

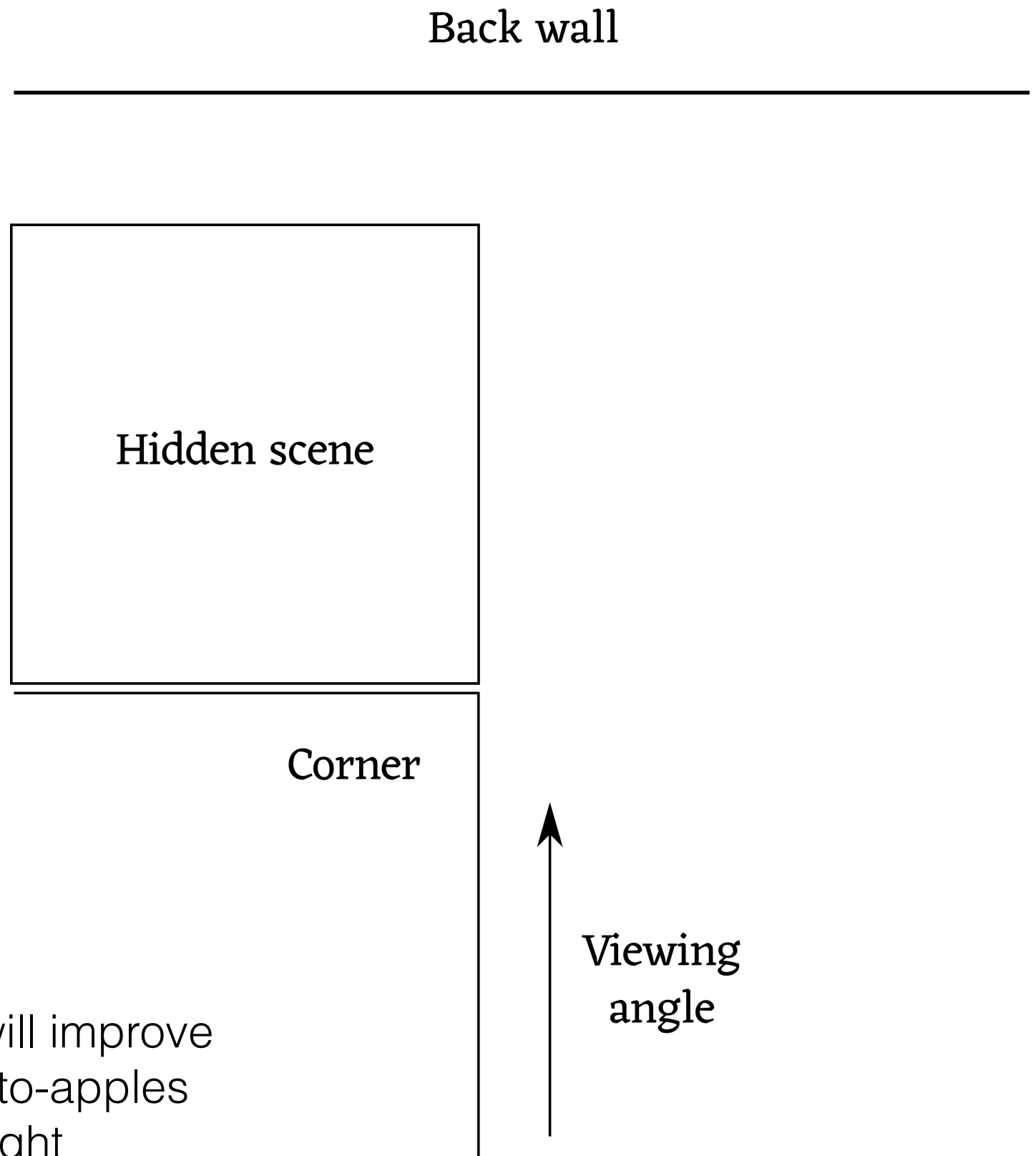
When peering into a room partly hidden by a corner (or other wall), we can make use of that corner to infer information about the hidden scene. The occlusion from the corner makes the reconstruction problem better-conditioned.

