

A Deep Learning Approach to Camera Pose Estimation

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Abstract—The task of camera pose estimation aims to find the position of the camera in an image within a given environment. While different geometric approaches have already been studied in the literature, the aim of this project is to study the performances of deep learning models for the camera pose estimation problem. In this work, we analyze models for both relative camera pose estimation (MeNet) and absolute camera pose estimation (PoseNet, MapNet). Moreover, we propose a pipeline for the generation of a ground truth dataset based on structure from motion techniques (COLMAP). Finally, we (1) show how the proposed framework has been used to build a dataset of the second floor of the Povo 1 building in the University of Trento, (2) train an absolute pose estimation model with PyTorch, (3) and deploy it through a web dashboard using FastAPI. The deep learning approach could give interesting results in combination with geometric methods, especially for: relocation after lost tracking, closed-loop detection, better dealing with moving objects in the scene.

Index Terms—camera pose estimation, COLMAP, deep learning, vision

I. INTRODUCTION

The *camera pose*, referenced also with *camera extrinsics*, can be expressed as a combination of two components:

- 1) a tuple of three elements that identifies the absolute coordinates x, y and z in a reference space:

$$x_c = (x, y, z) \quad x, y, z \in \mathbb{R} \quad (1)$$

- 2) a quaternion of four elements that identifies the rotation of the camera:

$$q_c = (qw, qx, qy, qz) \quad qw, qx, qy, qz \in \mathbb{R} \quad (2)$$

Consequently, the pose is referred as $p_c = (x_c, q_c)$.

It is important to notice that this is not the only available representation of a pose: other methods are based also on rotation matrices and Euler angles. It is worth specifying that even if Euler angles are the most straightforward and efficient in terms of memory consumption, they suffer from the Gimbal lock problem. Even if rotation matrices guarantee a good representation, they are more memory expensive (9 values) than quaternions (only 4 values): for this reason the latter form is preferred here.

Given an image I_c captured by a camera C , an absolute pose estimator E tries to predict the 3D pose orientation and location of C in world coordinates, defined for some

arbitrary reference 3D model. The *absolute pose estimation (APE)* problem can be formally defined as the problem of estimating a function E taking as input an image I_c captured by a camera C and as output its respective pose:

$$E(I_c) = (x_c, q_c) \quad (3)$$

Apart from APE, a popular task is also *relative pose estimation (RPE)*. In this kind of approach the estimator takes two images I_c^1 and I_c^2 captured by C and aims to predict the relative pose between them. In this case, the formulation of the function E described in eq. (3) is a little different, since it receives in input two images:

$$E(I_c^1, I_c^2) = (x_c^{rel}, q_c^{rel}) \quad (4)$$

where x_c^{rel} is defined as the absolute pose with *coordinates reference system* in I_c^1 or, in an equivalent way, as the translation vector from I_c^1 to I_c^2 .

With this work, we show how it is possible to build a deep learning model which is able to learn the function E using a data-driven approach.

II. RELATED WORKS

In the literature there are many deep learning approaches used to perform RPE and APE: here we focus on MeNet for the first and PoseNet and MapNet for the latter.

APE deep learning models rely mostly on *transfer learning*: the idea is to use SOTA vision models to extract features from images and use them to estimate camera extrinsics. The PoseNet model (link to paper) has been the first to be developed following this idea. The starting network for the knowledge transfer was a GoogLeNet (link to paper), where the softmax classification layer is replaced with a sequence of fully connected layers. Even if the obtained results are decent, the model lacks of generalization when applied to unseen scenes.

In order to solve this problem, other techniques have been developed, which can be classified in:

- *end-to-end* approaches;
- *hybrid* approaches.

Most of the end-to-end proposed models are based on the PoseNet architecture, with the addition of some components, such as *encoder/decoder blocks*, *linear layers*, and *LSTM*

blocks. The most successful model on this category is MapNet and related variants MapNet+ and MapNet+PGO (link to the paper).

Hybrid approaches instead try to focus on different support tasks with the goal of helping the final pose prediction. Those techniques rely on unsupervised learning, 3D objects reconstruction and other data extracted with external tools: for this reason those methods are under the scope of our work.

III. DATASET GENERATION

A. Tested approaches

The deep learning approaches explained in this document are *supervised learning* techniques that require a labeled dataset. Several paths were tested in order to generate this kind of dataset:

- *IMU sensors*: usage of gyroscope and accelerometer sensors of a smartphone to estimate the position of the camera during a video given a fixed origin point.
- *digital video*: usage of free online 3 dimensional datasets in which video can be recorded in a digital way.
- *motion capture system*: usage of a motion capture system that estimates the camera position following some tracking objects attached to the subject.
- *structure from motion techniques*: techniques that compute a sparse and dense reconstruction from a sequence of images.

