

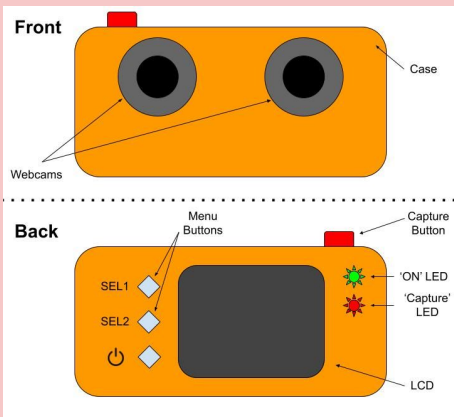
# The Do-Pro: A Minimalistic Stereo Vision Camera

Team: Timothy Do, Daniel Jilani, Zaya Lazar, Harrison Nguyen | Advisor: Dr. Glenn Healey



## Background:

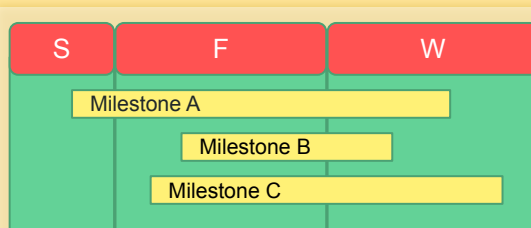
To perceive depth, two images of a scene must be observed at different points along a shared axis. Stereo vision cameras are specialized instruments designed to produce depth from at least two images. These cameras are specialized and expensive with state-of-the-art commercial cameras costing \$500 and requiring a mount. In this proposal, we aim to produce a more affordable stereo vision camera designed for versatile applications.



A conceptual illustration of the proposed stereo vision camera. The camera is similar in style to most handheld digital cameras

## Milestones:

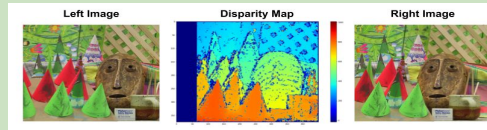
- Milestone A - Develop simple stereo camera model and achieve functionality on breadboard
- Milestone B - Calibrate stereo-vision cameras
- Milestone C - Implement stereo vision processing, camera software mechanics, and PCB functionality



## References:

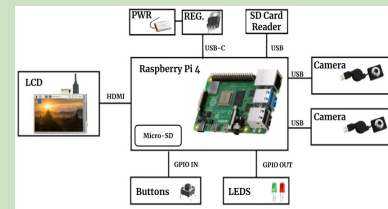
- [1] A. Vij, "Stereo vision: How do 'terminators' see the world?," *Medium*, 23-Mar-2021. [Online].
- [2] B.K.P. Horn,, "Robot Vision", Cambridge, MA: MIT Press, 1986, ch. 13.
- [3] D. Scharstein, R. Szeliski and R. Zabih, "A taxonomy and evaluation of dense two-frame stereo correspondence algorithms," *Proceedings IEEE Workshop on Stereo and Multi-Baseline Vision (SMBV 2001)*, 2001, pp. 131-140, doi: 10.1109/SMBV.2001.988771.

## Software Deliverable:



Example of depth estimation on stereo vision image set.

## Hardware Deliverable:



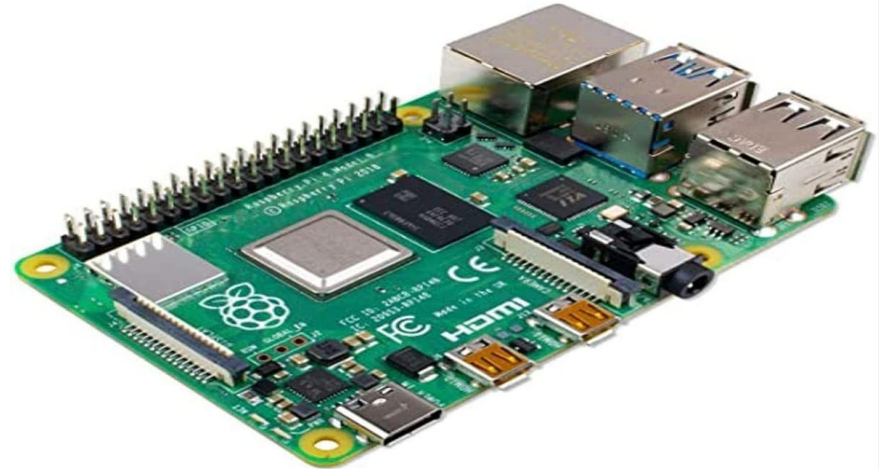
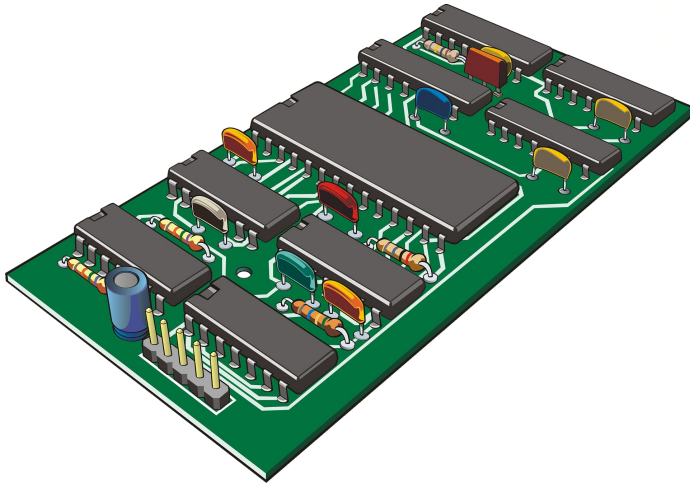
High level wiring schematic of the proposed stereo vision camera system

## General Deliverables:

- Functional camera – 3D-printed chassis and manufactured PCB
- Auto-calibration
- Image & video Processing
- UI + touch screen + instruction manual
- \*\*\*Object tracking\*\*\*

# Estimated Expenses

\$185



# Stereo-Vision Demonstration



[https://youtu.be/KSEhb\\_ojmms](https://youtu.be/KSEhb_ojmms)