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(71) Applicant(s):
Sharp Kabushiki Kaisha
(Incorporated in Japan)
22-22 Nagaike-cho, Abeno-ku,
Osaka 545-8522, Japan

(72) Inventor(s):
David James Montgomery
Graham Roger Jones

(74) Agent and/or Address for Service:
Marks & Clerk
4220 Nash Court,
Oxford Business Park South, OXFORD,
OX4 2RU, United Kingdom

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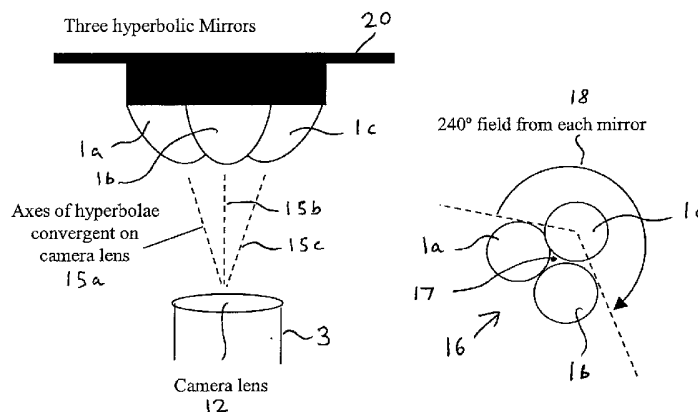
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(54) Abstract Title: **Panoramic adapter with mirrors formed by rotating conic section**

(57) An adapter is provided for adapting an optical instrument, such as a camera (3) or a projector, to capture or display panoramic three-dimensional images. The adapter comprises a plurality of mirrors (1a, 1b, 1c), each of which has a reflective surface which is in the shape of a curved non-circular conic section rotated about an axis of symmetry (15a, 15b, 15c). The reflective surfaces have first foci which are spaced perpendicularly from a longitudinal axis of the adapter and which are angularly spaced around the longitudinal axis. For example, the conic section may be a hyperbola with first foci equidistantly spaced from the longitudinal axis and equiangularly spaced around the longitudinal axis. The axes of symmetry (15a, 15b, 15c) of the mirrors (1a, 1b, 1c) converge to intersect the longitudinal axis at a point which is coincident with the front principal point of, for example, a camera lens (12). Thus, single shot capture of all the image data for the or each panoramic three-dimensional image may be performed. Each of the mirrors may have a convex hyperboloidal, concave ellipsoidal or convex paraboloidal reflective surface.

Figure 7



$3 \times 240^\circ = 2 \times 360^\circ$ homologous images \Rightarrow 3D panoramic image
 Stereo baseline determined by distance between mirrors

Figure 1 (PRIOR ART)

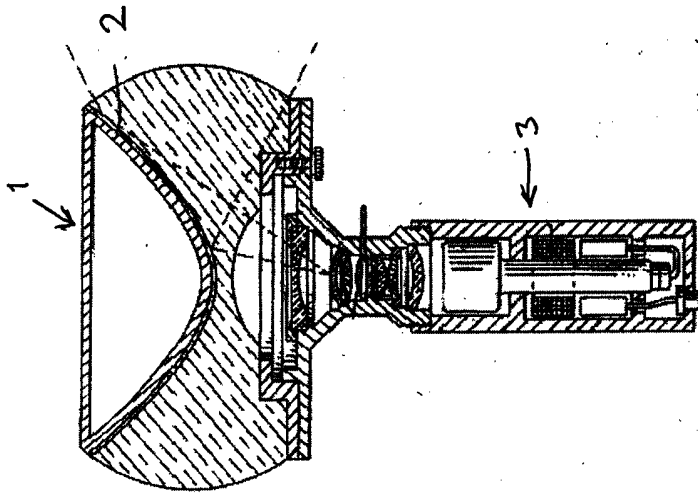
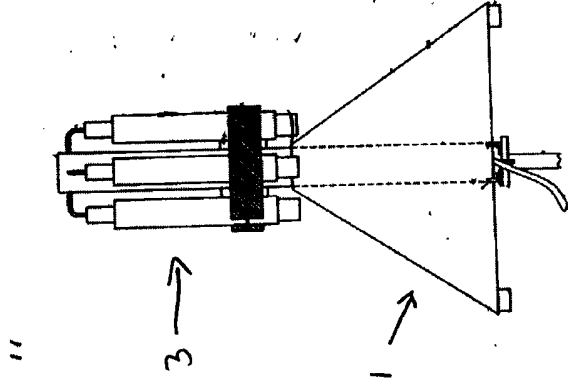