The main problem encountered with IMU sensors was the high noise presence during acquisitions, the final signal was very dirty, and the resolution was not acceptable for the dataset generation. A possible solution could have been the usage of a well calibrated hardware used in other kind of contexts.

Most of the 3 dimensional acquisitions available online for free are acquired with *depth sensors* or *LIDAR sensors*, for this reason although the camera pose estimation would not have presented any errors the images would have been at low quality.

The motion capture system is able to follow the position of the tracked objects with extremely precision, the main problematic remains the association of poses to video captured from the camera held by the tracked subject. Other difficulties involved the calibration of the tool.

The techniques of structure from motion were invented with the goal of generating structures for which a huge amount of photos is available. The overall idea is to feed the algorithm with data in order to extract features and build a recomposition of the environment. A step required in order to obtain a result is the estimation of the pose of images. These intermediate requirements have been exploited by us to generate a labeled dataset.

B. Pipeline

The implemented pipeline requires a video captured by any camera, it is not required any calibration of the sensor. It is composed by several steps:

- 1) video split: the captured video is split into many frames;

- 2) structure from motion: images obtained from the previous step are fed into a structure motion tool called *COLMAP*;
- 3) cross validation dataset: positions obtained during the camera estimation of the reconstruction process are split into three batches: train, validation, test.

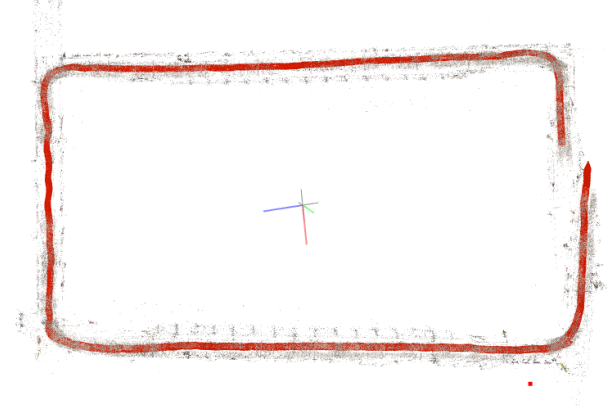


Fig. 1. Trajectory computed by COLMAP

In fig. 1 is presented the trajectory obtained with the structure from motion technique through COLMAP. The process involves a feature extraction phase, elements obtained are shown in fig. 2.

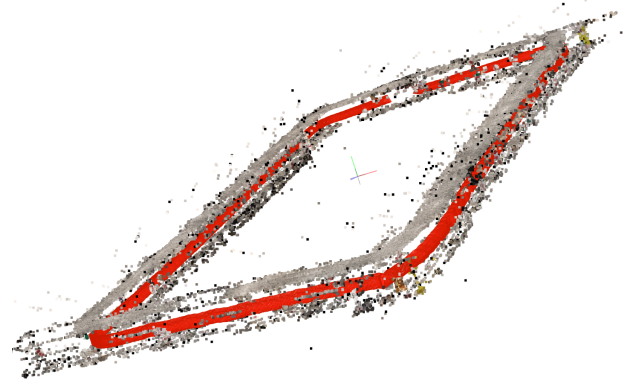


Fig. 2. Features extracted by COLMAP

IV. MODELS

In this work we took in consideration some models used in the state of the art, also adding small modifications to make them fit better to our use case scenario. In particular, we focused on:

- Menet for RPE;
- PoseNet and MapNet for APE.

A. Menet

The first model we would like to analyze is the Menet model (fig. 3), which is specifically targeted for RPE. The

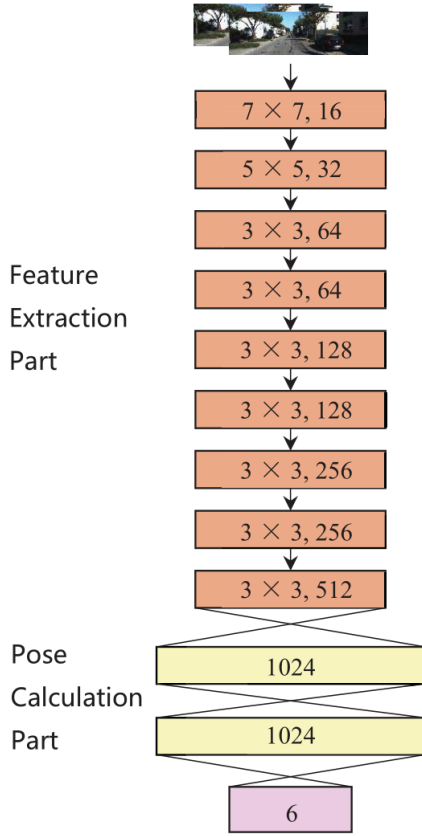


Fig. 3. The architecture of the MeNet model.

input of the network consists in a stack of two images: the goal is to estimate the relative pose of the second image with respect to the first one.