We believe that this specific scenario lends itself particularly well to a hybrid active-passive approach. Introducing time-of-flight information into the problem yields two benefits:

- We can image static scenes
- We gain a second dimension in our reconstructions (depth)

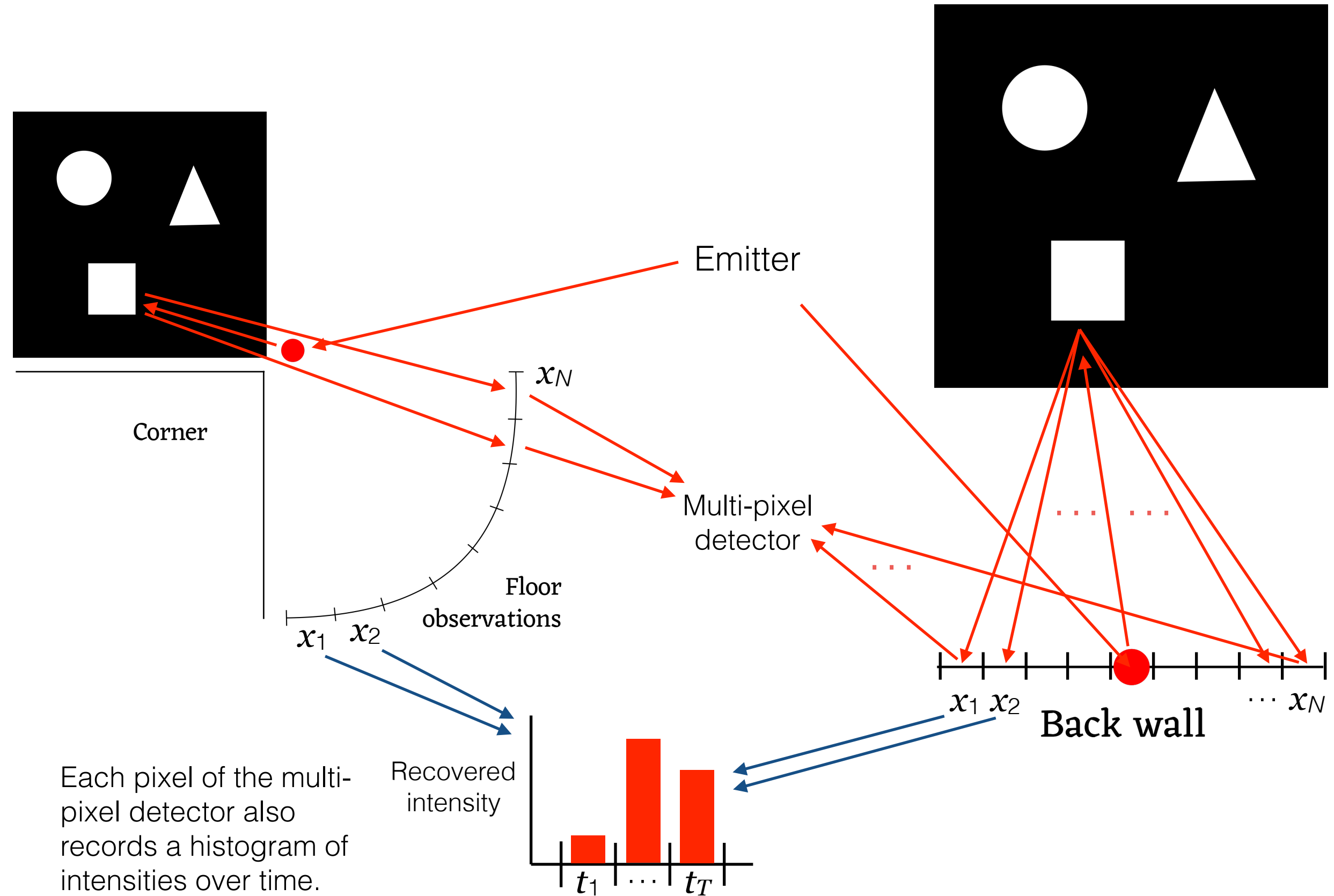
Obviously, introducing time-of-flight will improve reconstruction quality. For an apples-to-apples comparison, we compare a time-of-flight approach that makes use of the corner to one that makes use of the back wall.

