

Human-Digital Content Interaction for Immersive 4D Home Entertainment

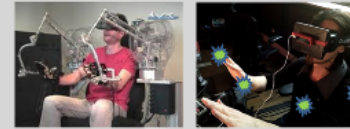
The Whole Picture: Immersive and Interactive Mixed Reality



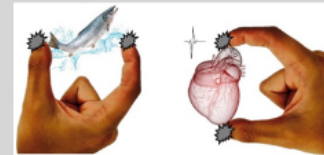
Interaction techniques for the immersive MR contents

- Use hands/fingers (Direct interaction)
 - Tracking: Kinect, Leap, Glove, Camera-image, Camera-Fiducial
 - Outside in vs. Inside out
- 2 Finger Pinch
 - Natural and intuitive
 - For selection and manipulation
 - Pinch/release detection (Ewha)
- Multimodal
 - Visual: Real / Virtual (Ewha)
 - Aural
 - (Vibro)Tactile
 - Application of tactile illusion (minimize actuators)
 - Extension to ring-like design (improve wearability)
 - Kinesthetic (Ewha also)
 - Vibro-tactile rendering methods for different effects (richer experience)
 - Fusing pseudo and actual force feedback
- Use whole body (Experiential)
 - Tracking: Kinect, Camera-image/Fiducial, Wearable sensor + SVM/HMM/IK
 - Detection of extreme motion
 - Application to interaction design for immersive contents

Year 1

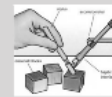


Intricate haptic device is not so convenient ... and simple vibration cannot convey much ...



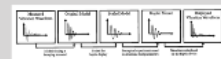
Use illusion, multimodality fusion and rendering variation to create wearable yet richer experience

Year 2

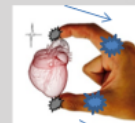


$$Q(f) = A(f)e^{-Bf} \sin(2\pi fC)$$

Material	A [m ²]	B (s ⁻¹)	C (Hz)
Rubber	~240	60,000	30
Wood	~150	30,000	100
Aluminium	~300	80,000	300

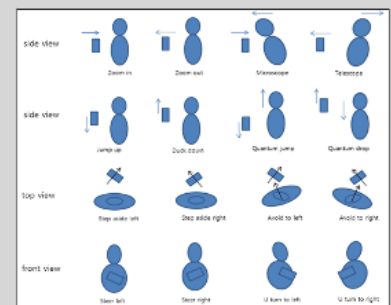


Vibro-tactile rendering for various effects



Ring-type: Improving wearability / Validation

Year 3



Detecting body dynamics and associating it to contents

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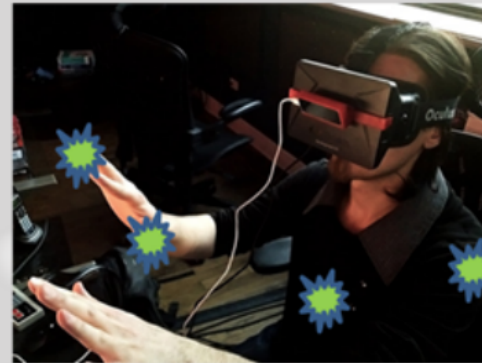
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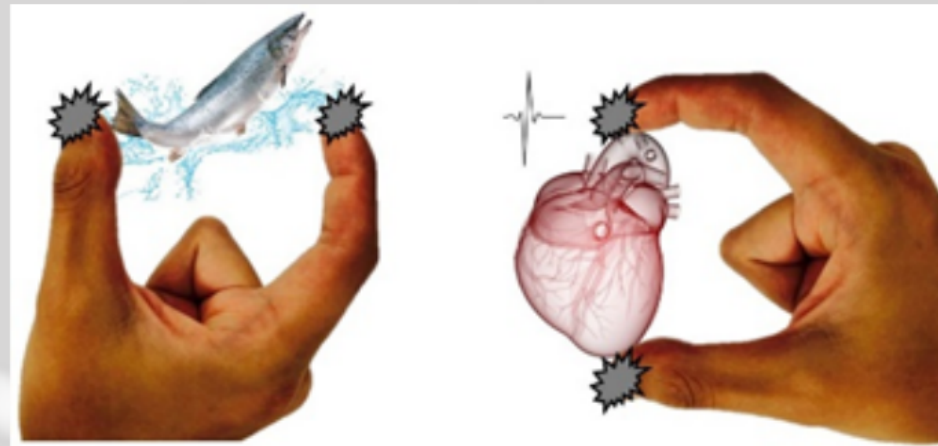
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Year 1



