The Microsoft Kinect is a human interface device originally developed for the Xbox to facilitate natural user interraction. The Kinect has a 640x480 RGB camera as well as a 640x480 IR camera. An infrared projector shines a known dot pattern on the scene, and by computing disparity between the known pattern and what is observed from the IR camera, a depth value can be computed for any given pixel.

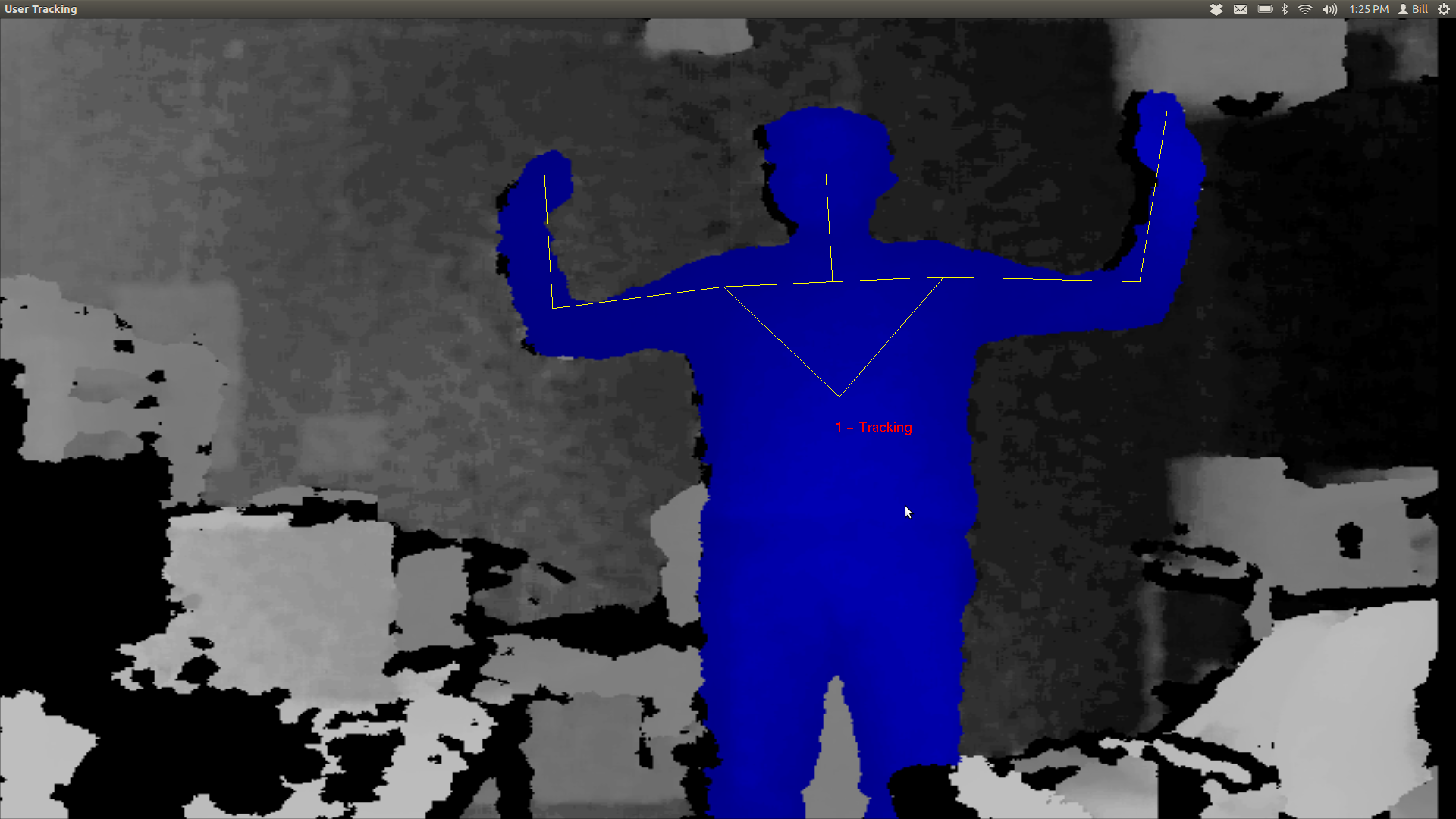
The Kinect is remarkably proficient at its intended task, although when mounted on a moving base like Harlie, the Kinect is operating outside of its design parameters. The Kinect has a limited field of view (57 degrees), and normally has to be calibrated on a user before tracking can begin. The Kinect was designed to track users from a fixed position, and has trouble when used from a mobile vantage point. The Kinect is especially sensitive to sudden jolts and vibrations. The Kinect also does not work well outdoors, especially in direct sunlight (which interferes with the projected IR pattern).

