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ACEngine: Augmented Reality UNIX C++ Engine for Enhanced Visual Guidance in Digital Fabrication

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Summary

ACEngine is a lightweight and fast-developing UNIX C++ engine for prototyping AR applications leveraging bleeding-edge robotic vision research for digital fabrication. It features a modular layer-stack flow, a geometry framework for managing 3D objects, a computed feedback system for visual guidance, and an AR rendering system for synthesizing digital instructions into a simple monocular camera feed.

Statement of need

ACEngine (ACE) addresses critical limitations in existing augmented reality (AR) tools for digital fabrication. CompasXR (Kenny et al., 2024), the only open-source AR tool available in the digital fabrication field, provides a valuable common platform, particularly for assembly tasks. However, it currently lacks a streamlined integration pipeline for advanced robotic vision technologies due to its reliance on Unity (Unity Technologies, 2023) and the Windows operating system (OS). In the field of AR fabrication, developers from the current Incon.ai (Furrer et al., 2024) represent the peak of AR engine innovation with robotic vision algorithm integration for digital fabrication in research (Mitterberger et al., 2020; Sandy et al., 2016; Sandy & Buchli, 2018), nevertheless, its codebase remains unavailable to the public.

AC aims to fill this gap by providing a lightweight, open-source, and UNIX-compatible C++ engine for AR applications in digital fabrication. Its software architecture is similar to existing free engines (T. ezEngine Contributors, 2024; T. T. 3D. Contributors, 2024; Linietsky et al., 2024), yet it prioritizes rapid prototyping, flexibility, and customization for extended reality (XR) manufacturing using accessible sensors and hardware. Unlike feature-rich game engines with excessive functionalities or proprietary constraints (Epic Games, 2019; Unity Technologies, 2023), ACE is lightweight, aided by the adoption of a bloat-free UI system (T. D. Contributors, 2024), and maintains full compatibility with Linux systems—crucial for integrating the latest open-source robotic vision technologies in AR manufacturing.

Layer-stack flow

The main AR engine is managed by a layer-stack flow. Designed as a modular system, each layer encapsulates the code for a specific domain of the AR application, such as camera processing, sensor's self-localization, object tracking, UI, and rendering. The general order and expansion of these layers can be configured in the top-level main file `ACApp.cpp`. This architecture provides flexibility to customize key AR features as needed, including integrating new sensors, modifying the rendering pipeline, or adapting camera pose estimation methods. For instance, users can implement pose estimation based on tags (Muñoz-Salinas et al., 2019), features (Campos et al., 2021), or hybrid (Settimi et al., 2024) approaches as supported by

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the software out of the box.

Each layer in the stack inherits from a superclass interface defined in `Layer.h`, which includes event-like methods triggered at various points during frame processing (e.g., `OnFrameAwake()`, `OnFrameStart()`, etc). These methods are invoked by the main `Run()` function in the singleton application loop from `Application.h`. This design allows application tasks to be containerized and executed sequentially while facilitating data exchange between specific layers through the `AIAC_APP` macro, enabling the retrieval of any particular layer data. Exchange between layers can also take place in a more structured way with the integrated event system (`ApplicationEvent.h`), which is capable of queuing events from layers and trigger them in the next main loop.

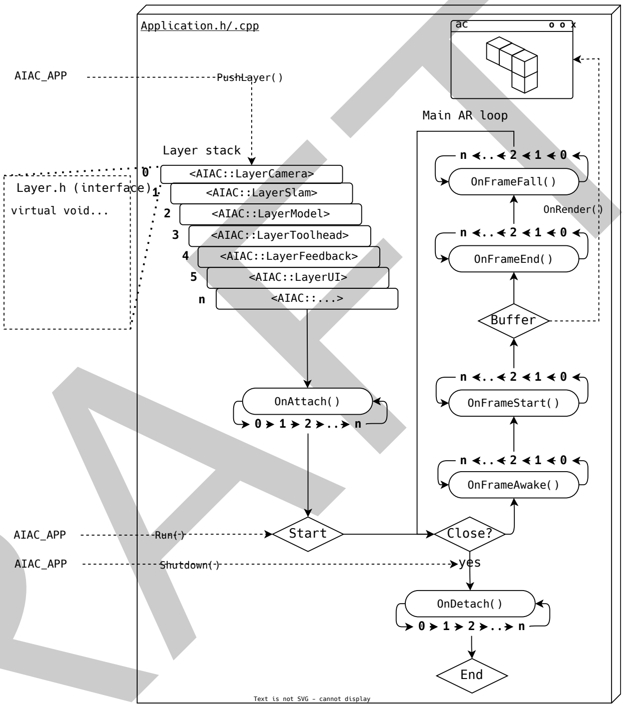

Figure 1: Illustration of the layer-stack design and the main loop for the AR engine.

Geometry framework

The geometry framework provides a unified infrastructure for handling all 3D objects in the scene, including CAD models, scanned models, and fabrication instructions. This framework enables easy interaction between application layers and 3D objects while being tightly integrated with the rendering system, which implicitly manages OpenGL resources, simplifying the workload for application layers.

The geometry is organized into the following primitive shapes: point, line, circle, cylinder, polyline, triangle, mesh, and text. Each of them is a class (e.g., `GOPoint`, `GOLine`, `GOCircle`, etc.) that inherits the base class `GOPrimitive`, where "GO" stands for Geometry Object. The base class manages general attributes and provides interfaces such as visibility and transformation, while the subclasses handle their specific data and functions.

