robotics hw4 cv

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2023 / 11 / 29

Regression

Extend camera matrix to homogeneous form 4×4 and denote as CameraMat. Objects position in base coordination, gripper coordination and image coordination are denoted as obj_base, obj_gripper and obj_img respectively. Under the pinhole camera, we can write the projection relation from base coordination to image coordination as.

$$
\begin{bmatrix}
\text{obj\_img\_w} \times \text{obj\_img\_d} \\
\text{obj\_img\_h} \times \text{obj\_img\_d} \\
\text{obj\_img\_d} \\
1
\end{bmatrix}
= \text{CameraMat} \times T_{\text{gripper to camera}} \times T_{\text{base to gripper}}
\begin{bmatrix}
\text{obj\_base\_x} \\
\text{obj\_base\_y} \\
\text{obj\_base\_z} \\
1
\end{bmatrix}
$$

We have already known that

$$
\text{obj\_img\_d} \times \sqrt{\text{obj\_area}} = \text{obj\_alpha} \qquad \text{obj\_img\_d} = \text{obj\_alpha} \times \text{obj\_area}^{-0.5}
$$

obj_alpha only depends on object. Then

$$
\begin{bmatrix}
\text{obj\_img\_w} \times \text{obj\_alpha} \times \text{obj\_area}^{-0.5} \\
\text{obj\_img\_h} \times \text{obj\_alpha} \times \text{obj\_area}^{-0.5} \\
\text{obj\_area}^{-0.5} \\
1
\end{bmatrix}
$$

$$
=
\begin{bmatrix}
\text{obj\_alpha} & 0 & 0 & 0 \\
0 & \text{obj\_alpha} & 0 & 0 \\
0 & 0 & \text{obj\_alpha} & 0 \\
0 & 0 & 0 & 1
\end{bmatrix}
\begin{bmatrix}
\text{obj\_img\_w} \times \text{obj\_area}^{-0.5} \\
\text{obj\_img\_h} \times \text{obj\_area}^{-0.5} \\
\text{obj\_area}^{-0.5} \\
1
\end{bmatrix}
$$

$$
= \text{CameraMat} \times T_{\text{gripper to camera}} \times T_{\text{base to gripper}}
\begin{bmatrix}
\text{obj\_base\_x} \\
\text{obj\_base\_y} \\
\text{obj\_base\_z} \\
1
\end{bmatrix}
$$

Merge obj_alpha, CameraMat and $T_{\text{gripper to camera}}$ to obj_M. Then

$$
T_{\text{base to gripper}}
\begin{bmatrix}
\text{obj\_base\_x} \\
\text{obj\_base\_y} \\
\text{obj\_base\_z} \\
1
\end{bmatrix}
= \text{obj\_M}
\begin{bmatrix}
\text{obj\_img\_w} \times \text{obj\_area}^{-0.5} \\
\text{obj\_img\_h} \times \text{obj\_area}^{-0.5} \\
\text{obj\_area}^{-0.5} \\
1
\end{bmatrix}
$$

Regressing to acquire obj_M. The regression process needs N cases ($N \geq 4$). Each case contains: 1. a captured image, 2. the transformation from base coordination to gripper coordination when the image is captured, 3. object locations in base coordination.

Inference

When inferring, $T_{\text{base to gripper}}$ and obj_M show be known. obj_img and bj_area also can be detect from image. Then

$$
\begin{bmatrix}
\text{obj\_base\_x} \\
\text{obj\_base\_y} \\
\text{obj\_base\_z} \\
1
\end{bmatrix}
= T^{-1}_{\text{base to gripper}} \text{obj\_M}
\begin{bmatrix}
\text{obj\_img\_w} \times \text{obj\_area}^{-0.5} \\
\text{obj\_img\_h} \times \text{obj\_area}^{-0.5} \\
\text{obj\_area}^{-0.5} \\
1
\end{bmatrix}
$$