The Kinect is accessed through an open-source API called OpenNI (Open Natural Interraction). However, the actual skeleton tracking is done by a closed-source binary (NITE, made by PrimeSense.) NITE provides few options for configuration, so it was not possible to probe the inner workings of the drivers and provide fixes at that level. Higher-level software workarounds had to be employed.

The Kinect has several disadvantages that had to be overcome, largely due to the closed-source nature of the skeleton-tracking software.

# CALIBRATION

By default, whenever OpenNI detects a new user in its field of view it requires the user to stand in a calibration pose to enable an accurate measure of the user's limbs. This calibration step takes several seconds and requires the target to be still.



When the Kinect is on a moving base, occasionally the target will be lost due to relative motion or jolts as discussed later. Upon target reacquisition, recalibration is frequently necessary. Recalibration would require both Harlie and the target to come to a halt, which is unacceptable given the goal of smoothly following the target. Luckily, through somewhat of a hack, OpenNI can be instructed to save the calibration of the first detected user, and for all subsequent users to use the saved calibration.

Skipping the calibration step comes at a cost. The distinctive pose required for calibration reduces the possibility of the robot following the wrong user, because it is highly unlikely that a bystander would make the pose. Without the calibration step, Harlie no longer has an easy way of telling which user to track. Furthermore, when on a moving base, the Kinect tends to classify some chairs as users. These chairs would never pass the calibration step, although without calibration they appear as spurious measurements.

Also an issue with OpenNI, the default behavior of the software is to track the entire human body (head, arms, torso, and legs). Full-body tracking is desirable for the Kinect’s intended application as a game controller, although Harlie's Kinect is mounted in such a way that users’ legs are often obscured (INSERT MECHANICAL DRAWING OF KINECT'S FOV). Luckily, OpenNI can be instructed to ignore legs and just track the target's upper torso , head, and arms. This results in an additional tradeoff: without the shape cues that legs provide, the tracking software loses an important characteristic that can discriminate people from inanimate objects.

# DISCRIMINTATION BETWEEN USERS

A major issue with the Kinect is the lack of built-in facilities for discriminating between different users. While in theory the Kinect has the potential to store color and texture information to recognize individuals, in practice, once OpenNI calibrates on a user, no information is stored other than limb measurements.

If a user exits the scene, there is no guarantee that when the user is re-detected that user will be assigned the same ID. The same is true if a target is momentarily lost due to a sudden bump or relative motion.

The Kinect relies on continuity between frames to maintain a lock on a target, which is perfectly fine for its intended application as a game controller where players never leave the field of view and the Kinect is stationary so the target lock is rarely broken.

However, for my application with a moving base, frequent dropouts are a fact of life and must be dealt with. My solution, as explained later, is to use the Kinect as one of several inputs to a Kalman filter that tracks the overall hypothesized location of a person (to be discussed in a later section.)

# LIMITED FIELD OF VIEW

The Kinect has a field of view of 57 degrees. While this is sufficient for tracking a target with limited freedom from a fixed vantage point, it shows weaknesses for moving targets.

