

DEPTH MAP SYSTEM FOCUSED ON DISTANCE DETERMINATION
SISTEMA DE MAPA DE PROFUNDIDAD ENFOCADO EN DETERMINACIÓN
DE DISTANCIAS

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Abstract: The objective of this work is the Development of a Depth Map Generation System, oriented to the determination of distances. Where a process of exploration of the methods of Artificial Vision and Structured Light is performed, to obtain the depth map of a certain scene. By means of this map it is possible to extract the 3D location data of the objects present in the scene. The work addresses the problem of 3D distance estimation through the generation of the Depth Map, thus presenting a tool for the development of future applications, such as classification systems, surface reconstruction, 3D printing and recognition, among others. The algorithmic development is carried out through Matlab software. It should be noted that the work focuses specifically on the process of determining distances over a fixed scene under controlled lighting conditions, and not on light variations of the scene or moving environments. With the proposed development, the system presents a good response in scenes with depth variations between 540mm to 640mm, presenting errors of less than 5.5% in the mentioned range.

Keywords: Depth maps, structured light, distance measurement, computer vision, computational geometry.

Resumen: Este trabajo tiene como objetivo el Desarrollo de un Sistema de Generación de Mapas de Profundidad, orientado a la determinación de distancias. Donde se realiza un proceso de exploración de los métodos de Visión Artificial y Luz Estructurada, para obtener el mapa de profundidad de una determinada escena. Ya que mediante este mapa se pueden extraer los datos de localización 3D de los objetos presentes en la escena. El trabajo aborda el problema de la estimación de las distancias 3D mediante la generación del Mapa de Profundidad, presentando así una herramienta para el desarrollo de futuras aplicaciones, como sistemas de clasificación, reconstrucción de superficies, impresión y reconocimiento 3D, entre otras. El desarrollo algorítmico se realiza a través del Software Matlab. Cabe destacar que el trabajo se centra específicamente en el proceso de determinación de distancias sobre una escena fija en condiciones de iluminación controlada, y no en variaciones lumínicas de la escena o entornos en movimiento. Con el Desarrollo planteado,

el Sistema presenta una buena respuesta en escenas que tienen variaciones de profundidad entre 540mm to 640mm, presentando errores de menos del 5.5% en el rango mencionado.

Palabras Clave: Mapas de Profundidad, Luz Estructurada, Medición de Distancia, Visión por Computador, Geometría Computacional.

1. INTRODUCTION

In the last decade, great strides have been made in capturing the three-dimensional structure of real scenes or objects (Andaló et al., 2015; Avendano et al., 2017; Herrero-Huerta et al., 2015; Lanman et al., 2009). Growing computational capabilities make it possible today to process previously intractable volumes of data, improving techniques and making them faster and more accurate. This ability to model real world scenes on a computer is very advantageous in areas such as industry (Mera et al., 2016), industrial design (Montalto et al., 2016) or graphic arts (Zeng et al., 2014). 3D reconstruction techniques are an essential tool in all those disciplines in which the recovery of the three-dimensional structure of a scene is necessary. For this reason, numerous reconstruction methods have been developed in recent years, including the structured light technique (Pardo-Beainy et al., 2020), laser telemetry (Parmehr et al., 2014), reconstruction by moving camera (Avendano et al., 2017) or the multiview vision technique, where the stereoscopic vision or three-dimensional reconstruction of a scene is found from at least two 2D views, or stereo of the same (Saiz Muñoz, 2010).

This project was inspired by research work carried out in the Department of Engineering and Computer Science at Brown University. Which has focused his attention on topics such as Applied Computational Geometry, Computer Graphics, 3D Modeling, and Computer Vision (Akleman et al., 2015; Andaló et al., 2015; Godin et al., n.d.; Lanman et al., 2009; Lanman & Taubin, 2009; Zhao & Taubin, 2011).