The loss function used is a composition of two Mean Square Errors (MSE) computed separately on the position and rotation. Then they are combined weighting them:

$$Loss(w) = \frac{1}{N} \sum_{i=1}^N \left\| P^i - \hat{P}^i \right\|_2^2 + \alpha \left\| Q^i - \hat{Q}^i \right\|_2^2 \quad (5)$$

where the P is the translation, Q the rotation and α the weight for balancing the displacement error and the rotation angle error.

B. PoseNet

The network is based on the ResNet architecture (reference)

...

C. MapNet

The MapNet model for APE represents an evolution of the PoseNet model: in fact, the model architecture remains actually the same. On the contrary, the main difference between the PoseNet is the loss function used to train the model. In this case, the errors in the prediction of absolute poses are not the only ones which are penalized: also errors in the relative poses are taken in consideration.

The size of the last linear block depends on the dimension of the map that we would like to introduce.

V. RESULTS

A. PoseNet

B. MapNet

Several pretrained models can be used as features extractor in the MapNet structure. In table I are presented the most powerful ones for features extraction tested on the same final linear encoder. The overall trend is similar, this highlights that the extracted features are enough for the task independently from the backbone used.

TABLE I
MAPNET BACKEND COMPARISON

Model	Position err.	Rotation err.	Params	Tr. ^a params
ResNet-18	0.202	0.0658	14,853,703	3,677,191
ResNet-34	0.187	0.0757	24,961,863	3,677,191
ResNet-50	0.220	0.0969	30,330,951	6,822,919
ResNet-152	0.233	0.0869	64,966,727	3,677,191
EfficientNet-B7	0.210	0.0848	71,658,455	7,871,495

^aTrainable

Another point that emerges is the importance of the final encoder, it works in a similar way of the *bag of words* used by structure from motion (link al paper). Extracted features are mapped in a space that is used later as a comparison tool for new images for which the pose is asked.

C. Comparison

D. Dashboard

A dashboard was developed with the aim to easily allow users to interact with model inference through a webserver. In fig. 4 is presented the *UI* where red zones are not walkable areas.

VI. MATERIALS

Every material used in the project have been uploaded respectively:

- the datasets have been uploaded on the Google Drive folder;
- the code is available in the GitHub repository.

The project has been developed in Python 3, using common data science libraries, such as numpy, pandas, PyTorch, matplotlib, scipy, and many others.

A. Repository organization

The repository follows the structure:

- camera-pose-estimation/
 - model/ contains everything related to the deep learning part of the project. It also includes the code used for implementing the web server under `webserver.py` and `static/`.
 - tools/ contains scripts used for the dataset generation pipeline.

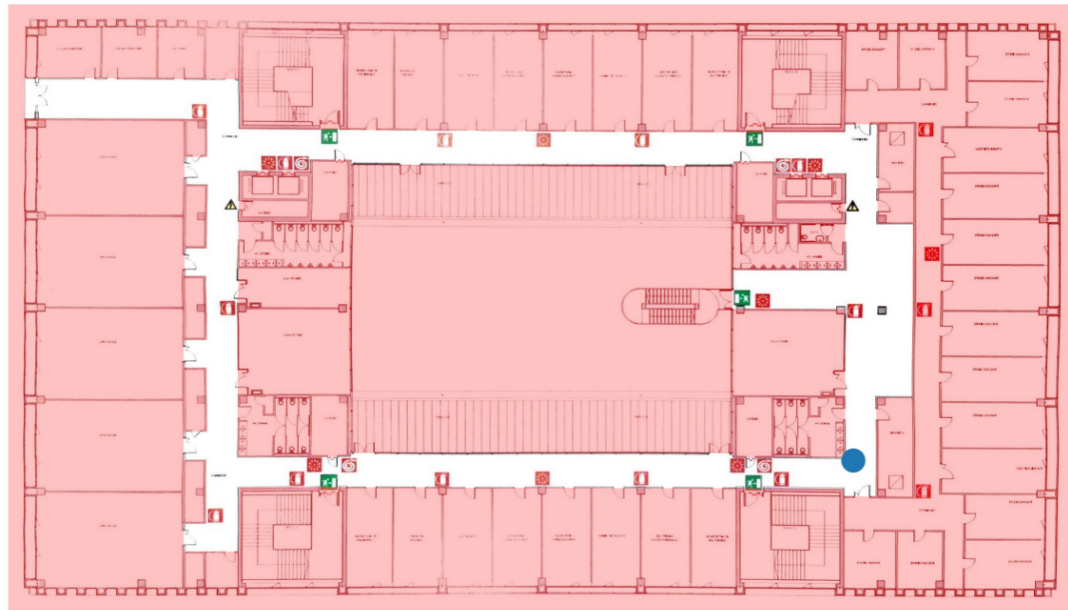
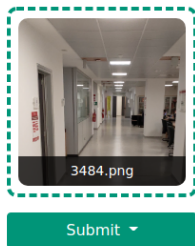


