Cam Fx Pixel Free

Katsushi Ikeuchi,Yasuyuki Matsushita,Ryusuke Sagawa,Hiroshi Kawasaki,Yasuhiro Mukaigawa,Ryo Furukawa,Daisuke Miyazaki

Reconstruction-Free Compressive Vision for Surveillance Applications Henry Braun,Pavan Turaga,Andreas Spanias,Sameeksha Katoch,Suren Jayasuriya,Cihan Tepedelenlioglu,2022-05-31 Compressed sensing (CS) allows signals and images to be reliably inferred from undersampled measurements. Exploiting CS allows the creation of new types of high-performance sensors including infrared cameras and magnetic resonance imaging systems. Advances in computer vision and deep learning have enabled new applications of automated systems. In this book, we introduce reconstruction-free compressive vision, where image processing and computer vision algorithms are embedded directly in the compressive domain, without the need for first reconstructing the measurements into images or video. Reconstruction of CS images is computationally expensive and adds to system complexity. Therefore, reconstruction-free compressive vision is an appealing alternative particularly for power-aware systems and bandwidth-limited applications that do not have on-board post-processing computational capabilities. Engineers must balance maintaining algorithm performance while minimizing both the number of measurements needed and the computational requirements of the algorithms. Our study explores the intersection of compressed sensing and computer vision, with the focus on applications in surveillance and autonomous navigation. Other applications are also discussed at the end and a comprehensive list of references including survey papers are given for further reading.

NASA Tech Briefs ,1996

Active Lighting and Its Application for Computer Vision Katsushi Ikeuchi,Yasuyuki Matsushita,Ryusuke Sagawa,Hiroshi Kawasaki,Yasuhiro Mukaigawa,Ryo Furukawa,Daisuke Miyazaki,2020-09-07 This book describes active illumination techniques in computer vision. We can classify computer vision techniques into two classes: passive and active techniques. Passive techniques observe the scene statically and analyse it as is. Active techniques give the scene some actions and try to facilitate the analysis. In particular, active illumination techniques project specific light, for which the characteristics are known beforehand, to a target scene to enable stable and accurate analysis of the scene. Traditional passive techniques have a fundamental limitation. The external world surrounding us is three-dimensional; the image projected on a retina or an imaging device is two-dimensional. That is, reduction of one dimension has occurred. Active illumination techniques compensate for the dimensional reduction by actively controlling the illumination. The demand for reliable vision sensors is rapidly increasing in many application areas, such as robotics and medical image analysis. This book explains this new endeavour to explore the augmentation of reduced dimensions in computer vision. This book consists of three parts: basic concepts, techniques, and applications. The first part explains the basic concepts for understanding active illumination techniques. In particular, the basic concepts of optics are explained so that researchers and engineers outside the field can understand the later chapters. The second part explains currently available active illumination techniques, covering many techniques developed by the authors. The final part shows how such active illumination techniques can be applied to various domains, describing the issue to be overcome by active illumination techniques and the advantages of using these techniques. This book is primarily aimed at 4th year undergraduate and 1st year graduate students, and will also help engineers from fields beyond computer vision to use active illumination techniques. Additionally, the book is suitable as course material for technical seminars.

Self-Calibration of Multi-Camera Systems Ferid Bajramovic,2010 Multi-camera systems play an increasingly important role in computer vision. They enable applications like 3D video reconstruction, motion capture, smart homes, wide area surveillance, etc. Most of these require or benefit from a calibration of the multi-camera system. This book presents a novel approach for automatically estimating that calibration. In contrast to established methods, it neither requires a calibration object nor any user interaction. From a theoretical point of view, this book also presents and solves the novel graph theoretical problem of finding shortest triangle paths.

