Multi-video-camera array calibration for detection of object existence

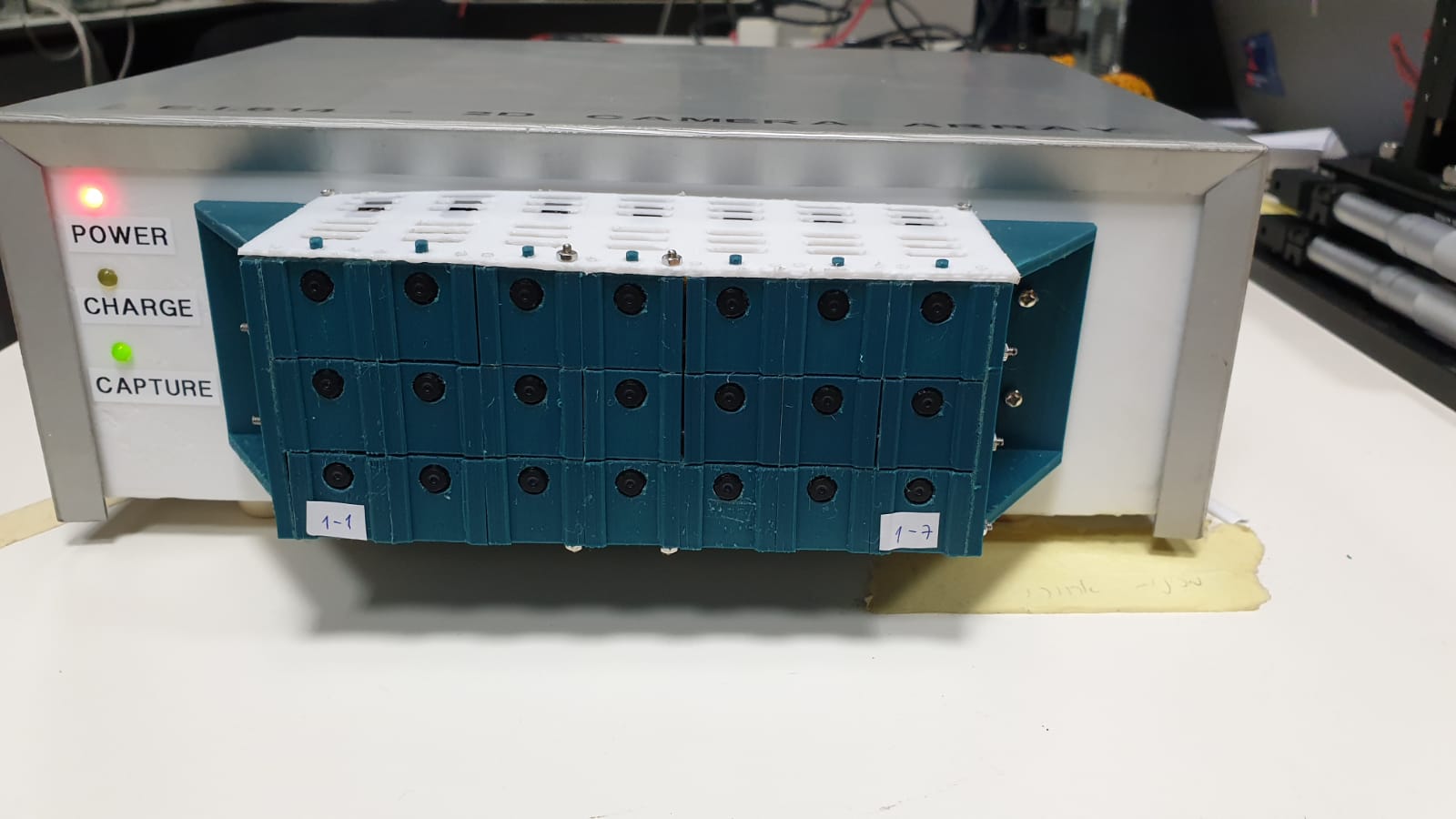
from a reconstructed planes, obtained by computational integral imaging

