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Dense, metric and real-time 3D reconstruction for autonomous drone navigation

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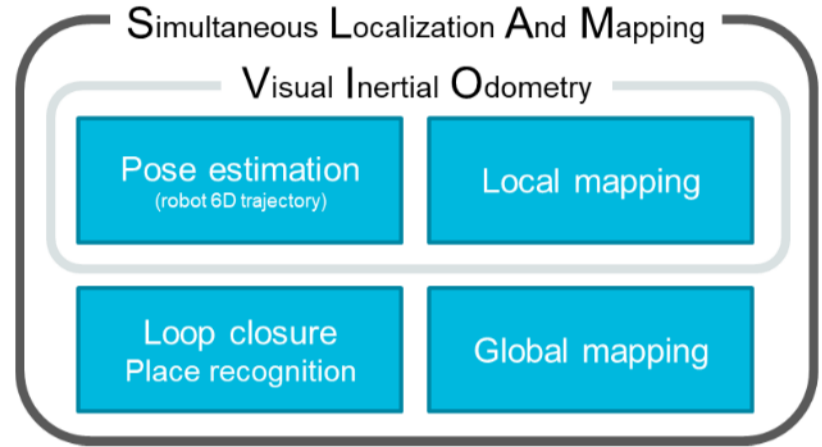
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1. Context:

- ▶ Autonomous navigation
 - **Dense** and **metric** mapping
 - **Real-time** application on aerial robots
- ▶ Constraints and challenges
 - Limited computation resources, low energy consumption
 - Use of passive sensors only
 - Restriction to monocular cameras
 - Fast motions
 - Illumination changes

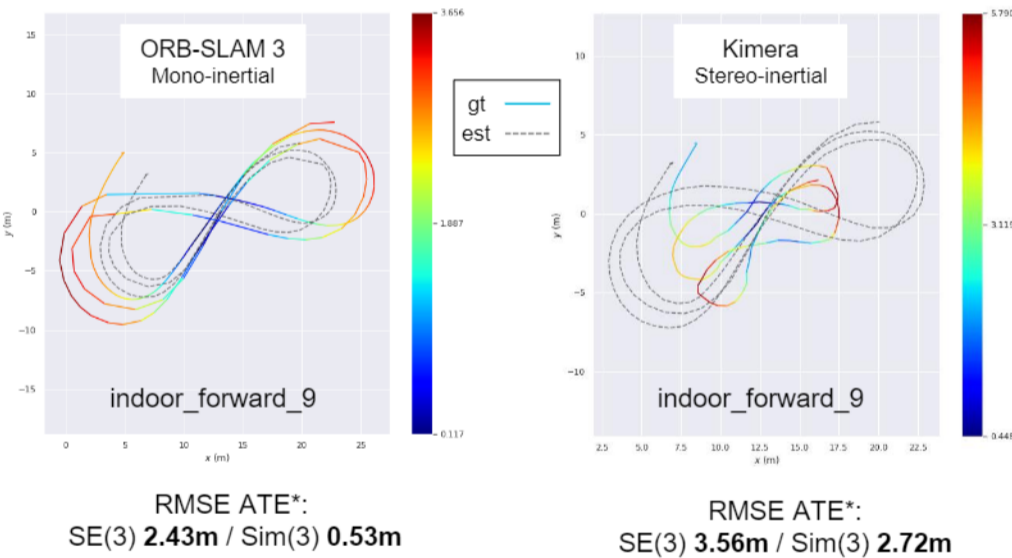
2. Approach:



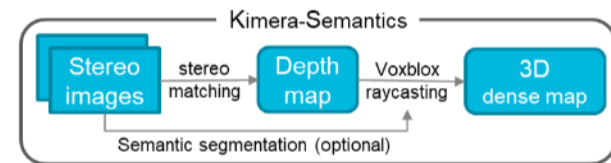
- ▶ State-of-the-art methods:
 - **ORB-SLAM3** [2] (Mono/Stereo inertial, RGB-D)
 - **Kimera** [1] (Stereo inertial)