Stereo vision-based road condition monitoring Brunken, Hauke,2021-05-12 When planning road construction measures, it is essential to have up-to-date information on road conditions. If this information is not to be obtained manually, it is currently obtained using laser scanners mounted on mobile mapping vehicles, which can measure the 3D road profile. However, a large number of mobile mapping vehicles would be necessary to record an entire road network on a regular basis. Since 2D road damages can be found automatically on monocular camera images, the idea was born to use a stereo camera system to capture the 3D profile of roads. With stereo camera systems, it would be possible to equip a large number of vehicles and regularly collect data from large road networks. In this thesis, the potential applications of a stereo camera system for measuring road profiles, which is mounted behind the windshield of a vehicle, are investigated. Since this requires a calibration of the stereo camera system, but the effort for the user should be kept low, the camera self-calibration for this application is also examined. 3D reconstruction from stereoscopic images is a well-studied topic, but its application on road surfaces with little and repetitive textures requires special algorithms. For this reason, a new stereo method was developed. It is based on the plane-sweep approach in combination with semi-global matching. It was tested with different measures for pixel comparison. Furthermore, the plane-sweep approach was implemented in a neural network that solves the stereo correspondence problem in a single step. It uses the stereoscopic images as input and provides an elevation image as output. A completely new approach was developed for the self-calibration of mono cameras and stereo camera systems. Previous methods search for feature points in several images of the same scene. The points are matched between the images and used for the calibration. In contrast to these methods, the proposed method uses feature maps instead of feature points to compare multiple views of one and the same plane. To estimate the unknown parameters, the backpropagation algorithm is used together with the gradient descent method. The measurements obtained by stereoscopic image processing were compared with those obtained by industrial laser scanners. They show that both measurements are very close to each other and that a stereoscopic camera system is in principle suitable for capturing the surface profile of a road. Experiments show that the proposed self-calibration method is capable of estimating all parameters of a complex camera model, including lens distortion, with high precision. Bei der Planung von Straßenbaumaßnahmen ist es unabdingbar, über aktuelle Informationen über den Straßenzustand zu verfügen. Sollen diese Informationen nicht manuell gewonnen werden, werden derzeit Messfahrzeug mit Laserscannern verwendet, welche das 3D-Straßenprofil vermessen können. Für die regelmäßige Erfassung eines gesamten Straßennetzes wäre jedoch eine große Anzahl von Messfahrzeugen erforderlich. Da 2D-Straßenschäden automatisch auf monokularen Kamerabildern gefunden werden können, entstand die Idee, ein Stereokamerasystem zur Erfassung des 3D-Profils zu verwenden. Eine große Anzahl von Fahrzeugen könnte damit ausgerüstet werden und es könnten regelmäßig Daten von großen Straßennetzen erfasst werden. In dieser Arbeit werden die Einsatzmöglichkeiten eines Stereokamerasystems zur Messung von Straßenprofilen untersucht, dass sich hinter der Windschutzscheibe eines Fahrzeugs befindet. Da hierzu das Stereokamerasystems kalibriert sein muss, der Aufwand für den Anwender aber geringgehalten werden soll, wird außerdem die Selbstkalibrierung für diesen Einsatzzweck untersucht. Die 3D-Rekonstruktion aus stereoskopischen Bildern ist ein viel untersuchtes Thema, aber ihre Anwendung auf Straßenoberflächen mit wenig und sich wiederholenden Texturen erfordert spezielle Algorithmen. Aus diesem Grund wurde ein neues Stereoverfahren entwickelt. Es basiert auf dem Plane-sweep-Ansatz in Kombination mit Semi-global Matching. Es wurde mit verschiedene Maßen für den Vergleich von Pixeln getestet. Darüber hinaus wurde der Plane-sweep-Ansatz in einem neuronalen Netzwerk implementiert, das das Stereo-Korrespondenzproblem in einem einzigen Schritt löst. Es verwendet die stereoskopischen Bilder als Eingabe und liefert als Ausgabe ein Höhenbild. Für die Selbstkalibrierung von Monokameras und Stereokamerasystemen wurde ein völlig neuer Ansatz entwickelt. Bisherige Methoden suchen nach Merkmalspunkten in mehreren Bildern der gleichen Szene. Die Punkte werden zwischen den Bildern zugeordnet und für die Kalibrierung verwendet. Die vorgeschlagene Methode verwendet anstelle von Merkmalspunkten Feature-Maps um mehrere Ansichten derselben Ebene zu vergleichen. Zur Schätzung der unbekannten Parameter wird der Backpropagation-Algorithmus zusammen mit dem Gradientenabstiegsverfahren verwendet. Die durch stereoskopische Bildverarbeitung erhaltenen Messungen wurden mit Messungen von industriellen Laserscannern verglichen. Sie zeigen, dass beide sehr nahe beieinander liegen und dass ein Stereokamerasystem für die Erfassung des Oberflächenprofils einer Straße grundsätzlich geeignet ist. Experimente zeigen, dass die neue Selbstkalibrierungsmethode in der Lage ist, alle Parameter eines komplexen Kameramodells, einschließlich der Linsenverzerrung, mit hoher Präzision

abzuschätzen.