**Introduction**

One of the requirements for three-Dimensional (3D) image sensing, visualization, and processing using computational integral imaging (CII) plane reconstruction [1],[2] is to use constant shifted camera array in each direction, so basically, the same distances between the cameras in the camera array along the X axis and the Y axis, placed on the same surface. As we know, till now, there are no such as application that used video cameras array computing 3D reconstructed planes based on the CII. We propose a solution to compute the reconstructed plane from camera array video signal build from low-cost video cameras, while the mounting of the camera array is not super accurate, assembled on 3D printed mounter. Our calibration and rectification process offer lens distortion removal for each camera, finding the transformation matrix between the array output images, relative to the middle camera output image by finding the matching features between each one of the cameras relative to the centre camera and relative to them, estimate the 2-D affine geometric transformation between the array cameras to the centre camera to compare scale, translation, rotation and shearing. Then to shift the cameras exactly in a constant distance between one to outer, we detect in each one of the cameras a robust and flexible visual fiducial marker called AprilTag [3], uses a 2D bar code style “tag”, allowing full 6 DOF localization of features from a single image. Then we shift the elemental images of the camera array in a precise why and validate the accuracy of the calibration process.

**The Proposed Method**

The purpose of this study is to automatically calibrate and rectify multi-video-camera array for detection of object existence from a reconstructed plane, obtained by computational integral imaging in a continues frame grabbing for later tracking objects in a 3D scene, navigation and, etc. For that we developed a step-by-step calibration method. The imaging system lab device that we used in this research as shown in Fig. 1 allows simultaneous capture of multiple images and video clips from 2-D camera array. The 2-D camera array consists of 21 cameras arranged in 3 rows with 7 cameras per row. The pitch between any adjacent cameras is 21.1mm both vertically and horizontally. The 2-D camera array system consists of dedicated hardware and software and is fully controlled through the PC software.



Centre Camera 2.4

Camera 3.7

Camera 1.1

***Fig. 1.*** *The imaging system lab device*

Due to cost of accurate assembled design and required thin size of the array we design a low cost and thin as possible mechanical assembly using 3D printer to print our array frame mounter and try to be accurate as possible in the placement of the cameras in each one of the axis and also in the angle. The array raw true color RGB images converted to the grayscale image by eliminating the hue and saturation information while retaining the luminance for more efficient calibration process and required less computational resources by working on a m-by-n numeric array instead of m-by-n-by-3 numeric array. The grayscale array images are shown in Fig. 2 before calibration and rectification. In Fig. 2 we can see clearly that the array not rectify, not in row and not in column. To use CII, the array should be rectified with small shifting of the camera between one to her neighbour, while the shifting between them should be constant. Without different shooting angle or magnification resulting from misalignment in the row and column in the z axis.

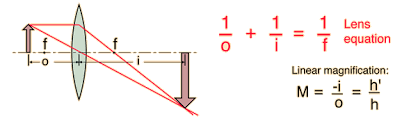
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***Fig. 2.*** *The imaging system lab device Gray level images before calibration process (camera 1.1 top left, camera 3.7 down right)*

By looking on the array images it is possible to see the shift between them. but we also can see a different offset between the camera images and a different shooting angle and magnification that effecting from the distance between the camera to the object plane. The linear magnification is the ratio of the image size to the object size. If the image and object are in the same medium so the magnification can be calculated also by image distance divided by the object distance as shown in Fig. 3.

