

Development of intelligent systems (RInS)

Object detection in 3D

Danijel Skočaj

University of Ljubljana

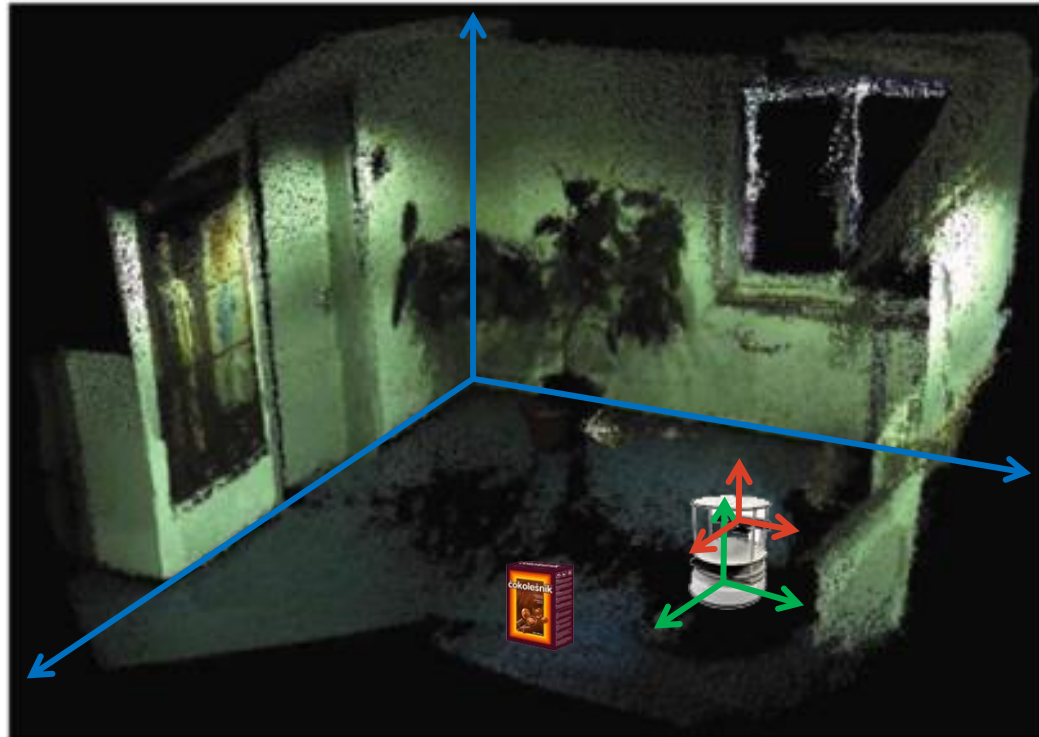
Faculty of Computer and Information Science