Remote Sensed Data and Processing Methodologies for 3D Virtual Reconstruction and Visualization of Complex Architectures Diego Gonzalez-Aguilera,Fabio Remondino,Pablo Rodríguez-Gonzálvez,Erica Nocerino,2018-09-28 This book is a printed edition of the Special Issue Remote Sensed Data and Processing Methodologies for 3D Virtual Reconstruction and Visualization of Complex Architectures that was published in Remote Sensing

Advances in Cooperative Robotics Mohammad O Tokhi,Gurvinder S Virk,2016-08-04 This book provides state-of-the-art scientific and engineering research findings and developments in the area of mobile robotics and associated support technologies around the theme of cooperative robotics. The book contains peer reviewed articles presented at the CLAWAR 2016 conference. The book contains a strong stream of papers on multi-legged locomotion and cooperative robotics. There is also a strong collection of papers on human assistive devices, notably wearable exoskeletal and prosthetic devices, and personal care robots and mobility assistance devices designed to meet the growing challenges due to the global ageing society. Robot designs based on biological inspirations and ethical concerns and issues related to the design, development and deployment of robots are also strongly featured.

Popular Photography ,1993-03

Maximum PC ,2007-06 Maximum PC is the magazine that every computer fanatic, PC gamer or content creator must read. Each and every issue is packed with punishing product reviews, insightful and innovative how-to stories and the illuminating technical articles that enthusiasts crave.

Camera-Aided Robot Calibration Hangi Zhuang,Zvi S. Roth,2018-04-24 Robot calibration is the process of enhancing the accuracy of a robot by modifying its control software. This book provides a comprehensive treatment of the theory and implementation of robot calibration using computer vision technology. It is the only book to cover the entire process of vision-based robot calibration, including kinematic modeling, camera calibration, pose measurement, error parameter identification, and compensation. The book starts with an overview of available techniques for robot calibration, with an emphasis on vision-based techniques. It then describes various robot-camera systems. Since cameras are used as major measuring devices, camera calibration techniques are reviewed. Camera-Aided Robot Calibration studies the properties of kinematic modeling techniques that are suitable for robot calibration. It summarizes the well-known Denavit-Hartenberg (D-H) modeling convention and indicates the drawbacks of the D-H model for robot calibration. The book develops the Complete and Parametrically Continuous (CPC) model and the modified CPC model, that overcome the D-H model singularities. The error models based on these robot kinematic modeling conventions are presented. No other book available addresses the important, practical issue of hand/eye calibration. This book summarizes current research developments and demonstrates the pros and cons of various approaches in this area. The book discusses in detail the final stage of robot calibration - accuracy compensation - using the identified kinematic error parameters. It offers accuracy compensation algorithms, including the intuitive task-point redefinition and inverse-Jacobian algorithms and more advanced algorithms based on optimal control theory, which are particularly attractive for highly redundant manipulators. Camera-Aided Robot Calibration defines performance indices that are designed for off-line, optimal selection of measurement configurations. It then describes three approaches: closed-form, gradient-based, and statistical optimization. The included case study presents experimental results that were obtained by calibrating common industrial robots. Different stages of operation are detailed, illustrating the applicability of the suggested techniques for robot calibration. Appendices provide readers with preliminary materials for easier comprehension of the subject matter. Camera-Aided Robot Calibration is a must-have reference for researchers and practicing engineers-the only one with all the information!

Computer Vision – ECCV 2020 Andrea Vedaldi,Horst Bischof,Thomas Brox,Jan-Michael Frahm,2020-10-09 The 30-volume set, comprising the LNCS books 12346 until 12375, constitutes the refereed proceedings of the 16th European Conference on Computer Vision, ECCV 2020, which was planned to be held in Glasgow, UK, during August 23-28, 2020. The conference was held virtually due to the COVID-19 pandemic. The 1360 revised papers presented in these proceedings were carefully reviewed and selected from a total of 5025 submissions. The papers deal with topics such as computer vision; machine learning; deep neural networks; reinforcement learning; object recognition; image classification; image processing; object detection; semantic segmentation; human pose estimation; 3d reconstruction; stereo vision; computational photography; neural networks; image coding; image reconstruction; object recognition; motion estimation.