When using the Kinect as the sole source of observation, Harlie must constantly face the user (within ±29 degrees) or lose the target. This puts severe constraints on the ability to maneuver and plan paths while maintaining contact with the target.

Even a task such as following a target down a straight hall can be problematic. If an obstacle appears between the user and the robot, the robot must navigate around the obstacle. As part of the obstacle avoidance, the robot will likely rotate far enough that the user leaves the Kinect's field of view, leading to a target loss. When the robot once again faces the user, it will have to re-acquire the user, leading to delay.

The situation becomes even worse if the user doubles back behind the robot. In tight spaces such as hallways, the user will necessarily come close to Harlie when moving behind it. The Kinect’s depth camera breaks down when targets are approximately closer than 0.7m away. Thus, Harlie has a blind spot when relying on the Kinect alone, and has trouble tracking targets that are very close. In a hallway scenario, this can result in Harlie being stuck pointing at close range to a wall, within the blind-spot range. (IMAGE OF DESCRIBED SCENARIO WITH TWO-FOOT BLIND SPOT)

# MOVING BASE PROBLEM

The Kinect was designed to be placed in front of a television to track users playing a game. Mounting the Kinect on Harlie's moving base poses challenges outside of the Kinect’s design parameters. Tests were performed to characterize the Kinect's performance from a moving base. First, the robot was rotated back and forth through with a sinusoidal velocity profile through 1 radian of angle, corresponding to the Kinect's FOV. Second, performance was tested with the robot in motion front to back, also with a sinusoidal velocity profile.

When the Kinect is still, its performance is obviously best. The Kinect can detect users rapidly moving through the scene and it can easily deal with partial occlusion. The Kinect only loses a lock when a target moves very quickly, or exits and reenters the scene. The Kinect can be confused if two users come close together, not being able to tell users apart by means other than their spatial positions.

The Kinect’s performance gradually degrades as Harlie’s angular velocity increases. With a peak velocity below 0.3 radians/sec (17 degrees/sec), the performance is almost identical to the case of standing still. The Kinect is still able to robustly track targets through its field of view with few dropsouts. As the maximum speed increases, performance starts to degrade. Around 0.5 radians/sec, the target will occasionally occasionally be dropped. Usually the Kinect will reacquire it right away, resulting as a flickering effect as the Kinect struggles to keep a lock. The incidence of flickering increases with speed, as well as the chance that the Kinect will lose a target and not reestablish it.

A similar trend was observed for front/back motion. At low speeds, the tracking performance is comparable to standing still. As the speed increases, the performance once again drops off.

Even so, the Kinect tracks targets from a moving base remarkably well given that it is operating outside of its design parameters. Although it frequently loses a lock, it is usually able to reacquire. Several environmental parameters were observed to affect the quality of tracking. The Kinect is able to track closer users more reliably, likely because they have a greater number of constituent pixels. Occluded users are more dificult to track, especially if the occluding object is close by [SEE PICTURE OF CHAIR BEING INTERPRETED AS BODY PART]. Relative motion is a more significant problem than absolute motion. If the target keeps pace with the robot's rotation to remain in the center of the Kinect's FOV, tracking is very accurate.



The Kinect seems to track fairly well when Harlie is in smooth motion. At any speed, though, the Kinect is very sensitive to jolts and sharp step commands in velocity. A sudden jolt, due to a bump in the floor or the dynamics of Harlie at high speed, usually causes the Kinect to drop its target. When bumps are involved, the also Kinect performs poorly at target acquisition. Frequently, the robot must come to a halt before the target can be reacquired.

In general, the Kinect performs well from a moving base. At low speeds, there is not much difference from the Kinect’s stationary performance. At higher speeds, the Kinect performs fairly well as long as bumps are not involved. The Kinect is better able to track targets with low relative motion (staying in the middle of the field of view). As soon as bumps and vibrations are introduced, the Kinect’s performance drops off rapidly.