

Absolute scale velocity determination combining visual and inertial measurements for micro aerial vehicles

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INRIA



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Micro aerial vehicles



Micro aerial vehicles



Micro aerial vehicles



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Micro aerial vehicles



Localization in various environments

Micro aerial vehicles



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Micro aerial vehicles



A basic state vector:

$$X = \begin{bmatrix} \textit{position} \\ \textit{velocity} \\ \textit{orientation} \end{bmatrix}$$

Localization in various environments

Micro aerial vehicles



A basic state vector:

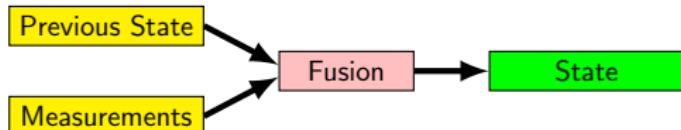
$$X = \begin{bmatrix} \textit{position} \\ \textit{velocity} \\ \textit{orientation} \end{bmatrix}$$

Localization in various environments

The goal of sensor fusion for state estimation is to **recover X**

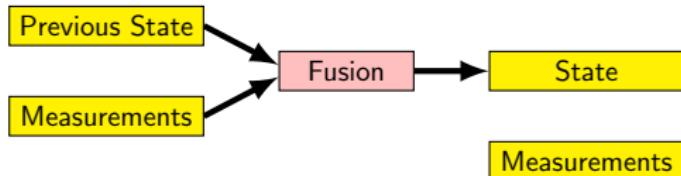
Visual-inertial sensor fusion

Filter based method



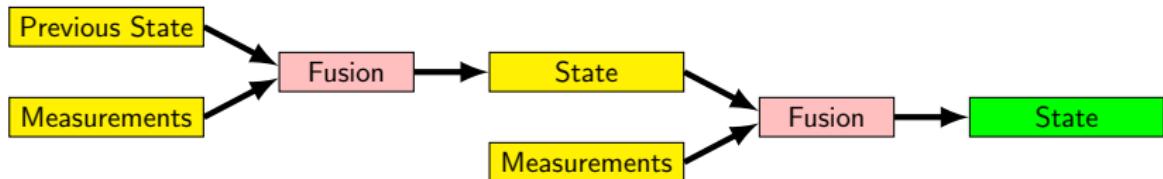
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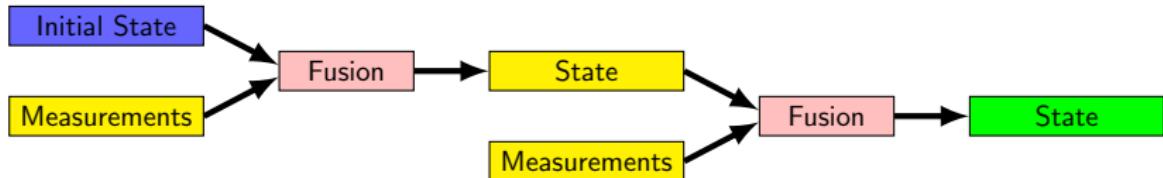
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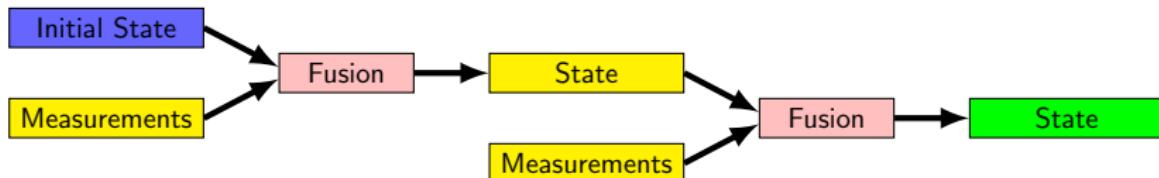
Filter based method



How to recover the **initial state**?

