Evaluation of Orientation Ambiguity and Detection Rate in April Tag and WhyCode

Joshua Springer, Marcel Kyas

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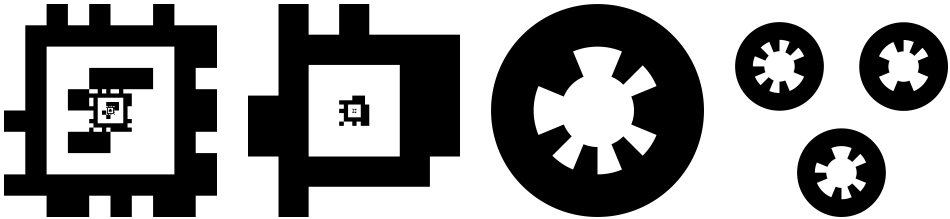
Reykjavik University
Department of Computer Science

Fiducial Markers

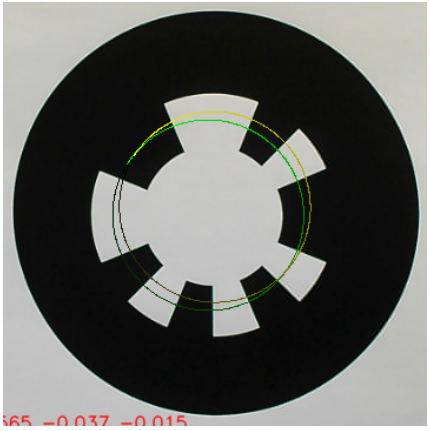


April Tag 48h12[1] April Tag 24h10 WhyCode[2] (Orig) WhyCode Multi

- Marker *position* → accurate
- Marker *orientation* → ambiguous
- Application: autonomous drone landing (requiring pose transformation using the orientation)

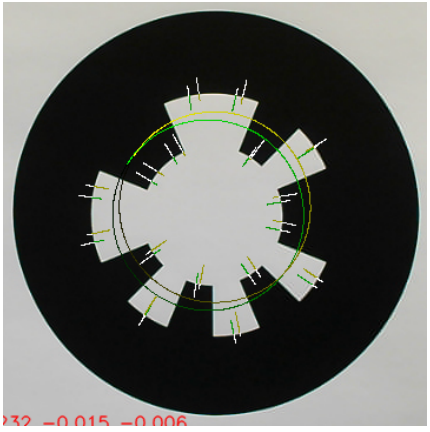
[1] Krogius, Haggenmiller, and Olson 2019.
[2] Lightbody, Krajník, and Hanheide 2017.

WhyCode (Orig)



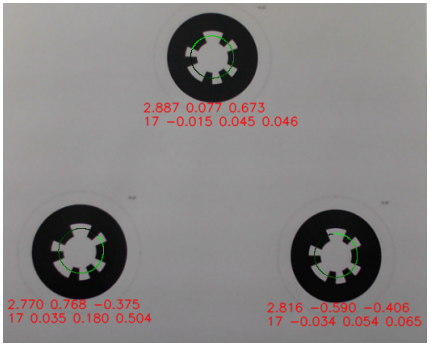
- Position → camera intrinsics, marker size (known)
- Orientation → two candidates (yellow/green ellipses)
  - Which one fits better?
  - Minimize variance of intersection length of sampling circle with each tooth

WhyCode “Ellipse”



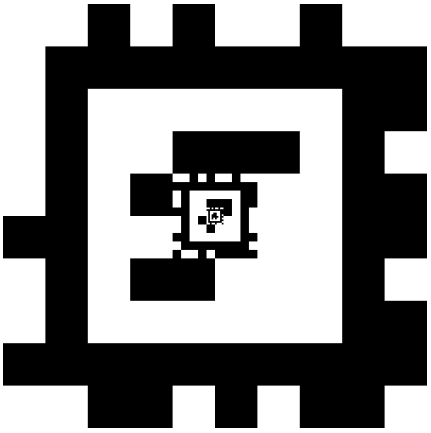
- Changes the method for choosing the orientation candidate
  - Original sampling predicts tooth transition locations
  - Sample again along radii through tooth centers
  - Try to center radial sampling lines on white-to-black transitions

WhyCode “Multi”



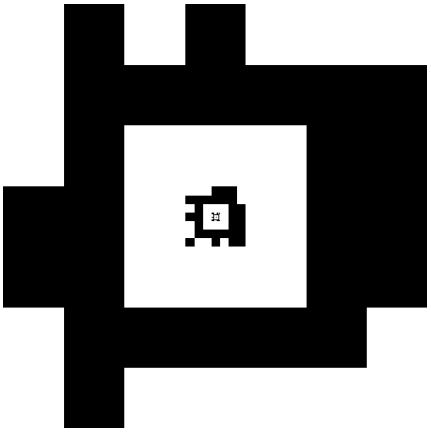
- Assumes coplanar marker arrangements
- Samples as in WhyCode Orig
- Uses only marker size, positions and IDs.
- Regresses a plane to the marker positions
- Assigns the plane’s orientation to all of the markers