Top-down view of the imaging setup



Corner imaging (top-down view)

Back-wall imaging (top-down view)



Transfer matrix

N : # of pixels on multi-pixel detector
(spatial resolution)

T : # of buckets in time histogram
(temporal resolution)

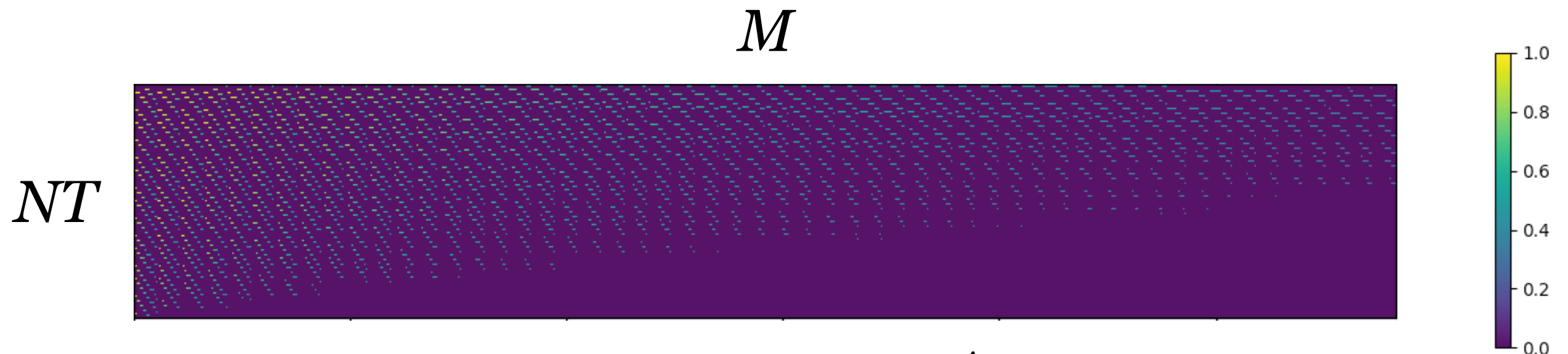
M : # of pixels in the scene
(simulation parameter)

Each matrix column corresponds to the impulse response from one point in the scene.

Each matrix row corresponds to the observations recorded from at one bar of the time-histogram from a single spatial observation.

Matrix entries take a value of 0 if the no light from that part of the scene returns at that time and space.

Otherwise matrix entries take a non-zero value.