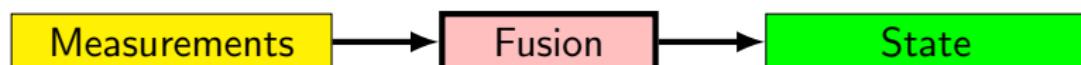
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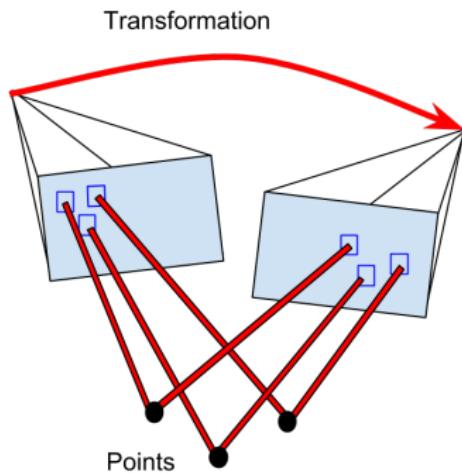


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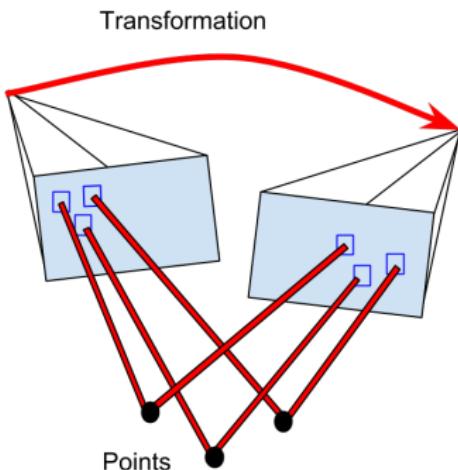
We need a **deterministic solution**



Deterministic solutions in Computer Vision



Deterministic solutions in Computer Vision



But the relative **translation** and **distance to features** are recovered only
up to scale

Absolute scale from visual measurements

How big is this building?



Absolute scale from visual measurements



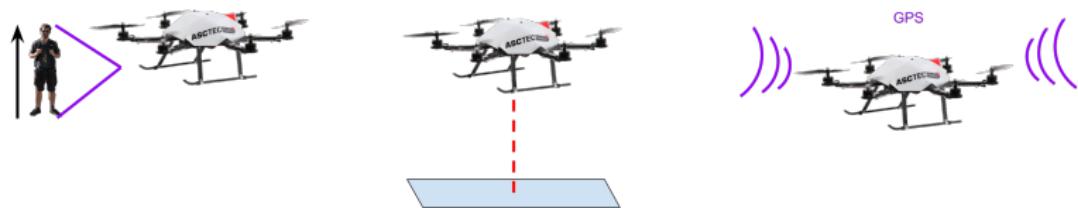
Methods to recover the absolute scale



Methods to recover the absolute scale



Methods to recover the absolute scale



Methods to recover the absolute scale



Not suited to
unknown
environments



Not precise, works
only in hover



Does not work in GPS
denied environments

Inertial Measurement Unit (IMU)

The IMU consists of two sensors providing **physical quantities**:

- ▶ Accelerometer: linear acceleration (and gravity) (m/s^2);
- ▶ Gyroscope: angular velocity (rad/s).

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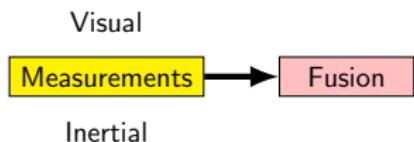
Visual

Measurements

Inertial

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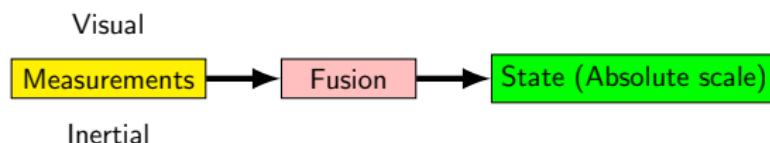


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- Validation

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The closed-form solution

Transactions on Robotics (T-RO) 2012

International Journal of Computer Vision (IJCV) 2014

The Closed-Form Solution

Requires:

- ▶ Calibrated camera;
- ▶ Inertial Measurement Unit (IMU);
- ▶ External Camera IMU transformation.

Output:

- ▶ Initial velocity;
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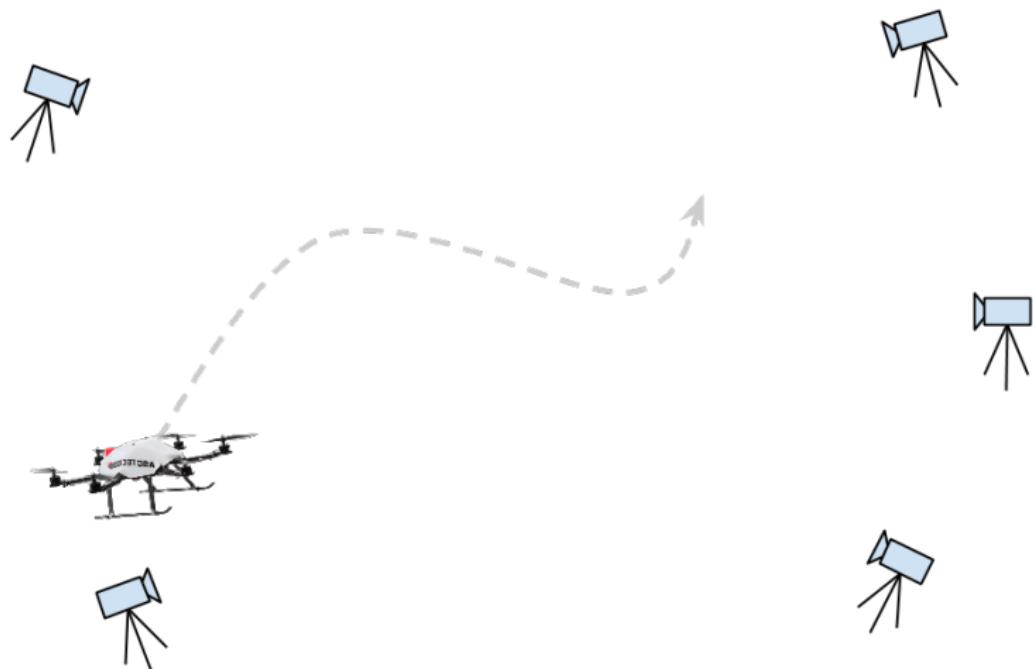
Test setup