Academic year: 2022/23

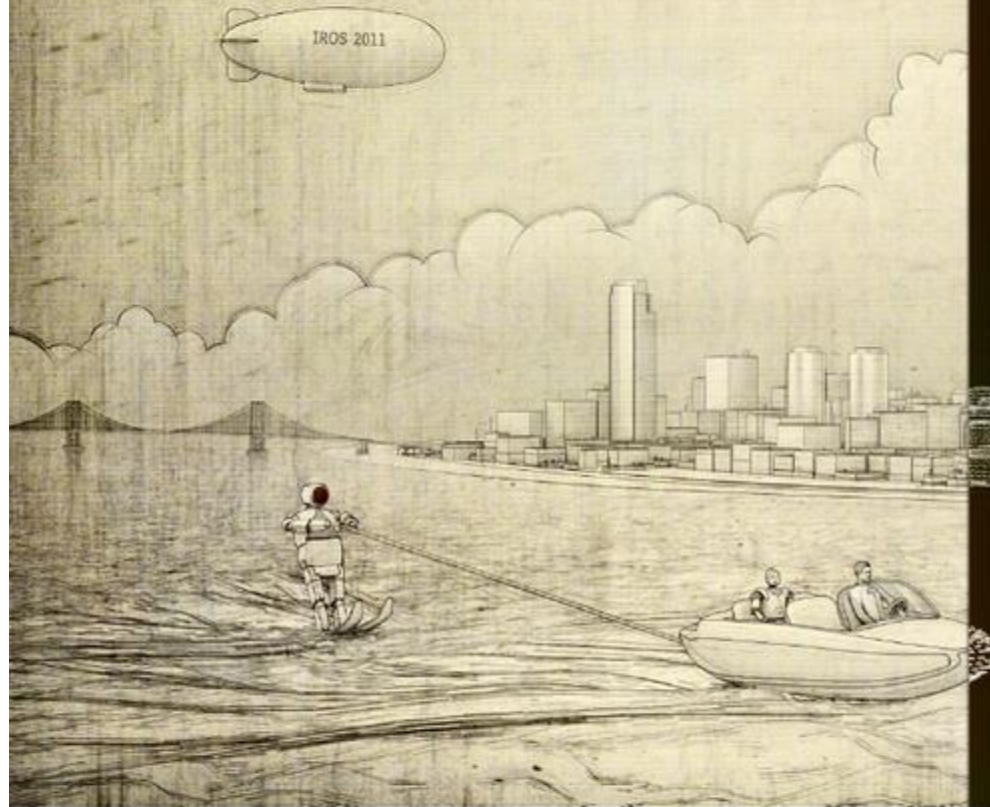
Detection of obstacles and objects



3D perception



Celebrating 50 Years of Robotics



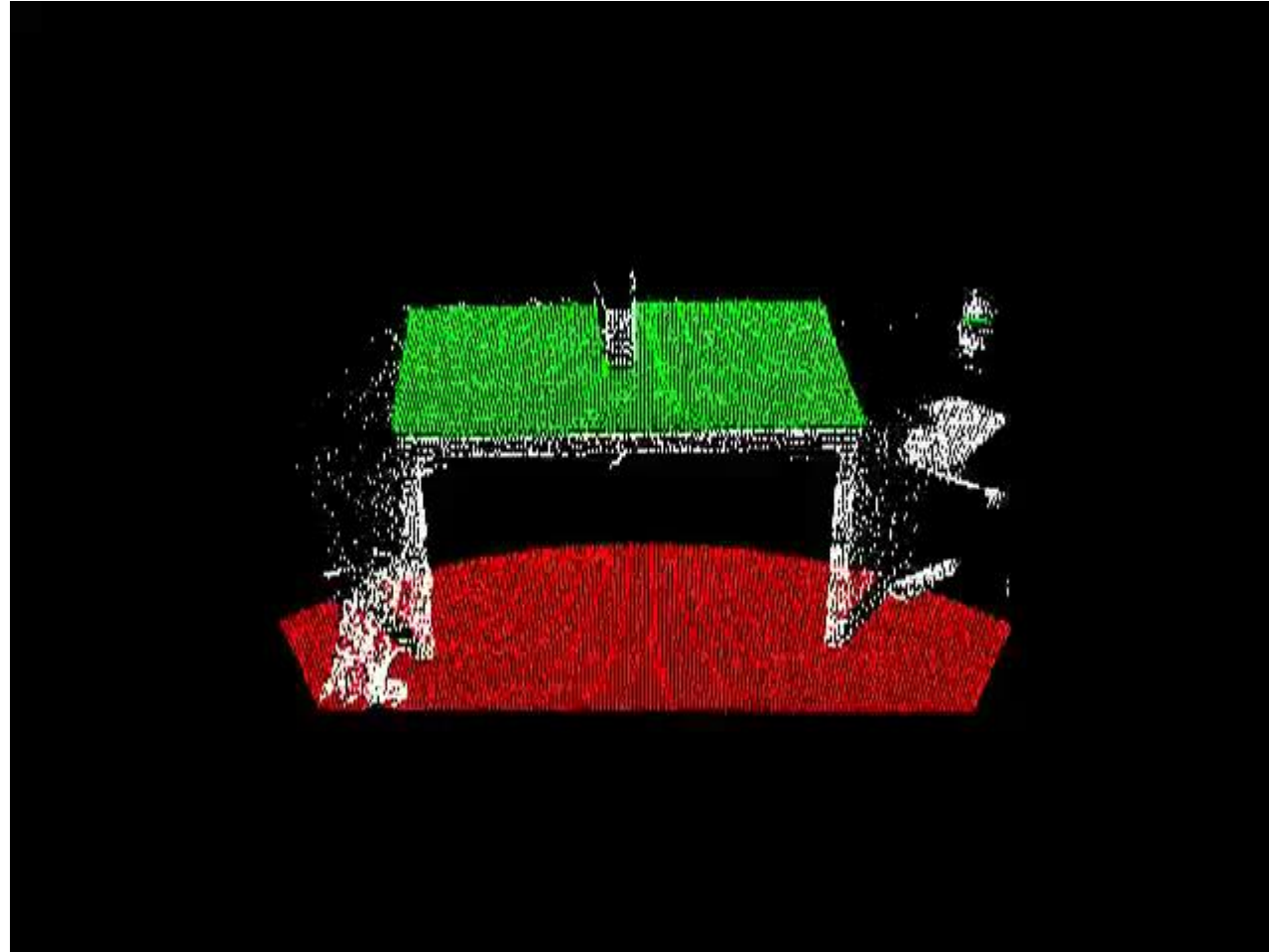
 pointcloudlibrary

PCL :: Segmentation

September 25, 2011

Radu Bogdan Rusu, Nico Blodow, Willow Garage, PCL

Detection of planes



- Random Sampling Consensus [Fischler, Bolles '81]

In: $U = \{x_i\}$ set of data points, $|U| = N$

$f(S) : S \rightarrow p$ function f computes model parameters p given a sample S from U

$\rho(p, x)$ the cost function for a single data point x

Out: p^* p^* , parameters of the model maximizing the cost function

$k := 0$

Repeat until $P\{\text{better solution exists}\} < \eta$ (a function of C^* and no. of steps k)

