



Cameras In Motion

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Beardsley**

Cameras In Motion:

Official Class B Product List and Product Assignment Directory United States. Business and Defense Services Administration,1957 Camera ,1929 Defense Supply Management Handbook United States. Office of the Assistant Secretary of Defense (Supply and Logistics),1953 **Continuous Models for Cameras and Inertial Sensors** Hannes Ovrén,2018-07-25 Using images to reconstruct the world in three dimensions is a classical computer vision task Some examples of applications where this is useful are autonomous mapping and navigation urban planning and special effects in movies One common approach to 3D reconstruction is structure from motion where a scene is imaged multiple times from different positions e g by moving the camera However in a twist of irony many structure from motion methods work best when the camera is stationary while the image is captured This is because the motion of the camera can cause distortions in the image that lead to worse image measurements and thus a worse reconstruction One such distortion common to all cameras is motion blur while another is connected to the use of an electronic rolling shutter Instead of capturing all pixels of the image at once a camera with a rolling shutter captures the image row by row If the camera is moving while the image is captured the rolling shutter causes non rigid distortions in the image that unless handled can severely impact the reconstruction quality This thesis studies methods to robustly perform 3D reconstruction in the case of a moving camera To do so the proposed methods make use of an inertial measurement unit IMU The IMU measures the angular velocities and linear accelerations of the camera and these can be used to estimate the trajectory of the camera over time Knowledge of the camera motion can then be used to correct for the distortions caused by the rolling shutter Another benefit of an IMU is that it can provide measurements also in situations when a camera can not e g because of excessive motion blur or absence of scene structure To use a camera together with an IMU the camera IMU system must be jointly calibrated The relationship between their respective coordinate frames need to be established and their timings need to be synchronized This thesis shows how to automatically perform this calibration and synchronization without requiring e g calibration objects or special motion patterns In standard structure from motion the camera trajectory is modeled as discrete poses with one pose per image Switching instead to a formulation with a continuous time camera trajectory provides a natural way to handle rolling shutter distortions and also to incorporate inertial measurements To model the continuous time trajectory many authors have used splines The ability for a spline based trajectory to model the real motion depends on the density of its spline knots Choosing a too smooth spline results in approximation errors This thesis proposes a method to estimate the spline approximation error and use it to better balance camera and IMU measurements when used in a sensor fusion framework Also proposed is a way to automatically decide how dense the spline needs to be to achieve a good reconstruction Another approach to reconstruct a 3D scene is to use a camera that directly measures depth Some depth cameras like the well known Microsoft Kinect are susceptible to the same rolling shutter effects as normal cameras This thesis quantifies the effect of the

