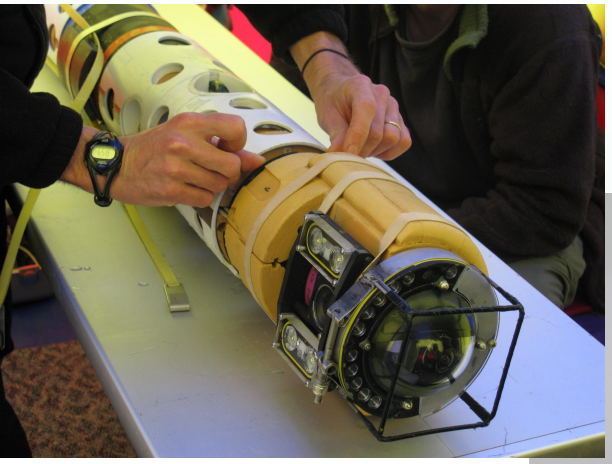
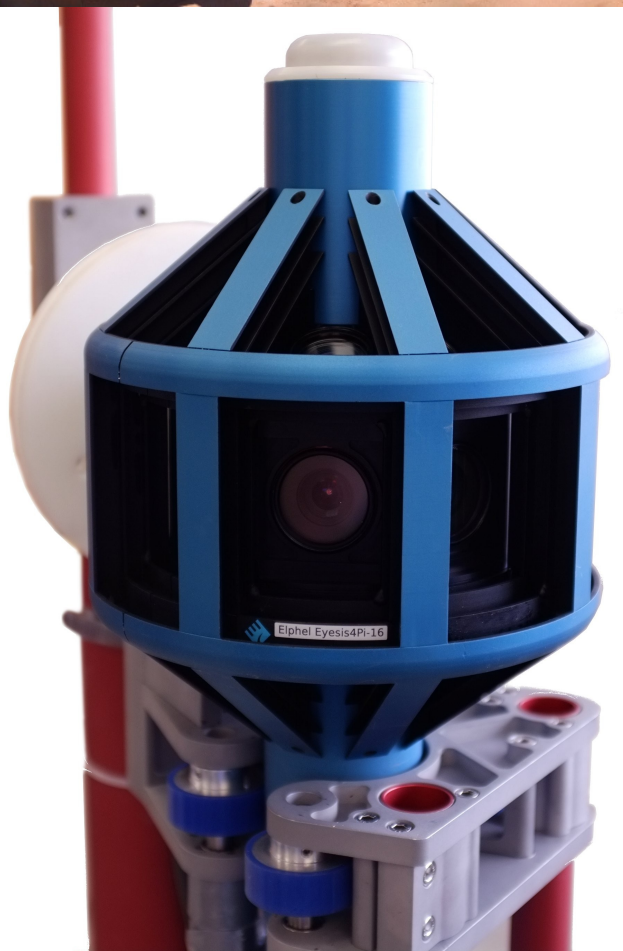
Open Hardware Cameras





Olga Filippova
Elphel, Inc. 1405 W. 2200 S. #205
West Valley City, UT 84119

Hardware: NC353L

Tech specs:

5 Megapixel CMOS Sensor

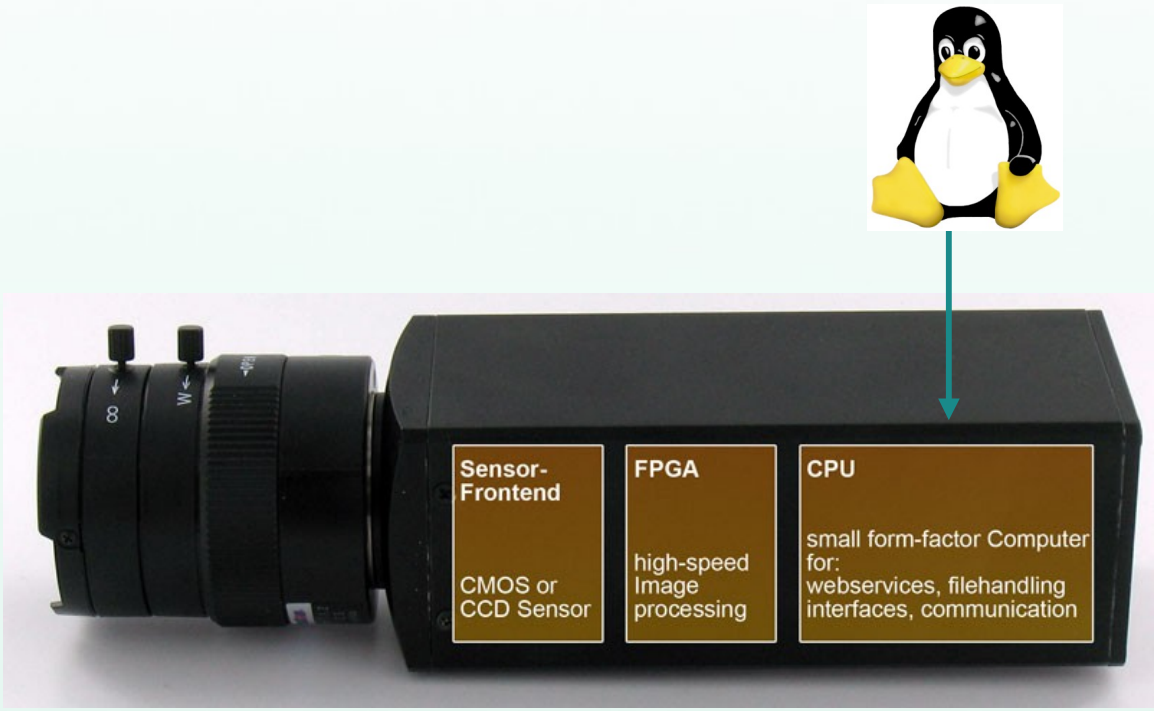
Exchangeable Lens (c-mount)

75 Megapixels/second Throughput

FPGA with Image pipeline

Embedded Linux computer

(webserver, Ethernet, USB, SATA connections)



Applications: Document Scanning

Elphel Model 323

35-mm format Kodak CCD image sensor

11 megapixels resoluion (4008 x 2672)

2 fps framerate

Nikon F-mount

Applications: Panoramic Imaging

WIKIPEDIA
The Free Encyclopedia

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Article | Discussion

Google Street View

From Wikipedia, the free encyclopedia
(Redirected from Streetview)

This article **may need to be updated**. Please update this article to reflec
the talk page for more information.

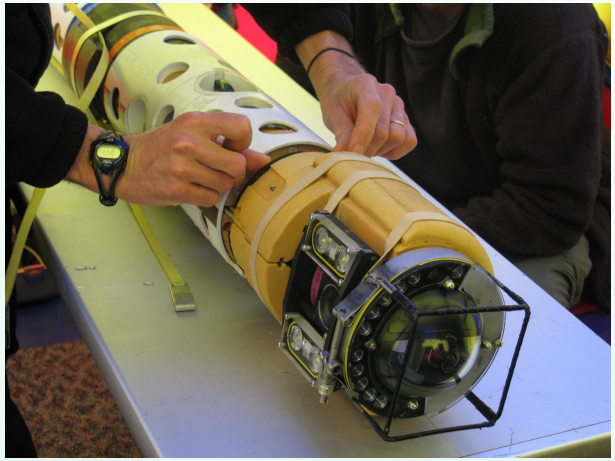
Google Street View is a technology featured in Google Maps and Google Earth that provides panoramic views
on May 25, 2007, originally only in several cities in the United States, and has since gradually expanded to includ

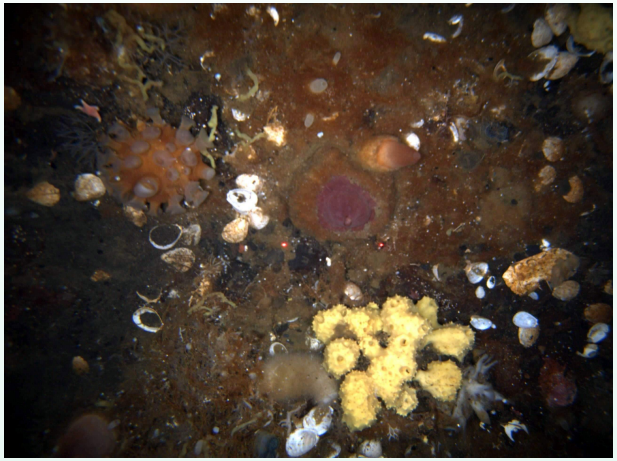
Google Street View displays images taken from a fleet of specially adapted cars. Areas not accessible by car, lik
sometimes covered by *Google Trikes* (tricycles) or a snowmobile.[2] On each of these vehicles there are nine dir
units for positioning and three laser range scanners for the measuring of up to 50 meters 180° in the front of th
and Wi-Fi hotspots.[3] Recently, 'high quality' images are based on open source hardware cameras from Elphel.