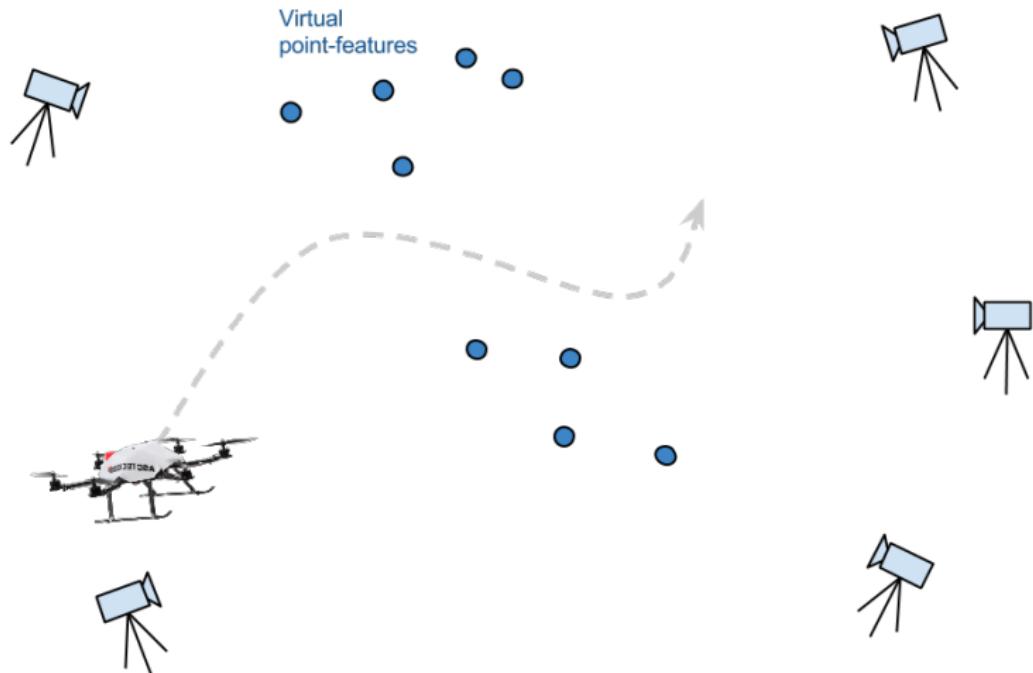
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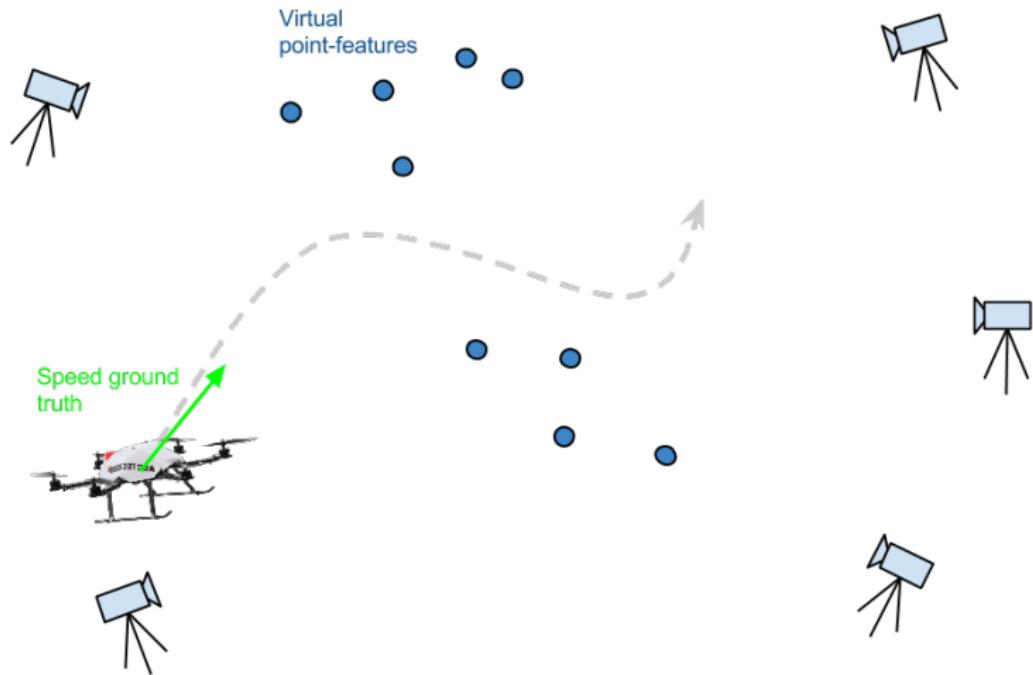
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