(1)

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h

***Fig. 3.*** *Linear magnification, effected by object distance o* [hyperphysics.phy-astr.gsu.edu]

By simply detect the AprilTag in each one of the array raw images and estimate the pose location in a world unit with respect to the specified camera intrinsic parameters that achieved by camera calibration and size of the tags in a world unit, we can see clearly that the array not aligned with the required physical pitch between the cameras. The desired pose of the Tag between camera to here neighbored should be 21.1[mm] shifted (row and column) but due to the encumbrance to high mechanical assembly accuracy the error of the required constant shift between cameras is at the maximum value 29[mm] and minimum 2[mm] in more than one of the cameras to her neighbor in each one of the translation axis caused a specially due to different shooting angle. To fix that error we use the following process:

**Step 1 - Camera Calibration**

Calibrate each of the array cameras to remove the lens radial distortion (occurs when light rays bend more near the edges of a lens than they do at its optical centre, the smaller the lens, the greater the distortion) and finding the intrinsic parameters of the cameras. We are using camera calibration tool [4],[5],[6],[7] to calibrate each of the cameras by capture 10 frames with calibration pattern as shown in Fig. 4, camera calibration tool’s suggestion is to use 10-20 images of the calibration pattern for best calibration results and to calibrate the camera with a variety of images of the pattern to account for as much of the image frame as possible. Lens distortion increases radially from the centre of the image and is not always uniform across the image frame. To capture this lens distortion, the pattern must include areas near the edges of the captured images. We use chessboard as our calibration target by known the exact squares size of the board in world unit to find eventually the intrinsic parameters of the calibrated camera. The intrinsic parameters include the focal length, the optical centre, also known as the principal point, and the skew coefficient, while later on we will use the intrinsic parameter to find the location of the AprilTag in the frame in a world unit.

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***Fig. 4.*** *Selected 10 frames of Camera1.1 that used for the camera calibration process*

**Step 2 - Estimate the geometric transform between the array output images relative to the centre camera output image**

To estimate the geometric transform matrixes, we first finding matching feature on a target between the undistorted elemental images of the array relative to the centre camera undistorted image, while we are capturing a static scene with the array cameras. We use SURF (Speeded-Up Robust Features) [8] to find the feature in an image as shown in Fig. 5. SURF presents a novel scale- and rotation-invariant interest point detector and descriptor, it mainly rich corner and blob features in the image and the features are invariant to size, orientation, color, etc., so they are very good for matching between objects in two shifted/twisted images. In our case we rich the match features between the centre camera undistorted image to the rest of the elemental undistorted images on the same calibration target by using their extracted feature vectors, also known as descriptors, and their corresponding locations of matched points in the images. Matching method between features [9] specifies how nearest neighbors between features set to outer features set are found. Two feature vectors match when the distance between them is less than the pre-defined threshold. Then by knowing the matching features we can estimate the geometric transform by find the transformation corresponding to the matching point pairs by using multiple view geometry analysis tool [10]. This tool using the statistically robust M-estimator sample consensus (MSAC) algorithm [11]. It removes outliers matching point while computing the 2-D affine geometric transformation.

Graphical user interface

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***Fig. 5.*** *Matching point after estimation of the transformation and removal of the outliers over the images of camera 1.1 relative to camera 2.4. camera image 2.4 marked in red and camera image 1.1 marked in blue*

**Step 3 - Apply the geometric transform to the array elemental undistorted images relative to centre camera image**

In this step, by determines the value of pixels in the output image by mapping locations in the output image to the corresponding locations in the input image (inverse mapping). By interpolates within the input image to compute the output pixel value to the array cameras output image, by knowing the 2-D affine geometric transformation from the previous step, that enables forward and inverse transformations that contain the transformation matrix between the camera array undistorted elemental images relative to the centre camera (camera number 2.4), as shown in Fig. 6, an example of camera 1.1 after applying the 2-D affine geometric transform (left) and the undistorted image of the array central camera 2.4 (right). After applying the transformation, we can see more clearly that camera 1.1 rectify to camera 2.4. The tag corners position in pixels unit is in the same location on both images, detected with AprilTag detector. Also, the width of the tag is in the same pixels size in both images, meaning that the magnification is also the same in both images. By applying that step over all the array elemental images, we can rectify the camera array relative to centre camera.