$k := k + 1$

I. Hypothesis

(1) select randomly set $S_k \subset U$, sample size $|S_k| = m$

(2) compute parameter $p_k = f(S_k)$

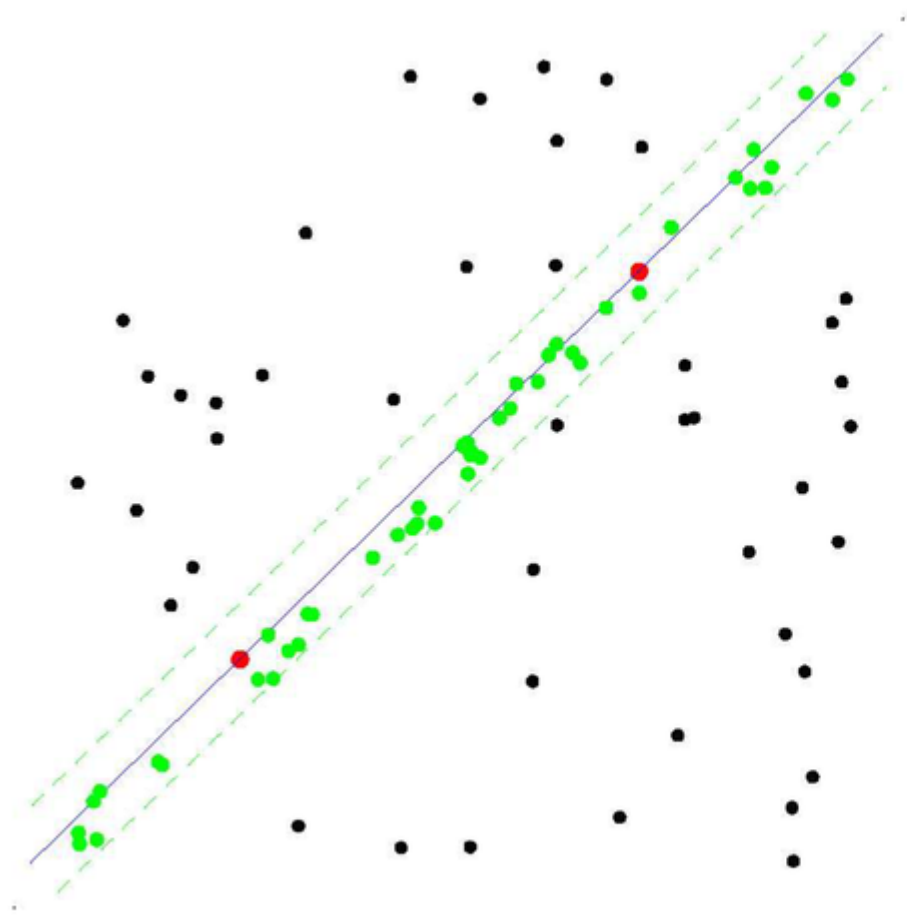
II. Verification

(3) compute cost $C_k = \sum_{x \in U} \rho(p_k, x)$

(4) if $C^* < C_k$ then $C^* := C_k$, $p^* := p_k$

end

RANSAC



ALL-INLIER SAMPLE

RANSAC time complexity

$$t = k(t_M + \bar{m}_s N)$$

k ... number of samples drawn

N ... number of data points

t_M ... time to compute a single model

\bar{m}_s ... average number of models per

sample

J. Matas @ CVPR 11 Registration Tutorial

the “gold standard” algorithm:

In: $U = \{x_i\}$ set of data points, $|U| = N$

$f(S) : S \rightarrow p$ function f computes model parameters p given a sample S from U

$\rho(p, x)$ the cost function for a single data point x

Out: p^* p^* , parameters of the model maximizing the cost function

$k := 0$

Repeat until $P\{\text{better solution exists}\} < \eta$ (a function of C^* and no. of steps k)

$k := k + 1$

I. Hypothesis

(1) select randomly set $S_k \subset U$, sample size $|S_k| = m$

(2) compute parameters $p_k = f(S_k)$

II. Verification

(3) compute cost

(4) if $C^* < C_k$ then $C^* := C_k, p^* := p_k$ $C_k = \sum_{x \in U} \rho(p_k, x)$

end Repeat

p^{out} = least square fit on the set of inliers to p^*

J. Matas @ CVPR 11 Registration Tutorial

RANSAC in PCL

Point Cloud Library (PCL) 1.10.1-dev

[Main Page](#)[Related Pages](#)[Modules](#)[Namespaces ▾](#)[Classes ▾](#)[Classes | Functions](#)

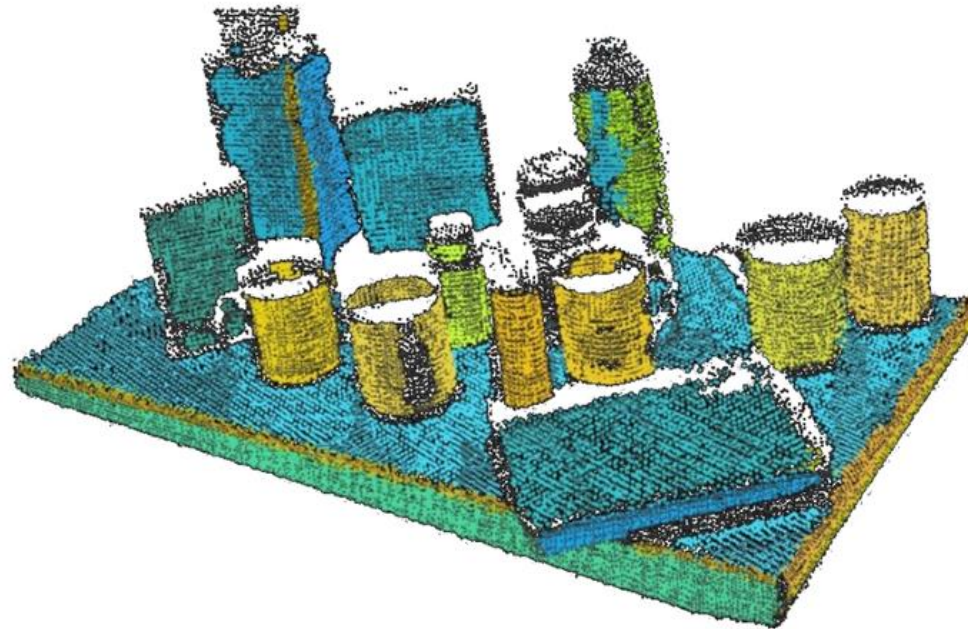
Module `sample_consensus`

[Detailed Description](#)

Overview

The `pcl_sample_consensus` library holds Sample Consensus (SAC) methods like RANSAC and models like planes and cylinders. These can be combined freely in order to detect specific models and their parameters in point clouds.