Figure 2 (PRIOR ART)



1/19

Figure 3 (PRIOR ART)

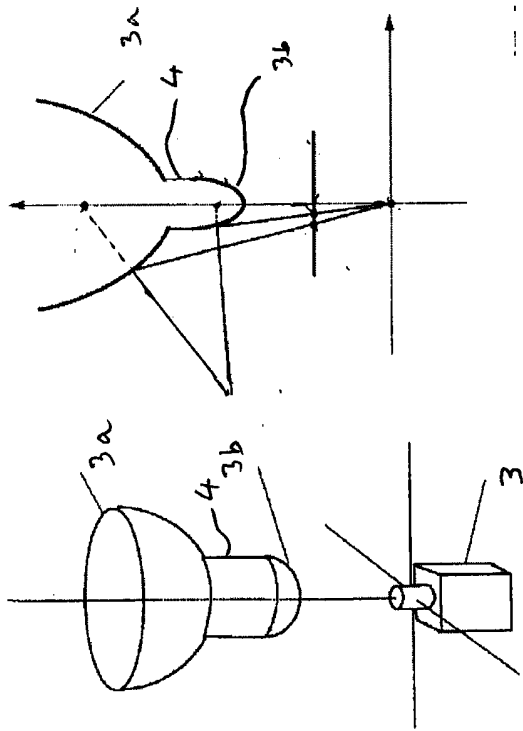


Figure 4 (PRIOR ART)

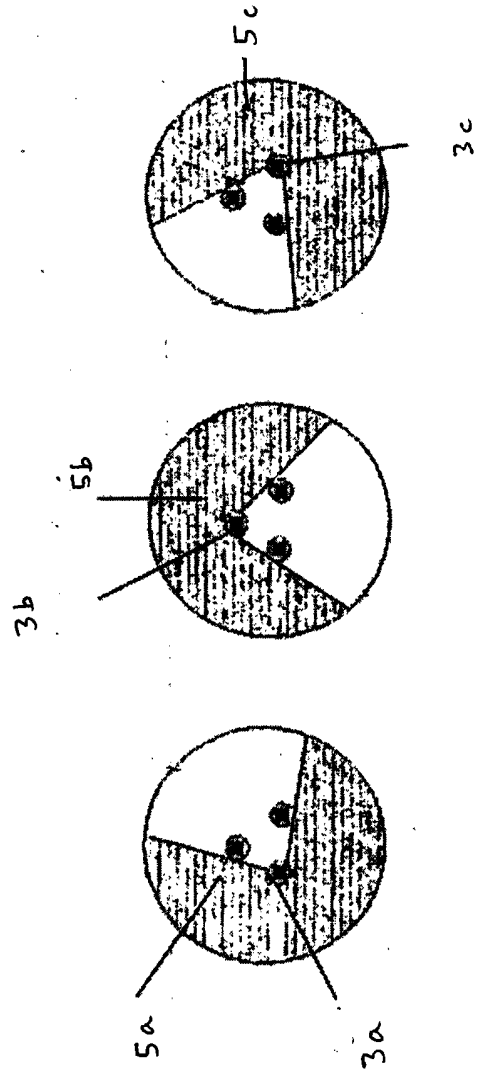


Figure 5 (PRIOR ART)