3. Indicative performance of state-of-the-art

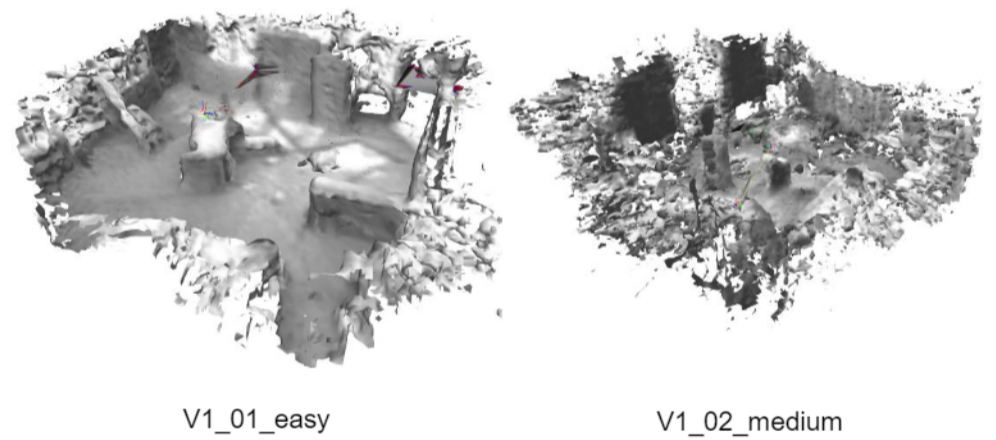
VIO evaluation on UZH FPV Drone Racing dataset [3]



* Root Mean Square Error (RMSE) of the Absolute Trajectory Error (ATE)



Kimera 3D reconstruction on EuRoC [4] dataset



4. Monocular depth estimation

- ▶ As we restrain our study to monocular cameras, stereo-matching is replaced by Deep Learning-based depth estimation.

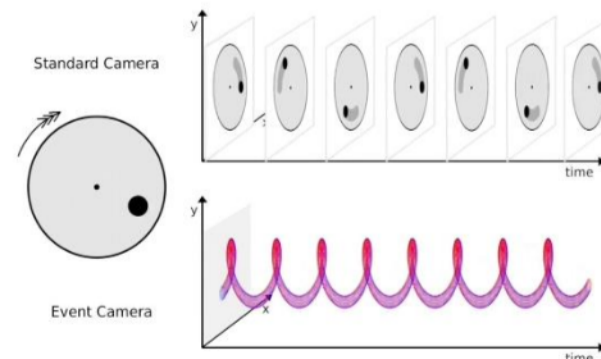


PackNet [5] monocular depth map prediction

Training	Supervised, Unsupervised, Semi-supervised
Architectures	CNN, Auto-encoder, RNN, GAN
Task	Single task: Depth map Multi-tasks: Depth map, visual odometry, optical flow, semantic segmentation

5. Event cameras

- ▶ The characteristics of the sensor are particularly suitable for our context. It is robust to fast motions and high illumination changes.



High Dynamic Range: 120 dB	No direct intensity value
Asynchronous High update rate: 1MHz	No data in static scenes
Low Energy consumption: 20 mW	Few computer vision algorithms

[1] Rosinol, Antoni et al. "Kimera: an Open-Source Library for Real-Time Metric-Semantic Localization and Mapping." 2020 IEEE International Conference on Robotics and Automation (ICRA).

[2] Campos, Carlos et al. "ORB-SLAM3: An Accurate Open-Source Library for Visual, Visual-Inertial, and Multimap SLAM". IEEE Transactions on Robotics. (2021): 1-17.

[3] Delmerico, Jeffrey et al. "Are We Ready for Autonomous Drone Racing? The UZH-FPV Drone Racing Dataset." 2019 International Conference on Robotics and Automation (ICRA).

[4] Burri, Michael et al. "The EuRoC micro aerial vehicle datasets". The International Journal of Robotics Research. (2016).

[5] Guizilini, Vitor et al. "3D Packing for Self-Supervised Monocular Depth Estimation." 2020 IEEE/CVF Conference on Computer Vision and Pattern Recognition (CVPR)