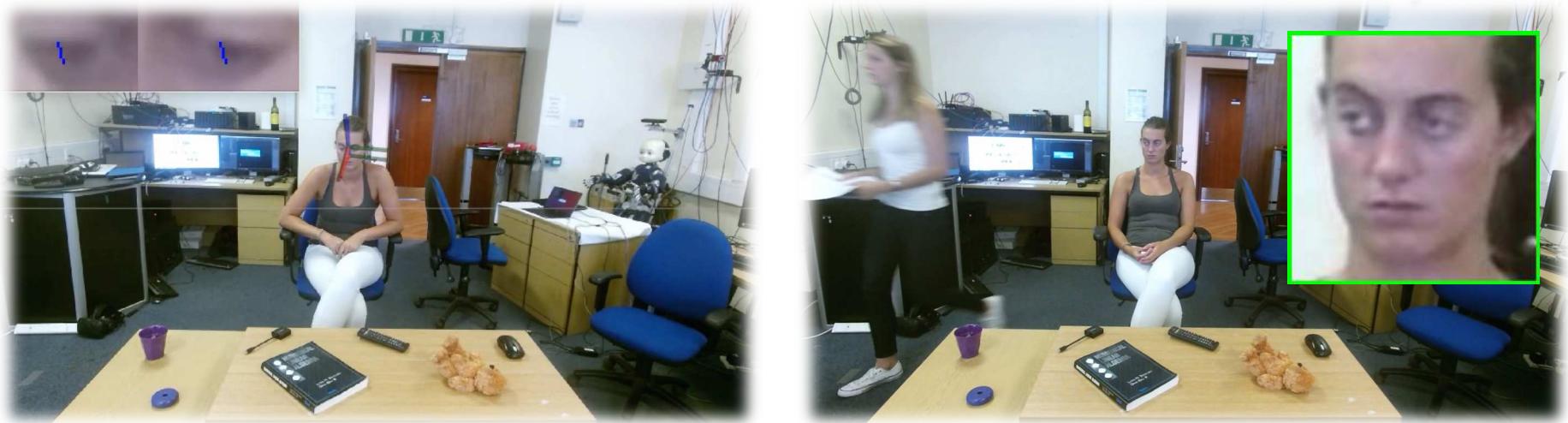
Computer Vision in the Personal Robotics Lab

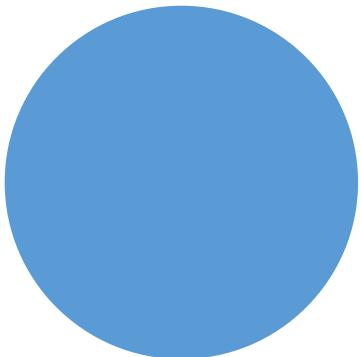
- Robot motion retargeting



Computer Vision in the Personal Robotics Lab

- Gaze & blink estimation





Other popular computer
vision resources

All code available!
Keep in mind you
need powerful GPU

Computer Vision with Tensorflow & PyTorch

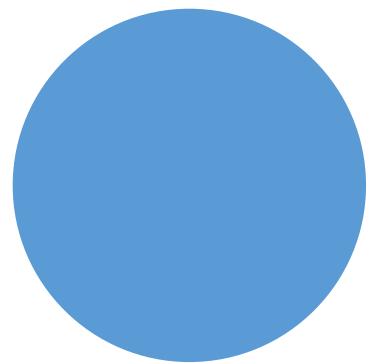
- Human pose estimation using Detectron2



Computer Vision with Tensorflow & PyTorch

- Object classification & segmentation using Detectron2

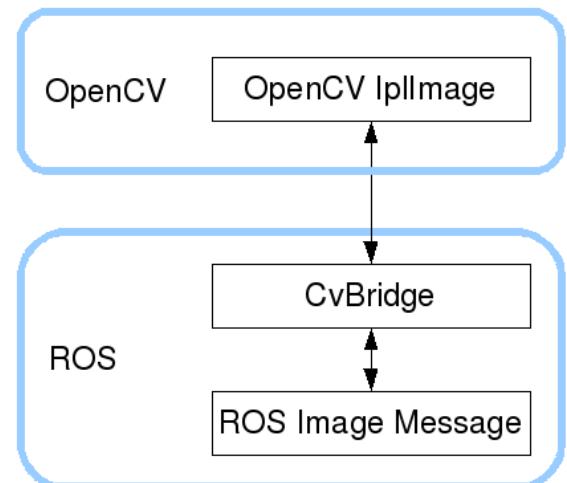




Computer Vision
& ROS |

Computer Vision & ROS

- My recommendation: Python for ease of use
- C++ & Python nodes can interact!
- Most common underlying data structure: Numpy
- Easy conversion between ROS `sensor_msgs/Image` & OpenCV using `cv_bridge`