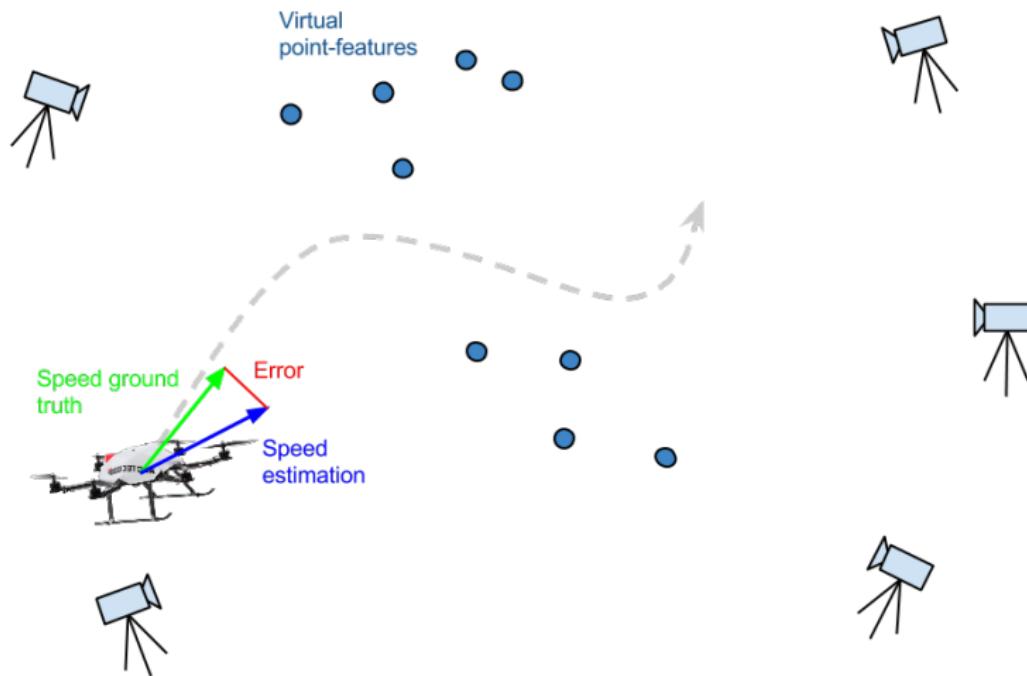
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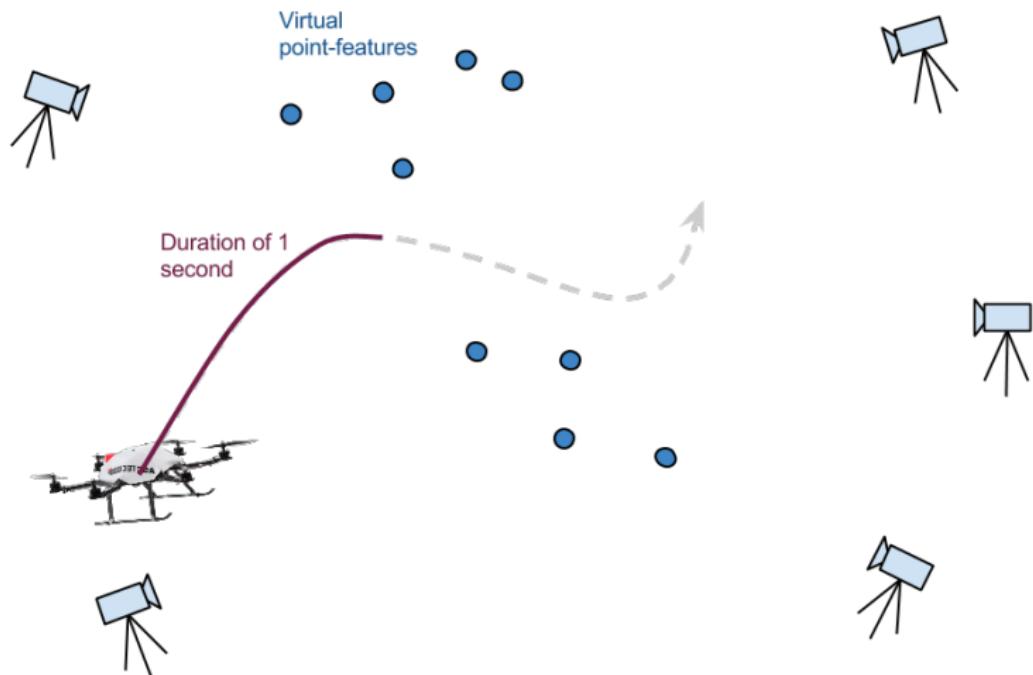
Test setup