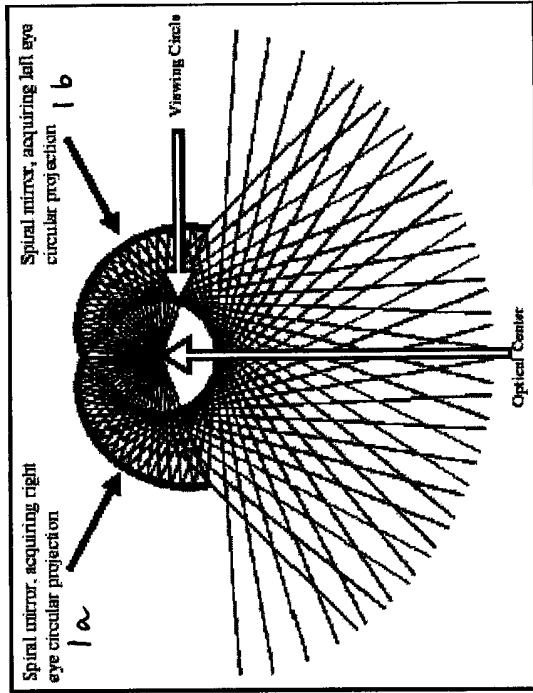
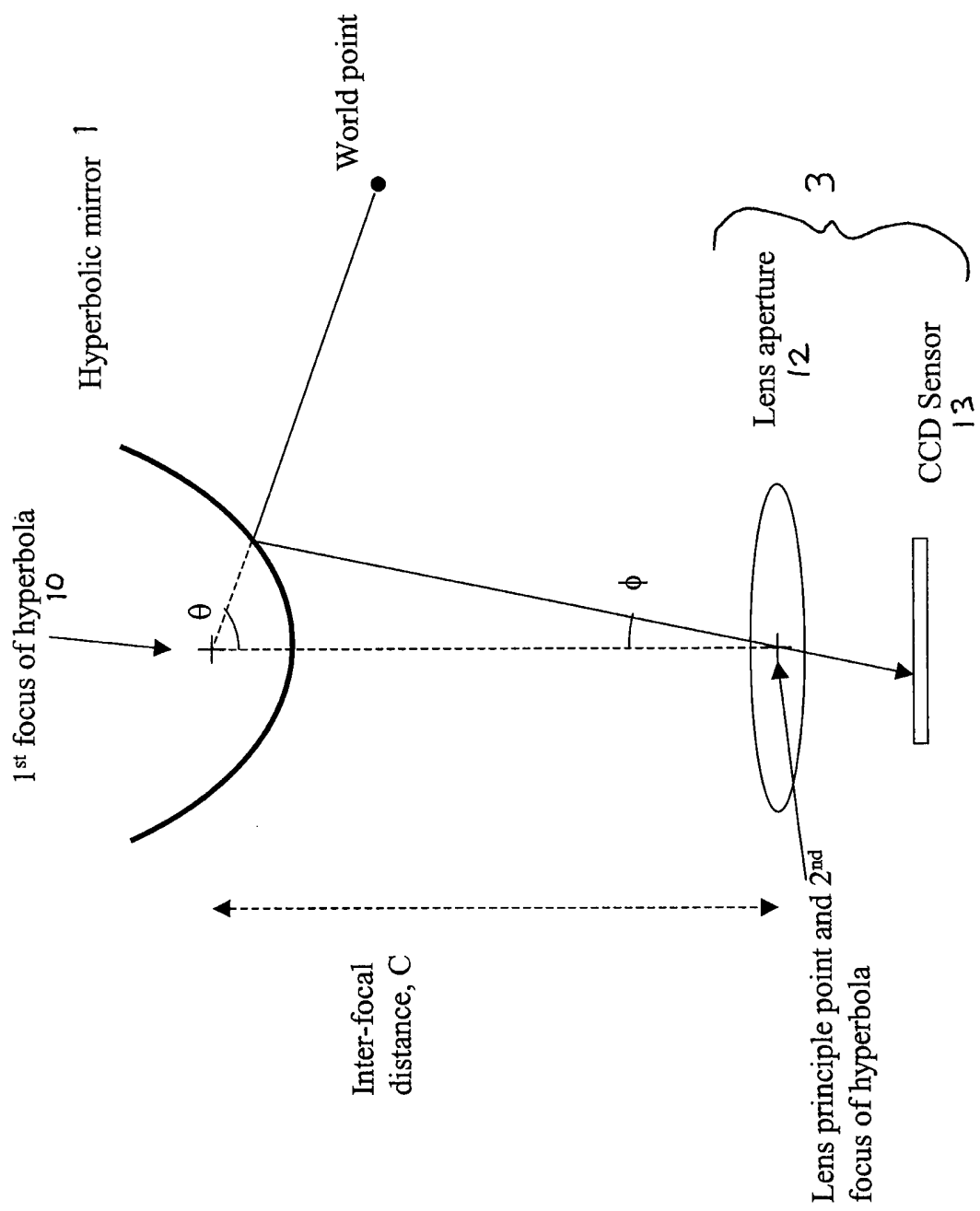