Some of the models implemented in this library include: lines, planes, cylinders, and spheres. Plane fitting is often applied to the task of detecting common indoor surfaces, such as walls, floors, and table tops. Other models can be used to detect and segment objects with common geometric structures (e.g., fitting a cylinder model to a mug).

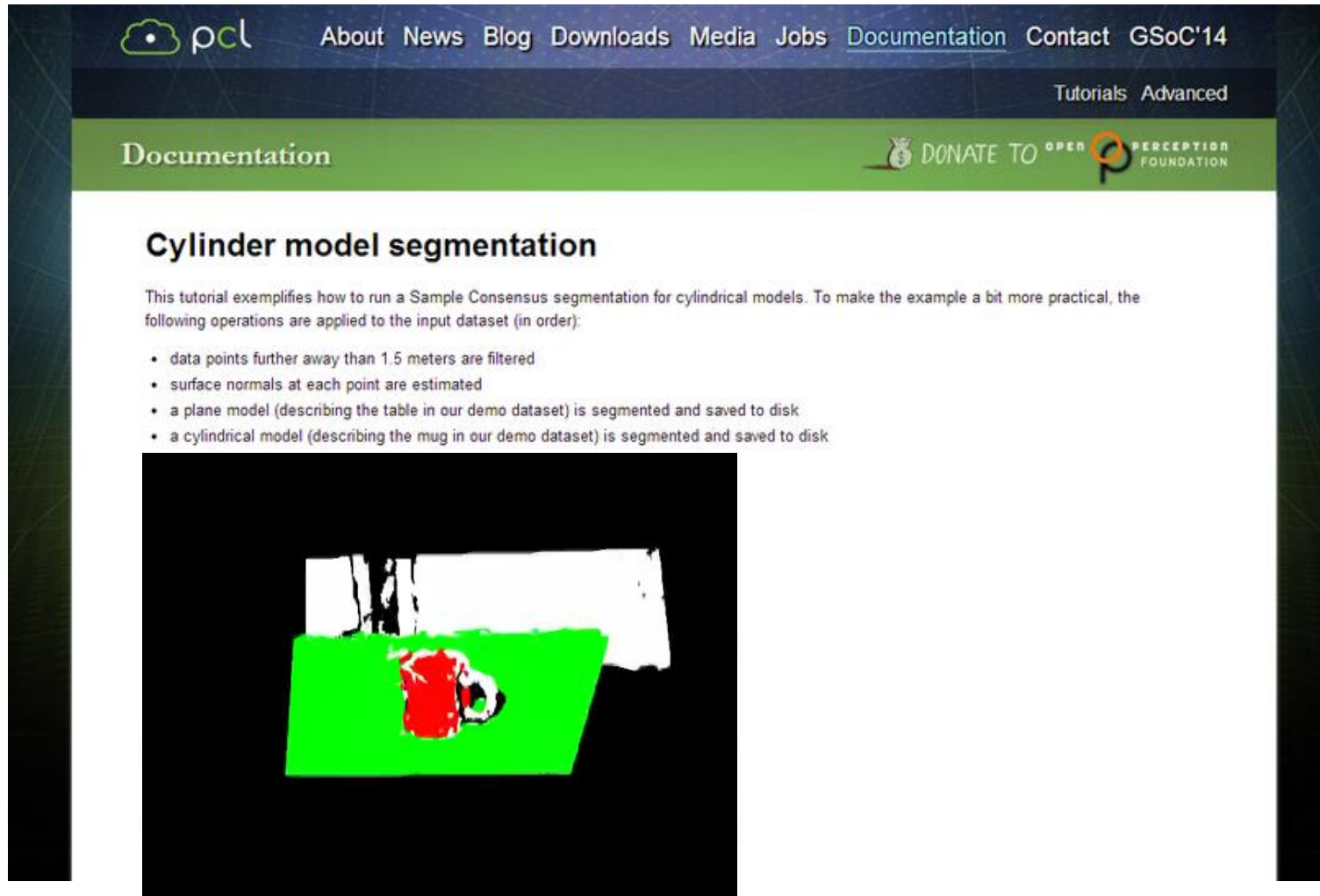


RANSAC in PCL

The following models are supported:

- **SACMODEL_PLANE** - used to determine plane models. The **four** coefficients of the plane are its Hessian Normal form: [normal_x normal_y normal_z d]
- **SACMODEL_LINE** - used to determine line models. The **six** coefficients of the line are given by a point on the line and the direction of the line as: [point_on_line.x point_on_line.y point_on_line.z line_direction.x line_direction.y line_direction.z]
- **SACMODEL_CIRCLE2D** - used to determine 2D circles in a plane. The circle's **three** coefficients are given by its center and radius as: [center.x center.y radius]
- **SACMODEL_CIRCLE3D** - used to determine 3D circles in a plane. The circle's **seven** coefficients are given by its center, radius and normal as: [center.x, center.y, center.z, radius, normal.x, normal.y, normal.z]
- **SACMODEL_SPHERE** - used to determine sphere models. The **four** coefficients of the sphere are given by its 3D center and radius as: [center.x center.y center.z radius]
- **SACMODEL_CYLINDER** - used to determine cylinder models. The **seven** coefficients of the cylinder are given by a point on its axis, the axis direction, and a radius, as: [point_on_axis.x point_on_axis.y point_on_axis.z axis_direction.x axis_direction.y axis_direction.z radius]
- **SACMODEL_CONE** - used to determine cone models. The **seven** coefficients of the cone are given by a point of its apex, the axis direction and the opening angle, as: [apex.x, apex.y, apex.z, axis_direction.x, axis_direction.y, axis_direction.z, opening_angle]
- **SACMODEL_TORUS** - not implemented yet
- **SACMODEL_PARALLEL_LINE** - a model for determining a line **parallel** with a given axis, within a maximum specified angular deviation. The line coefficients are similar to **SACMODEL_LINE**.
- **SACMODEL_PERPENDICULAR_PLANE** - a model for determining a plane **perpendicular** to a user-specified axis, within a maximum specified angular deviation. The plane coefficients are similar to **SACMODEL_PLANE**.
- **SACMODEL_PARALLEL_LINES** - not implemented yet
- **SACMODEL_NORMAL_PLANE** - a model for determining plane models using an additional constraint: the surface normals at each inlier point has to be parallel to the surface normal of the output plane, within a maximum specified angular deviation. The plane coefficients are similar to **SACMODEL_PLANE**.
- **SACMODEL_NORMAL_SPHERE** - similar to **SACMODEL_SPHERE**, but with additional surface normal constraints.
- **SACMODEL_PARALLEL_PLANE** - a model for determining a plane **parallel** to a user-specified axis, within a maximum specified angular deviation. The plane coefficients are similar to **SACMODEL_PLANE**.
- **SACMODEL_NORMAL_PARALLEL_PLANE** defines a model for 3D plane segmentation using additional surface normal constraints. The plane normal must lie **parallel** to a user-specified axis. **SACMODEL_NORMAL_PARALLEL_PLANE** therefore is equivalent to **SACMODEL_NORMAL_PLANE** + **SACMODEL_PERPENDICULAR_PLANE**. The plane coefficients are similar to **SACMODEL_PLANE**.
- **SACMODEL_STICK** - a model for 3D stick segmentation. A stick is a line with a user given minimum/maximum width.

Detection of cylinders



The screenshot shows the PCL website's documentation page for cylinder model segmentation. The page has a dark blue header with the PCL logo and navigation links: About, News, Blog, Downloads, Media, Jobs, Documentation, Contact, and GSoC'14. Below the header is a green bar with the word "Documentation" on the left and a "DONATE TO OPEN PERCEPTION FOUNDATION" logo on the right. The main content area has a white background and features the title "Cylinder model segmentation" in bold. Below the title is a paragraph explaining the tutorial's purpose and a list of operations applied to the input dataset. At the bottom of the page is a 3D point cloud visualization of a scene with a red cylindrical mug on a green table, with a white background and black shadows.

pcl About News Blog Downloads Media Jobs Documentation Contact GSoC'14

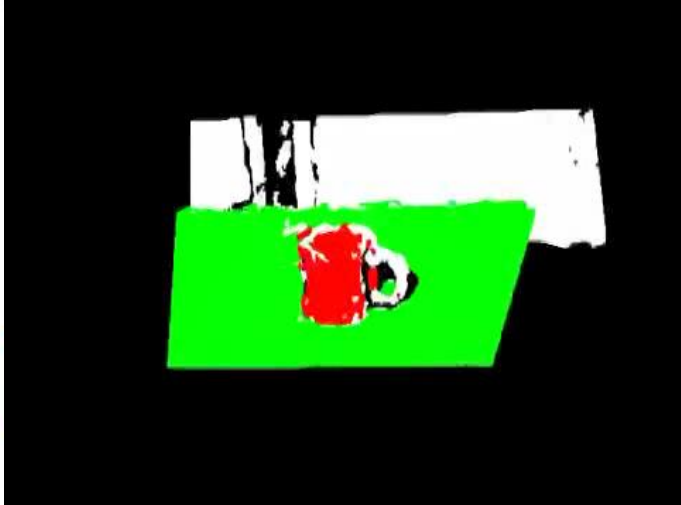
Tutorials Advanced

Documentation

Cylinder model segmentation

This tutorial exemplifies how to run a Sample Consensus segmentation for cylindrical models. To make the example a bit more practical, the following operations are applied to the input dataset (in order):