Variety of Applications:

SCINI - Antarctic Underwater Exploration Robot

Submersible Capable of under-Ice Navigation and Imaging

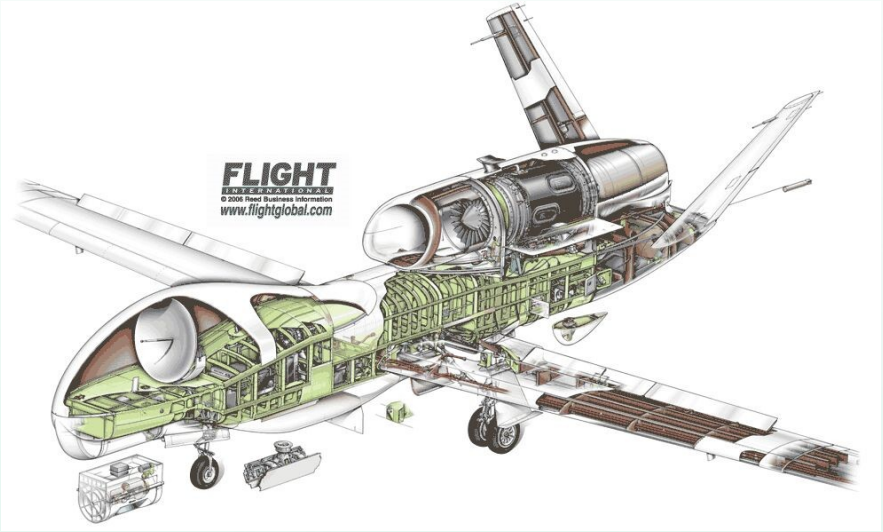




Moss Landing Marine Lab

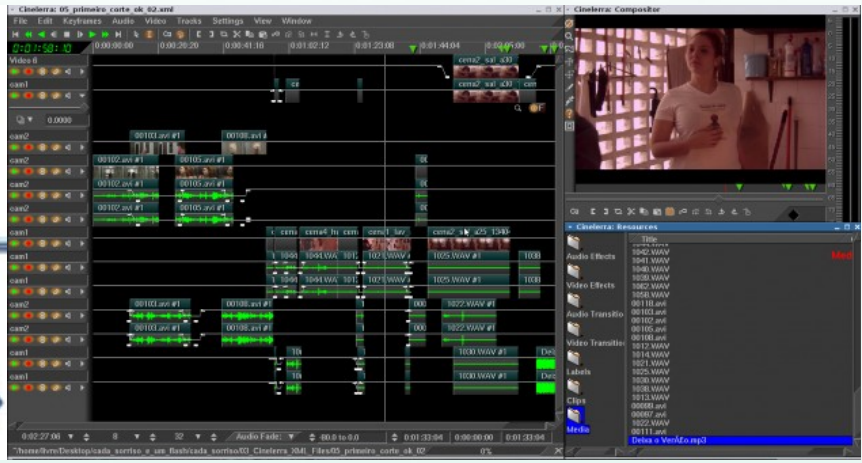
Applications: NASA Global Hawk UAV

Aerial Near Space Exploration



Applications: Cinematography

Apertus, Floresta Vermelha Project



Triclop Camera

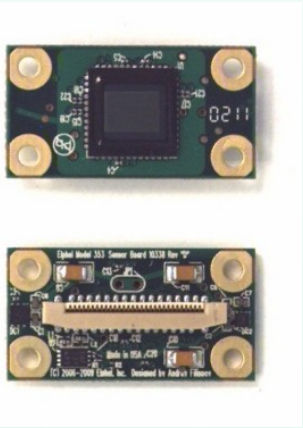
Depth of Field from 3D information

Sintel – Open Moview by Blender Foundation

Boards Overview

10353 System Board

10369 IO Board



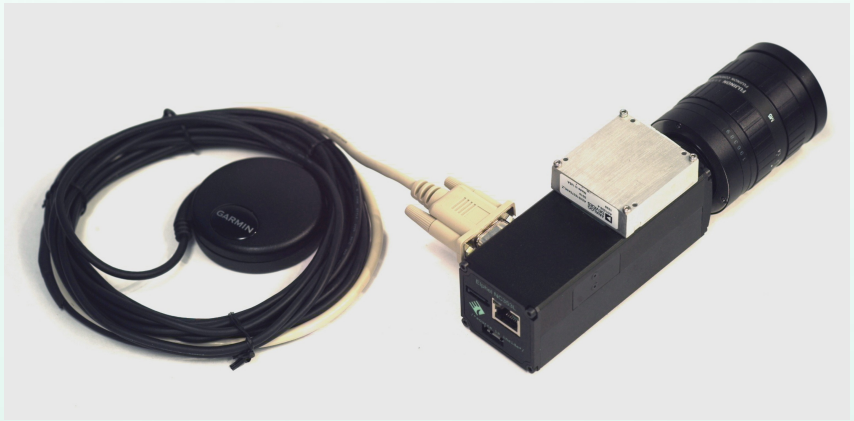
- ✔ *10338 Sensor Board*

- ✔ *10359 Multi Sensor Board*

Camera Configurations

Basic camera NC353

Stereo



IMU & GPS

HDD

/* source is inside */

Camera is regonfigurable and user/developer friendly.

Controlled through a web-based user interface.

- HTML, JavaScript, PHP
- C, C++
- Verilog HDL

elphel open hardware imaging

sourceforge FIND AND DEVELOP OPEN SOURCE SOFTWARE

Find Software | Develop | Create Project | Blog | Site Support | About

SourceForge.net > Find Software > Elphel reconfigurable cameras

Elphel reconfigurable cameras

by apolto, elphel, geekjim, khlut, oneartplease, …

Summary | Files | Support | Develop | Hosted Apps | Tracker | Mailing Lists

Software and HDL code for Elphel reconfigurable network cameras

Download Now! elphel353-8.0.8.48.tar.gz (4.5 MB) OR View all files

/www3.elphel.com

Create an account or log in

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10353

10353 processor board is the computer part of the Elphel 353/363 series cameras.

- It uses ETRAX FS processor running GNU/Linux (currently kernel 2.6.19) that has support for multiple hardware interfaces with the following of them used/connected in the Model 353:
  - 10/100 Ethernet
  - USB 1.1 (host)
  - IDE (ATA-6)
  - RS-232
- Teridian 78Q2123 is used as Ethernet PHY in the camera - it has Auto-MDI/X, so no more crossover cables are needed when connecting camera directly to a PC.
- 64MB of 32-bit white system SDRAM provide memory to run multiple applications in the camera. It is also used as a buffer for video/images and as a RAM-disk.
- 128MB of system flash memory work as a

10353 board, top view

10353 board, bottom view

navigation
- Main Page
- Current events
- Recent changes
- Random page
- Community portal
- Help
- Elphel, Inc

search
Go Search

toolbox
- What links here
- Related changes
- Upload file
- Special pages
- Printable version

Code is available on

SourceForge.net

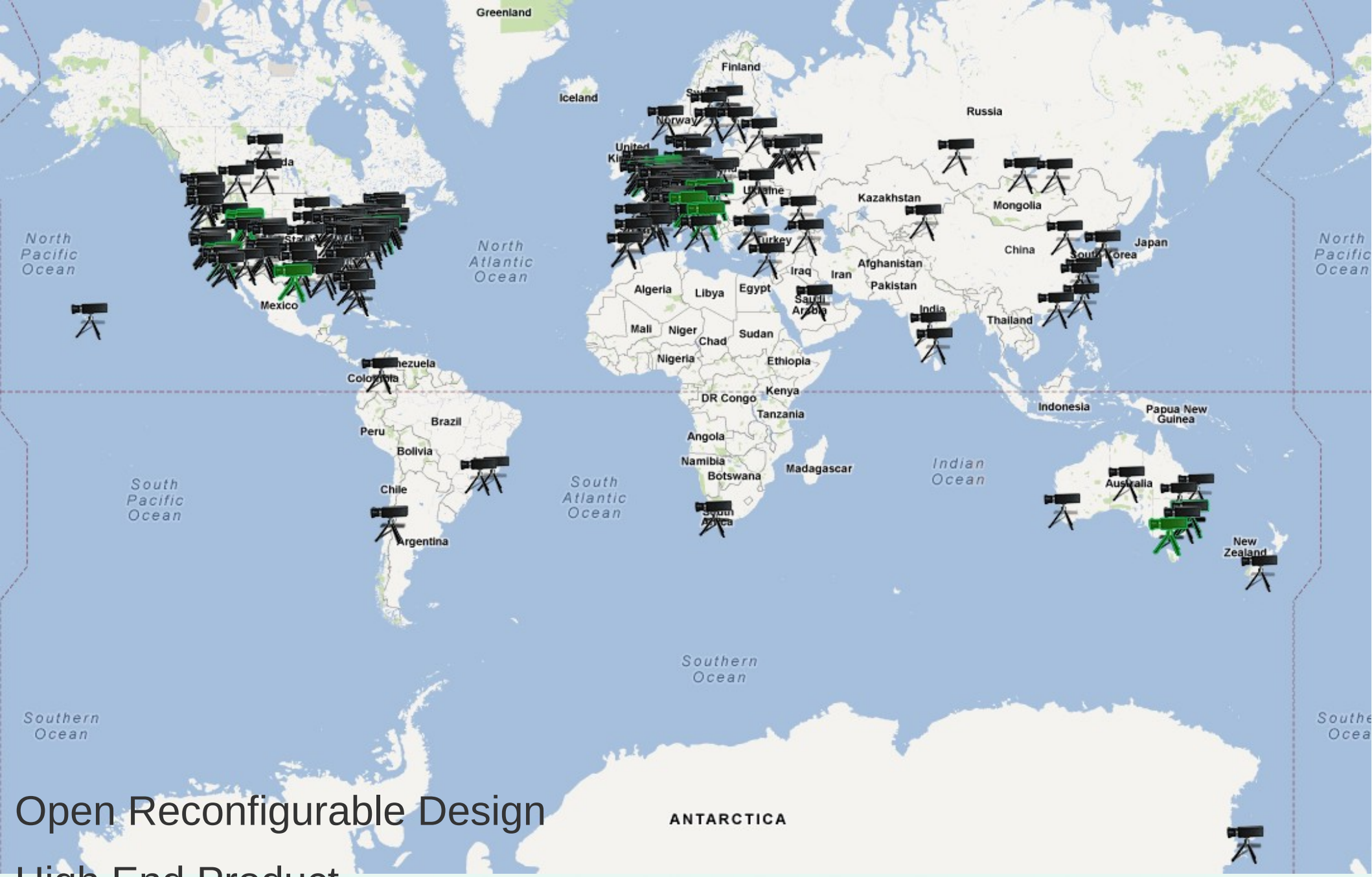
Schematics,

PCB layout & Documentation

wiki.elphel.com

Licenses:

- *GNU GPL V3*
- *GNU Free Documentation License V1.3*
- *CERN Open Hardware License V1.1*