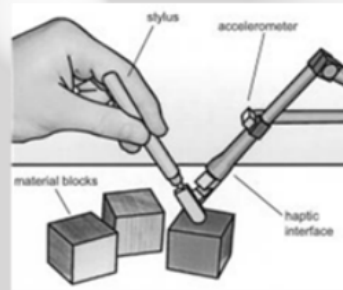
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variation to create wearable yet richer experience

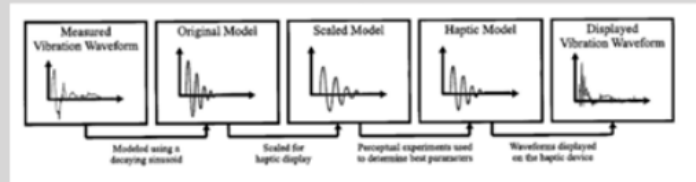
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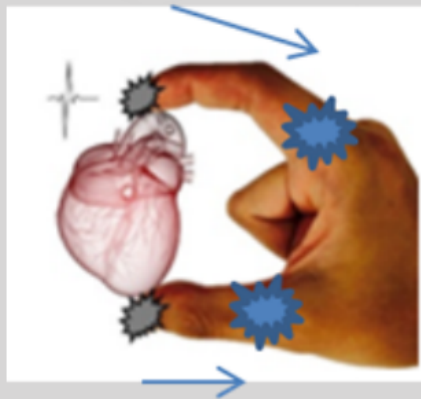


$$Q(t) = A(v)e^{-Bt} \sin(2\pi\omega t).$$

Material	$A (s^{-1})$	$B (s^{-1})$	$\omega (Hz)$
Rubber	-240	60,000	30
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Aluminum	-300	90,000	300



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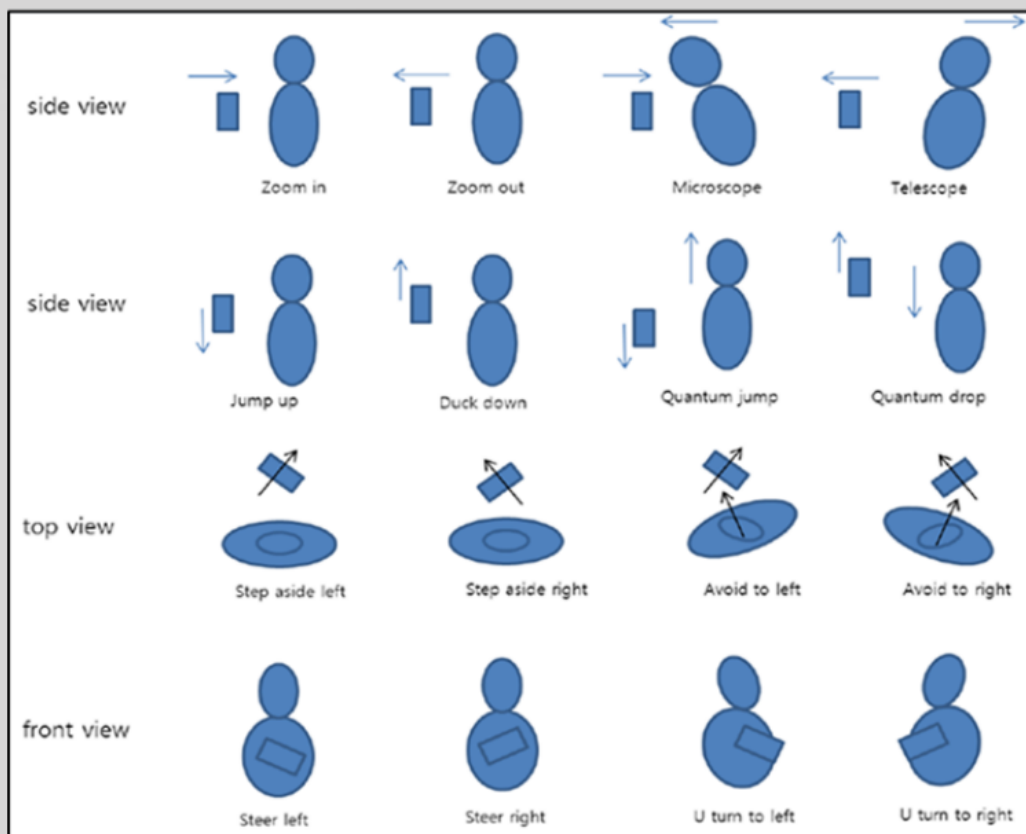
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Year 3



Little movement

Big movement



Detecting body dynamics and associating it to contents