

Parallel Tracking and Mapping for Small AR Workspaces

Abstract

a system specifically designed to track a hand-held camera in a small AR workspace, and split tracking and mapping into two separate tasks, processed in parallel threads

Explanation

- Track : build 3D data by outside input message
- Map : display graphic model on the screen

Method Overview

- Tracking and Mapping are separated, and run in two parallel threads.
- Mapping is based on keyframes, which are processed using batch techniques (Bundle Adjustment).
- The map is densely initialized from a stereo pair (5-Point Algorithm)
- New points are initialized with an epipolar search.
- Large numbers (thousands) of points are mapped.

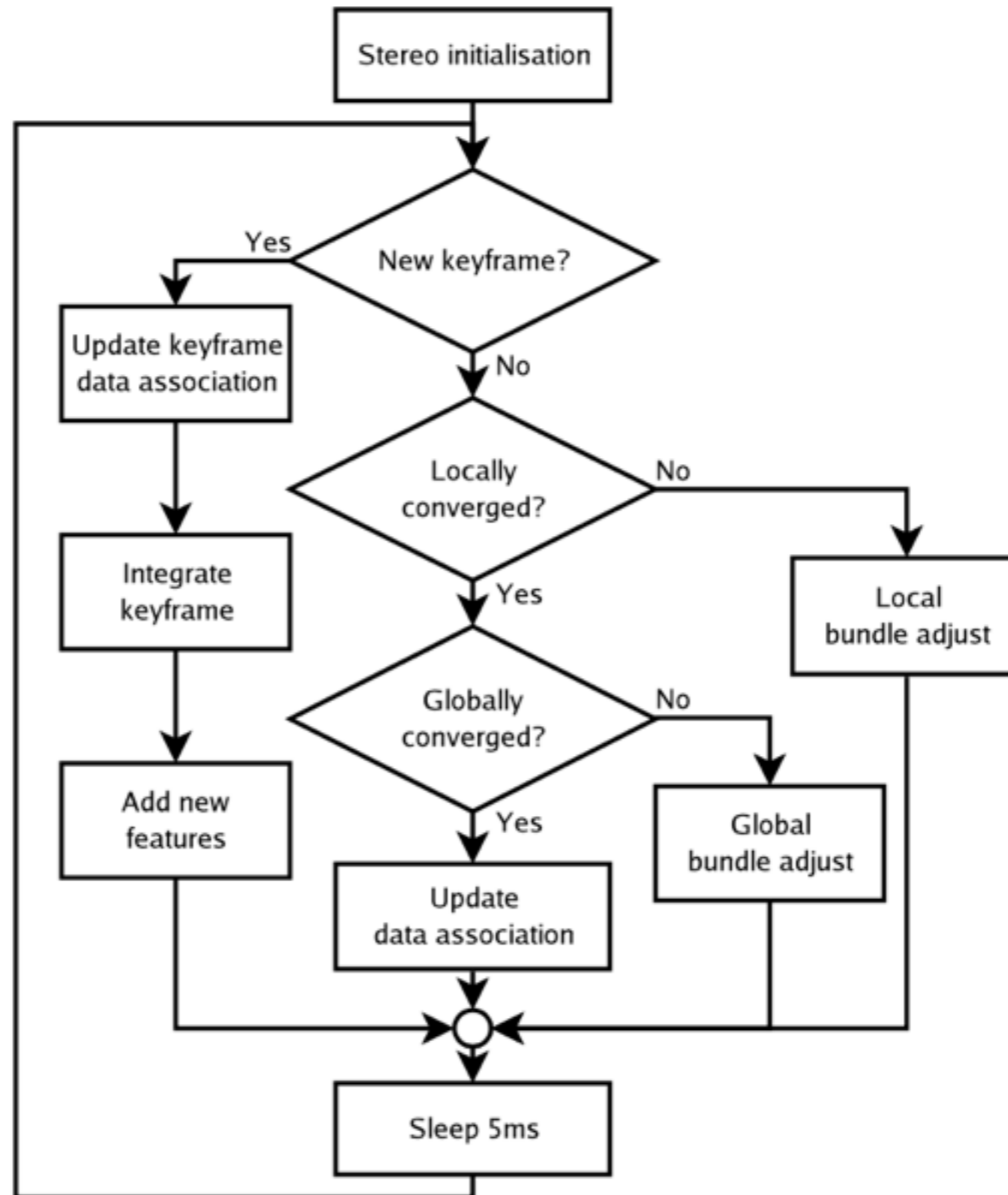
Environment

- A world coordinate frame : Each point feature represents a locally planar textured patch in the world. Each point also has a unit patch normal and a reference to the patch source pixels.
- Keyframes : These are snapshots taken by the handheld camera at various points in time. Each keyframe has an associated camera-centered coordinate frame. Each keyframe also stores a four-level pyramid of greyscale 8bpp images; level zero stores the full 640×480 pixel camera snapshot, and this is sub-sampled down to level three at 80×60 pixels.

Tracking

1. A new frame is acquired from the camera, and a prior pose estimate is generated from a motion model.
2. Map points are projected into the image according to the frame's prior pose estimate.
3. A small number (50) of the coarsest-scale features are searched for in the image.
4. The camera pose is updated from these coarse matches.
5. A larger number(1000) of points is re-projected and searched for in the image.
6. A final pose estimate for the frame is computed from all the matches found.

Mapping



Demo

<https://www.youtube.com/watch?v=Y9HMn6bd-v8>

Progress report

- Done : Fix crowdsourcing server
- Todo : build the appearance of Pokemon app