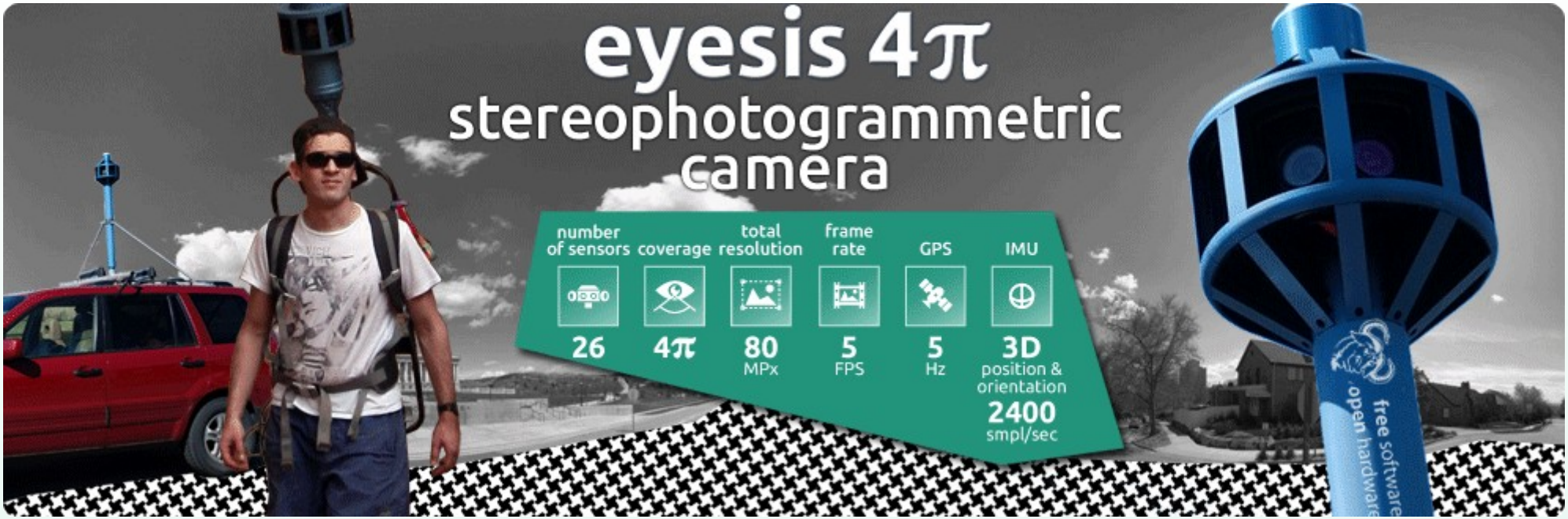


Open Reconfigurable Design

High End Product

Camera users around the world

Eyesis 4π – Stereophotogrammetric Camera

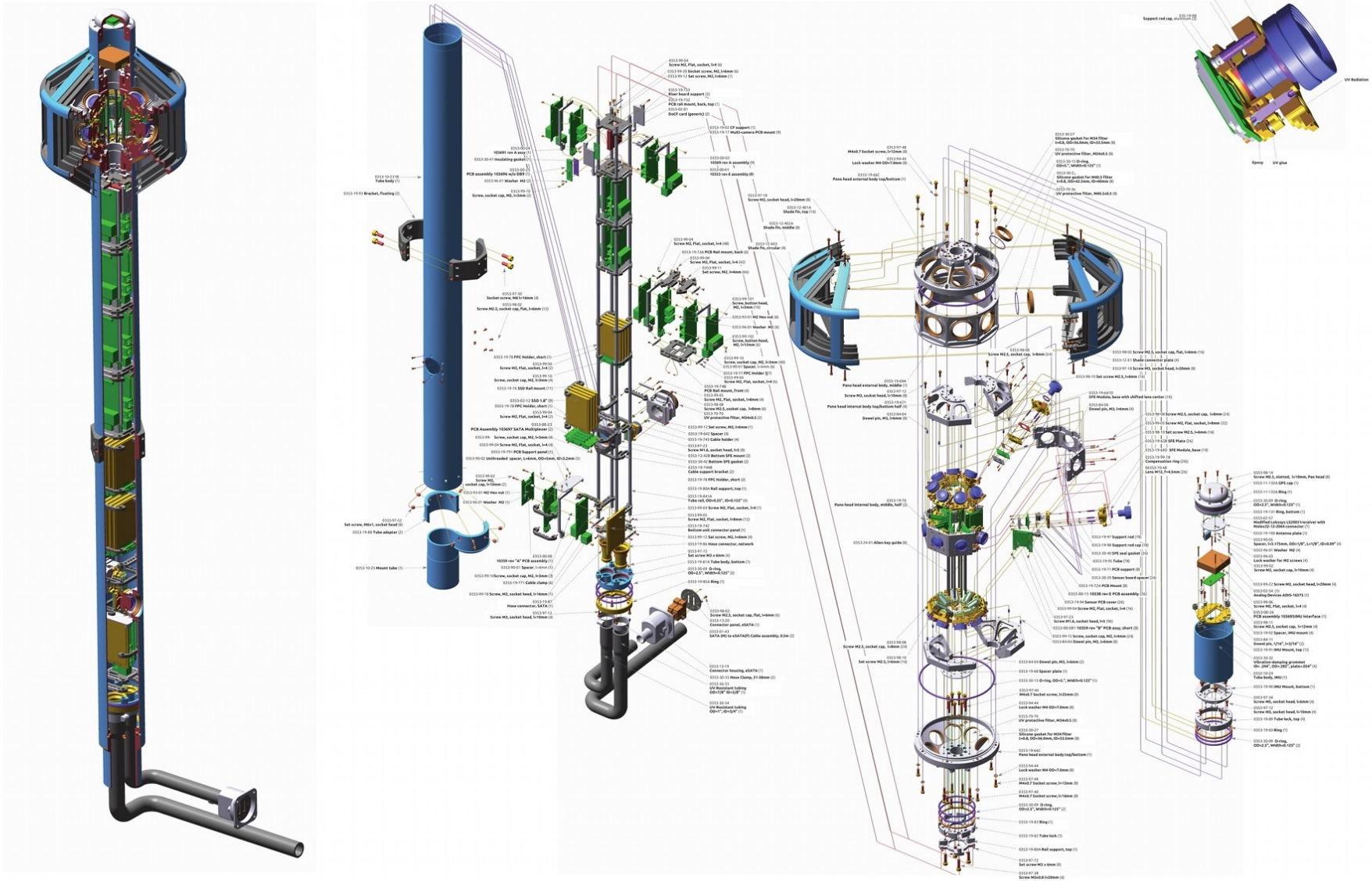


- Full Sphere Panoramic Camera
- High Resolution: 120 Mpix, total (64 Mpix - panorama)
- Images are synchronized with GPS and IMU
- Photogrammetry ready

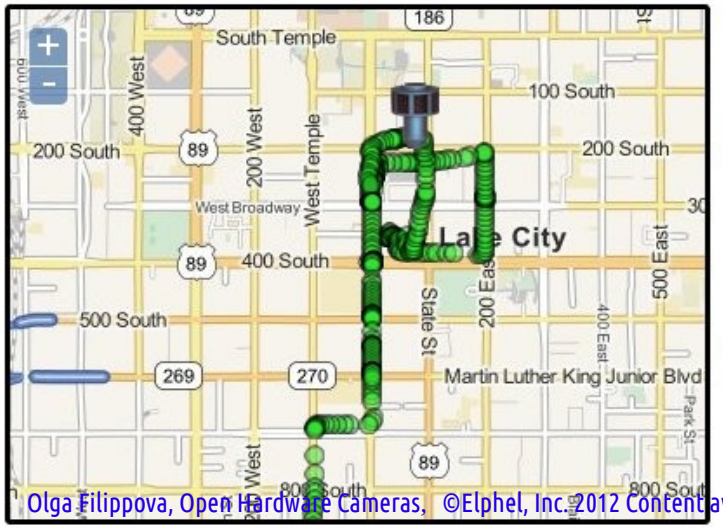
Elphel at SIGGRAPH 2012

Calibrated camera for 3D reconstruction

eyesis 4π ASSEMBLY DRAWING



Eyesis 4π – Footage Preview



Full size preview

Process files as JPEGs:

20120721a

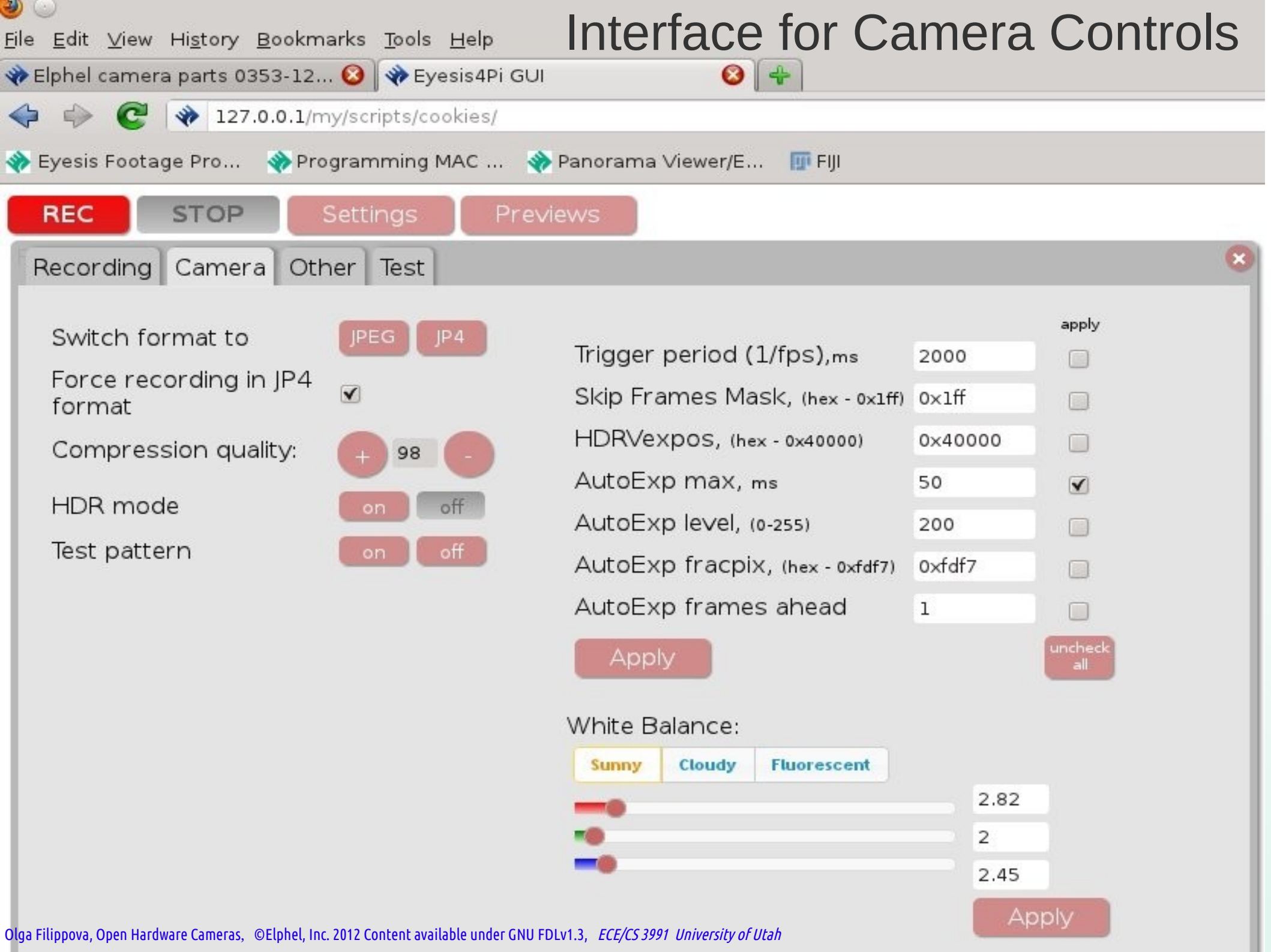
Image number - 295 +

Image name: 1/1342928263_838636_1.jp4

Copy All OR 1 image set(s) Copy to /data/post-processing/src/

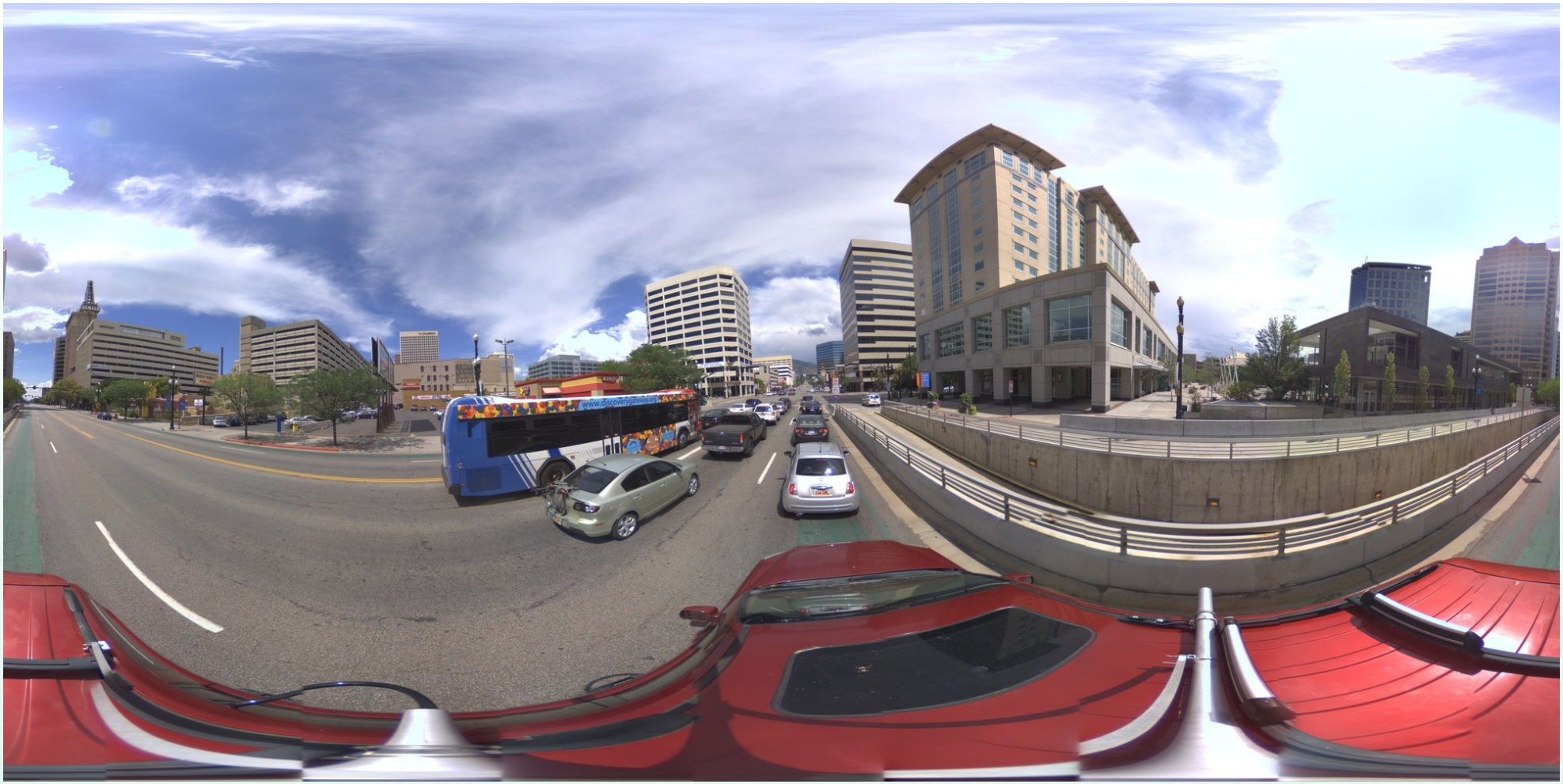
Status: *Working.*

Interface for Camera Controls

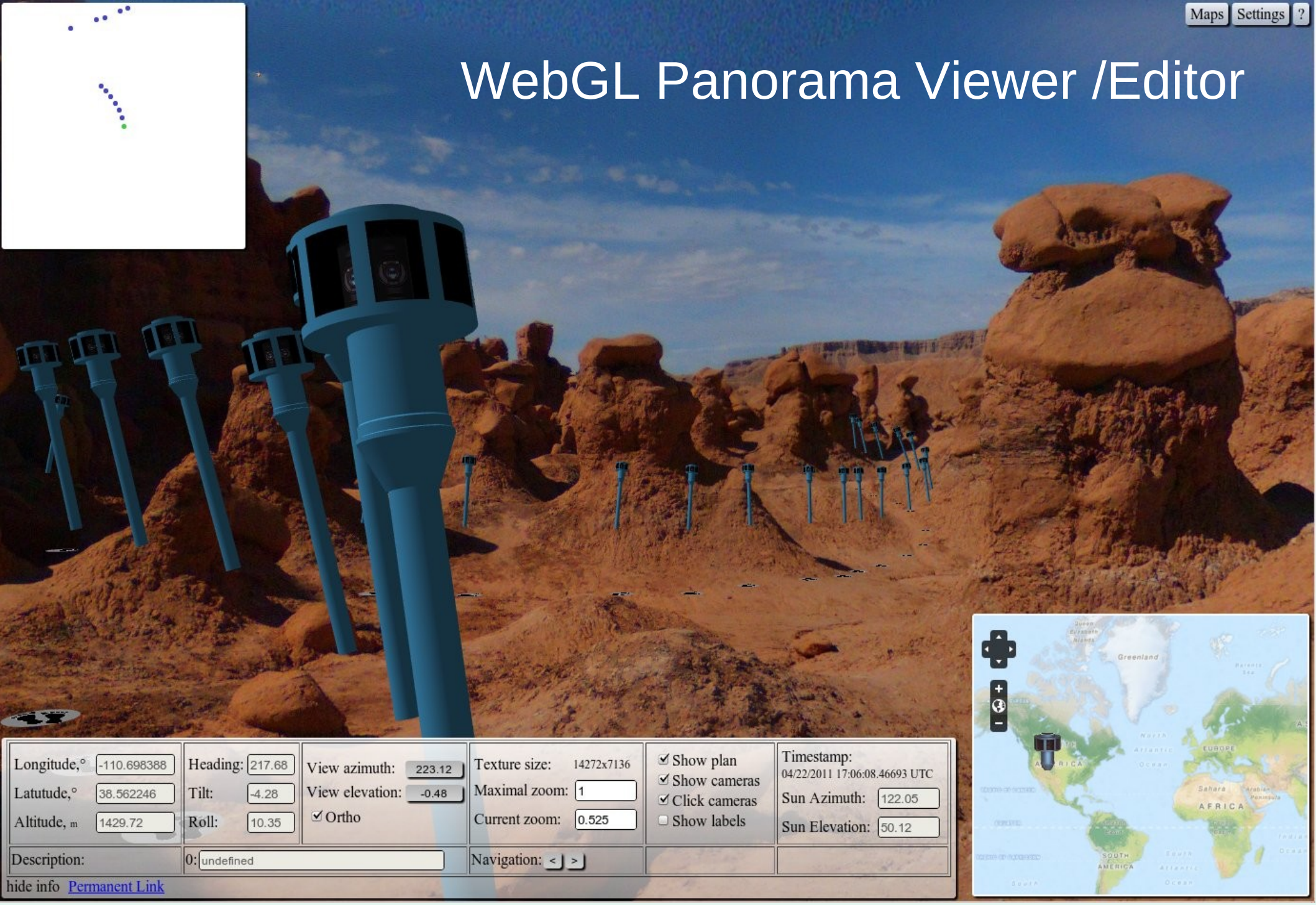


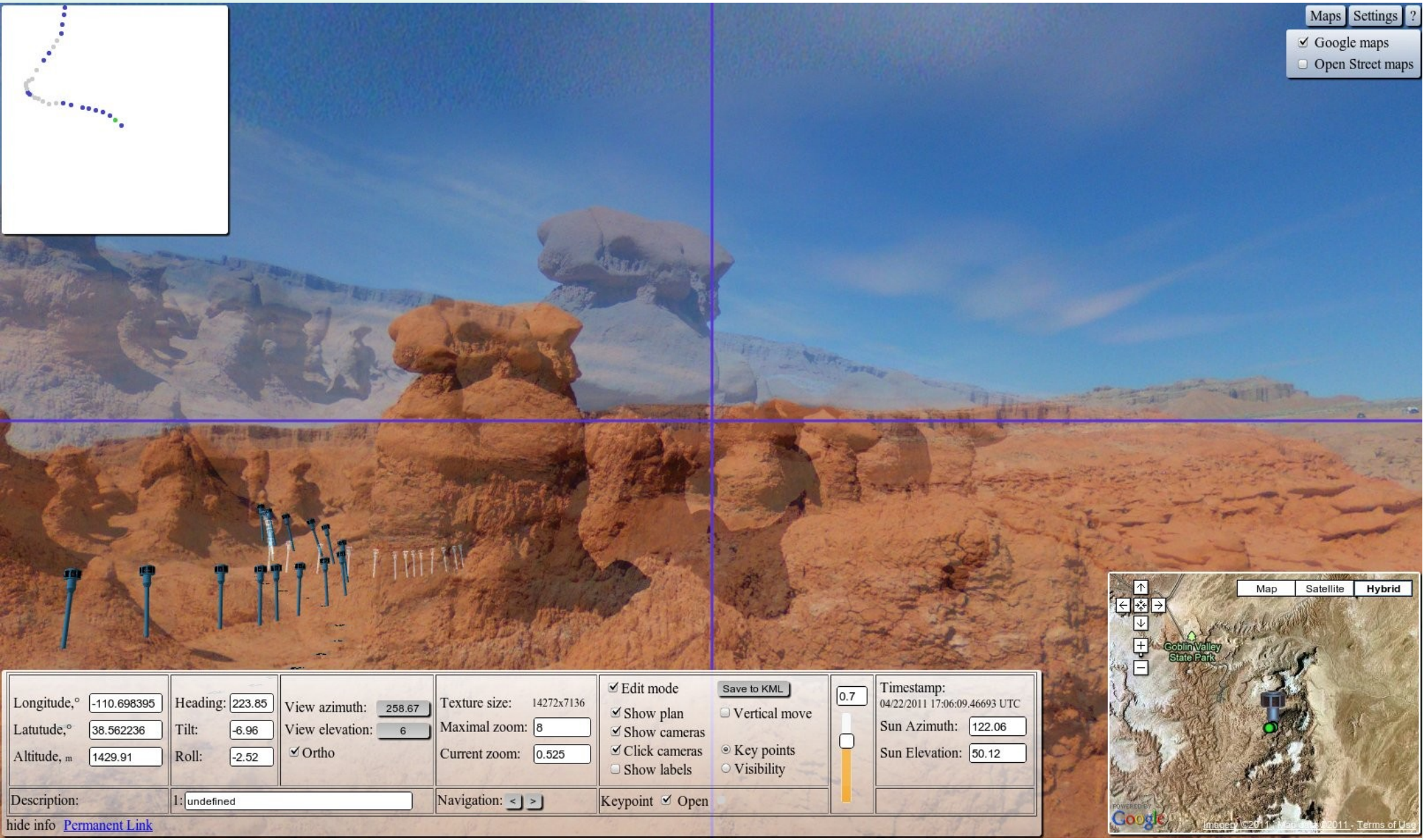
Eyesis 4π – Panoramic Image

- Full Size(14268x7135), Equirectangular Projection
- WebGL Viewer