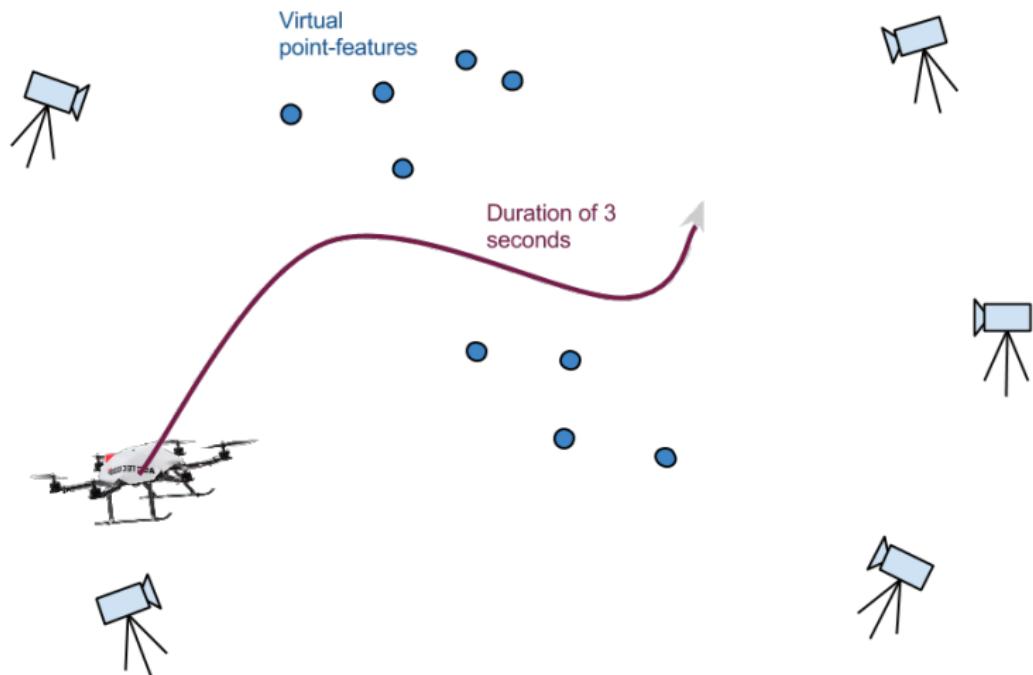
Test setup



Test setup



Test setup



Problem: not robust in practice

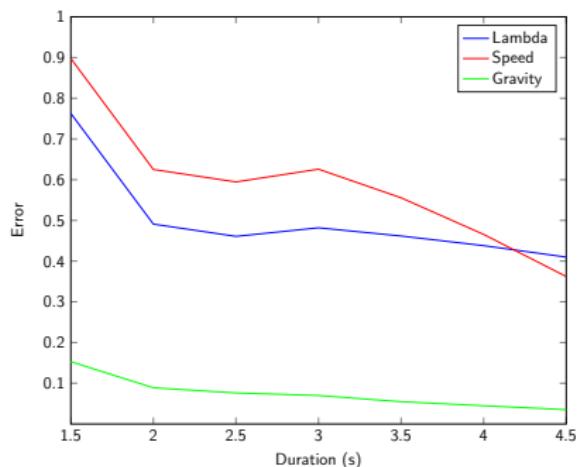
"A closed-form solution for state estimation with a visual-inertial system that does not require initialization was presented. However, this approach is not suitable for systems that rely on noisy sensor data"

— Matthias Faessler, ICRA 2015

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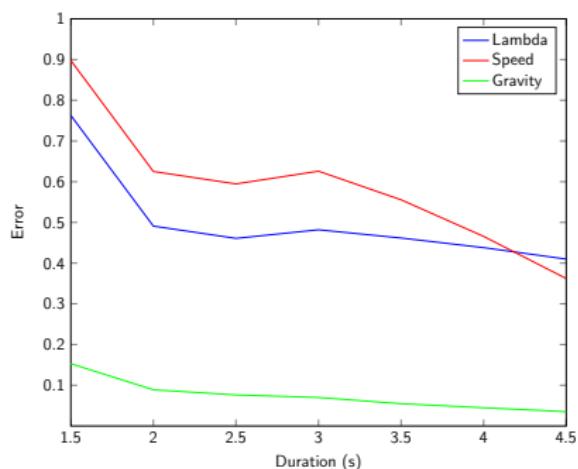
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50% relative error on speed and distance estimation

Improving the performance

What makes the estimations so bad?

Possible bottlenecks

- ▶ Motion;

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Sensors provide measurements affected by a Gaussian noise:

$$N(\mu + B, \sigma^2)$$

Improving the performance

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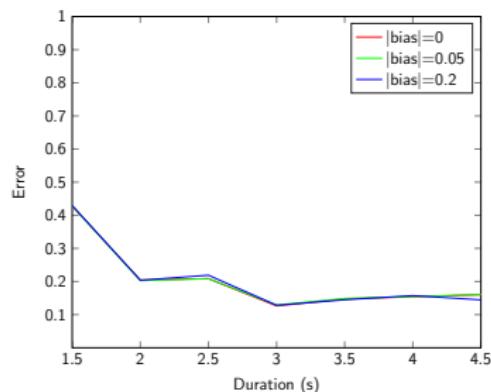
$$N(\mu + B, \sigma^2)$$

We considered:

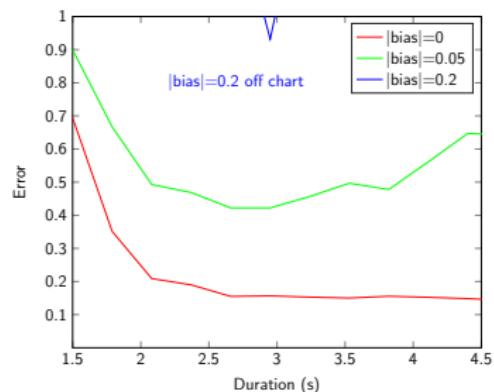
- ▶ Biased accelerometer;
- ▶ Biased gyroscope.