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***Fig. 6.*** *In the left image, camera 2.4 undistorted image. In the right image, camera 1.1 after 2-D affine geometric transform relative to centre camera 2.4*

**Step 4 - Applying constrain offsets**

Detect the AprilTag as shown in Fig. 7, in each one of the transformed array images and estimate the pose location in a world unit with respect to the specified camera intrinsic parameters that achieved by step A, camera calibration and size of the tags in a world unit. In each one of the array images the Tag should be located in the same place with the same magnification due to the previous step.

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x=-36.5[mm]

y=90.6[mm]

z=1150[mm]

***Fig. 7.*** *Example of AprilTag detection of camera 2.4 and the pose of the tag in the world unit relative to the principal axis of the camera (translation), annotate the detection corners of the tag*

Poses of tags with respect to the camera principal axis, returned as an 3D affine matrix. The origin of each tag frame is located at the centre of the corresponding tag. By knowing the tag position in world unit in each one of the elemental images we validate the calibration and rectification process and use it for the constant shift calculation. By simply cropping the image frame according to the position and dimensions specified in the crop rectangle, we calculated offset from the main axis and automatically shifting the array elemental images in a constant offset by cropping the array images with offset that correspond to the real shifts between the cameras by transform the millimetres unit to pixels:

(2)

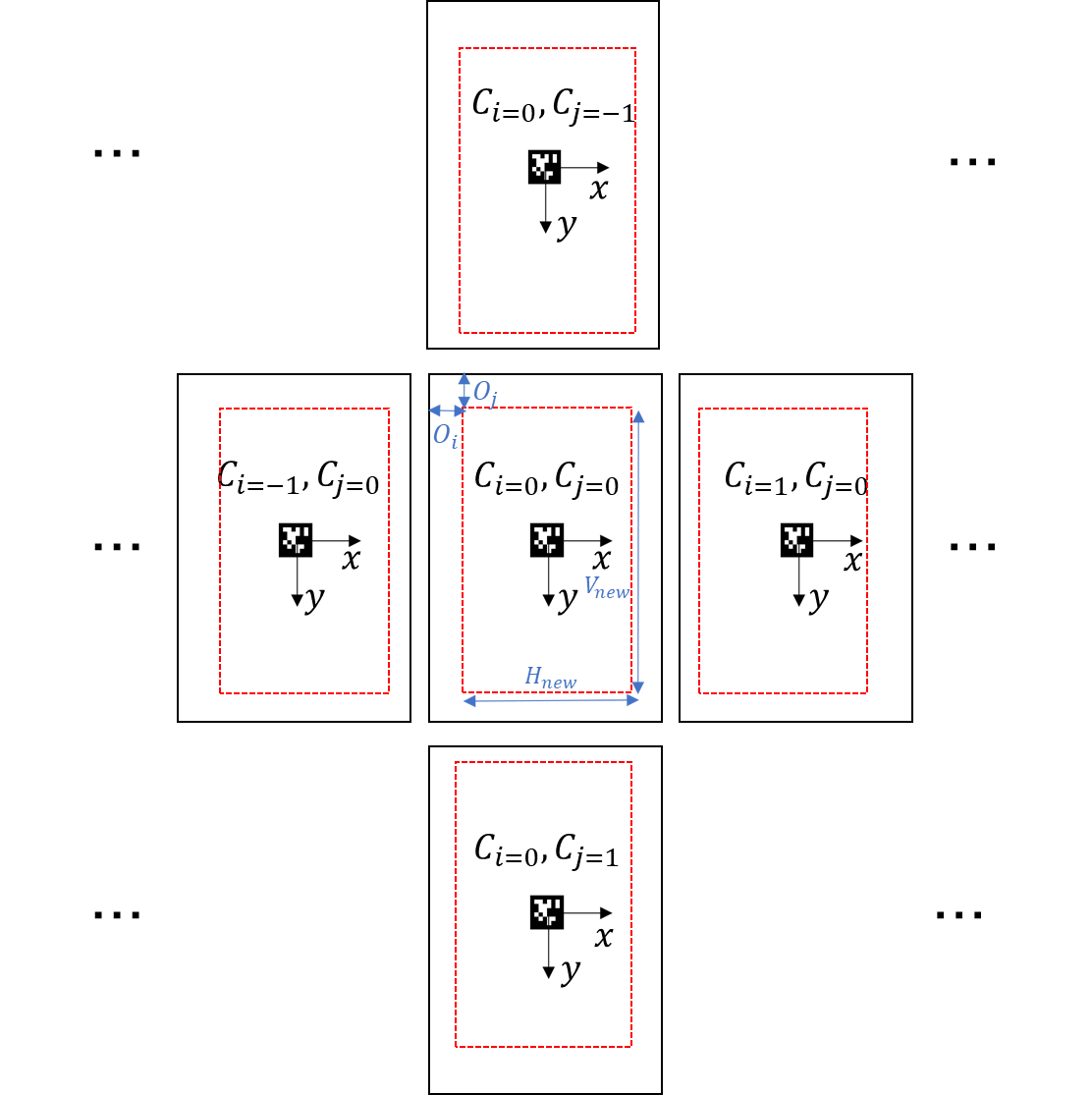
While is the measured offset between cameras that using for cropping the images with respect to the real shift between the array images, is the tag width in pixels unit known by the detection of the tag in the image and effected directly from the magnification, is the predefined mechanical design distance between the cameras and is the known tag width in millimetres. The new image frame dimension for all the array images mast be the same and calculated as:

(3)

While is the new horizontal frame size in pixels, is the original horizontal frame size in pixels, l(i) is the length of a uniformly spaced vector i derived from the camera number of the array row, is the new vertical frame size in pixels, is the original vertical frame size in pixels and l(j) is the length of a uniformly spaced vector j derived from the camera number of the array column as shown in Fig. 8. Due to of that the new frame size is smaller than the raw frame size and depending in the calculated offset in pixels and the number of cameras in the row and column, in Fig. 8 we demonstrate the shift of the new frame size in the Red rectangle relative to the original frame and the position of the tag relative to the cropped frame. From Eqs. (2-3) we can calculated the required tag origin position in the new cropped frame. The tag new origin position calculated as:

(4)

From Eqs. (4) we derived the defined crop offset for each one of the new cropped frame relative to the raw elemental images frame, while the offset in the frame horizontal axis is pixels and the offset in the frame vertical axis is pixels as shown in Fig. 8.



***Fig. 8.*** *Illustration of the rectification process. In the Red rectangle, the new frame size calculated in Eqs, 3 and the AprilTag origin position in the new frame relative to the detected AprilTag origin in the original frame (Black rectangle). Centre camera is relative to that frame we rectify the array, while the cropping offset () of the new frame in the horizontal and the vertical axis of each one of the frames calculated in Eqs. 4.*

The final rectification result shown in Fig. 9, after applying the full calibration process.

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***Fig. 9.*** *Camera array rectify results on the raw camera array data, after applying the full process of the calibration, rectification and shifting by cropping with constrain offset*

**EXPERIMENTAL RESULTS**

**Applying the calibration and rectification results params on a video frames acquisition**

Finally, we applying the calibration results over the camera array video frames. By simply removing lens distortion, by the camera calibration results, having the intrinsic results of each camera and the transformation matrix of the array cameras frame relative to the centre camera and having the constrain offset. the final rectification result shown in Fig. 10.

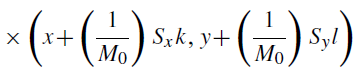
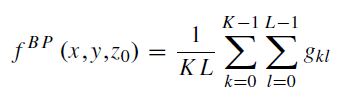
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***Fig. 10.*** *Video camera Array rectify results. The integral imaging system (elemental images). Over video frame acquisition (random selected frame).*

**Computational reconstructed integral-imaging in order to detect 3D objects in the space**

In our research, we use the computational reconstructed integral-imaging in order to detect 3D objects in the space [1],[2]. Mathematically, the integral imaging reconstruction operation is:

.