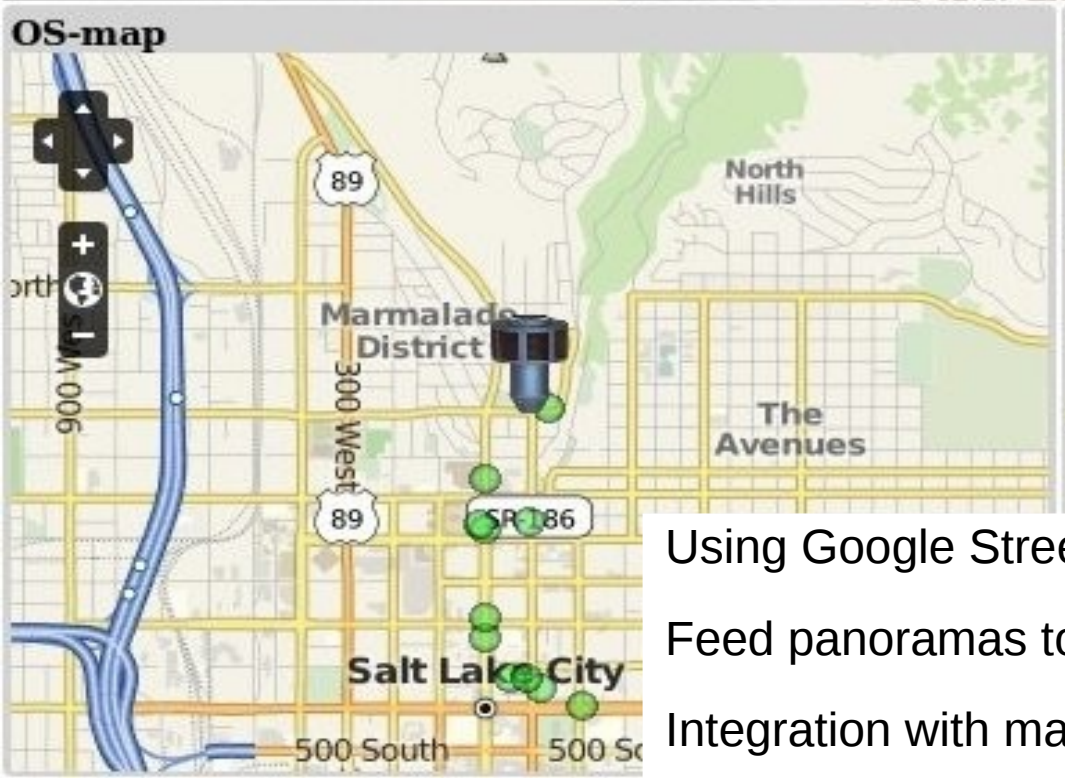
WebGL Panorama Viewer /Editor

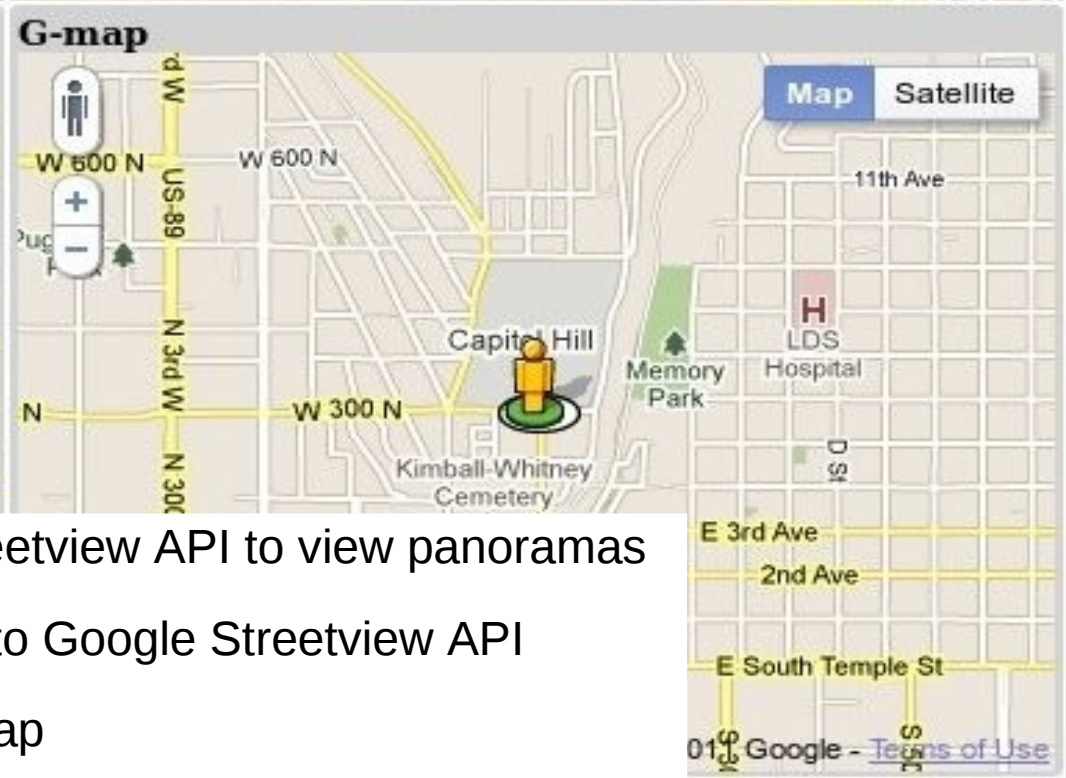




WebGL Panorama Viewer / Editor

Integration with Maps





Using Google Streetview API to view panoramas

Feed panoramas to Google Streetview API

Integration with map

Post-processing

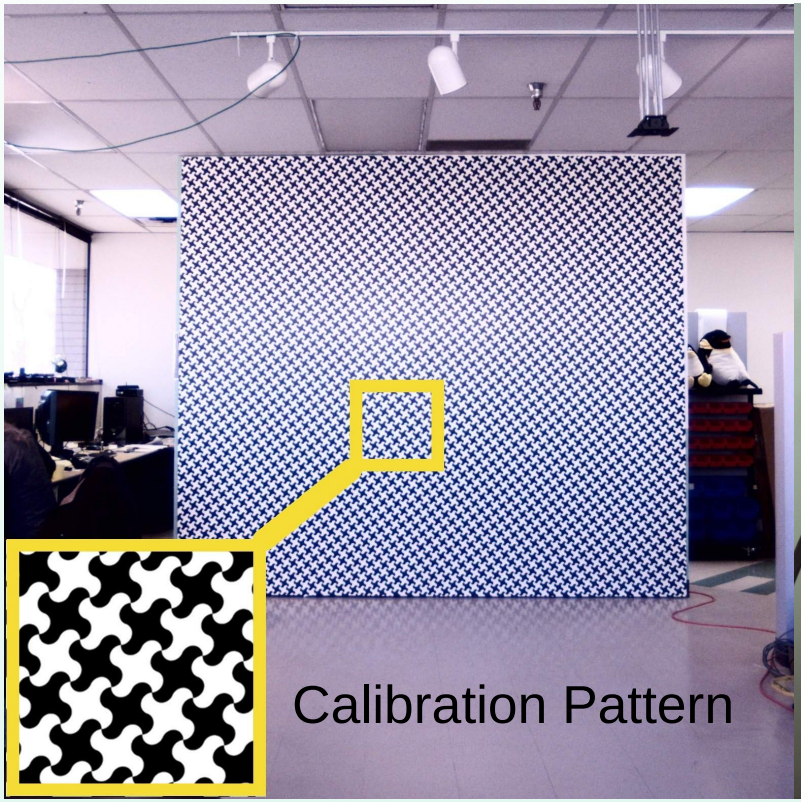
- Metadata extraction
- RAW conversion
- Aberration correction
- Distortion Correction
- Photogrammetry ready

