DroneMOM

Drone Model Output Machine

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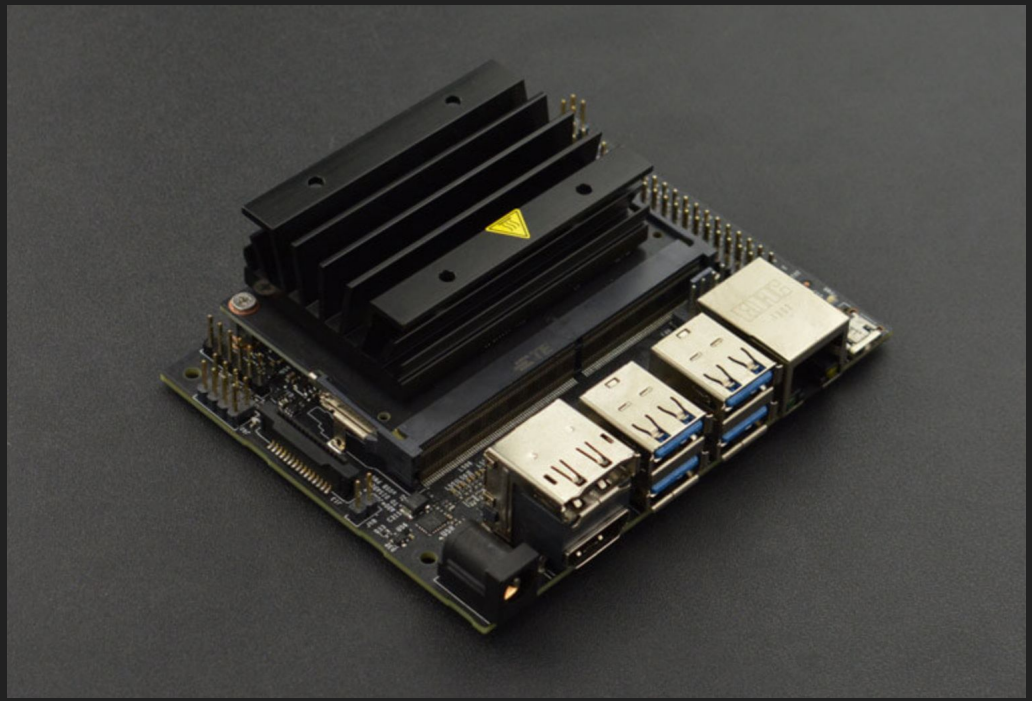
System Design

Jetson Nano

- System On Chip with Nvidia GPU
- Limited RAM + Storage
- Limited Processing Capabilities
- Used for Aerial Platforms
- Robot Operating System (ROS) provides system infrastructure

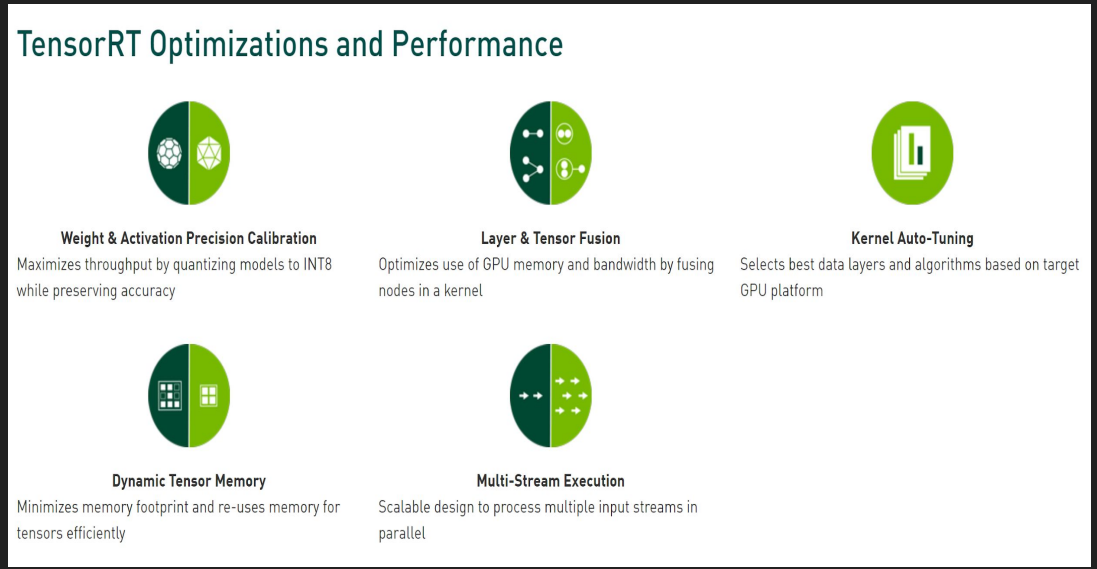


Classification

- Utilized Mobilenet as architecture
- Accelerated classification with TensorRT
- Implemented cuda algorithms with shared memory
- Bounding Boxes show what is classified in the frame
- ~50ms per inference
- Used ROS to implement a complex system