Additionally, the system maintains a global registry, `GORegistry`, to keep track of all GOs. To add a GO to the scene, the static function `Add()` of the desired shape must be called, e.g., GOPoint::Add() or GOLine::Add(). Upon initialization, each GO acquires a unique UUID and registers itself in the global hash table. Since this table is accessible throughout the system, application layers can retrieve specific objects by their UUIDs or iterate through all objects to

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perform operations.

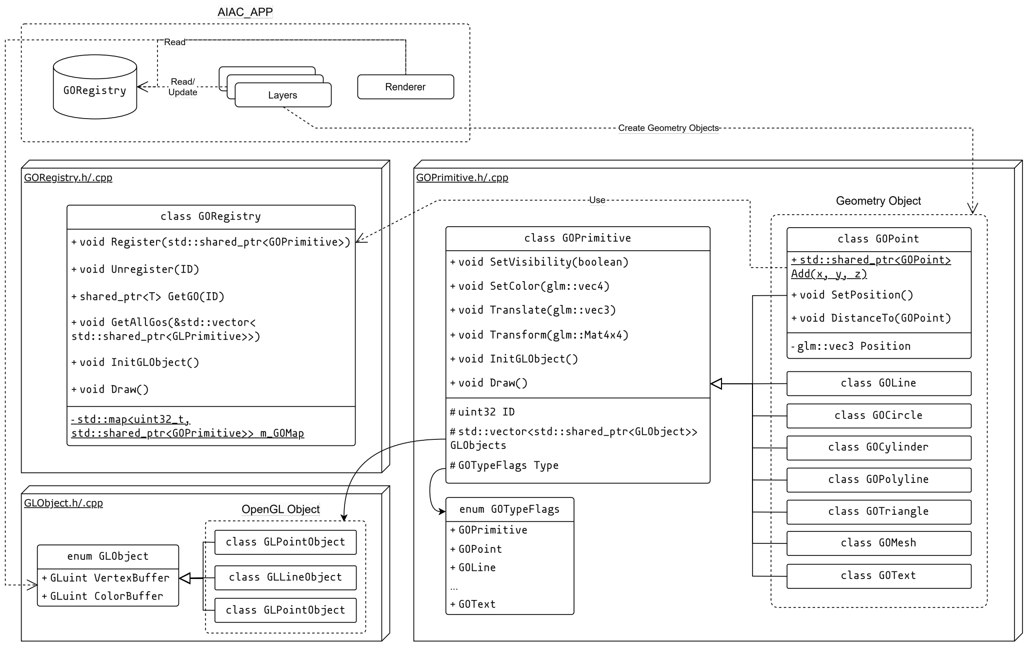

Figure 2: Structure of the Geometry Framework.

Computed Feedback System

The `LayerFeedback.h` module manages the computation of all essential data required to provide visual guidance to users during the fabrication process. Feedback computation primarily relies on data retrieved from two preceding layers:

1. `LayerModel.h`: contains the execution model and geometries associated with the currently active hole or cut.
2. `LayerToolhead.h`: provides similar information, but specific to the toolhead currently attached to the tool.

Feedback is categorized based on similar operations, such as drilling (`HoleFeedback.h`), circular cutting (`CutCircularSawFeedback.h`), and chainsaw cutting (`CutChainSawFeedback.h`). Each feedback category inherits from an interface class (`AIAC/Feedback/FabFeedback.h`), which defines high-level control functions like `Update()`, `Activate()`, and `Deactivate()`.

The visual guidance for each tool may consist of multiple visual cues, most of which are implemented using the template `FeedbackVisualizer.h`. These internal components (e.g., `CutBladeThicknessVisualizer.h` or `CutPlaneVisualizer.h`) handle their own geometric visual cue calculations and store representations as `GO` instances in a member vector of the corresponding superclass. Visualization of these `GO` elements, and thus the feedback itself, can be selectively enabled or entirely toggled on/off using the `Activate()` and `Deactivate()` functions.

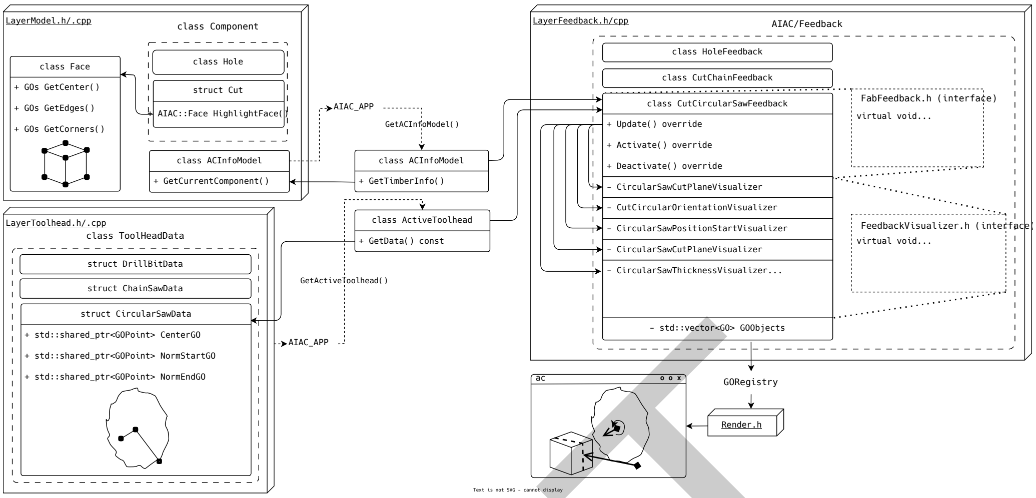

Figure 3: Dataflow for the functioning of the Augmented Carpentry's feedback system.

AR rendering

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