

# TSDF Volume Reconstruction

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# Outline

1 Introduction

2 Approach

3 Results

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# Introduction

- Reconstruct 3D voxel grid from multiple input frames
- Frames consist of color (RGB) and depth images
- Must be fast enough to use in real-time with a Kinect (or a similar sensor)



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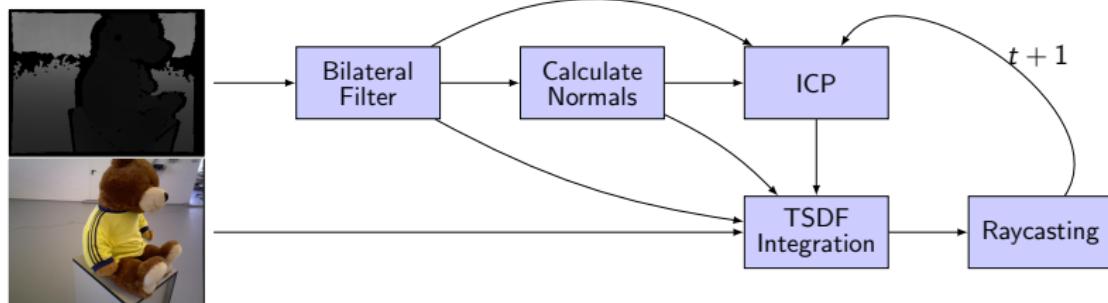
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1 Introduction

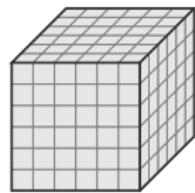
2 Approach

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# The Pipeline

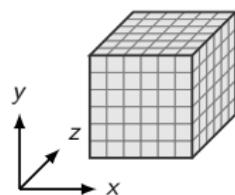
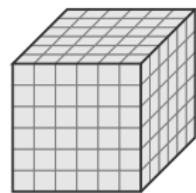


# Transformations between the different coordinate systems



$$\begin{pmatrix} x \\ y \\ z \end{pmatrix}$$

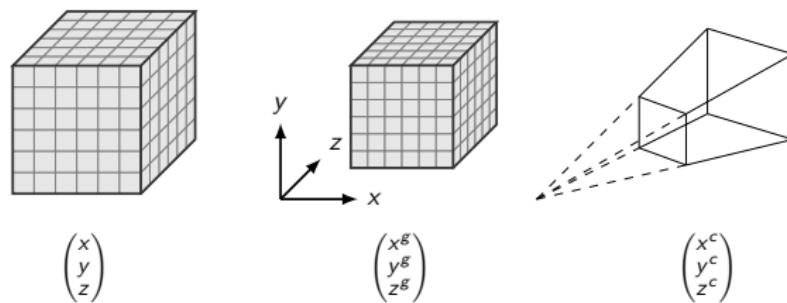
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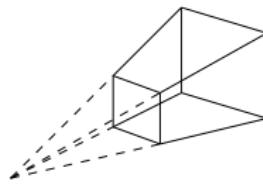
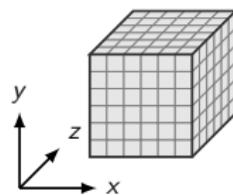
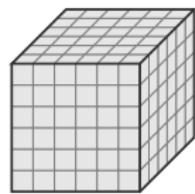
$$\begin{pmatrix} x \\ y \\ z \end{pmatrix}$$

$$\begin{pmatrix} x^g \\ y^g \\ z^g \end{pmatrix}$$

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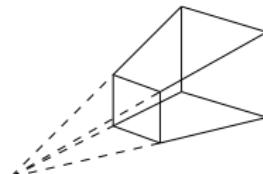
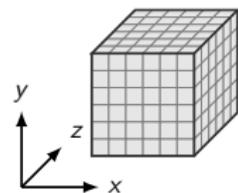
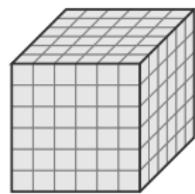
$$\begin{pmatrix} x \\ y \\ z \end{pmatrix}$$

