

Annotation of Calibration Patterns for RGB-LiDAR Evaluations using Segmentation Models

Bruno Silva
Gonçalo Ribeiro
University of Aveiro
PhD. in Mechanical Engineering.

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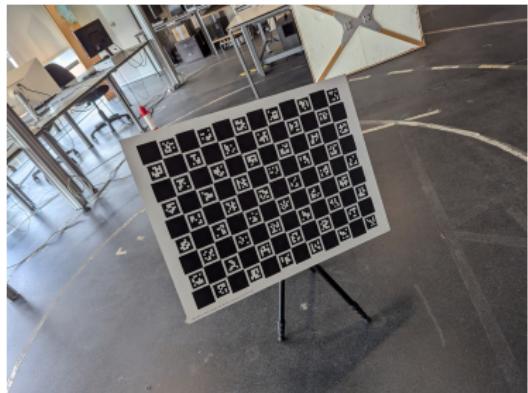
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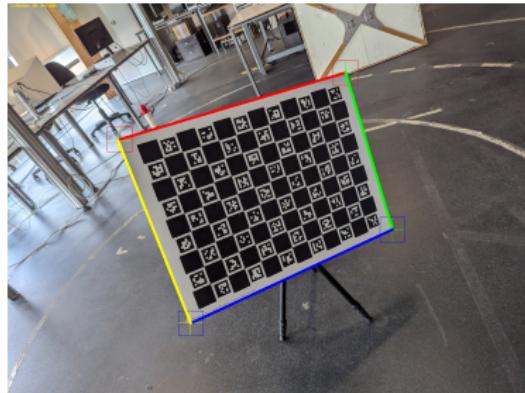
2. Abordagens

3. Conclusion

Definição do problema



Input image



Desired Output Image

Escolha do tipo de rede

Modelos de Segmentação

- Número de cantos variável visíveis na imagem;
- Possíveis obstruções parciais do padrão;
- Solução CNN + FC inviável por tamanho do output variável;
- Rede de segmentação evita todos os possíveis os edge cases.

Escolha do tipo de rede

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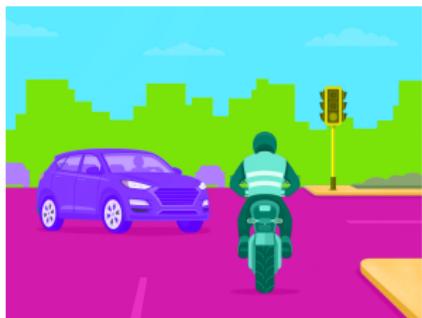
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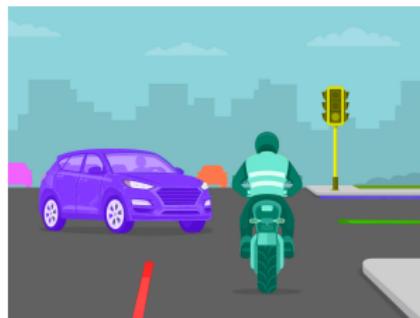
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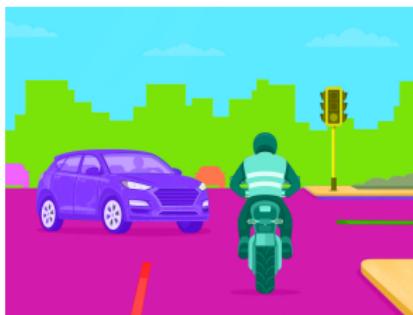
Tipos de redes de segmentação



Semântica



De instâncias



Panóptica

DeepLabV3

Com backbone Resnet50

- 41M Total Parameters
- 17M Trainable Parameters
- Model did not converge
- Complications with training

U-net

Treinada do raíz

-
-



U-net

Com Resnet50 Backbone

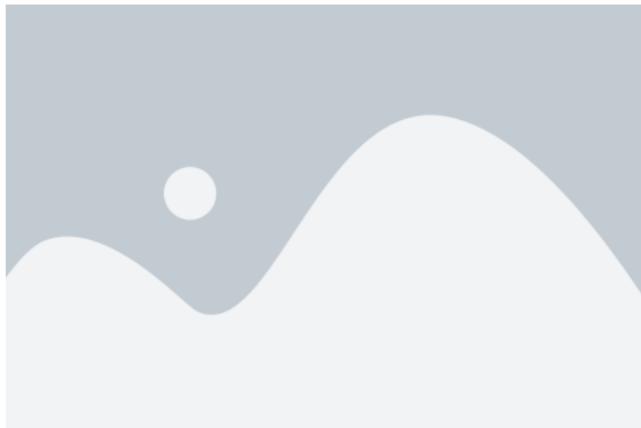
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Performance Comparisons



Bla



Bla

Conclusion

- The segmentation mask approach effectively overcomes the challenges of variable outputs and occluded corners in calibration pattern detection.
- A U-Net model with a pretrained ResNet50 backbone delivered superior performance compared to more complex transfer learning models like DeepLabV3.
- This method streamlines the calibration evaluation process, reducing manual effort and improving overall usability.

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