In the same way, this Project provides as a means of consultation for future implementations of 3D scanning systems using structured light, presenting the first steps to begin creating distance sensor devices from image acquisition, which may be used in future projects with applications for reconstruction of three-dimensional scenes.

The goal of this work is the Development of a Depth Map Generation System, aimed at distance determination purposes. Where a process of exploration of the methods of Artificial Vision and Structured Light is carried out, in order to be able to

obtain the depth map of a certain scene. Since, by means of this map, the 3D location data of the objects present in the scene can be extracted. The work focuses on the problem of estimating 3D distances by generating a Depth Map of a scene. Presenting in this way a tool for the development of future applications, such as classification systems (Oh et al., 2010), surface reconstruction (Maurice et al., 2011), 3D recognition and printing (Young et al., 2007), among other.

The present project proposes as a scope the Implementation of a Depth Map Generation System, oriented to the purposes of determining distances, through the use of the structured light technique. The algorithmic development is carried out using the Matlab Software. It should be noted that the work specifically focuses on the process of determining distances on a fixed scene under controlled lighting conditions, and not on light variations in the scene or the environment or moving environments.

2. MATERIALS AND METHODS

2.1 Structured Light

The structured light technique is based on the relationship between a camera and a light source, which projects a known pattern on the scene to be scanned. With this pattern, only the points illuminated by the light source are captured by a camera, which will be in sync with the light emitting source. By matching the captured image to the original pattern, it is possible to triangulate the position of each pixel and determine its depth with respect to the plane perpendicular to the camera. In this way, the camera will capture the deformations of the patterns emitted by the light source (Projector).

Sensors based on structured light are based on three elements: a light pattern, a detector or camera system, and a processing system. The light source is responsible for emitting a light pattern on the object to be scanned, which will cause a deformation in the pattern that will later be measured by a camera (Verdú et al., 2013). The 3D information comes

from the deformation of this pattern based on trigonometric functions (Godin et al., n.d.). Fig. 1. presents a general diagram of a 3D capture system based on structured light.

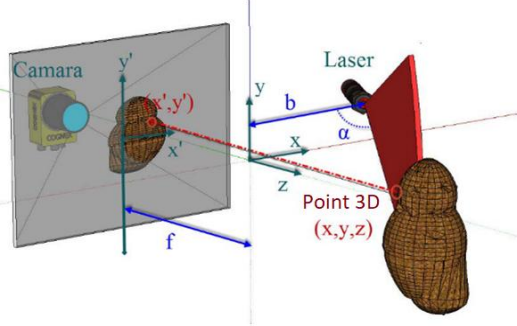


Fig. 1. Scheme of a 3D capture system based on structured light
(Ivorra Martínez, 2015)

2.2 Line-Plane Intersection

A projected line creates a light plane, the intersection of a light plane with the object, usually containing many illuminated curved segments. Each of these segments is made up of many illuminated dots. A single illuminated point, visible to the camera, defines a camera beam. The equations of the projected planes, as well as the equations of the camera rays corresponding to the illuminated points, are defined by parameters that can be measured. From these measurements, the location of the illuminated points can be recovered by intersecting the planes or rays of light with the camera rays corresponding to the illuminated points. In this way, the recovery of a 3D surface model is allowed (Lanman & Taubin, 2009).

To calculate the intersection of a line and a plane, the line is represented in parametric form (1):

$$L = \{p = q_L + \lambda v ; \lambda \in R\} \quad (1)$$

And the plane is represented implicitly (2):

$$P = \{p : n^t(p - q_P) = 0\} \quad (2)$$

If the line and the plane did not cross, it could be said that they are parallel. This is the case if the vectors v and n are orthogonal, that is, if $n^t v = 0$. The vectors v and n are also orthogonal when the line L is contained in the plane P . Neither of these two conditions would be applicable to the structured light system proposed in this work.