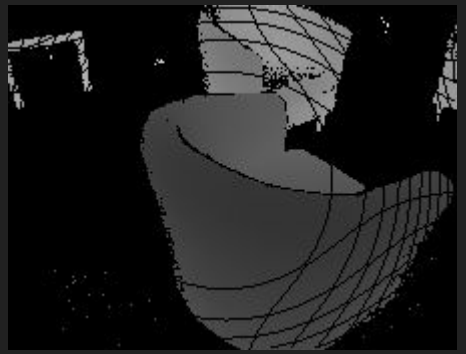
What is TensorRT?

- Think of it like DXR
- Build a tensorRT engine (like CPU side of DXR)
- Run inference on GPU based on this accelerated engine.



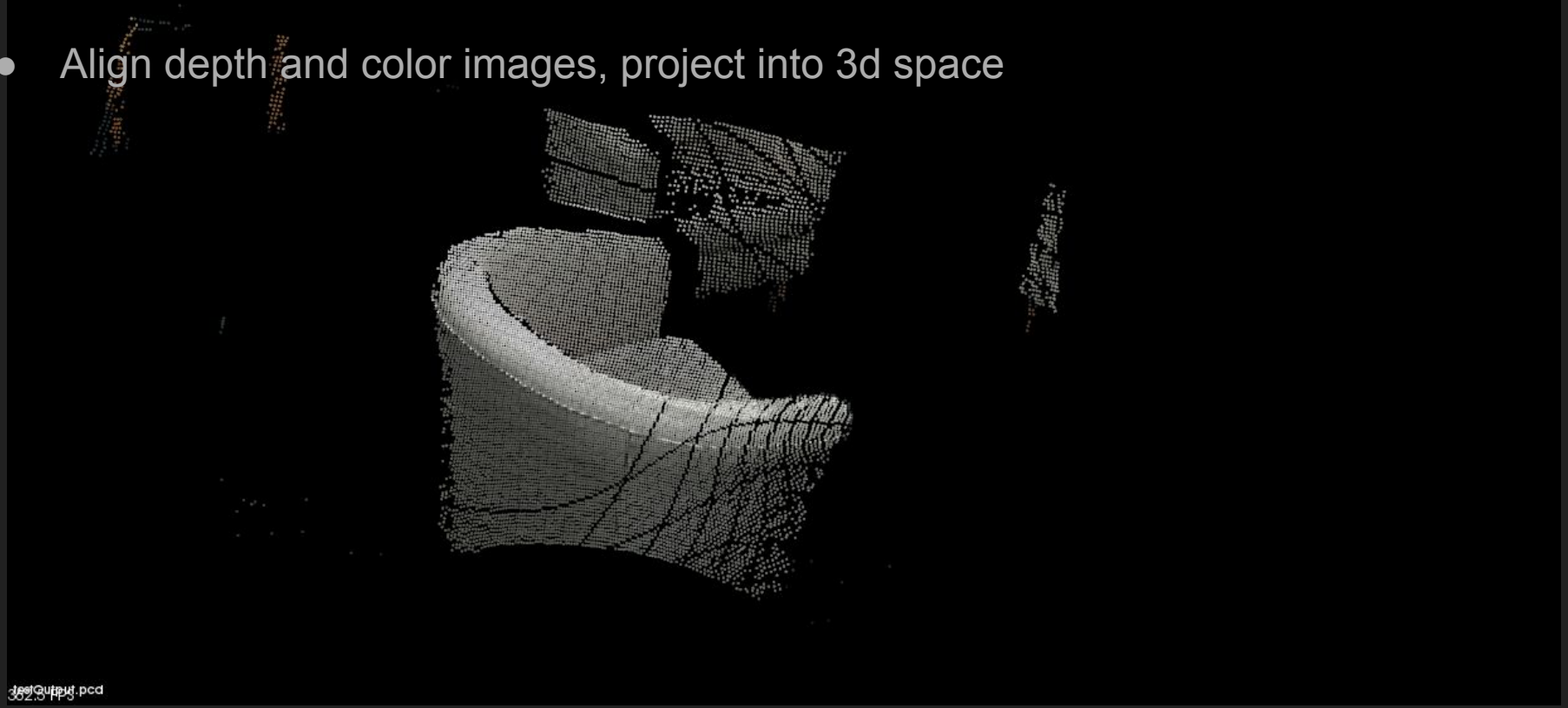
Point Cloud Generation

- Input: color image, depth image



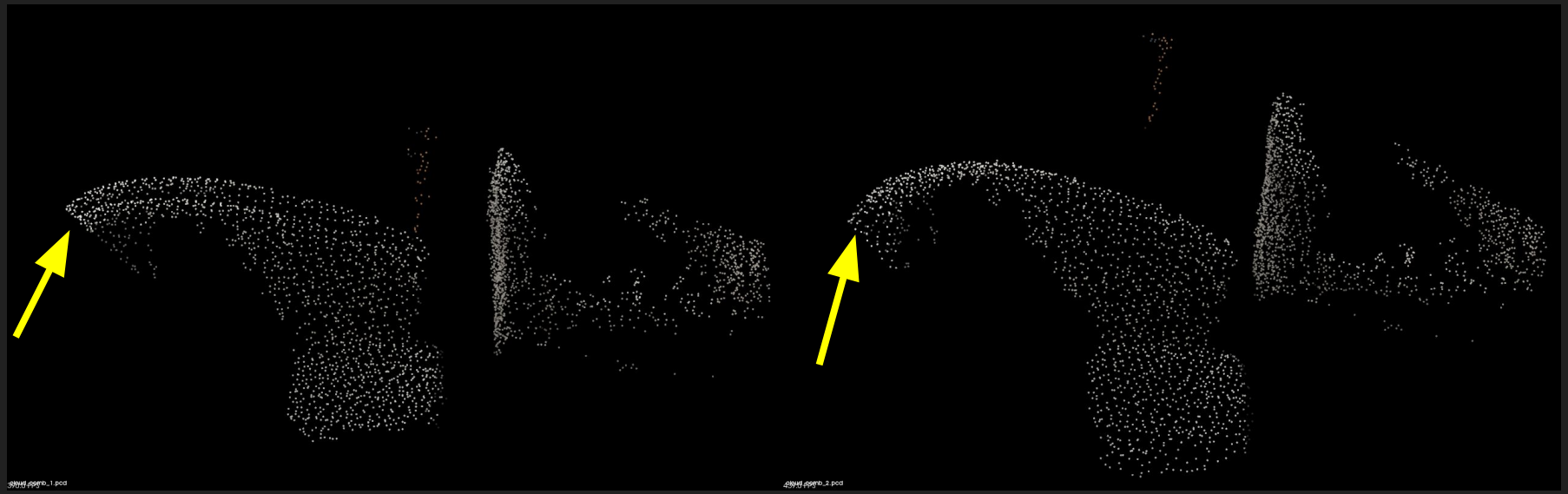
Point Cloud Generation

- Align depth and color images, project into 3d space



Point Cloud Generation

- Align and register frames for subsequent point clouds



