

# CONTENTS

1	INTRODUCTION	1
1.1	List of Contributions	2
1.2	Publications	4
1.3	Outline	6
I	PERCEPTION AND SEGMENTATION	7
2	EFFICIENT PERCEPTION FOR OBJECT MANIPULATION	9
2.1	Introduction	10
2.2	Related Work	12
2.3	Table Top Segmentation with ToF Cameras	15
2.3.1	Pipeline Overview	15
2.3.2	Preprocessing	17
2.3.3	Normal and Curvature Estimation	19
2.3.4	Table Plane Detection	21
2.3.5	Object Detection	22
2.3.6	Object Shape Detection	23
2.3.7	Preliminary Experiments and Results	27
2.4	Fast RGB-D Table Top Segmentation	29
2.4.1	Pipeline Overview	30
2.4.2	Fast Computation of Local Surface Normals	31
2.4.3	Extracting Horizontal Points	33
2.4.4	Fast Plane Segmentation	34
2.4.5	Table Plane and Object Detection	36
2.5	Experiments and Results	38
2.5.1	Accuracy and Runtime for Computing Normals	38
2.5.2	Object Detection Accuracy	39
2.5.3	Runtime Evaluation	41
2.6	Application to Fast Object Perception and Grasping	43
2.6.1	Introduction	43
2.6.2	Perception and Grasping Pipeline	44
2.6.3	Experiments and Results	46
2.7	Application to Mobile Robot Depalletizing	47
2.7.1	Introduction	47
2.7.2	Object Perception Pipeline	47
2.7.3	Experiments and Results	51
2.8	Conclusion	52
3	EFFICIENT SEGMENTATION OF RGB-D IMAGES	55
3.1	Introduction	55
3.2	Related Work	57
3.2.1	Segmentation based on Sample Consensus	57
3.2.2	Hough-based Plane Segmentation and Clustering	58
3.2.3	Scan Line Grouping	59

3.2.4	Segmentation using Region Growing . . . . .	60
3.3	Overview of the Segmentation Pipeline . . . . .	61
3.4	Fast Approximate Surface Reconstruction . . . . .	62
3.4.1	Surface Reconstruction Algorithms . . . . .	63
3.4.2	Exploiting Structure for Approximate Meshing . . . . .	65
3.4.3	Fast Computation of Local Surface Normals . . . . .	67
3.4.4	Multilateral Filtering . . . . .	69
3.5	Region Models and Segmentation . . . . .	70
3.5.1	Region Growing-based Segmentation . . . . .	70
3.5.2	Different Region Models for Segmentation . . . . .	71
3.5.3	Probabilistic Plane Segmentation . . . . .	71
3.5.4	Approximate Plane Segmentation . . . . .	72
3.5.5	Smooth Surfaces and Geometric Primitives . . . . .	72
3.6	Camera Noise Models . . . . .	74
3.7	Experiments and Results . . . . .	76
3.7.1	Runtime Evaluation . . . . .	76
3.7.2	Influence of the Camera Noise Model . . . . .	78
3.7.3	Plane Segmentation . . . . .	80
3.7.4	Cylinder Segmentation . . . . .	85
3.8	Application to Stair Detection . . . . .	87
3.9	Conclusions . . . . .	91
II	REGISTRATION AND MAPPING . . . . .	93
4	REGISTRATION AND MAPPING WITH MAVS . . . . .	95
4.1	Introduction . . . . .	95
4.2	Related Work . . . . .	97
4.2.1	Perception and Mapping with MAVs . . . . .	97
4.2.2	3D Scan Registration . . . . .	99
4.2.3	Multi-View Scan Registration and SLAM . . . . .	100
4.2.4	Landmark-based SLAM . . . . .	101
4.3	Registration of Sparse Laser Scans . . . . .	102
4.3.1	Registration of 3D Point Clouds . . . . .	103
4.3.2	Generalized Iterative Point Cloud Registration . . . . .	104
4.3.3	Approximate Surface Reconstruction . . . . .	104
4.3.4	Approximate Covariance Estimates . . . . .	106
4.3.5	Registration with Approx. Covariance Estimates . . . . .	107
4.4	Mapping with Sparse 3D Laser Scans . . . . .	108
4.4.1	Graph-Based SLAM . . . . .	108
4.4.2	Baseline System — Single Edge Connections . . . . .	109
4.4.3	Proposed Approach — Multi-Edge Connections . . . . .	110
4.5	Experiments and Results . . . . .	112
4.5.1	Experiments on Pairwise Registration . . . . .	113
4.5.2	Experiments on SLAM . . . . .	116
4.5.3	Runtime Evaluation . . . . .	121
4.5.4	Mapping an Indoor Environment . . . . .	121
4.5.5	Complete Outdoor Mapping Missions . . . . .	123
4.6	Conclusions and Future Work . . . . .	124

5	REGISTRATION AND MAPPING FOR RGB-D CAMERAS	129
5.1	Introduction	129
5.2	Related Work	131
5.3	Method	134
5.3.1	Approximate Surface Reconstruction	135
5.3.2	Multilateral Filtering	136
5.3.3	Approximate Normal and Covariance Estimates	136
5.3.4	Surface-to-Surface Alignment	137
5.3.5	Multi-Edge Graph Optimization	138
5.3.6	Local Window Alignment	139
5.3.7	Loop Closure Detection and Global Optimization	140
5.3.8	Keyframe Selection	141
5.3.9	Point Subsampling and Correspondence Filtering	142
5.4	Experiments and Results	142
5.4.1	Accuracy of Local Alignments	144
5.4.2	Trajectory Optimization and Global Alignment	145
5.5	Local Window Alignment for Mapping with MAVs	150
5.6	Conclusions	153
6	DISCUSSION AND CONCLUSION	155
	BIBLIOGRAPHY	163