Biased inertial measurements

Speed estimation error



Varying accelerometer bias



Varying gyroscope bias

Estimating the gyroscope bias

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$$\text{cost}(B) = \operatorname{argmin}_X \|\Xi X - S\|^2$$

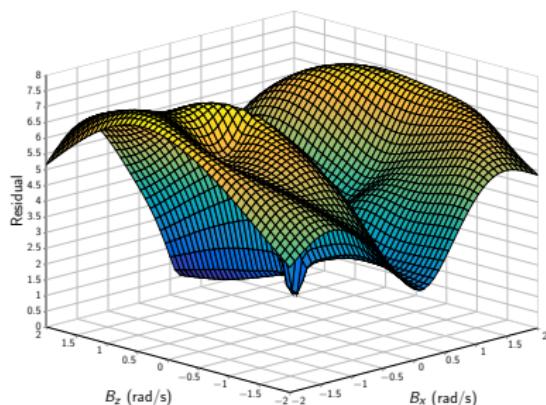
With B the gyroscope bias, Ξ and S computed with respect to B

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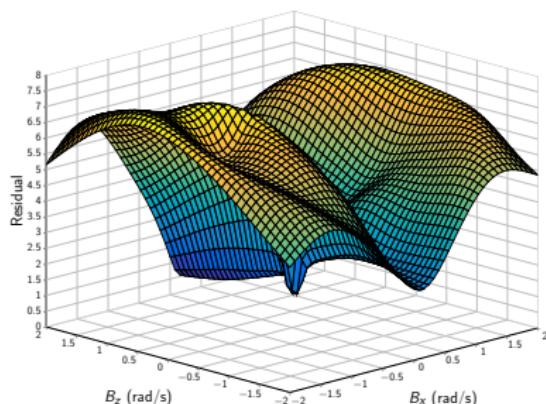


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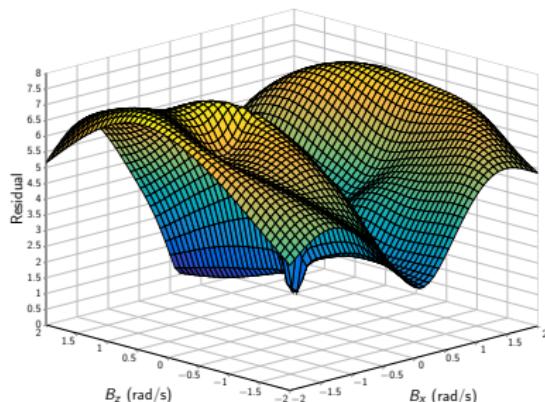
Symmetry induced by the strong weight of the gravity

Estimating the gyroscope bias

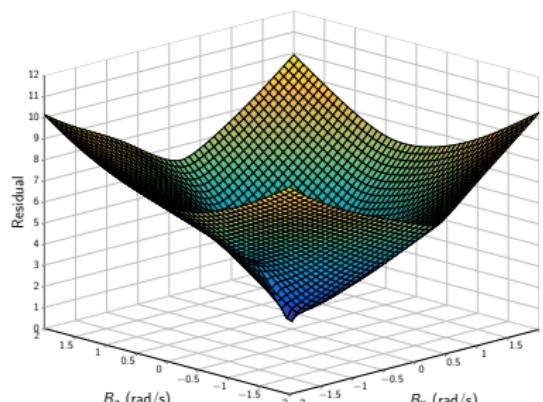
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$$\text{cost}(B) = \operatorname{argmin}_X \|\Xi X - S\|^2 + \lambda \times |B|$$

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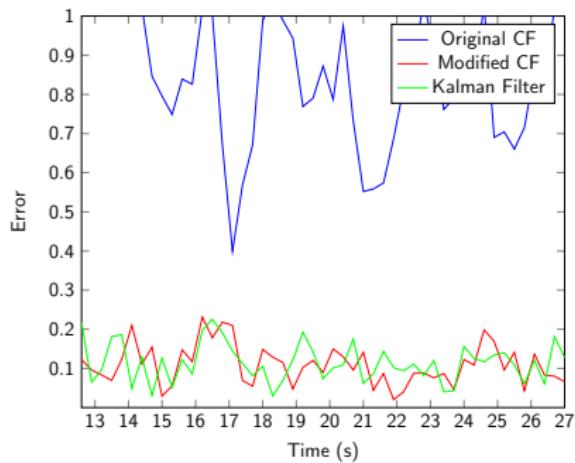
Symmetry induced by the strong weight of the gravity



With regularization $\lambda = 3$

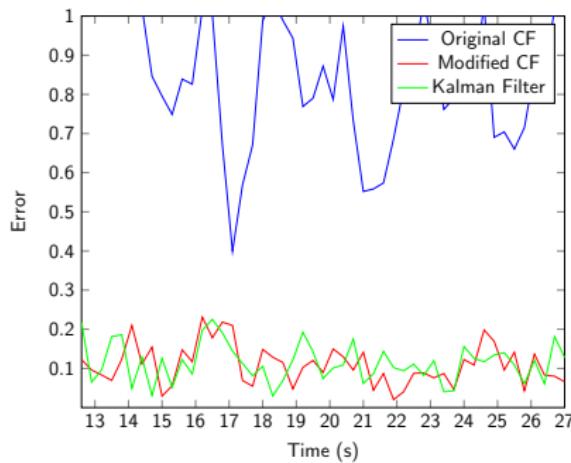
Results

Speed estimation error



Results

Speed estimation error



Moreover, our technique:

- ▶ Does not require initialization;
- ▶ Provides the gyroscope bias.