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$$\begin{pmatrix} x^c \\ y^c \\ z^c \end{pmatrix}$$

$$\begin{pmatrix} x^p \\ y^p \end{pmatrix}$$

# Transformations between the different coordinate systems



$$\begin{pmatrix} x \\ y \\ z \end{pmatrix}$$

$$\begin{pmatrix} x \\ y \\ z \end{pmatrix} + \begin{pmatrix} \text{gridPos}_x \\ \text{gridPos}_y \\ \text{gridPos}_z \end{pmatrix}$$

$$\begin{pmatrix} x^g \\ y^g \\ z^g \end{pmatrix}$$

$$\text{camPose}^{-1} \cdot \begin{pmatrix} x^g \\ y^g \\ z^g \\ 1 \end{pmatrix}$$

$$\begin{pmatrix} x^c \\ y^c \\ z^c \end{pmatrix}$$

$$(K \cdot \begin{pmatrix} x^c \\ y^c \\ z^c \\ 1 \end{pmatrix}) / z^p$$

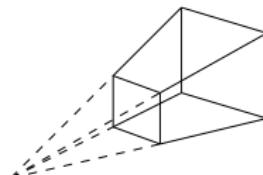
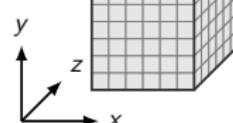
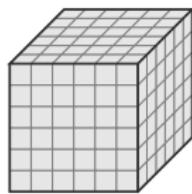
$$\begin{pmatrix} x^p \\ y^p \end{pmatrix}$$

# Transformations between the different coordinate systems

$$\begin{pmatrix} x^g \\ y^g \\ z^g \end{pmatrix} - \begin{pmatrix} \text{gridPos}_x \\ \text{gridPos}_y \\ \text{gridPos}_z \end{pmatrix}$$

$$\text{camPose} \cdot \begin{pmatrix} x^c \\ y^c \\ z^c \\ 1 \end{pmatrix}$$

$$K^{-1} \cdot \begin{pmatrix} x^p \cdot z^p \\ y^p \cdot z^p \\ z^p \\ 1 \end{pmatrix}$$



$$\begin{pmatrix} x \\ y \\ z \end{pmatrix}$$

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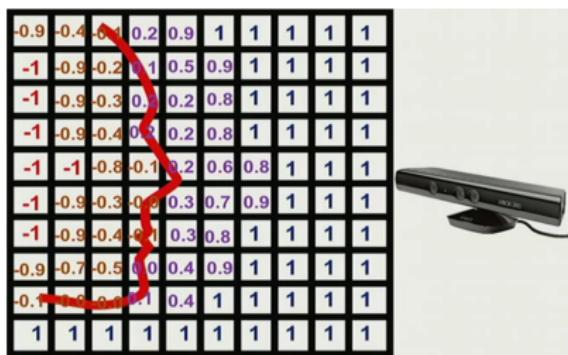
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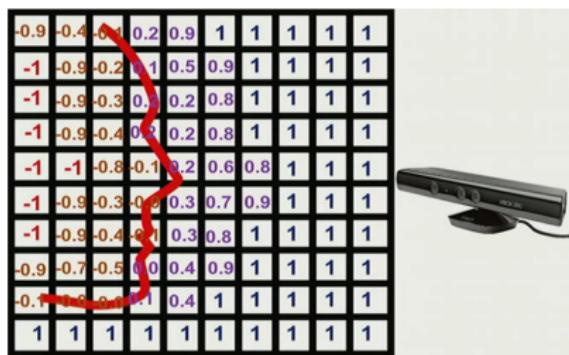
# Truncated Signed Distance Function (TSDF)

- Get distance of the corresponding pixel of each voxel within the voxel grid
- Subtract it from the distance of the voxel itself and divide by the truncation threshold
- Update TSDF and color values in global memory



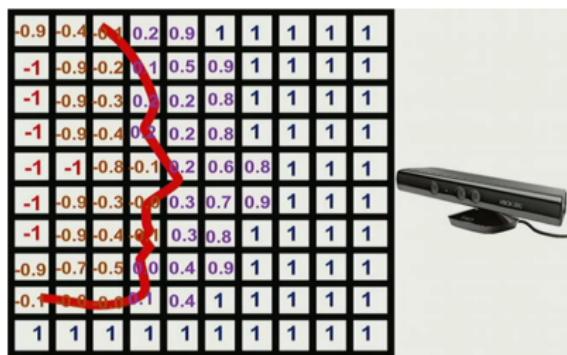
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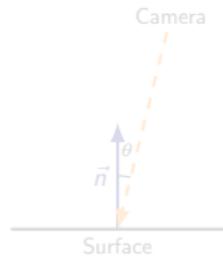
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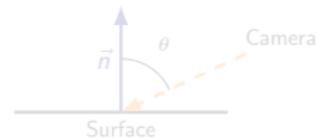


