Mesh Adition Based on the Depth Image (MABDI)

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Abstract— **Many robotic applications, especially those whose goal is to aid or assist through human robot interaction, utilize a rich map of the world for reasoning tasks such as collosion detection, path planning, or object recognition. Such map, and the method used to produce it, must take into consideration real-world constraints. Most mesh-based mapping algorithms resemple a "black box" and do no provide a mechanism to close the loop and make decisions about the incoming information. MABDI leverages the global mesh by finding the difference between what we expect to see and what we are actually seeing, and using this to classify the incoming measurements as novel or not. This allows the surface reconstruction method to be run only on data that hasn't yet been represented in the global mesh. Resulting in an algorithm that becomes computationally inexpensive once the environment is known, but can also react to new objects.**

I. Introduction

Many robotic applications, especially those that involve human robot interaction, often require a rich representation of the environment in order to perform such behavior as path planning and obstacle avoidance. In general, a rich representation, or map, is useful for providing situational awareness to an autonomous agent. A map is also important for applications such as teleoperation [1].

The methodology to build this representation is a continuously evolving subject in the field of robotics. The origins of the research into this problem dates back roughly 25 years [2]. Since then the methods and the representations themselves have continued to evolve at an impressive rate. The main catalyst behind this growth is the advancement of sensing technologies over the same time period. In general, sensors have continued to generate measurements at higher rates, higher resolution, and lower cost over the years. This has provided an amazing opportunity to build richer and more useful representations of the environment.

In robotics map building in an unknown environment is referred to as the Simultaneous Localization and Mapping (SLAM) problem [3]. This label describes the fact that a methodology which solves the SLAM problem must simultaneously locate the robot in the environment as well as map the environment. The focus of this work is the mapping aspect of the SLAM problem. Fig. 1 gives a visualization of the goal.

There are different types of data structures that can define a map. All of which have intrinsic characteristics that impact the algorithms that generate them and create constraints that must be considered for real-world applications. In addition, we are concerned with rich representation types, in contrast to sparse representation types [4], because rich types have the most use in applications such as human robot interaction.

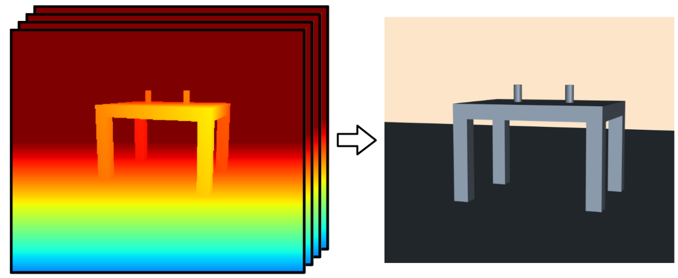

Fig. 1. Goal is to create a map from depth images

	Supported	Computationally Inexpensive	Low Memory Requirement
Point Clouds	x	x	-
Surfels	-	x	x
Implicit Functions	x	-	-
Mesh	x	x	x

TABLE I

Comparison of constraints for different map types

When considering what type of map is best for real-world applications, we must consider the constraints imposed by each type:

- Supported - Is there software, tools, research, algorithms, etc. for this type of map?
- Computationally Inexpensive - Can the algorithms be run on cost effective hardware?
- Low Memory Requirement - Can the algorithms be run on hardware with standard process memory?

Table I compares the constraints of common map types. We can see, in general a mesh type map satisfies real-world constraints. It has been used extensively by the gaming and graphics communities, and so benefits from an incredible amount of continued research and advances in hardware such as GPUs.

Currently, one of the issues with mesh mapping techniques is they are generally "black box" methods. Meaning the data comes in from the sensor, those measurements are turned into a mesh, and then that mesh is appended to a global mesh. Fig. 5 visualizes this common pipeline in black. The goal of this work is to design an algorithm to close the loop (as visualized in red) and allow the system to make decisions about the incoming data based on what it already knows.