rolling shutter distortion on 3D reconstruction depending on the amount of motion It is also shown that a better 3D model is obtained if the depth images are corrected using inertial measurements Att anv nda bilder f r att terskapa v rlden omkring oss i tre dimensioner r ett klassiskt problem inom datorseende N gra exempel p anv ndningsomr den r inom navigering och kartering f r autonoma system stadsplanering och specialeffekter f r film och spel En vanlig metod f r 3D rekonstruktion r det som kallas struktur fr n r relse Namnet kommer sig av att man avbildar fotograferar en miljö fr n flera olika platser till exempel genom att flytta kameran Det r d rf r n got ironiskt att m nga struktur fr n r relse algoritmer f r problem om kameran inte r stilla n r bilderna tas exempelvis genom att anv nda sig av ett stativ Anledningen r att en kamera i r relse ger upphov till st rningar i bilden vilket ger s mre bildm tningar och d rmed en s mre 3D rekonstruktion Ett v lk nt exempel r r relseosk rpa medan ett annat r kopplat till anv ndandet av en elektronisk rullande slutare I en kamera med rullande slutare avbildas inte alla pixlar i bilden samtidigt utan ist llet rad f r rad Om kameran r r p sig medan bilden tas uppst r d rf r st rningar i bilden som m ste tas om hand om f r att f en bra rekonstruktion Den h r avhandlingen ber r robusta metoder f r 3D rekonstruktion med r rliga kameror En r d tr d inom arbetet r anv ndandet av en tr ghetssensor IMU En IMU m ter vinkelhastigheter och accelerationer och dessa m tningar kan anv ndas f r att best mma hur kameran har r rt sig ver tid Kunskap om kamerans r relse ger m jlighet att korrigera f r st rningar p grund av den rullande slutaren Ytterligare en f rdel med en IMU r att den ger m tningar ven i de fall d en kamera inte kan g ra det Exempel p s dana fall r vid extrem r relseosk rpa starkt motljus eller om det saknas struktur i bilden Om man vill anv nda en kamera tillsammans med en IMU s m ste dessa kalibreras och synkroniseras relationen mellan deras respektive koordinatsystem m ste best mmas och de m ste vara verens om vad klockan r I den h r avhandlingen presenteras en metod f r att automatiskt kalibrera och synkronisera ett kamera IMU system utan krav p exempelvis kalibreringsobjekt eller speciella r relsem nster I klassisk struktur fr n r relse representeras kamerans r relse av att varje bild beskrivs med en kamera pose Om man ist llet representerar kamerar relsen som en tidskontinuerlig trajektoria kan man p ett naturligt s tt hantera problematiken kring rullande slutare Det g r det ocks enkelt att inf ra tr ghetism tningar fr n en IMU En tidskontinuerlig kameratrajektoria kan skapas p flera s tt men en vanlig metod r att anv nda sig av s kallade splines F rm gan hos en spline att representera den faktiska kamerar relsen beror p hur t tt dess knutar placeras Den h r avhandlingen presenterar en metod f r att uppskatta det approximationsfel som uppkommer vid valet av en f r gles spline Det uppskattade approximationsfelet kan sedan anv ndas f r att balansera m tningar fr n kameran och IMU n n r dessa anv nds f r sensorfusion Avhandlingen inneh ller ocks en metod f r att best mma hur t t en spline beh ver vara f r att ge ett gott resultat En annan metod f r 3D rekonstruktion r att anv nda en kamera som ocks m ter djup eller avst nd Vissa djupkameror till exempel Microsoft Kinect har samma problematik med rullande slutare som vanliga kameror I den h r avhandlingen visas hur den rullande slutaren i kombination med olika typer och storlekar av r relser p verkar den terskapade 3D modellen Genom att anv nda tr ghetism tningar fr n en IMU kan djupbilderna korrigeras vilket

visar sig ge en b ttre 3D modell **Amateur Movie Makers** ,1929 **Transactions of the Society of Motion Picture Engineers** Society of Motion Picture and Television Engineers,1919 **Camera** ,1938 **Cyclopedia of Motion-picture Work** David Sherrill Hulfish,1914 **The Technique of the Motion Picture Camera** H. Mario Raimondo Souto,1977

Wide Area Surveillance Vijayan K. Asari,2013-11-19 The book describes a system for visual surveillance using intelligent cameras The camera uses robust techniques for detecting and tracking moving objects The real time capture of the objects is then stored in the database The tracking data stored in the database is analysed to study the camera view detect and track objects and study object behavior These set of models provide a robust framework for coordinating the tracking of objects between overlapping and non overlapping cameras and recording the activity of objects detected by the system *Exhibitors Daily Review* ,1926 *A Condensed Course in Motion Picture Photography* New York Institute of Photography,1920 *Advances in Visual Information Systems* Guoping Qiu,Clement Leung,Xiang-Yang Xue,Robert Laurini,2007-11-18 This book constitutes the thoroughly refereed post proceedings of the 9th International Conference on Visual Information Systems VISUAL 2007 held in Shanghai China in June 2007 The papers are organized in topical section on image and video retrieval visual biometrics intelligent visual information processing visual data mining ubiquitous and mobile visual information systems semantics 2D 3D graphical visual data retrieval and applications of visual information systems

Motion Picture Herald ,1926 *American Photography* ,1928 *Motion Picture Photography for the Amateur* Herbert Couchman McKay,1924 **The Camera and Darkroom** ,1905 **Photo-era Magazine** Juan C. Abel,Thomas Harrison Cummings,Wilfred A. French,A. H. Beardsley,1914 **Incorporation and Bylaws** Society of Motion Picture and Television Engineers,1923 **Exhibitors' Times** ,1913

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