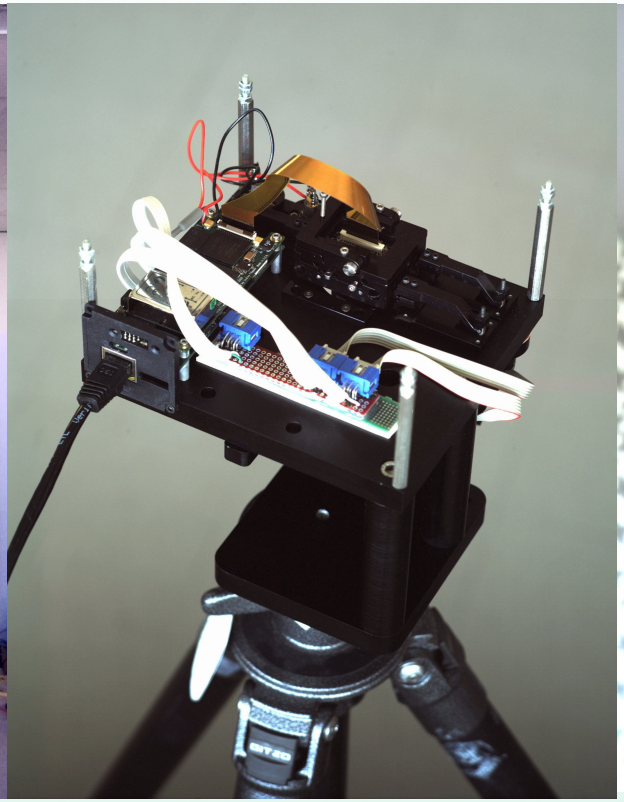
original

enhanced

Focus and Alignment

optical aberration measurement and correction developed for Eyesis cameras



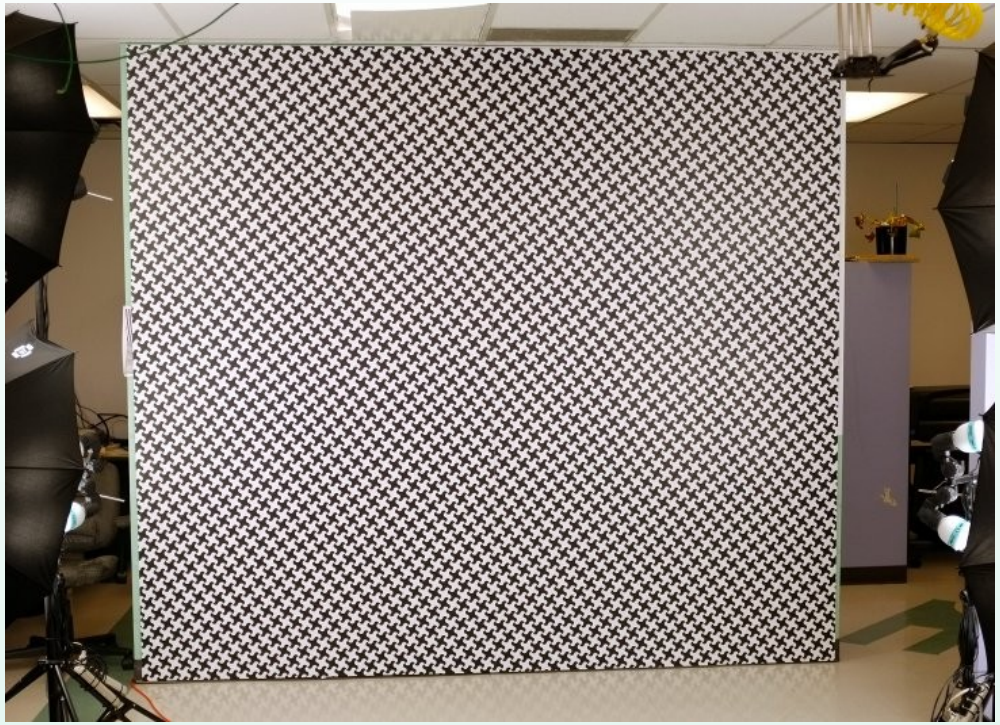


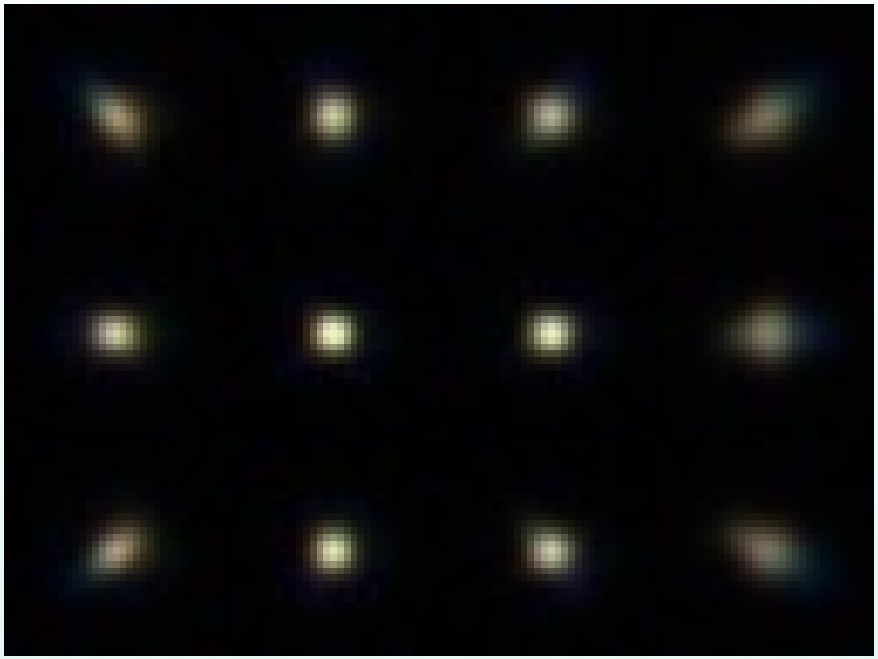
Lens is aligned and centered with sensor

Optical Aberrations of the Lens

Aberrations are more in the corners then in the center of the lens;

Point Spread Function of one of 12 areas of the pattern.

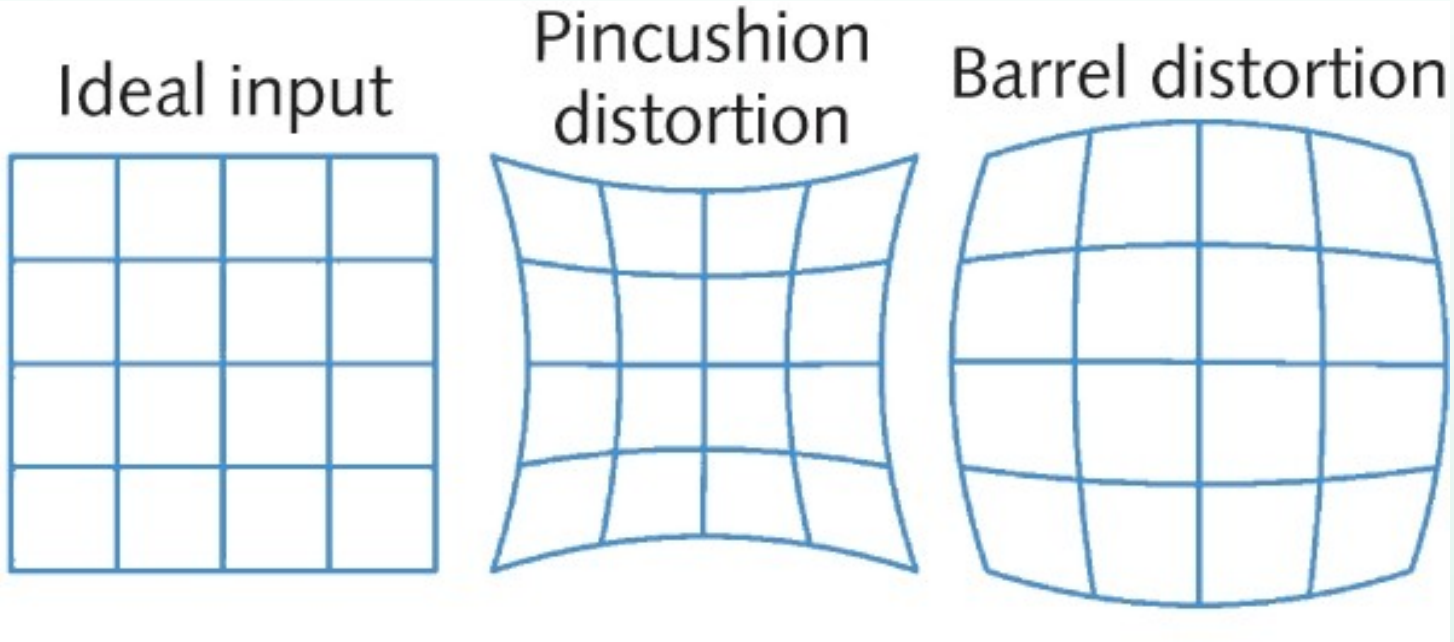




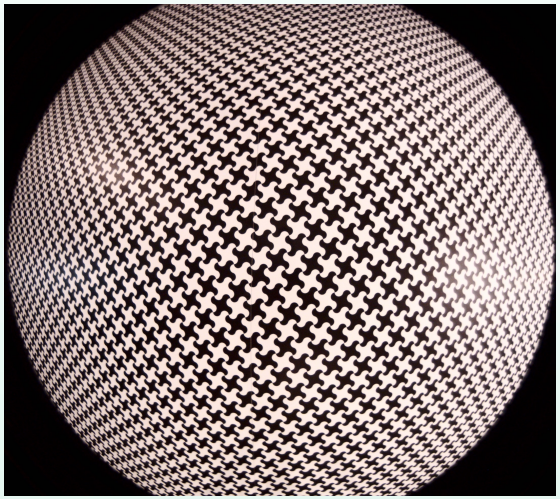
Aberration Correction - Results

With 1/2.5″ 5 megapixel sensor we achieved average sharpness improvement over the image area around 40% compared to the raw images, effectively doubling the resolved pixel count.