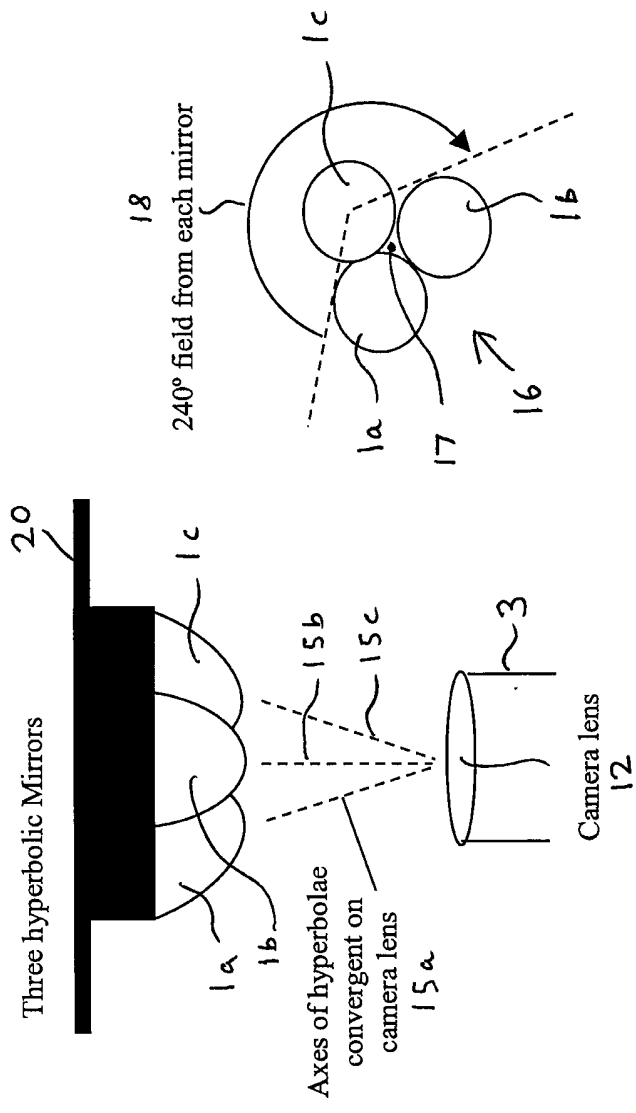
Figure 6 (PRIOR ART)