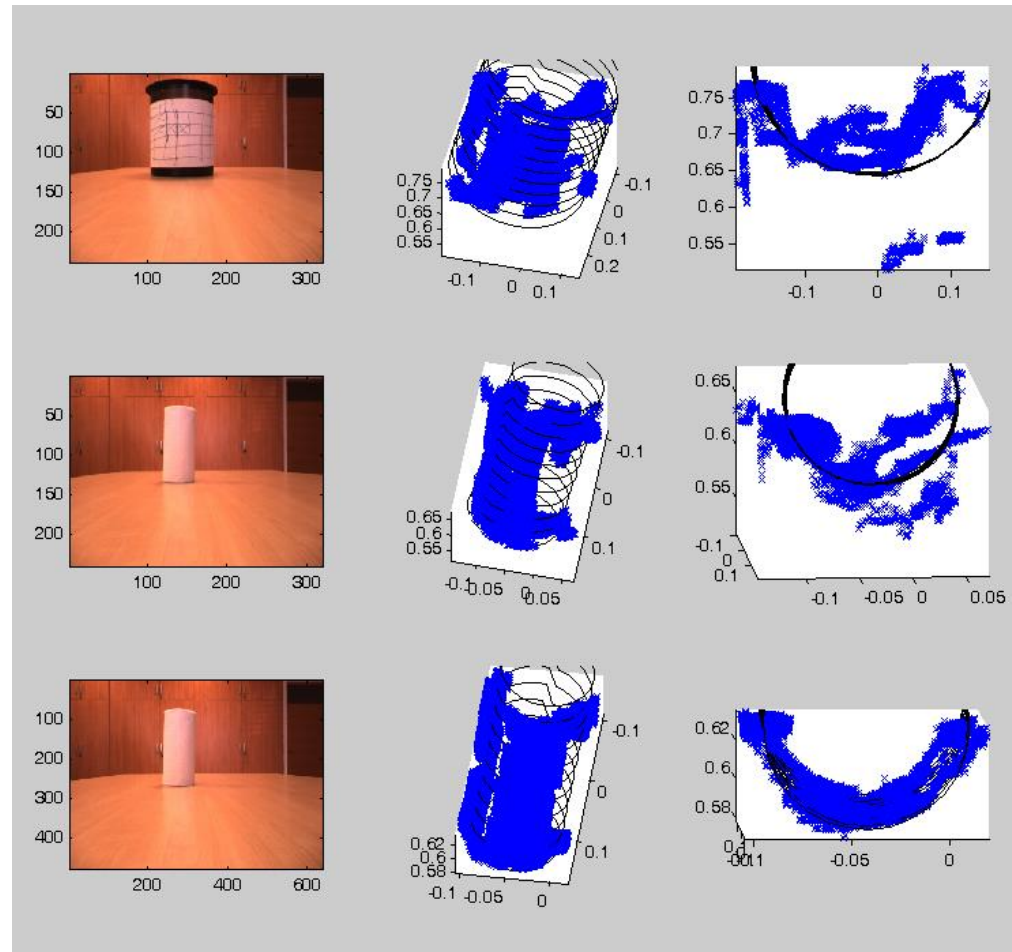
- data points further away than 1.5 meters are filtered
- surface normals at each point are estimated
- a plane model (describing the table in our demo dataset) is segmented and saved to disk
- a cylindrical model (describing the mug in our demo dataset) is segmented and saved to disk