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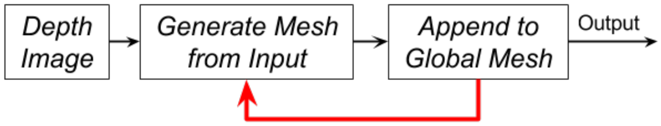

Fig. 2. Common "black box" pipeline in black. The contribution of MABDI in red.

II. Related Works

Works related to MABDI are generally based on RGB-D sensors. This type of sensor has become very popular since the release of the Kinect from Microsoft TODO ref, which was the first mass produced RGB-D sensor of its kind. RGB-D sensors are inexpensive and produce noisy 640x480 depth images at 30fps. The RGB-D sensor has excited the robotics community because this has been the first time that depth data has been so readily accessible from such an inexpensive sensor. Therefore, these methodologies must be able to quickly deal with very high rates of information.

One very impressive work came from Henry et al. in 2012 [5]. In this work they designed a system which used a RGB-D sensor to build a map made of surfels. In order to generate and maintain the surfel map they used the work of Weise et al. [6]. Surfels are circular disks which have a particular position and orientation and also a radial size based on confidence. The map consists of a large number of surfels. The surfel map can be updated given the new registered depth images from the sensor. Decisions are made of how to handle each measurement in the depth image based on the difference between an expectation generated using the current map and the actual readings from the sensor. Rendering a surfel map requires special methods [7] and is difficult to use in applications such as obstacle avoidance.

One of the next major advances was published by Whelan et al. in 2012 [8] and more recently in 2013 [9]. The system they developed was named Kintinuous and was able to produce a high quality mesh representation of the environment. Their system was a hybrid system and utilized the KinectFusion method [10] of Newcombe et al. to create a volumetric representation of the portion of the environment in front of the sensor. As the sensor moves, portions of the environment that leave the volume in front of the sensor are ray cast and turned into a mesh. They obtain very impressive results but also mention a limitation of their system for future work. The limitation is that the mesh can not be updated once created, which is an issue when revisiting parts of the environment. One of the most impressive current works which has an adaptable mesh came from Cashier et al. in 2012 [11]. In this work, they were able to generate and update a mesh with new measurements from a ToF sensor. They used the difference between the existing model and the actual measurements to decide whether to adapt the mesh or add new elements. The mesh topology was not adaptive to the environment and their experiments only showed results of mapping a single flat wall with no robot movement. The system needs to be tested for object addition and removal.

Research and development of new mapping algorithms are trending towards leveraging the information in the global map to make decisions about the incoming data. One can see parallels with how we as humans see the world. MABDI proposes do this in a computationally feasible way by using simply using differencing and thresholding imaging methods.

III. Approach

The algorithmic structure of MABDI can be seen in Fig. 3. The diagram is very similar to Fig. 5 with the exception of the Classification component, shown in blue. This Classification component is MABDI's contribution to the state-of-art in mesh based mapping algorithms, and is what gives MABDI the ability to make decisions about the incoming data.

The Classification component consists of two elements:

1) *Generate Expected Depth Image* E - Here we take the global mesh M, render it using computer graphics, and use the depth buffer of the render window to create a depth image E of what we expect to see from our sensor. This method requires the current pose P of the actual sensor (simulated for our experiments).
2) *Classify Depth Image* D - Here we classify the actual depth image D (simulated for our experiments) by first taking the absolute difference between E and D and thresholding. If the differences are small, those points are thrown away and if the differences are large, those points are kept as D_n. The idea behind this is, if the difference is large, the measurements are coming from a part of the environment that has not been seen before i.e. novel. The implication of is assumption, is that this version of MABDI can not handle object removal. It is worth noting, that MABDI can be extended to handle object removal by using the sign of the difference between E and D instead of the absolute value.