# Weighting of Color and Depth Values

- Bad samples exist and must be weighted accordingly
- Idea: use angle of incidence – lower angles usually correspond to better samples
- Implementation: multiply by z-coordinate of normal



Good sample



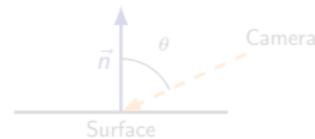
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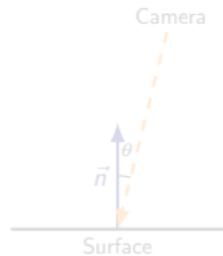
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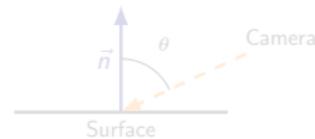
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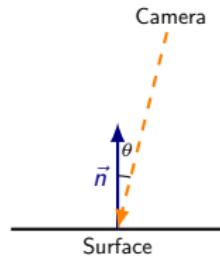
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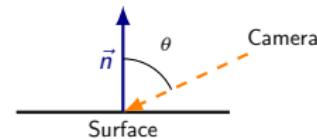
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## Adaptive Raycasting

- Cast a ray for each pixel of the picture being rendered
- Take a step in z-direction and transform coordinates to voxel grid
- Check TSDF value (using trilineal interpolation); if zero-crossing (= edge) was detected, use increasingly smaller step size until we are as close to zero as possible
- Write color value (using trilinear interpolation) to picture
- Algorithm does not include lighting or shadows

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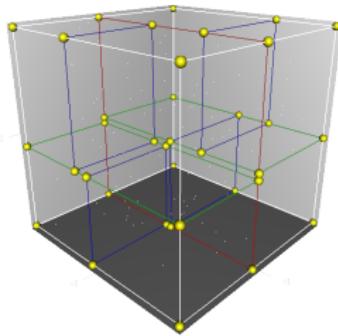
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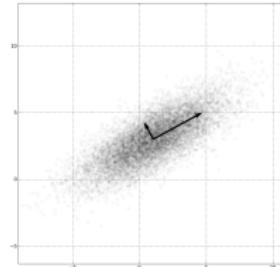
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## Normal Calculation using PCA

- Ideal for a more robust approach to calculate normals
- Combination of k-d tree and PCA
- Not used in final version due to large performance hit (CPU implementation) and only negligible improvements



k-d tree



PCA

Robust Normal Estimation

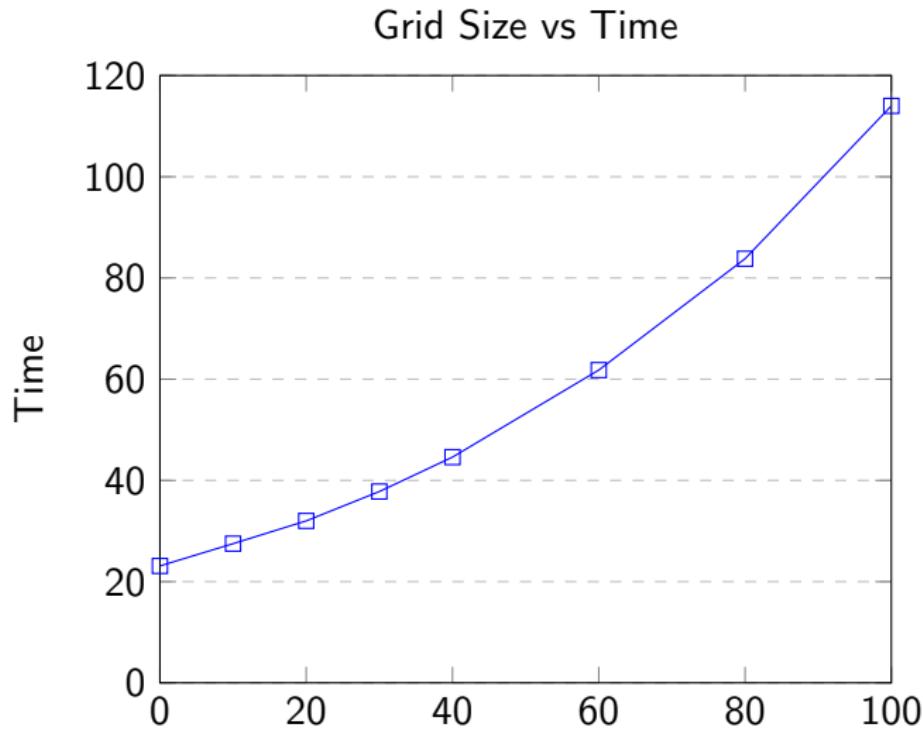
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## Results – different color weighting methods