April Tag 48h12



- 36 outer ID bits + 12 inner ID bits
- 28 black border bits
- 20 white border bits
- 4 undefined, center bits (for marker embedding)
- 42,211 markers in a single hash table in RAM

April Tag 24h10



- 24 outer ID bits
- 16 black border bits
- 8 white border bits
- 1 undefined center bit (for marker embedding)
- 18 total markers (enough for our purposes)

ROS Message Attributes

- For autonomous landing application
- A **position target** P in the a relative “east, north, up” (ENU) coordinate frame
- The marker’s **orientation quaternion** q

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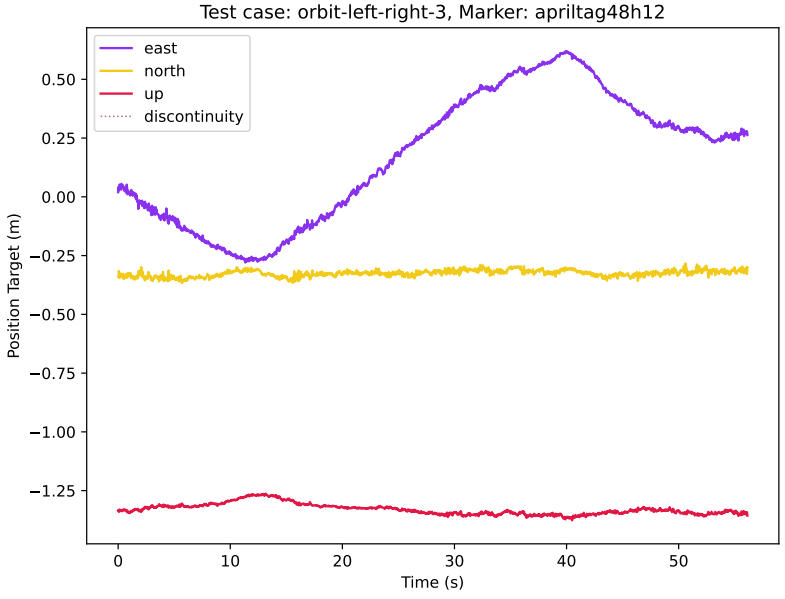
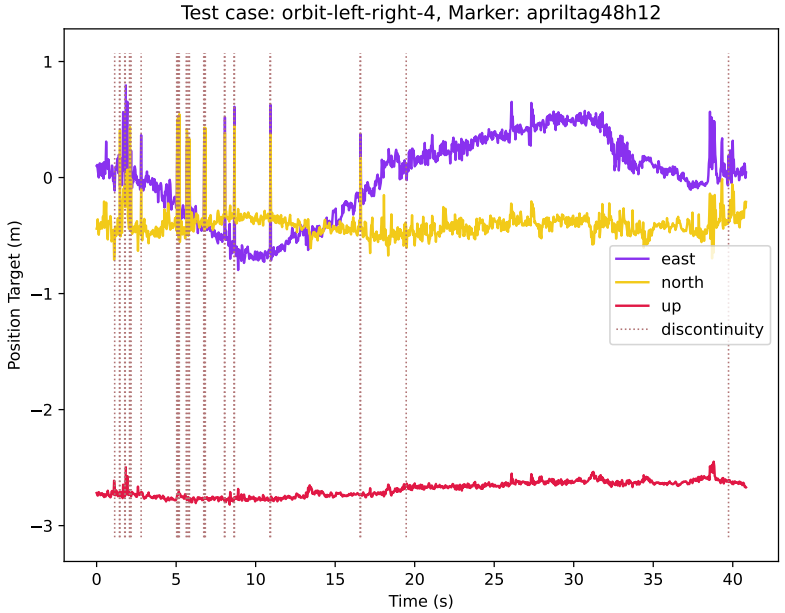
- Distances of 1-3 meters
- Creative Technology Live! Webcam at 480p, 30 fps
- Discontinuity rate: $r_d = \frac{d}{n}$: d is number of discontinuities, n is number of detections

Linear Discontinuities	Angular Discontinuities
$P = \langle p_e, p_n, p_u \rangle$	$q = \langle q_w, q_x, q_y, q_z \rangle$
$\frac{p_{x,i+1}}{p_{x,i}} < \theta_l < 0$	$s_a = \left\lvert \frac{\mathrm{dist}(q_i, q_{i+1})}{t} \right\rvert > \theta_a > 0$
$\theta_l = -0.8$	$\theta_a = 1.0 \frac{\mathrm{rad}}{s}$