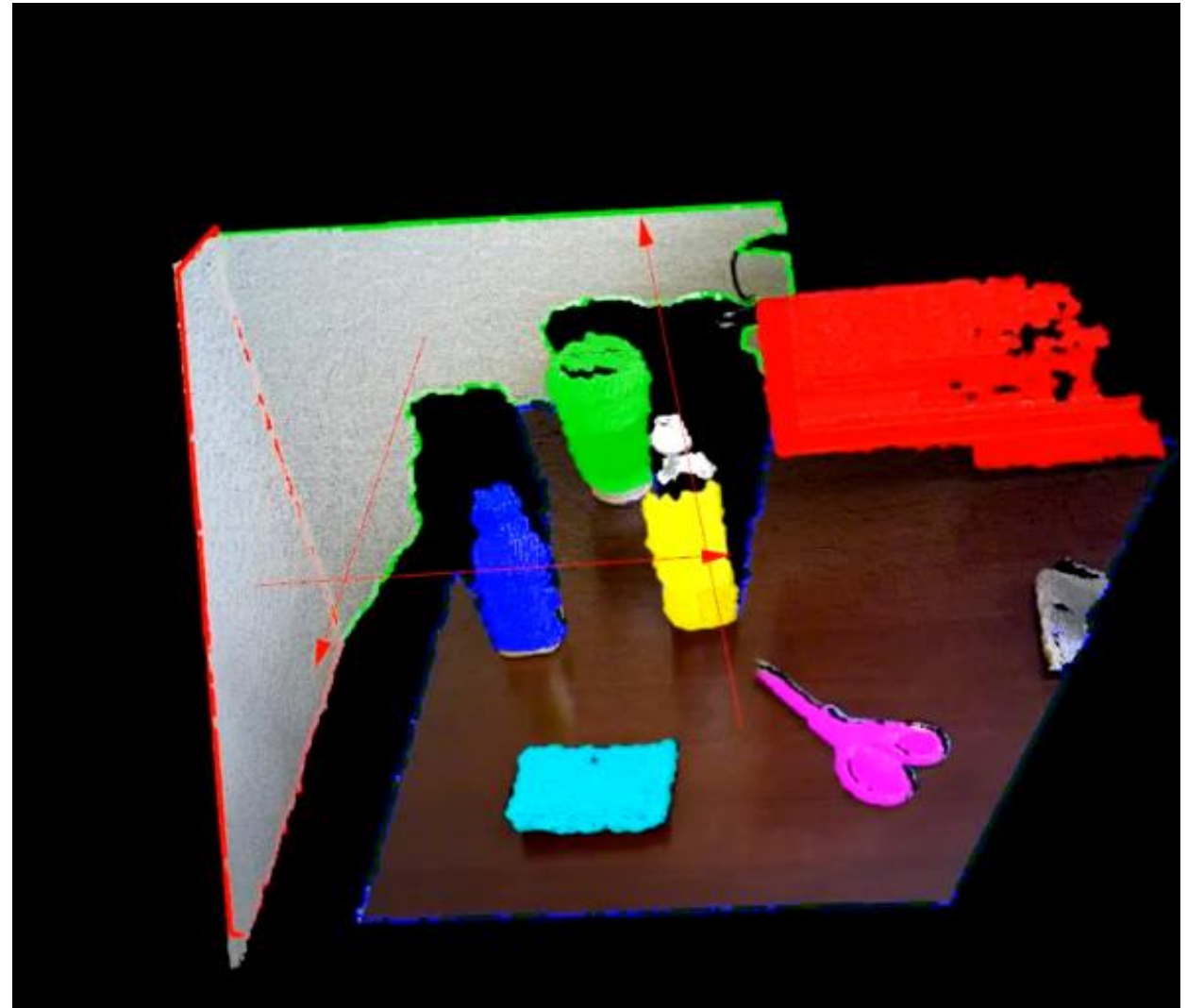
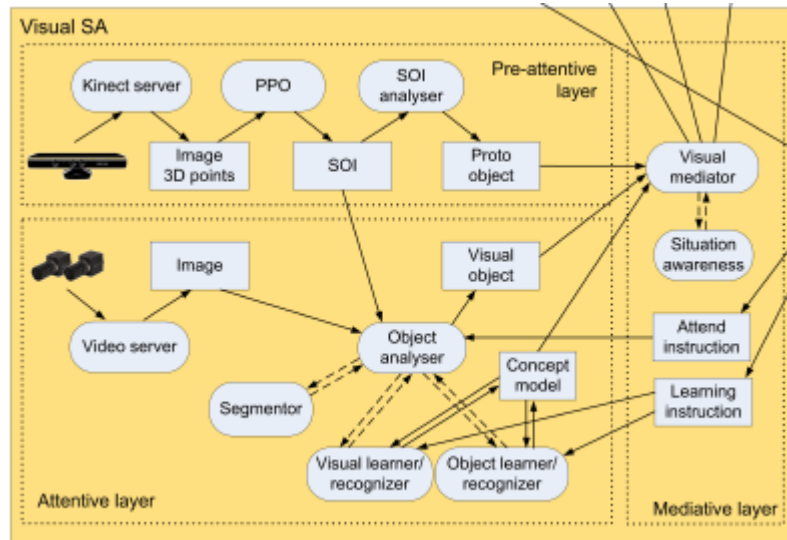
http://pointclouds.org/documentation/tutorials/cylinder_segmentation.php