If the vectors v and n are not orthogonal, that is if $n^t v \neq 0$, then the intersection of the line and the plane contains exactly one-point p . Since this point belongs to the line, it can be written as $p = q_L + \lambda v$, for a value λ that would need to be determined. Since the point also belongs to the plane, the value λ must satisfy the linear equation (3):

$$n^t(p - q_P) = n^t(q_L + \lambda v - q_P) = 0 \quad (3)$$

And when solving for λ we have (4):

$$\lambda = \frac{n^t(q_P - q_L)}{n^t v} \quad (4)$$

A geometric interpretation of the line-plane intersection is presented in Fig. 2.

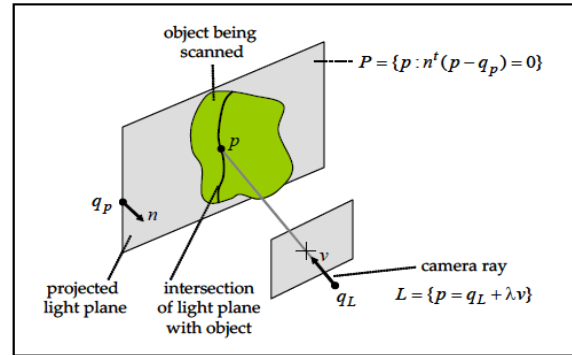


Fig. 2. Triangulation principle by Line-Plane intersection
(Lanman & Taubin, 2009)

2.3 General Perspective

Fig. 3 presents the general scheme of the proposed system. In this scheme, the central part is composed of a computer that has the Matlab R2018a software installed, and it is through this software that the execution of the system is developed, and that the user can appreciate the depth map finally generated in the reconstruction process. To the computer equipment, a projector and a camera are connected, responsible for the emission and acquisition respectively, of each of the considered patterns. These teams are each located on a tripod and oriented towards the scene to be scanned.



Fig. 3. General Scheme of the System

The structured light scanning system can be explained from the block diagram of Fig. 4.

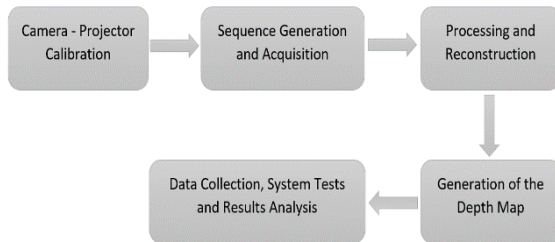


Fig. 4. General Block Diagram of the System

Each of these stages are presented below:

- **Camera - Projector Calibration:** A flat checkerboard calibration method is used to minimize the complexity and cost of calibration (Falcao et al., 2008). This method is based on considering the projector as a reverse camera, assigning 2D image intensities in 3D rays, so the calibration of a projector is the same as that of a camera. In this way, the system can be calibrated using a standard camera calibration method as implemented in the Bouguet calibration toolbox. (Bouguet, n.d.).
- **Sequence Generation and Acquisition:** In this stage a set of 42 structured light patterns is generated, using Gray coding; as these patterns are projected, an acquisition process is developed for their subsequent processing.
- **Processing and Reconstruction:** With the images from the acquisition system, the necessary processing is carried out to reconstruct a 3D point cloud, through triangulation. In this way, the depth map of the scene is generated.
- **Generation of the Depth Map:** With the point cloud of the reconstructed scene, the depth map of the scene is obtained, thus determining the separation distance that may exist between the acquisition device (camera) and a determined object being scanned.

- **Data Collection, System Tests and Results Analysis:** Once the implementation has been carried out, the behavior of the system is verified through data collection, system tests and analysis of the results obtained. As a result of this stage, the advantages and disadvantages of the implemented system can be concluded and future works that complement the proposed development can be proposed.

In Fig. 5, the placement of the camera and the projector can be seen, where both point to a scene arranged on a table for scanning.