(5)

Where is the K × L elemental image array, kl are indices for the particular elemental image, is the magnification factor that depends on the distance between the camera to the reconstructed plane . , are the distances between the cameras at x and y directions, respectively, and is 2D reconstructed image at distance . from the camera. Each reconstructed image may include focused and defocused regions (at different defocus levels), depending on the real depth location of the objects relative to the camera. As shown in Fig. 11, an example of a selected random reconstructed frame at given distance = 1000mm from the camera while the target placing at length of 1000mm from camera.



***Fig. 11.*** *Reconstructed image at - = 1000[mm] over the video rectify result using integral imaging reconstruction operation from Eqs. (5).*

**Localization of Objects in the Depth Axis**

In order to find 3D depth locations of objects in the 3D space, we are looking for the local higher gradient values of the gradient image [12]:



(6)

The average gradient magnitude of the reconstructed plane (AGMR) is then calculated:



(7)

Where , are the numbers of pixels along the x and y directions, respectively. In our experiment we create a scene with AprilTag target placed 1000[mm] from camera array as showen in Fig. 11 and calculate the AGMR over the integral imaging (InI) reconstructed plans as shown in Fig. 12 while the predefined scanning range is 100[mm]-1400[mm], in Fig. 12 we can see that the higher AGMR calculated value is exactly at 1000[mm] there we placed the AprilTag target. By detecting the maxima peaks of Fig. 11 graph, we can estimate object existence in the scene.

Chart, line chart

Description automatically generated

***Fig. 12.*** *Detection of object existent by measured AGMR over the InI reconstructed planes (over a rectangle region as shown in Fig. 13) on a static scene with AprilTag target placed 1000[mm] from camera and predefined scanning range from 100-1400[mm] in the depth axis Z.*

The AGMR calculated at the Green region as showen in Fig.13. In this example the AGMR from Eqs. (7) calculated on a different integral imaging reconstructed planes according to Eqs. (5).

A picture containing night sky

Description automatically generated  

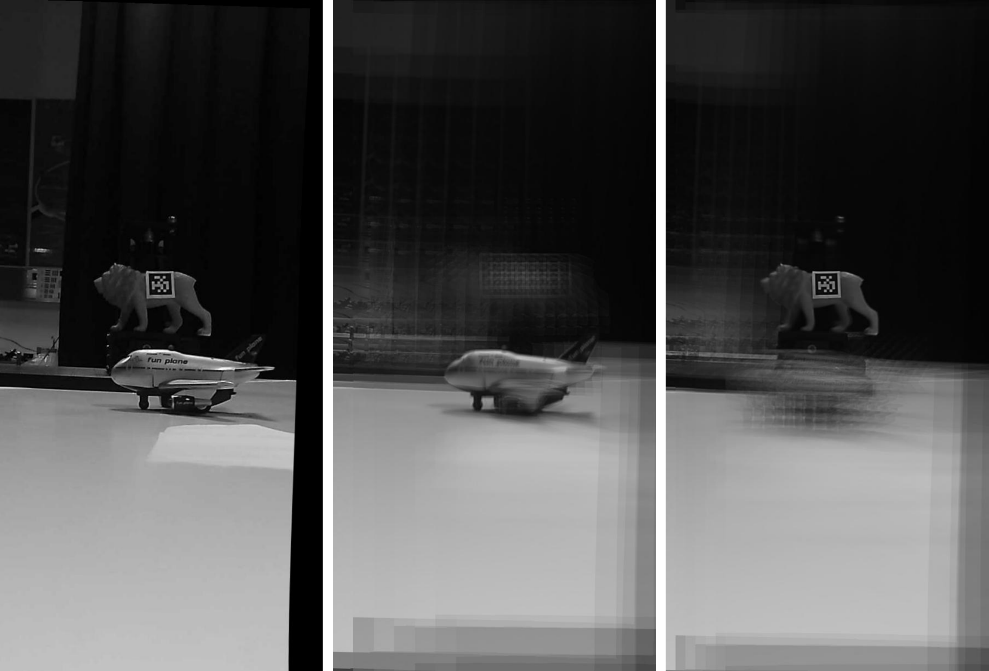
***Fig. 13.*** *In the left image, the integral imaging reconstructed plane with given =120[mm]. In the middle image, the integral imaging reconstructed plane with given =1000[mm]. In the right image, the integral imaging reconstructed plane with given =1380[mm]. While the AGMR* *measured region is in the green square and the tag placed 1000[mm] from camera.*