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1. Closed-form solution for visual-inertial fusion;
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3. Gyroscope bias is a performance bottleneck;
4. **Method to estimate this bias;**

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1. Closed-form solution for visual-inertial fusion;
 - ▶ No initialization required;
 - ▶ Recovers the absolute scale.
2. Does not work well in practice;
3. Gyroscope bias is a performance bottleneck;
4. **Method to estimate this bias;**
5. Works well in practice;
6. Also provides the gyroscope bias.

Future work

Implementation on a real platform



Thank you for your attention,
Any question?

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$$S_j = \lambda_1^i \mu_1^i - V t_j - G \frac{t_j^2}{2} - \lambda_j^i \mu_j^i$$

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The Overconstrained Linear System

$$S_j = \lambda_1^i \mu_1^i - V t_j - G \frac{t_j^2}{2} - \lambda_j^i \mu_j^i$$

Valid for every point-feature i at any time t_j :

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$$\begin{cases} S_2 = \lambda_1^1 \mu_1^1 - V t_2 - G \frac{t_2^2}{2} - \lambda_2^1 \mu_2^1 \\ S_2 = \lambda_1^2 \mu_1^2 - V t_2 - G \frac{t_2^2}{2} - \lambda_2^2 \mu_2^2 \\ \vdots \\ S_3 = \lambda_1^1 \mu_1^1 - V t_3 - G \frac{t_3^2}{2} - \lambda_3^1 \mu_3^1 \\ \vdots \\ S_N = \lambda_1^{n_i} \mu_1^{n_i} - V t_N - G \frac{t_N^2}{2} - \lambda_N^{n_i} \mu_N^{n_i} \end{cases}$$

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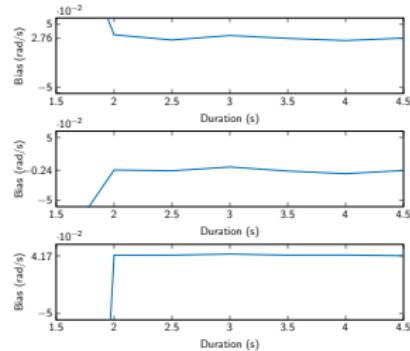
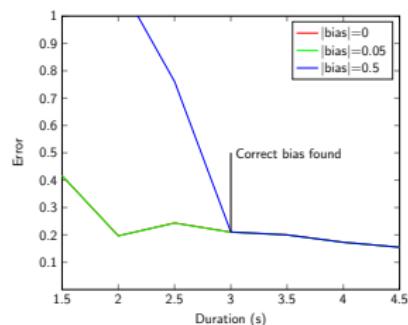
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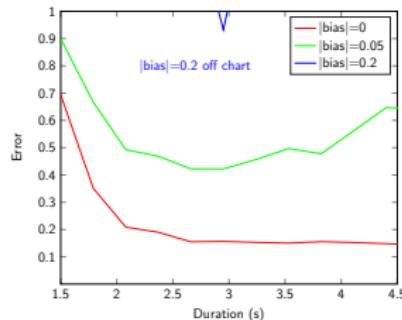
$$\Xi X = S$$

Gyroscope bias estimation

Optimized Closed-form solution



Original Closed-form solution



Numerical stability

$$\left[\begin{array}{lcl} S_j & = & \lambda_1^1 \mu_1^1 - Vt_j - G \frac{t_j^2}{2} - \lambda_j^1 \mu_j^1 \\ 0_3 & = & \lambda_1^1 \mu_1^1 - \lambda_j^1 \mu_j^1 - \lambda_1^i \mu_1^i + \lambda_j^i \mu_j^i \end{array} \right] \quad \left| \quad S_j = \lambda_1^i \mu_1^i - Vt_j - G \frac{t_j^2}{2} - \lambda_j^i \mu_j^i \right.$$