Fig. 5. Photograph of the placement of the Camera and Projector

3. RESULTS

3.1 Calibration Results

In this work, the method implemented for the calibration of the camera-projector system (Falcao et al., 2008), is an extension of the method proposed by Bouguet in Matlab's camera calibration toolbox (Bouguet, n.d.). As a first step in the development process, the images were acquired with the camera. For this, a sequential image acquisition and storage program developed from Matlab was generated.

After performing the camera calibration process, the extrinsic and intrinsic parameters of the camera are obtained, which will be loaded to continue with the projector calibration process. The results of the

calibration are recorded in a file called `calib_cam_proj.mat`, which is called from the Matlab program to take these parameters into account in its execution. Likewise, to observe the calibration parameters, a graph is presented with the extrinsic components of the calibration, in a plane that includes the camera and the projector. In this graph, the extrinsic components of the calibration can be visually verified and compared to the actual configuration.

Extrinsic parameters (camera-centered)

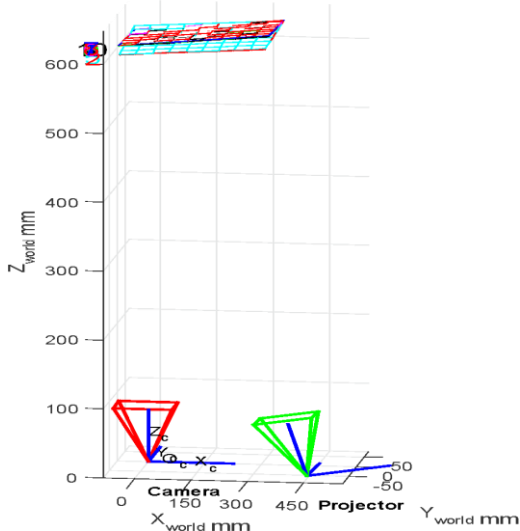


Fig. 6. Extrinsic parameters of the camera-projector calibration

3.2 Results of the generation and acquisition of sequences

As a test sequence, a set of blocks stacked in three stairs is used, which increase in depth as their levels increase; In total, there are 24 stairs that are stacked on a common base in three blocks of 8 stairs each, the stairs on the left being the ones closest to the camera and those on the right the furthest.

For the system tests, a sequence of 42 pattern images was generated following a gray code in the stripes projected on the selected scene. In this way, for each of the tests carried out, 42 images were acquired for subsequent processing. Each one of the images was stored in .BMP bitmap format and has a resolution of 1600 x1200 pixels and a size of 5.49MB. Fig 7 shows the images acquired with structured light sequence in gray code.

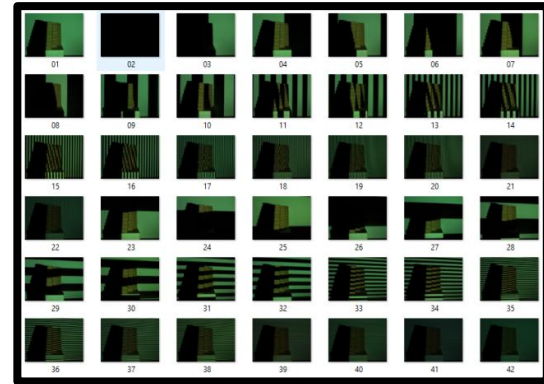


Fig. 7. Images Acquired with Structured Light Sequence in Gray Code

3.3 Processing and Reconstruction Results

Decoded correspondences are used to reconstruct a 3D point cloud of the scene, taking as a texture reference the first image acquired with a projected white pattern. By reconstructing the scene of stairs, the results presented below are obtained in a point cloud in an X, Y, Z plane. In Fig. 8, the distribution of the point cloud is shown taking the Z axis as the axis of depth in millimeters. The image presents the scene including the camera (represented in red) and the projector (represented in green).

