

IMPROVING THE ACCURACY OF MEASURING SEABED OBJECTS USING VIDEO IMAGES WITH A LASER SCALER

I.M. Anisimov

To study the bottom micro relief, geological features of the soil, as well as the structure of benthic fauna communities, video filming of the bottom surface with the help of towed, autonomous and remotely controlled vehicles is widely used. To determine the quantitative characteristics of the studied sea bottom areas, it is necessary to be able to carry out measurements based on the obtained images. One of the common methods for measuring objects on the bottom surface is to compare the size of the object in the image with a scale bar formed by projections of two or more laser pointers onto the bottom surface. This method shows good results when the bottom area is fairly flat. However, even in this case, the measurement error is affected by two types of image distortions: lens and porthole distortion and perspective distortions associated with the tilt of the image plane relative to the bottom plane. In this paper, the influence of distortions on the results of objects measurements on the bottom surface is studied, and a perspective correction method is proposed that allows one to align the bottom plane relative to the image plane. On the example of video recordings obtained with the towed vehicle "Videomodule", the effectiveness of the proposed method is shown.

Keywords: underwater video systems, sea bottom surveys, perspective correction, measurement error.

References

1. Harris S., Ballard R. ARGO: Capabilities for Deep Ocean Exploration. *OCEANS '86*. 1986. P. 6–8.
2. Jones D., Bett B., Wynn R., Masson D. The use of towed camera platforms in deep-water science. *Underwater Technology*. 2009. Vol. 28, No. 2. P. 41–50.
3. Klette R. *Komp'yuternoye zreniye. Teoriya i algoritmy*. Moscow: DMK Press, 2019. 506 p.
4. Beall C., Lawrence B.J., Ila V., Dellaert F. 3D reconstruction of underwater structures. *2010 IEEE/RSJ International Conference on Intelligent Robots and Systems*. Taipei: IEEE, 2010. P. 4418–4423.
5. Bobkov V.A., Kudryashov A.P. Rekonstruktsiya i vizualizatsiya prostranstvennoy stseny s ispol'zovaniyem global'noy tochechnoy modeli (Reconstruction and visualization of a spatial scene using a global point model // Informatics and control systems.). *Informatika i sistemy upravleniya*. 2017. No. 2 (52). P. 3–11.
6. Dunlop K.M., Kuhn L.A., Ruhl H.A., Huffard C.L., Caress D.W. An evaluation of deep-sea benthic megafauna length measurements obtained with laser and stereo camera methods. *Deep-Sea Research Part I: Oceanographic Research Papers*. 2015. Vol. 96. P. 38–48.
7. Bobkov V.A., Kudryashov A.P., Inzartsev A.V. Algoritmov identifikatsii podvodnogo ob'ekta po stereozobrazheniyam (Algorithm for Identification of an Underwater Object Based on Stereo Images). *Tekhnicheskiye problemy osvoyeniya Mirovogo okeana*. 2019. No. 8.
8. Purser A., Marcon Y., Dreutter S., Hoge U., Sablotny B., Hehemann L., Lemburg J., Dorschel B., Biebow H., Boetius A. Ocean floor observation and bathymetry system (OFOBS): A new towed camera/sonar system for deep-sea habitat surveys. *IEEE Journal of Oceanic Engineering*. 2019. Vol. 44, No. 1. P. 87–99.
9. Agisoft Metashape [Electronic resource]. URL: <https://www.agisoft.com/> (accessed: 18.01.2021).
10. Pilgrim D.A., Parry D.M., Jones M.B., Kendall M.A. ROV Image Scaling with Laser Spot Patterns. *Underwater Technology*. 2000. Vol. 24, No. 3. P. 93–103.
11. Rizzo A.A., Welsh S.A., Thompson P.A. A Paired-Laser Photogrammetric Method for In Situ Length Measurement of Benthic Fishes. *North American Journal of Fisheries Management*. 2017. Vol. 37, No. 1. P. 16–22.
12. Zalota A.K., Zimina O.L., Spiridonov V.A. Combining data from different sampling methods to study the development of an alien crab *Chionoecetes opilio* invasion in the remote and pristine Arctic Kara Sea. *PeerJ*. 2019. Vol. 7. P. e7952.
13. Baranov B., Galkin S., Vedenin A., Dozorova K., Gebruk A., Flint M. Methane seeps on the outer shelf of the Laptev Sea: characteristic features, structural control, and benthic fauna. *Geo-Marine Letters*. 2020. Vol. 40, No. 4. P. 541–557.
14. Harvey E., Shortis M., Stadler M., Cappo M. A Comparison of the Accuracy and Precision of Measurements from Single and Stereo-Video Systems. *Marine Technology Society Journal*. 2002. Vol. 36, No. 2. P. 38–49.
15. Wakefield W.W., Genin A. The use of a Canadian (perspective) grid in deep-sea photography. *Deep Sea Research Part A. Oceanographic Research Papers*. 1987. Vol. 34, No. 3. P. 469–478.
16. Zhang D. et al. Robust inverse perspective mapping based on vanishing point. *Proceedings 2014 IEEE International Conference on Security, Pattern Analysis, and Cybernetics, SPAC 2014*. 2014. P. 458–463.
17. Mallot H., Bülthoff H., Little J., Bohrer S. Inverse Perspective Mapping Simplifies Optical Flow Computation and Obstacle Detection. *Biological cybernetics*. 1991. Vol. 64. P. 177–185.
18. Tan S., Dale J., Anderson A., Johnston A. Inverse perspective mapping and optic flow: A calibration method and a quantitative analysis. *Image Vision Computing*. 2006. Vol. 24, No. 2. P. 153–165.
19. Konov S.G., Markov B.N. Algoritmov korrektsii pogreshnosti ot perspektivnykh iskazheniy izobrazheniy izmeritel'nykh metok (Algorithm for Correcting the Error from Perspective Distortions in Images of Measuring Marks). *Metrologiya*. 2011. No. 3. P. 8–15.