The transfer matrix A

Vector of spatio-temporal observations

Vectorized scene

Poisson noise

SNR

Scene prior covariance matrix

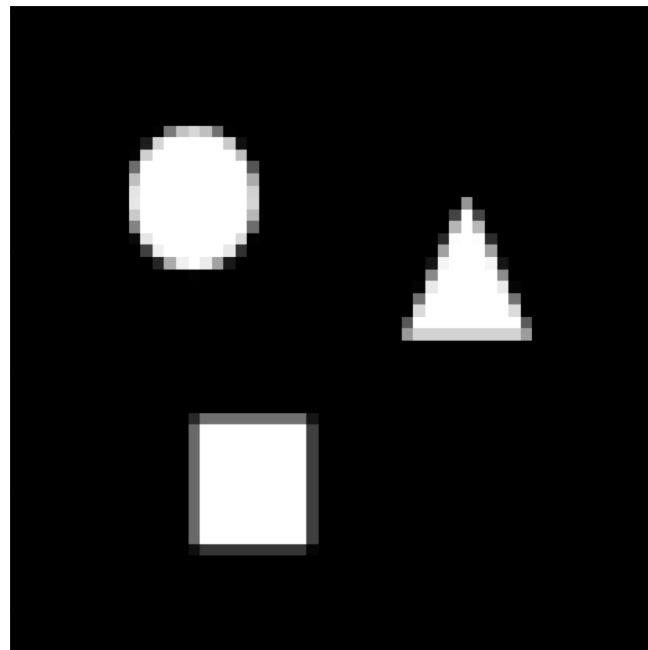
Reconstructed scene

$$y = Ax + \eta$$

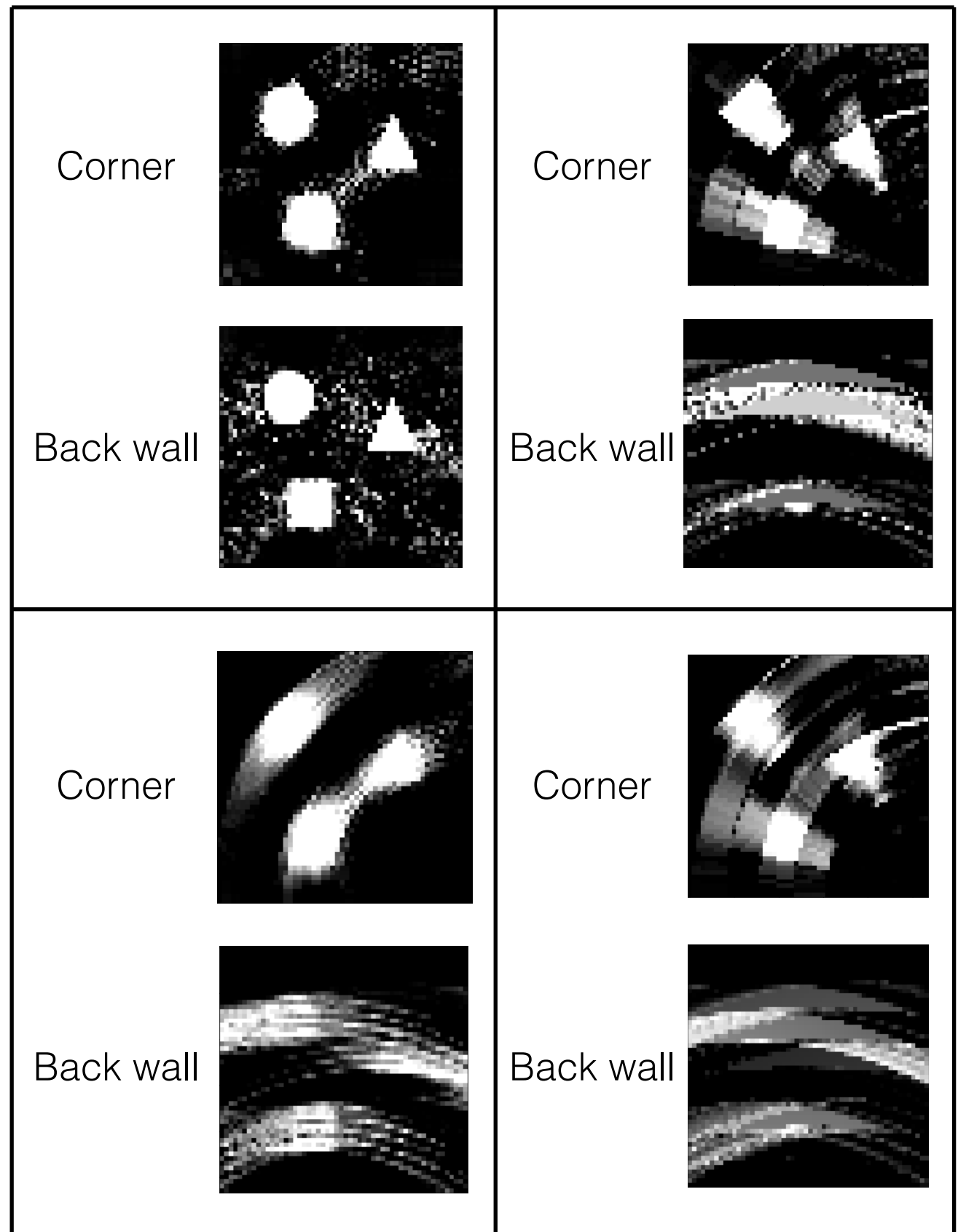
$$\hat{x} = \gamma^{-1} A^T (\gamma A Q A^T + I)^{-1} y$$

Reconstruction matrix

Ground truth



High SNR
(40 dB)



Low SNR
(0 dB)