Optical Distortions

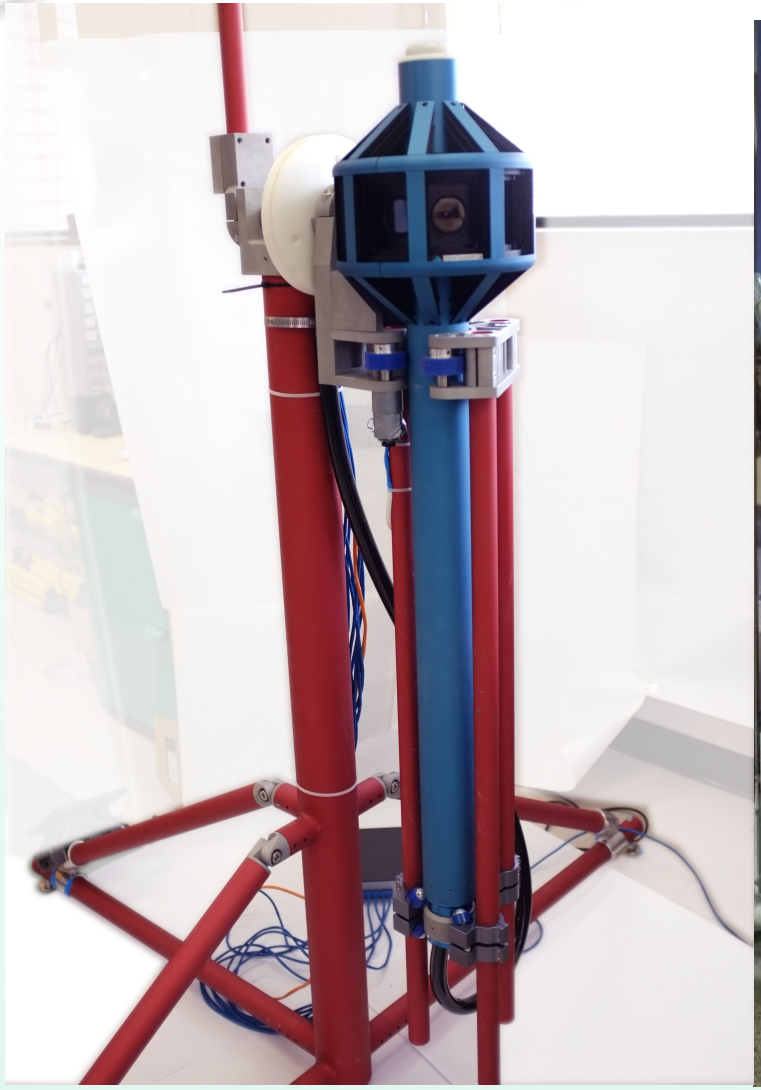


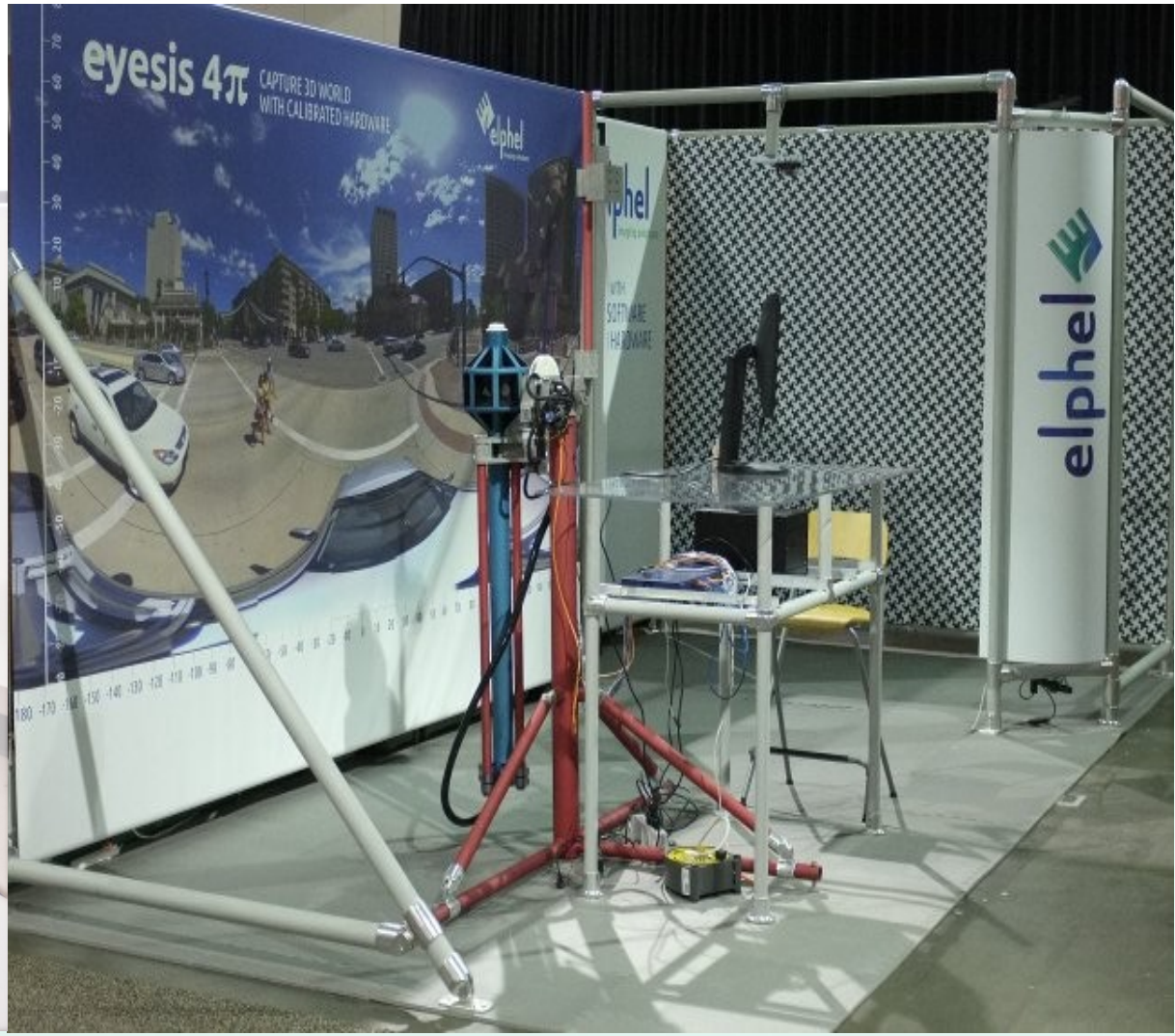
Fish-eye lens distortion



Calibration for Distortions

Calibration Machine and Pattern



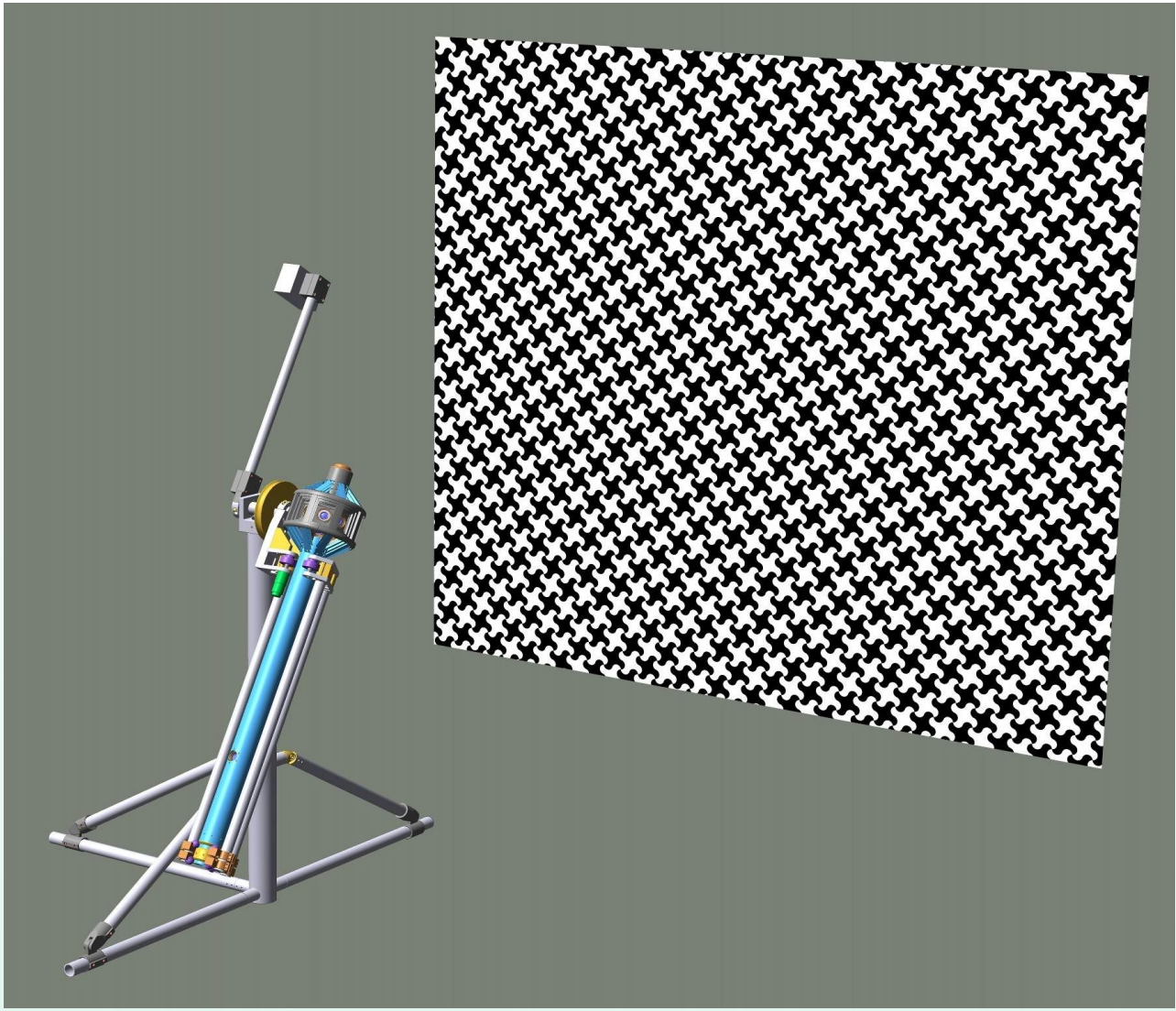


Pixel Mapping with sub-pixel resolution

Camera as a measuring tool

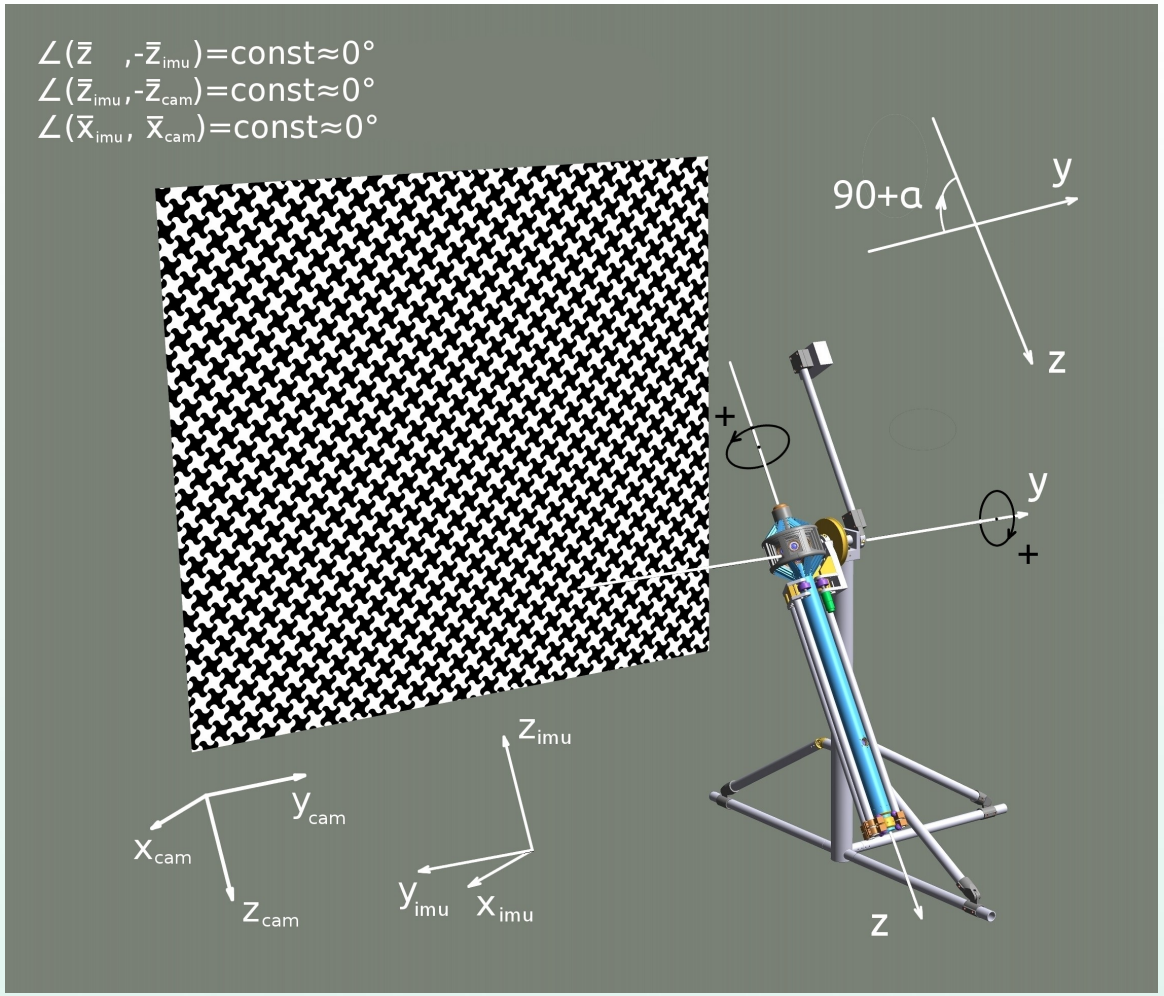
Photogrammetry

3D reconstruction



Inertial Measurement Unit (IMU):

IMU calibration

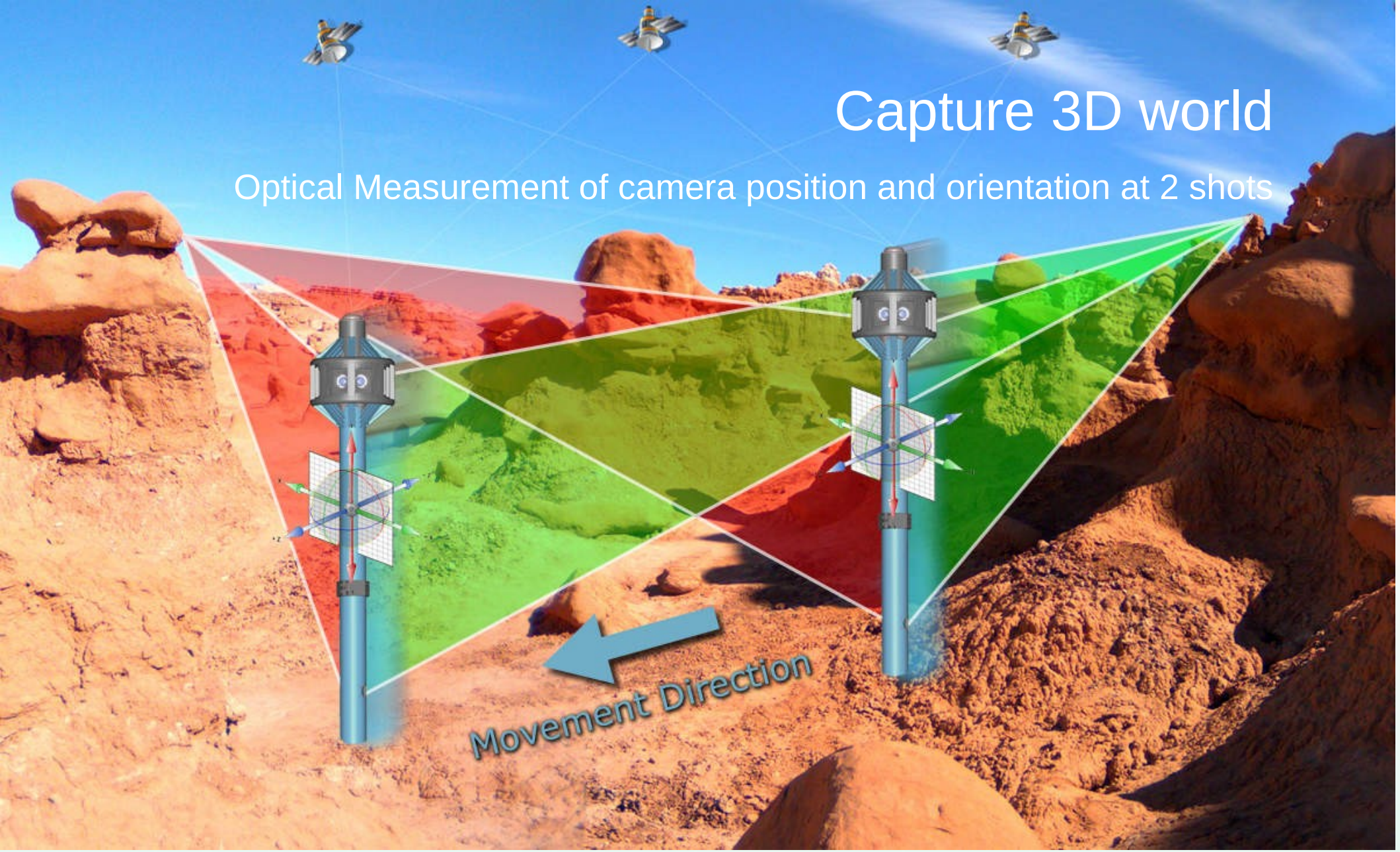


Inertial Measurement Unit (IMU):

Compensate ERS (Electronic Rolling Shutter) distortion by recording position /orientation of camera several times within each frame

Capture 3D world

Optical Measurement of camera position and orientation at 2 shots



HDR with moving camera,

will be possible with textures on 3D mesh

Eyesis 4π R&D

- Inertial Measurement Unit (IMU) :

  3D Position and Orientation

  Compensate for Rolling Shutter Distortion
- Photogrammetry
- 3D Reconstruction
- HDR with moving camera

Internship at Elphel

Programming:

- image processing for optics and cameras (Java, C/C++)
- Web applications (WebGL, PHP,Javascript, HTML)
- adapting camera for specific applications (PHP,Javascript, HTML, Java)
- IMU data processing: filtering, orientation (Java, C/C++)
- 3D reconstruction (Java, C/C++)
- FPGA programming (Verilog);

Experience working with electronics hardware

Electonics Design and Verification

Open house: October 10th,18th

12 – 2pm

1405 W 2200 S #205 WVC, UT 84119

www.elphel.com

Development Blog: http://blog.elphel.com

Documentation: wiki.elphel.com

Code: SourceForge.net

1405 W 2200 S #205 WVC, UT 84119