Exponential falloff

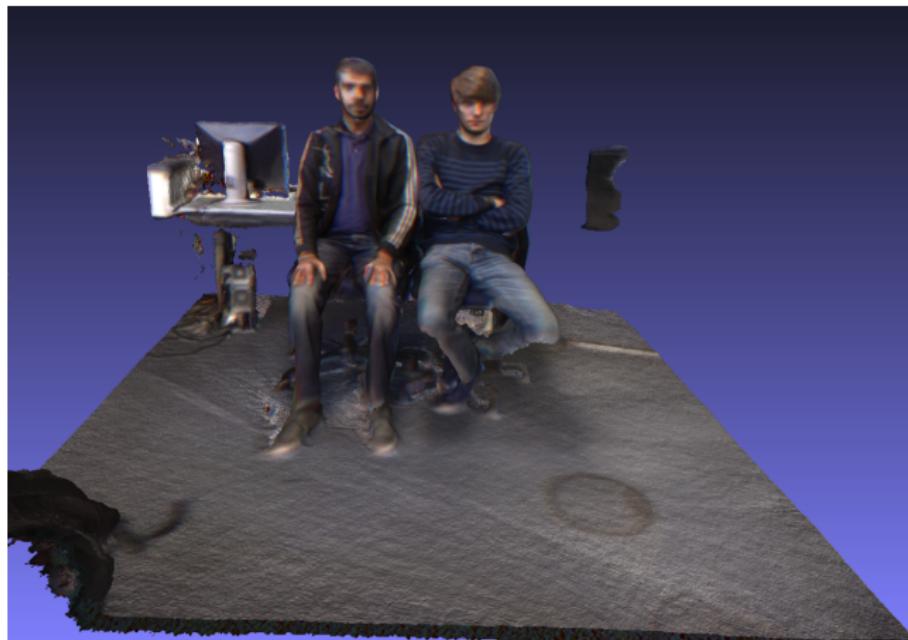


Linear falloff

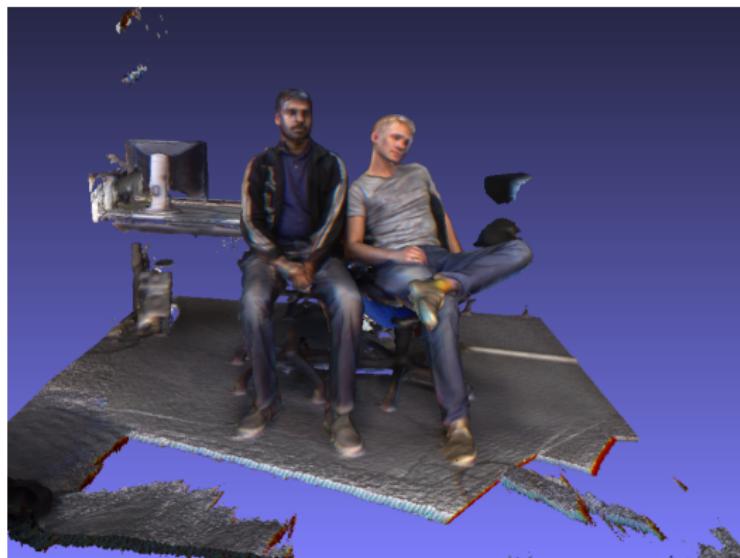


No falloff

## Results



## Results





## Results



Thank you  
for your attention!

## References

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