Acquiring images

- There are different packages to acquire images from a camera
- Webcam: uvc_camera or cv_camera
- Kinect / Asus Xtion: openni_launch <- Provides depth
- If one does not work, try another one ..
wiki.ros.org/Sensors/Cameras

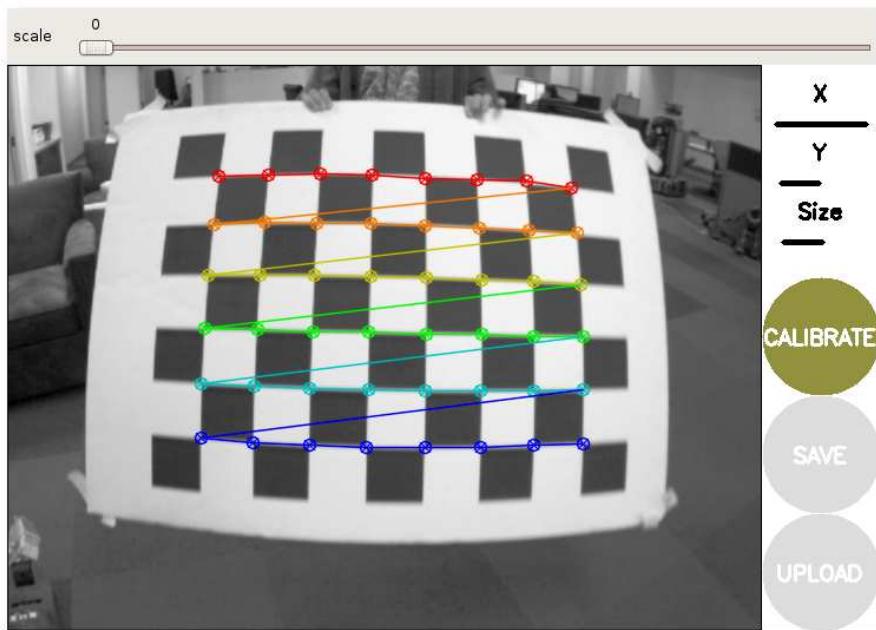
Acquiring images

- Unifying data format: sensor_msgs/Image

```
# This message contains an uncompressed image
# (0, 0) is at top-left corner of image
#
Header header          # Header timestamp should be acquisition time of image
                        # Header frame_id should be optical frame of camera
                        # origin of frame should be optical center of camera
                        # +x should point to the right in the image
                        # +y should point down in the image
                        # +z should point into to plane of the image
                        # If the frame_id here and the frame_id of the CameraInfo
                        # message associated with the image conflict
                        # the behavior is undefined
uint32 height           # image height, that is, number of rows
uint32 width             # image width, that is, number of columns
#
# The legal values for encoding are in file src/image_encodings.cpp
# If you want to standardize a new string format, join
# ros-users@lists.sourceforge.net and send an email proposing a new encoding.
string encoding          # Encoding of pixels -- channel meaning, ordering, size
                        # taken from the list of strings in include/sensor_msgs/image_encodings.h
uint8 is_bigendian        # is this data big endian?
uint32 step               # Full row length in bytes
uint8[] data              # actual matrix data, size is (step * rows)
```

Acquiring images

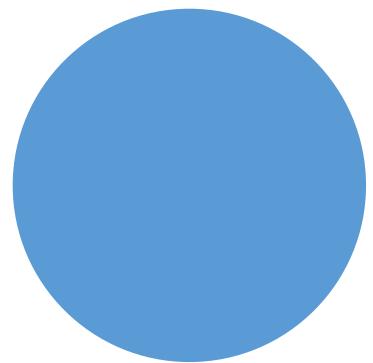
- It is often beneficial to make sure your camera is calibrated:
http://wiki.ros.org/camera_calibration/Tutorials/MonocularCalibration



- We have a checkerboard pattern in the lab

Pointers to other materials

- <https://github.com/osrf/rosbook>
“Programming Robots with ROS” Chapter 12: Follow-Bot
- [https://industrial-training-master.readthedocs.io/
en/melodic/_source/session5/OpenCV-in-Python.html](https://industrial-training-master.readthedocs.io/en/melodic/_source/session5/OpenCV-in-Python.html)
- ROS Wiki
- OpenCV
- PCL



Practical session

Practical session

1. Subscribing & publishing images, interfacing with OpenCV
2. Face detection with OpenCV
3. Obtaining 3D coordinates using Kinect-like sensor
Make sure you calibrate color AND depth cameras:
http://wiki.ros.org/openni_launch/Tutorials/IntrinsicCalibration
http://wiki.ros.org/openni_launch/Tutorials/ExtrinsicCalibration
4. TensorFlow specifics in ROS
5. PyTorch example