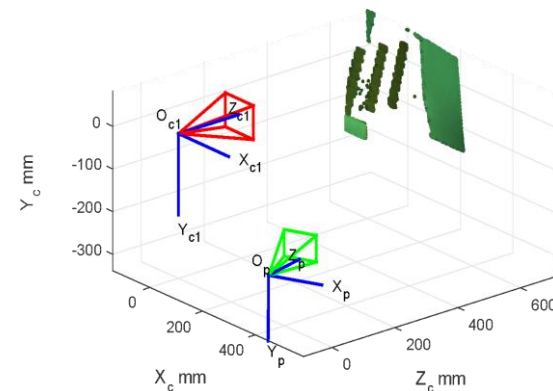


Fig. 8. 3D reconstruction through a decoded point cloud of the scene

3.4 Results of the Depth Map Generation

From the correspondence values of the previously presented point clouds, the depth map of the treated scenes was generated. For this, the coordinates of each of the points in X, Y, Z were taken, where Z represents the depth in millimeters of each point in the scene under consideration. Fig. 9, shows the depth map of the Stairs scene, where an equivalence of depth is proposed, associated with a map of color intensities of 100 rows per 100 columns of data and an interpolation with the closest values is proposed,

to appreciate a more uniform behavior on the depth map.

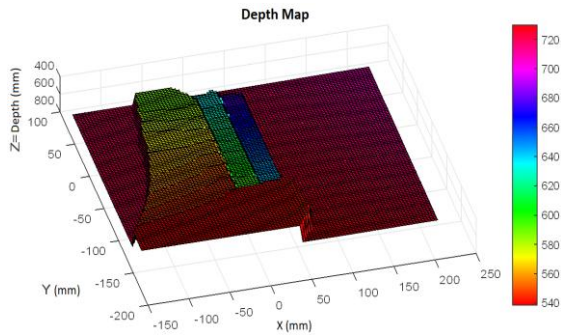


Fig. 9. Depth Map of Stairs Scene

To validate the data produced by the developed system, measurements of the scene were taken with a digital laser distance meter from the manufacturer Milesee Technology, which has a measurement precision of +/- 1.5mm. Measurements were made of the distance from the camera to each of the stairs in the scene, to make comparisons of its behavior, with respect to a set of reference data from another measurement instrument. Fig. 10 shows the validation procedure developed.



Fig. 10. Validation of depth with a digital laser distance meter

In total, 26 measurement points were taken, equivalent to the common base (Eb), the stairs of each of the columns ((Left column (Ea1 - Ea8)), (Central column (Eb1 - Eb8)) and (Column right (Ec1 - Ec8))) and the distance to the wall (P). With these measurements, a graph was developed that shows the behavior of each of the measurements. In Fig. 11 the results of the structured light measurement system can be seen in blue and in orange, the results obtained with the laser meter.

Likewise, and according to the data presented, a graph was made showing the percentage of error for

each of the samples taken. In Fig. 12, this error is shown in gray, which, according to the measurement scale on the right side of the graph, reaches its minimum point (0%) in stair Ea1 and its maximum point (11.7%) in the measurement made at the point corresponding to wall P. It can also be seen that there is a gradual increase in the error that corresponds to a second-order polynomial trend curve, as the depth is greater, and that the error is it maintains less than 5% in the range from 540mm to 630mm.

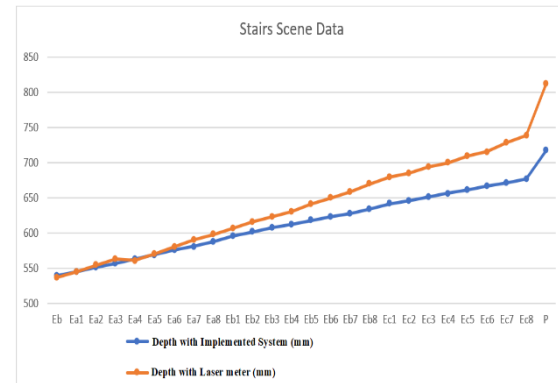


Fig. 11. Depth Measurement Data with the Structured Light system and the Laser meter on the Stairs scene