Unaligned

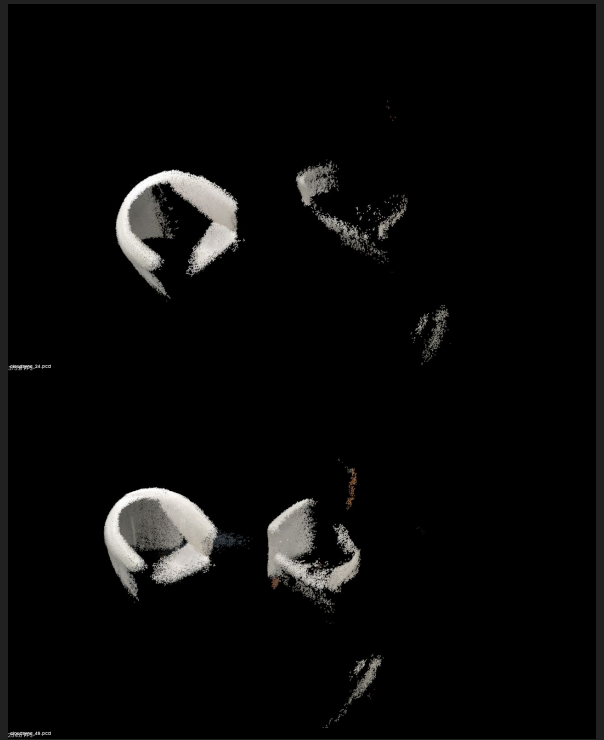
Aligned

Point Cloud Generation

- Accumulate subsequent frames to create overall point cloud

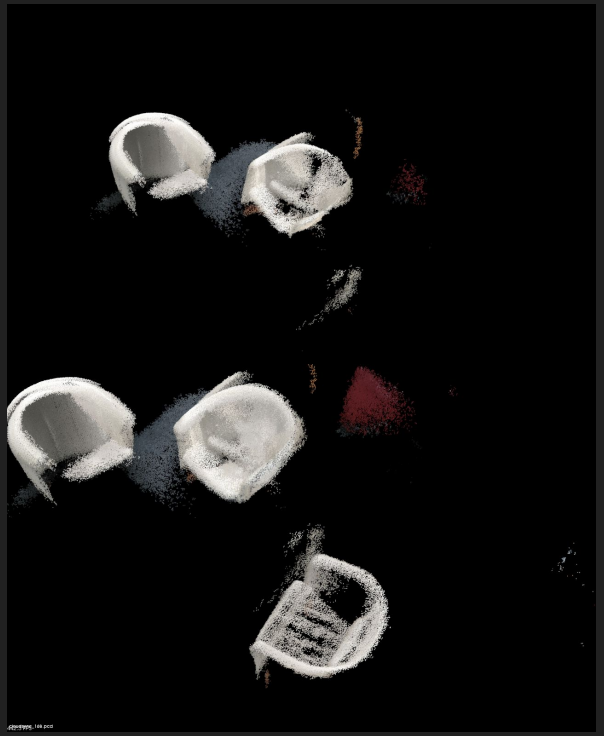
24 Frames

48 Frames



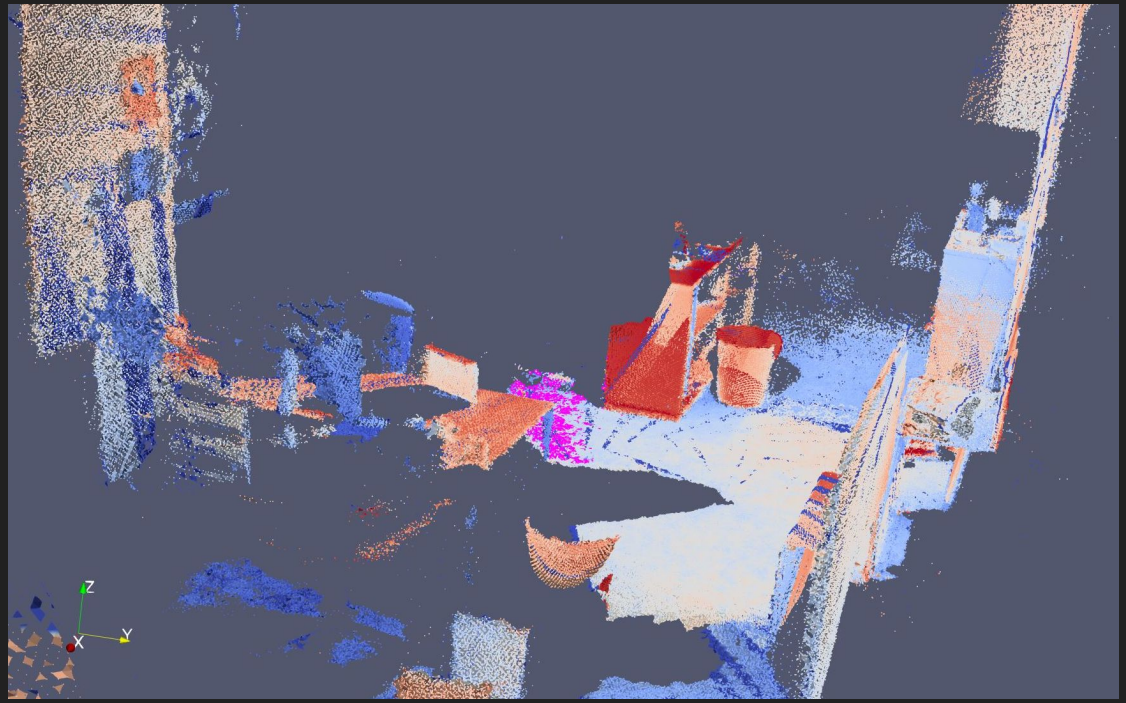
120 Frames

168 Frames



GLTF Mesh Construction

- Convert a Point Cloud into a GLTF Mesh
- Challenges
  - Noise in the Point Cloud
  - Too many points
  - Incomplete data



GLTF Mesh Construction

1. Downsample using a Uniform Voxel grid
2. Remove Statistical Outliers
3. Smoothing through Moving Least Squares
4. Point Normal Estimation
5. Greedy Triangulation Mesh Construction

Mesh using a small frame count

Output Mesh after 5GB of data

Not quite right…

- Coordinate system not preserved
- GLTF Vertex Winding Order

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Dewang + Vaibhav (Shadow Team Point cloud and ML help)
Tim Kaldeway (TensorRT advice+resources)
Andrew Feng

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