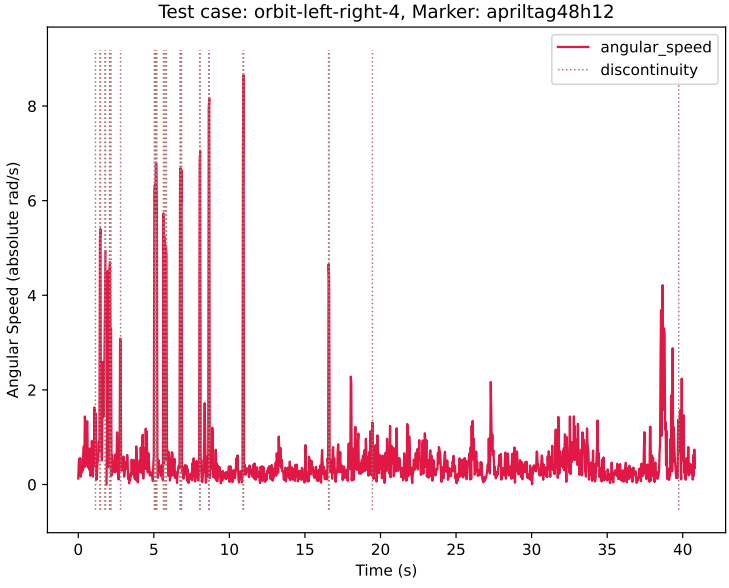
Example Test Case



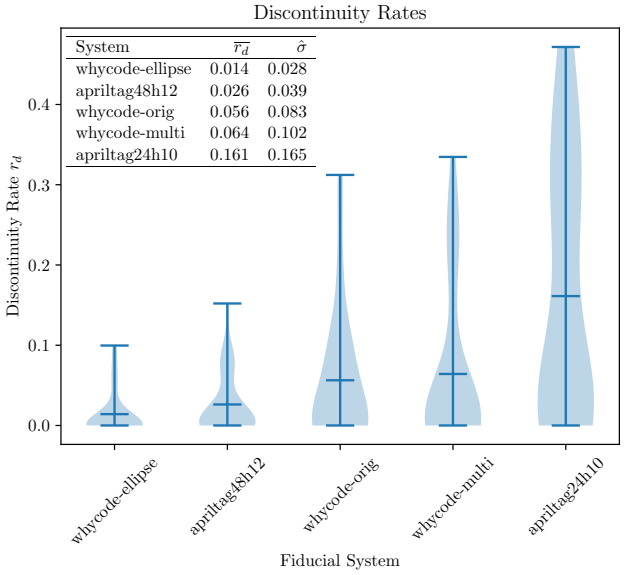
Example Test Case with Discontinuities



Example Test Case - Angular Speed



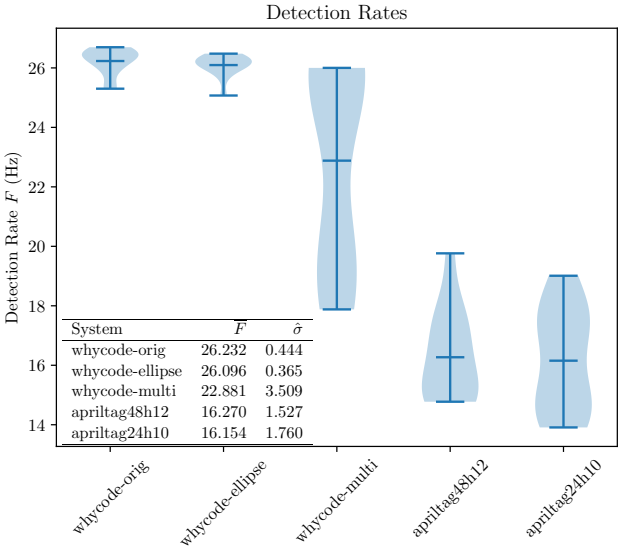
Results: Discontinuity Rates (Lower is Better)



Quantifying Detection Rate

- 16 test cases per marker
- distances of 0.6-3 meters (motivated by application)
- 8 normal, 8 with 45 degrees deflection
- One static marker per video
- Constant camera, framerate, resolution
- Detection rate: $F = \frac{n}{t}$: n is number of detections, t is the length in seconds of each test case
- Raspberry Pi 4 with 2 GB of RAM

Results: Detection Rates (Higher is Better)



System	$\overline{F}$	$\hat{\sigma}$
whycode-orig	26.232	0.444
whycode-ellipse	26.096	0.365
whycode-multi	22.881	3.509
apriltag48h12	16.270	1.527
apriltag24h10	16.154	1.760

Main Messages

- Fiducial markers: orientation is hard to determine
  - Orientation ambiguity manifests as sign flips
  - Present in all fiducial systems, but at different rates
- Detection rate
  - Influenced by hardware capabilities, software architecture
- Application to autonomous landing with gimbal:
  - Most tested systems are worth trying
  - April Tag 24h10 is likely to have issues