Fig. 4. Inference dashboard

- `config_parser/`: Python package written by us that allows to create configuration files, with the idea of improving reproducibility in our experiments. Each configuration file can be subdivided in sections: for each section you can define variables with the syntax `label=value`, where `value` is a parsable JSON object (boolean, int, float, list, object).
- `notebooks/` contains some Python Jupyter Notebooks that have been used for data exploration, validation, and post-processing of the model predictions.

B. Data organization

For each footage, a folder has been created:

- `imgs/` contains the video frames exported with `ffmpeg`;
- `processed_dataset/` contains the train, validation, and test datasets that can be reused during different trainings: this helps speeding up the loading procedure from ...minutes to ...seconds;
- `workspace/` contains the models generated by COLMAP;
- each of `train.csv`, `validation.csv`, and `test.csv` contains a table for specifying the pose for each image frame. This are the files generated with the `video_to_dataset.sh` script.

VII. CONCLUSION

VIII. EASE OF USE

A. Maintaining the Integrity of the Specifications

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Define abbreviations and acronyms the first time they are used in the text, even after they have been defined in the abstract. Abbreviations such as IEEE, SI, MKS, CGS, ac, dc, and rms do not have to be defined. Do not use abbreviations in the title or heads unless they are unavoidable.

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Number equations consecutively. To make your equations more compact, you may use the solidus (/), the exp function, or appropriate exponents. Italicize Roman symbols for quantities and variables, but not Greek symbols. Use a long dash rather than a hyphen for a minus sign. Punctuate equations with commas or periods when they are part of a sentence, as in:

$$a + b = \gamma \quad (6)$$

Be sure that the symbols in your equation have been defined before or immediately following the equation. Use “(6)”, not “Eq. (6)” or “equation (6)”, except at the beginning of a sentence: “Equation (6) is . . .”

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Please don’t use the `{eqnarray}` equation environment. Use `{align}` or `{IEEEeqnarray}` instead. The `{eqnarray}` environment leaves unsightly spaces around relation symbols.

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- The word “data” is plural, not singular.
- The subscript for the permeability of vacuum μ_0 , and other common scientific constants, is zero with subscript formatting, not a lowercase letter “o”.
- In American English, commas, semicolons, periods, question and exclamation marks are located within quotation marks only when a complete thought or name is cited, such as a title or full quotation. When quotation marks are used, instead of a bold or italic typeface, to highlight a word or phrase, punctuation should appear outside of the quotation marks. A parenthetical phrase or statement at the end of a sentence is punctuated outside of the closing parenthesis (like this). (A parenthetical sentence is punctuated within the parentheses.)
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- In your paper title, if the words “that uses” can accurately replace the word “using”, capitalize the “u”; if not, keep using lower-cased.
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- There is no period after the “et” in the Latin abbreviation “et al.”.
- The abbreviation “i.e.” means “that is”, and the abbreviation “e.g.” means “for example”.

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a) *Positioning Figures and Tables:* Place figures and tables at the top and bottom of columns. Avoid placing them in the middle of columns. Large figures and tables may span across both columns. Figure captions should be below the figures; table heads should appear above the tables. Insert figures and tables after they are cited in the text. Use the abbreviation “Fig. 5”, even at the beginning of a sentence.

TABLE II
TABLE TYPE STYLES

Table Head	Table Column Head		
	<i>Table column subhead</i>	<i>Subhead</i>	<i>Subhead</i>
copy	More table copy ^a		

^aSample of a Table footnote.



Fig. 5. Example of a figure caption.

Figure Labels: Use 8 point Times New Roman for Figure labels. Use words rather than symbols or abbreviations when writing Figure axis labels to avoid confusing the reader. As an example, write the quantity “Magnetization”, or “Magnetization, M”, not just “M”. If including units in the label, present them within parentheses. Do not label axes only with units. In the example, write “Magnetization (A/m)” or “Magnetization {A[m(1)]}”, not just “A/m”. Do not label axes with a ratio of quantities and units. For example, write “Temperature (K)”, not “Temperature/K”.

ACKNOWLEDGMENT

The preferred spelling of the word “acknowledgment” in America is without an “e” after the “g”. Avoid the stilted expression “one of us (R. B. G.) thanks ...”. Instead, try “R. B. G. thanks...”. Put sponsor acknowledgments in the unnumbered footnote on the first page.

REFERENCES

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For papers published in translation journals, please give the English citation first, followed by the original foreign-language citation [6].

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