

公开课视频回放 | 基于RGBD和IMU的实时室内SLAM及三维重建

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下载视频

倍速

大家都在看

直觉对于科研来说重要吗？ 推荐

用腾讯视频观看

欢迎加入直播交流QQ群（617030152），以后的直播通知、资料会第一时间分享到群里。
以下是部分PPT内容。

Real-time Localization and Dense Mapping with Fast Sensor Motion

Zunjie Zhu, Feng Xu, Chenggang Yan, et.al.

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Hangzhou Dianzi University

School of Software, Tsinghua University



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计算机视觉life

OVERVIEW

- Why fast?
- How fast?
- Problems
- Our method
- Future work

清华大学
Tsinghua University



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WHY FAST

- Augmented Reality & Mixed Reality
 - Unconstrained user action
- Robotics
 - High efficient work
- Other applications
 - Fast Reconstruction
 - Towards Robust SLAM

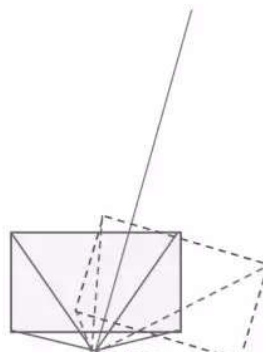
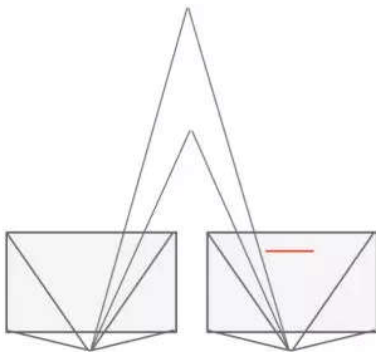


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HOW FAST

- Motion blur & Rolling Shutter
 - Relative motion during exposure time
 - Distance & motion type
 - image-resolution



- Linear velocity: 3 m/s
- Angular velocity: 360 deg/s
- FPS: 30Hz

Related motion:
10 cm/frame
12 deg/frame

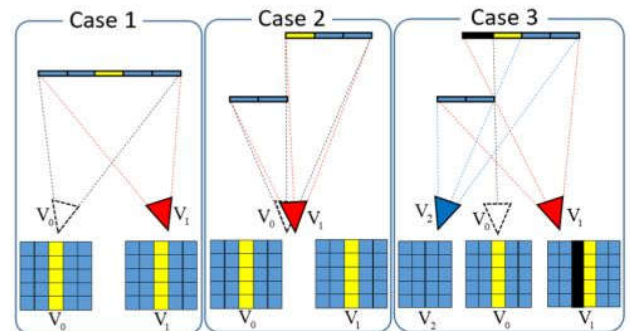


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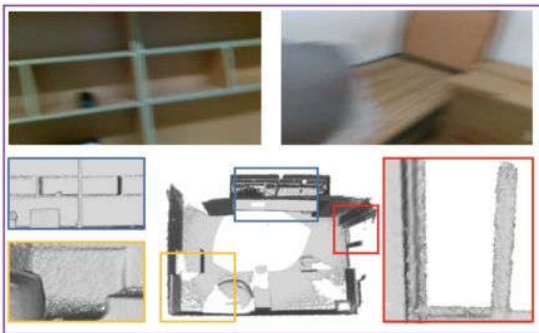
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PROBLEMS

- Reduce exposure time
 - Lower brightness
 - Worse SNR
- Feature point method
 - Insufficient feature
 - Miss & False match
- Direct method
 - Shrink Effect & Extend Effect (SE Effect)
- ICP algorithm
 - Local optimum



OUR METHOD

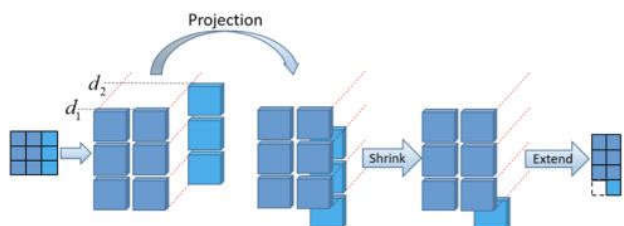


- Input: RGB-D-Inertial



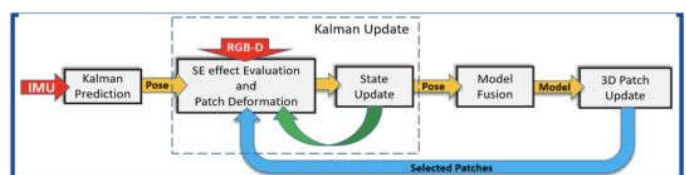
IMU
Linear acceleration:
 $a_x \ a_y \ a_z$
Angular velocity:
 $q_x \ q_y \ q_z \ w$