Flight Formation Control Josep Guerrero,Rogelio Lozano,2012-12-17 In the last decade the development and control of UnmannedAerial Vehicles (UAVs) has attracted a lot of interest. Bothresearchers and companies have a growing interest in improving thistype of vehicle given their many civilian and militaryapplications. This book presents the state of the art in the area of UAV FlightFormation. The coordination and robust consensus approaches arepresented in detail as well as formation flight control strategieswhich are validated in experimental platforms. It aims at helpingstudents and academics alike to better understand what coordinationand flight formation control can make possible. Several novel methods are presented: - controllability and observability of multi-agent systems; - robust consensus; - flight formation control; - stability of formations over noisy networks; which generate solutions of guaranteed performance for UAV FlightFormation. Contents 1. Introduction, J.A. Guerrero. 2. Theoretical Preliminaries, J.A. Guerrero. 3. Multiagent Coordination Strategies, J.A. Guerrero, R. Lozano,M.W. Spong, N. Chopra. 4. Robust Control Design for Multiagent Systems with ParametricUncertainty, J.A. Guerrero, G. Romero. 5. On Adaptive and Robust Controlled Synchronization of NetworkedRobotic Systems on Strongly Connected Graphs, Y.-C. Liu, N.Chopra. 6. Modeling and Control of Mini UAV, G. Flores Colunga, J.A.Guerrero, J. Escareño, R. Lozano. 7. Flight Formation Control Strategies for Mini UAVs, J.A.Guerrero. 8. Formation Based on Potential Functions, L. García, A.Dzul. 9. Quadrotor Vision-Based Control, J.E. Gomez-Balderas, J.A.Guerrero, S. SALAZAR, R. Lozano, P. Castillo. 10. Toward Vision-Based Coordination of Quadrotor Platoons, L.R.García Carrillo, J.A. Guerrero, R. Lozano. 11. Optimal Guidance for Rotorcraft Platoon Formation Flying inWind Fields, J.A. Guerrero, Y. Bestaoui, R. Lozano. 12. Impact of Wireless Medium Access Protocol on the QuadrotorFormation Control, J.A. Guerrero, Y. Challal, P. Castillo. 13. MAC Protocol for Wireless Communications, A. Mendez, M.Panduro, O. Elizarraras, D. Covarrubias. 14. Optimization of a Scannable Pattern for Bidimensional AntennaArrays to Provide Maximum Performance, A. Reyna, M.A. Panduro, A.Mendez.

Industrial Robotics ,2004

Advances in Smart Grid Technology Ning Zhou,S. Hemamalini,2020-09-18 This book comprises the select proceedings of the International Conference on Power Engineering Computing and Control (PECCON) 2019. This volume covers several important topics such as optimal data selection and error-free data acquiring via artificial intelligence and machine learning techniques, information and communication technologies for monitoring and control of smart grid components, and data security in smart grid network. In addition, it also focuses on economics of renewable electricity generation, policies for distributed generation, smart eco-structures and systems. This book can be useful for beginners, researchers as well as professionals interested in the area of smart grid technology.

Automotive Engineering International ,2003

PC Gamer ,2007

Popular Photography ,1993-03

Popular Photography ,1993-11

PC Mag ,2004-01-20 PCMag.com is a leading authority on technology, delivering Labs-based, independent reviews of the latest products and services. Our expert industry analysis and practical solutions help you make

better buying decisions and get more from technology.

Artificial Intelligence and Robotics Shuo Yang,Huimin Lu,2022-12-13 This two-volume set (CCIS 1700-1701) constitutes the refereed proceedings from the 7th International Symposium on Artificial Intelligence, ISAIR 2022, held in Shanghai, China, in October 2022. The 67 presented papers were thoroughly reviewed and selected from 285 submissions. The volumes present the state-of-the-art contributions on the cognitive intelligence, computer vision, multimedia, Internet of Things, robotics, and related applications.

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Quixote is an indomitable woman on a formidable quest: to become a knight and defeat the evil enchanters of modern America by pursuing ... Don Quixote: WHICH WAS A DREAM by Kathy Acker (Grove Nov 9, 1986 — The final section of "Don Quixote" is a long harangue against the evil empire--a hideous British-American landscape of corruption and decay. Don Quixote, which was a Dream - Kathy Acker Kathy Acker's Don Quixote is an indomitable woman on a formidable quest: to become a knight and defeat the evil enchanters of modern America by pursuing ... Don Quixote, Which Was a Dream - by Kathy Acker Kathy Acker's Don Quixote is an indomitable woman on a formidable quest: to become a knight and defeat the evil enchanters of modern America by pursuing ... 3 - Writing-through: Don Quixote: Which Was a Dream This chapter recognises that such scholarship is valuable to an understanding of Acker's work, yet seeks to move a conception of Acker's writing away from a ... Don Quixote Sep 1, 1989 — Kathy Acker's Don Quixote is an indomitable woman on a formidable quest: to become a knight and defeat the evil enchanters of modern America by ... THE LORD OF LA MANCHA AND HER ABORTION Nov 30, 1986 — The novel begins with Don Quixote, now a 66-year-old contemporary woman, having an abortion, which maddens her: ''She conceived of the most ... by Kathy Acker - Don Quixote, Which Was a Dream Kathy Acker's Don Quixote is an indomitable woman on a formidable quest: to become a knight and defeat the evil enchanters of modern America by pursuing 'the ...

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