The main goal is to detect the focused regions which are likely belonging to the objects located at that reconstructed plane depth, to automatically identify the objects located at the reconstructed plane. Reconstructed images may include at every reconstructed planes focused and defocused regions. The image of each reconstructed plane has a space-variant defocus level. The defocus level depends on the distance between the object at the corresponding scene location and the reconstructed plane [2]. While object surfaces that located at the specific reconstructed plane are fully focused in the image. By finding the AGMR local maxima peak over the InI reconstructed plans whit a prominence threshold we can declare that object exist in the reconstructed plane, calculated over a predefined scanning range to locate objects in the 3D space, as shown in fig. 14. While in this example the AGMR measured on the entire frame and not on a specified region.

Chart, line chart

Description automatically generated

***Fig. 14.*** *Calculated AGMR over the InI reconstructed plans and the detected 2 local maxima peaks (with* *a prominence threshold of 0.5) at 300mm and 600mm while the scanning range is 200-1000mm over Fig.15 scene.*

****

***Fig. 15.*** *Reconstructed images in the detected peaks of the AGMR over the InI reconstructed plans experimental results on a scene with static object, in left the elemental image while in the experimental scene we placed airplane toy 300mm in front of the array and a lion toy 600mm in front of the array. In the middle image, reconstructed plane in a z =300mm and in the right image z = 600mm*

**Integral imaging on a moving object**

Now that we can calibrate and rectify the video camera array and also detect localization of objects in the depth axis using AGMR on integral imaging reconstructed planes, we applying the calibration process over video frame acquisition from the video camera array that captures a moving object in the scene. The purpose of that is to locate the object in the depth axis and track the object in the depth axis. As shown in Fig. 16, an example of a selected random frame of the video camera array calibrated elemental image.

A picture containing indoor, camera, projector

Description automatically generated

***Fig. 16.*** *Calibrated elemental image of a video frame acquisition (random selected frame) during moving object scene (Car toy).*

As shown in Fig. 17. An example of a selected random reconstructed frame at given distance =375mm, while the front of the car toy placing at length of 375mm from camera, and the target placed at length of 800mm from camera, in the image we can see the defocus regions (target area) and the focus region in the car area.

A picture containing blurry

Description automatically generated

***Fig. 17.*** *Reconstructed image at =375mm on a moving car toy, while the front of the car toy placed 375mm from the array*

By having the technic to detect localization of objects in the depth axis by using AGMR over the integral imaging reconstructed planes, we can track the depth location of a moving objects in the scene by using a continues calibrated frames from the video array and calculate the integral imaging reconstructed plans in a increasing predefined distances on a predefined scanning range. After we detect the object localization in the depth axis we scanning in a shorter range near the detected depth of the object to reduce computing power by having a shorter rang to scan. In Fig. 18 we demonstrate the depth over time, which is the frame number of a array video, grabbed in a 30 frame per sec. The video grabbing a scene of a moving car toy as shown in Fig. 11, witch is the first frame number of the video. There, the car toy detects in a depth of 375mm from the camera array. slowly we moves the car closer to the camera and back to the same location. By tracking near detected object, frame by frame, we can see one of the big advantages of a video camera array for integral imaging system.

Chart, line chart

Description automatically generated

***Fig. 18.*** *Depth over time of the moving car toy*

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