- Geometry-aware patch deformation

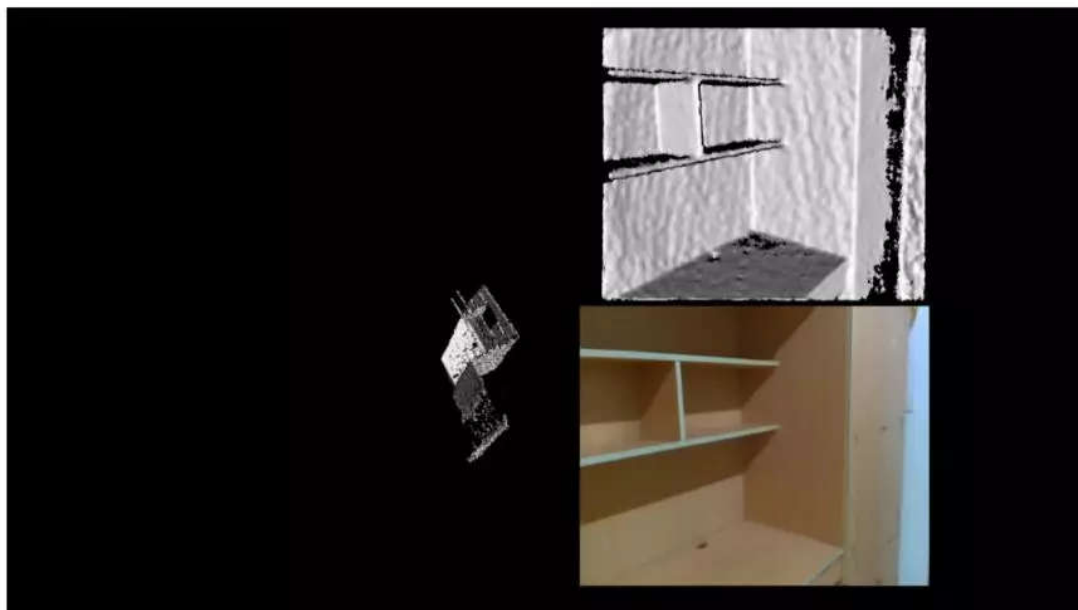


- Iterative EKF

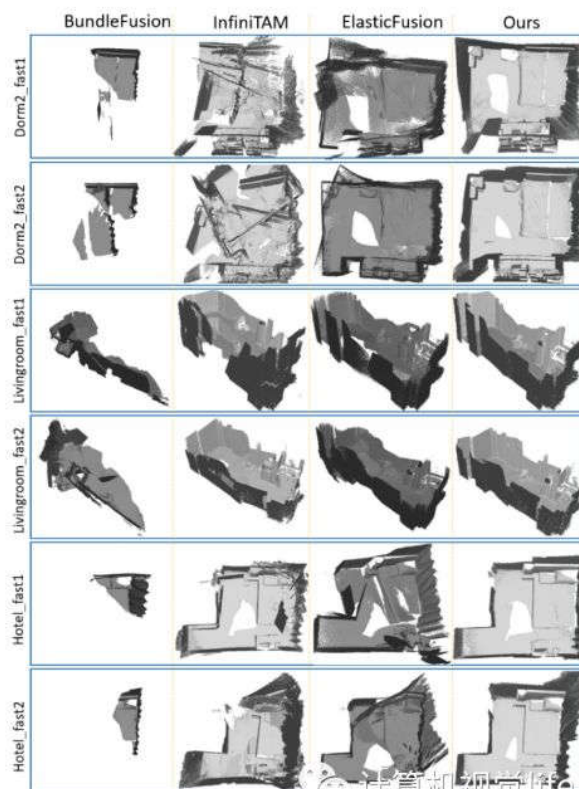
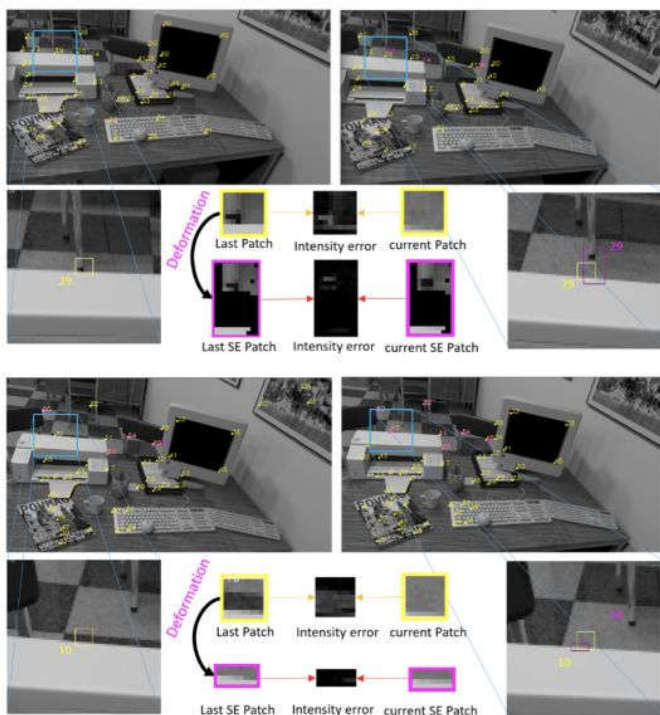
- Iteratively update deformed patches



RESULTS



RESULTS



FUTURE WORK



- Loop Closure
 - Loop detection
 - Loop correction
- Deblur
 - Video
 - Texture



THANKS!