Detection of cylinders

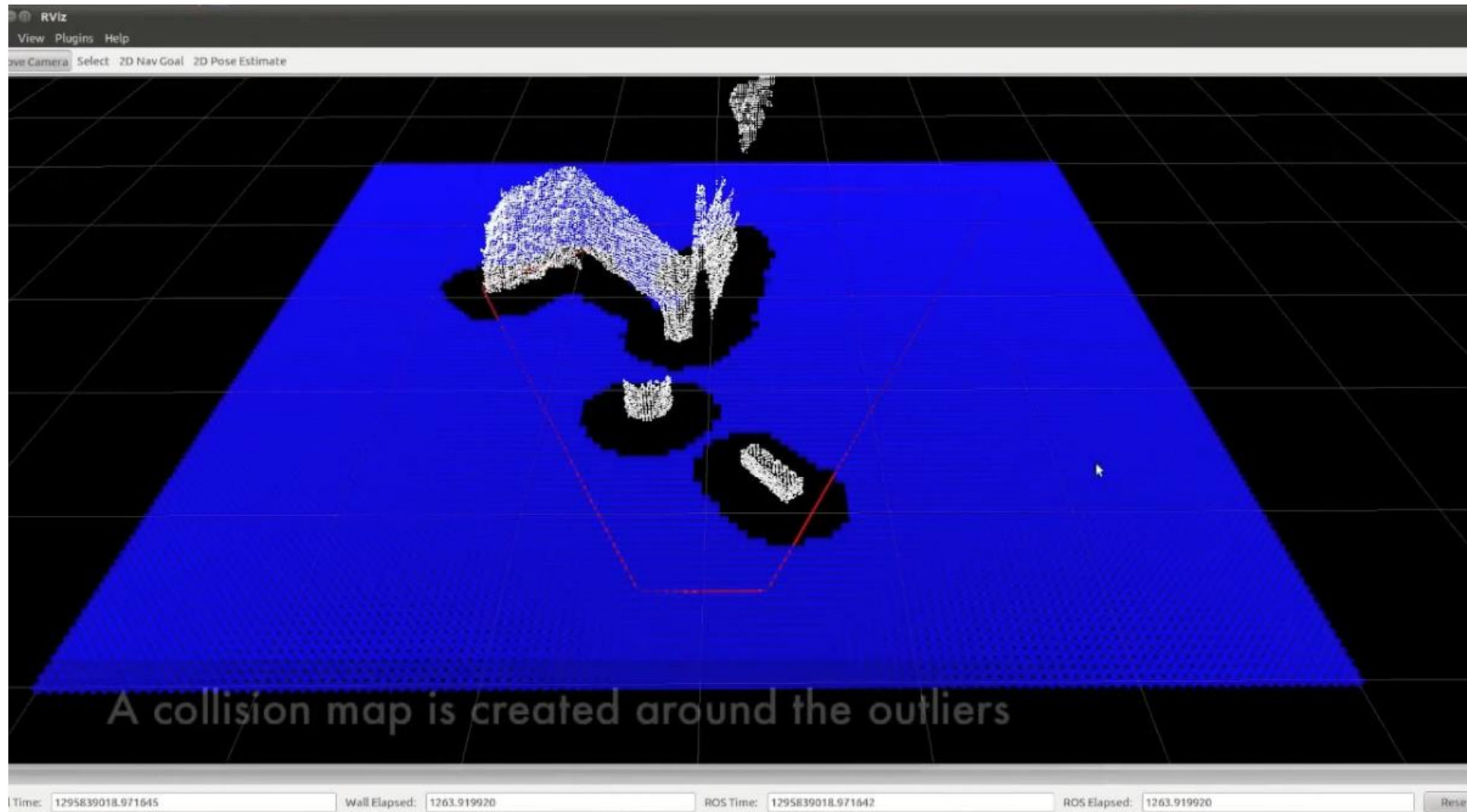
- Noisy data



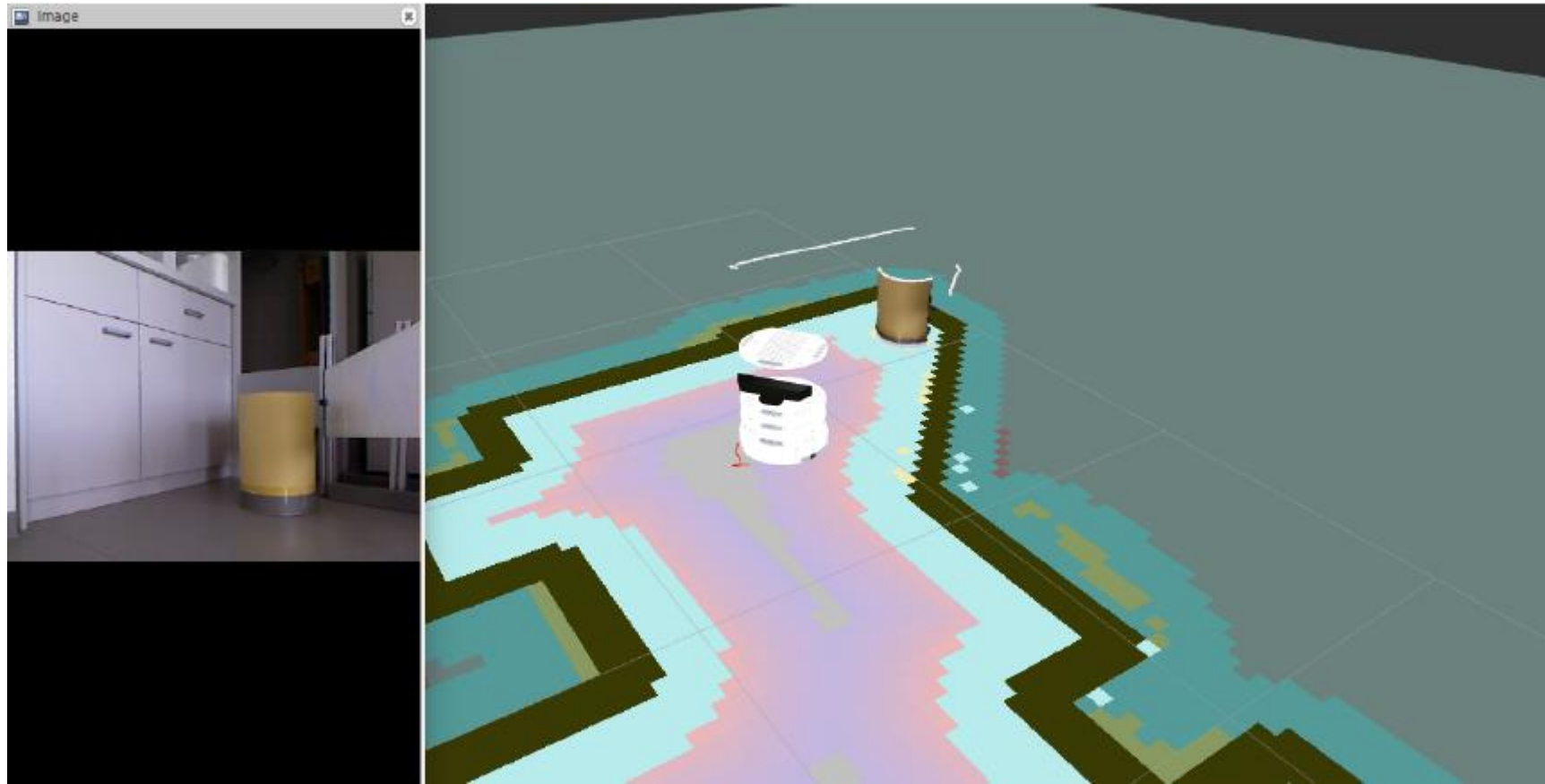
Detection of objects



Collision map



Cylinder detection



Ring detection