20. Istenič K., Gracias N., Arnaubec A., Escartín J., García R. Automatic scale estimation of structure from motion based 3D models using laser scalers in underwater scenarios. *ISPRS Journal of Photogrammetry and Remote Sensing*. 2020. Vol. 159. P. 13–25.
21. Tsai R., Huang T., Zhu W.-L. Estimating three-dimensional motion parameters of a rigid planar patch, II: Singular value decomposition. *IEEE Transactions on Acoustics, Speech, and Signal Processing*. 1982. Vol. 30, No. 4. P. 525–534.
22. Bertozzi M., Broggi A., Fascioli A. Stereo inverse perspective mapping: theory and applications. *Image and Vision Computing*. 1998. Vol. 16, No. 8. P. 585–590.
23. Szeliski R. *Computer Vision: Algorithms and Applications*. Springer Science & Business Media, 2010.
24. Menna F., Nocerino E., Fassi F., Remondino F. Geometric and Optic Characterization of a Hemispherical Dome Port for Underwater Photogrammetry. *Sensors*. 2016. Vol. 16. P. 48.
25. Zhang Z. A flexible new technique for camera calibration. *IEEE Transactions on Pattern Analysis and Machine Intelligence*. 2000. Vol. 22, No. 11. P. 1330–1334.
26. Anisimov I.M., Zalota A.K., Lesin A.V., Murav'ya V.O. Osobennosti issledovaniya biologicheskikh i tekhnogennykh ob'yektov s ispol'zovaniyem glubokovodnykh buksiruyemykh apparatov (Aspects of towed underwater vehicle "Videomodule" utilization for surveying underwater objects and benthic fauna). *Okeanologiya*. 2023. Vol. 63. No. 5. P. 840–852.
27. Galkin S.V., Zalota A.K., Udalov A.A., Pronin A.A. Otsenka plotnosti populatsiy kraba-vselentsa Shionoecetes opilio v Karskom more s ispol'zovaniyem BNPA "Videomodul'" (Estimation of the density of populations of the invasive crab Chionoecetes opilio in the Kara Sea using the BNPA "Videomodul'"). 2021. P. 207–210.
28. Anisimov I.M., Tronza S.N. Programmnaya kompleksirovaniye dannykh sinkhronnoy videoz'yemki i gidrolokatsionnogo obzora poverkhnosti dna (Software integration of data from synchronous video recording and sonar survey of the bottom surface). *Okeanologiya*. 2021. Vol. 61, No. 3. P. 479–490.
29. Negahdaripour S., Horn B.K.P. A Direct Method for Locating the Focus of Expansion. *Computer Vision, Graphics, and Image Processing*. 1987. Vol. 46, No. 3. P. 303–326.
30. Rublee E., Rabaud V., Konolige K., Bradski G. ORB: An efficient alternative to SIFT or SURF. *2011 International Conference on Computer Vision*. 2011. P. 2564–2571.
31. Fischler M.A., Bolles R.C. Random sample consensus: a paradigm for model fitting with applications to image analysis and automated cartography. *Communications of the ACM*. ACM New York, NY, USA, 1981. Vol. 24, No. 6. P. 381–395.
32. Hartley R., Zisserman A. *Multiple View Geometry in Computer Vision*. Cambridge University Press, 2003. 676 p.

About the author

ANISIMOV Ivan, Junior researcher

Shirshov Institute of Oceanology, Russian Academy of Science

Address: 115093, Moscow, Stremskiy per., 33, apt. 33

Scientific interests: Underwater towed vehicles, underwater vision systems, computer vision

Phone: +7 905 543 64 57

E-mail: anisimov.im@ocean.ru

ORCID: 0000-0002-1780-9004

Recommended citation:

Anisimov I. M. IMPROVING THE ACCURACY OF MEASURING SEABED OBJECTS USING VIDEO IMAGES WITH A LASER SCALER. *Underwater investigations and robotics*. 2023. No. 4 (46). P. 16–28. DOI: 10.37102/1992-4429_2023_46_04_02. EDN: KIQQPF.