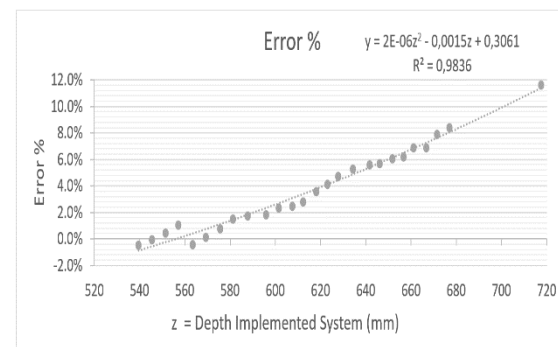


Fig. 12. Error % for each data

3.5 Compute Time

The computational performance of the system is verified through the time invested in the execution of each of its stages. The execution times of each stage were measured with the Matlab commands “tic” (at the beginning of each section) and “toc” (at the end of each section), giving the results presented in table 1.

Table 1: Measured Time for the Execution of the System

Stage	Measured time for the execution of the Stage
Camera Settings	0,2976 seconds
Generation and Acquisition of a single Structured Light sequence	0,7673 seconds
Generation and Acquisition of the 42 Structured Light sequences	35,1516 seconds
Processing and Reconstruction Stage	5,0931 seconds
Depth Map Generation Stage	0,1412 seconds
Full System Execution	41,8109 seconds

With the above table, it can be seen that the total time invested for the execution of the system is approximately 41,8109 seconds.

3.6 t Student Statistical Test

With the data presented, a statistical t Student test was carried out to determine if there are significant differences between the two groups of collected data (taken with the laser meter or taken with the structured light system proposed). This test was performed using the Excel data analysis tool, with a significance of 95% (that is, with an alpha of 0.05). For the test in question, two contexts were considered in the acquisition of the scene stairs; The first consisted of evaluating the similarity between the data taken, applied to the first line of stairs (Eb to Ea8), yielding the results presented in table 2. When developing this test, it was observed that its value is of 0.075225, and being greater than the value defined for alpha, it can be concluded that there is no evidence of a significant difference between the samples of the data taken in the first line of stairs with the two measurement systems used.

The same procedure was developed considering all the stairs taken in the scene. The results are presented in table 3 and in this case the value of the test is less than that defined for alpha, which implies a difference that becomes significant between the values taken with the two measuring instruments.

Table 2: Results of the t Student test applied to the first line of the Stairs scene

First Line of Stairs	Depth with Implemented System (mm)	Depth with Laser meter (mm)
Mean	563,2667	566,4444
Observations	9,0000	9,0000
Pearson's correlation coefficient	0,9887	

Degrees of freedom	8,0000
P(T<=t) two tails	0,075225

Table 3: Results of the t Student test applied to all samples of the Stairs scene

All Samples	Depth with Implemented System (mm)	Depth with Laser meter (mm)
Mean	614,5346	640,7308
Observations	26,0000	26,0000
Pearson's correlation coefficient	0,9965	
Degrees of freedom	25,0000	
P(T<=t) two tails	0,000009	

4. CONCLUSIONS

This project provides basic parameters that lead to the development of a depth map generation system, capable of being presented as an alternative to determine distances in a scene, generating a plane of Z values that can be used for subsequent applications where require the distances of the mentioned map.

It can be concluded that the system presents a good response to scenes that have depth variations between 540mm to 640mm, presenting errors of less than 5.5% in the mentioned range. This error is gradual, corresponding to a second order polynomial trend curve, as the depth is greater.

The development of distance determination systems through depth maps presents a much more complete data alternative than that found when making measurements with single point digital laser measurement systems, since it allows generating more information on the various depths at multiple coordinate points in the scene.

It could be seen that the shadows generated by the scene itself generate areas where the bands of coded structured light cannot be interpreted. For this reason, wrong depth measurements can be generated over the shadow area.

The total processing time of the system is close to 42 seconds, investing a time close to 35 seconds in the process of generation and acquisition of sequences.

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