IV. Experimental Setup

References

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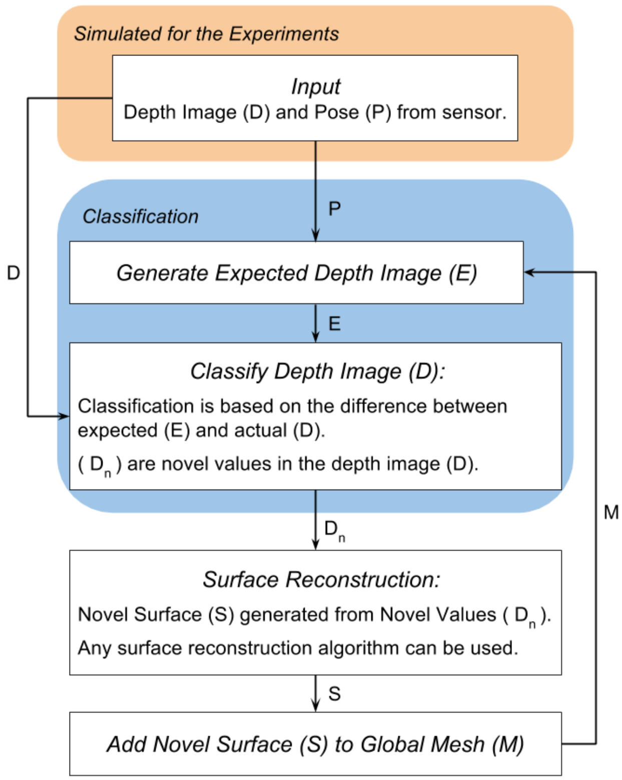

Fig. 3. MABDI system diagram

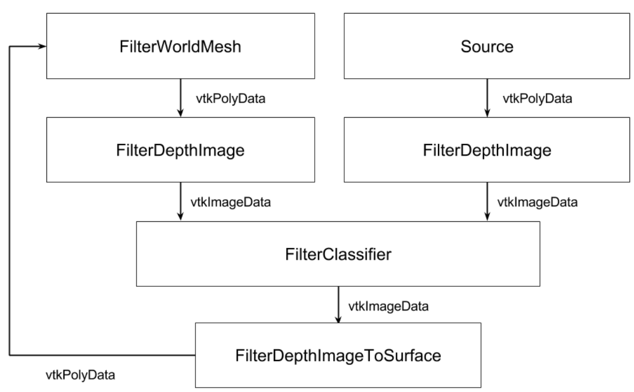

Fig. 4. MABDI software diagram

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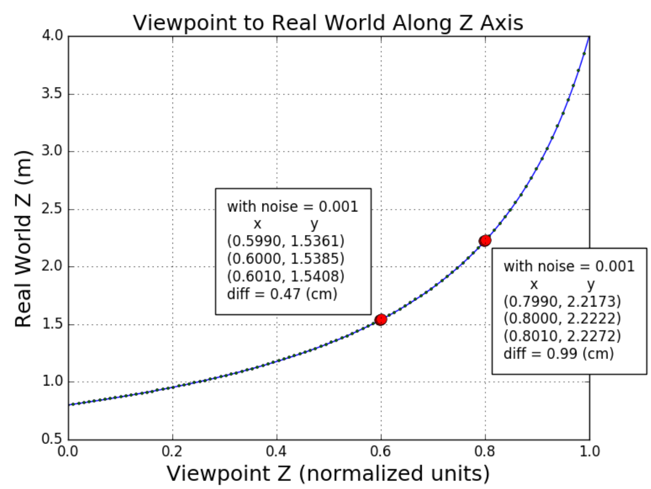

Fig. 5. Viewpoint coordinates to real world coordinates analysis. Viewpoint coordinates are obtained when a mesh is rendered into a render window, and can be transformed to real-world coordinates using the transformation matrix of the camera. Noise is added in simulation to the viewpoint coordinates. This graph shows the effect of that noise in real-world coordinates.