2D Panoramic camera using a hyperbolic mirror



4/19

Figure 7



5/19

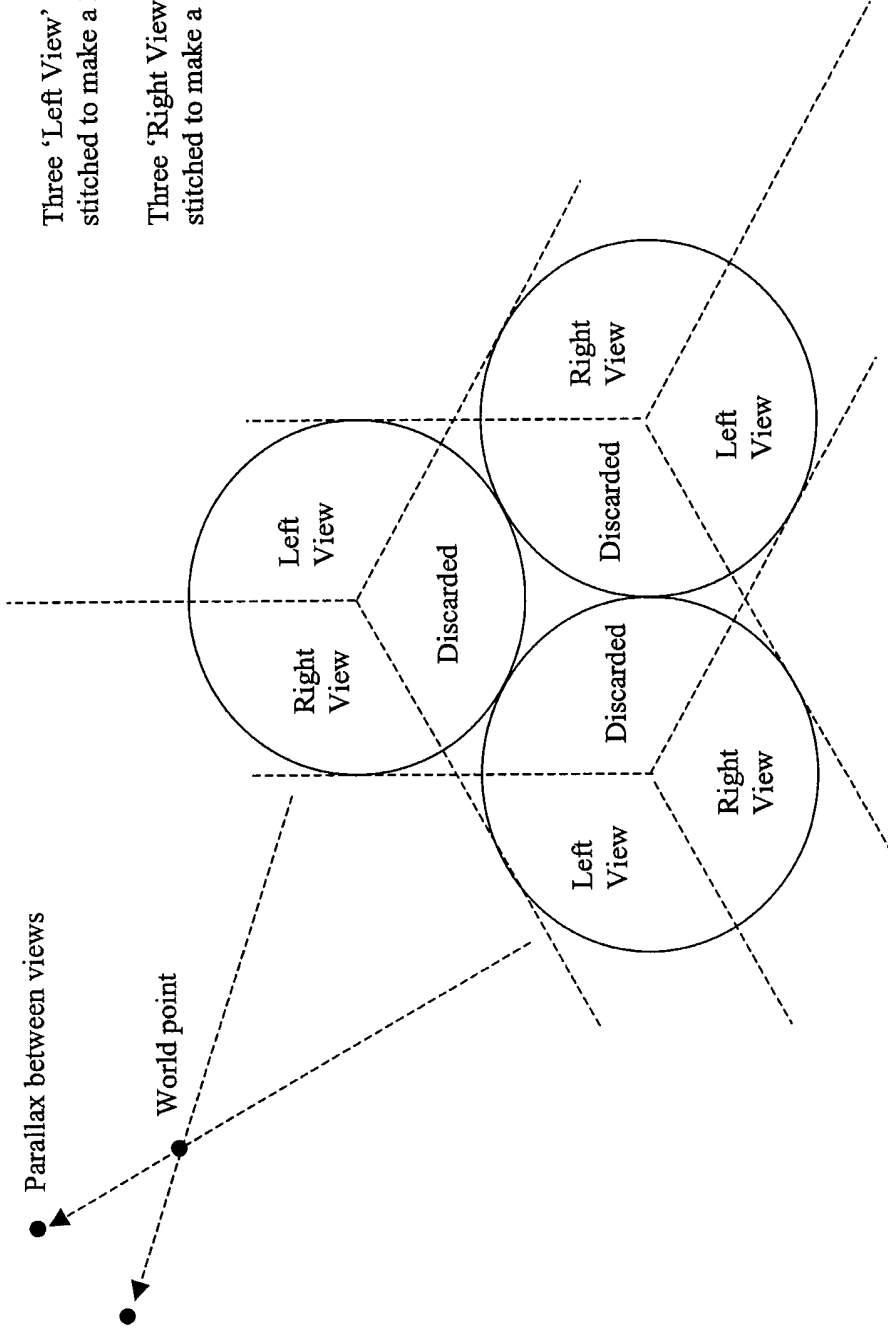
$3 \times 240^\circ = 2 \times 360^\circ$ homologous images \Rightarrow 3D panoramic image
Stereo baseline determined by distance between mirrors

Figure 9

Mirrors from top

● Parallax between views

● World point

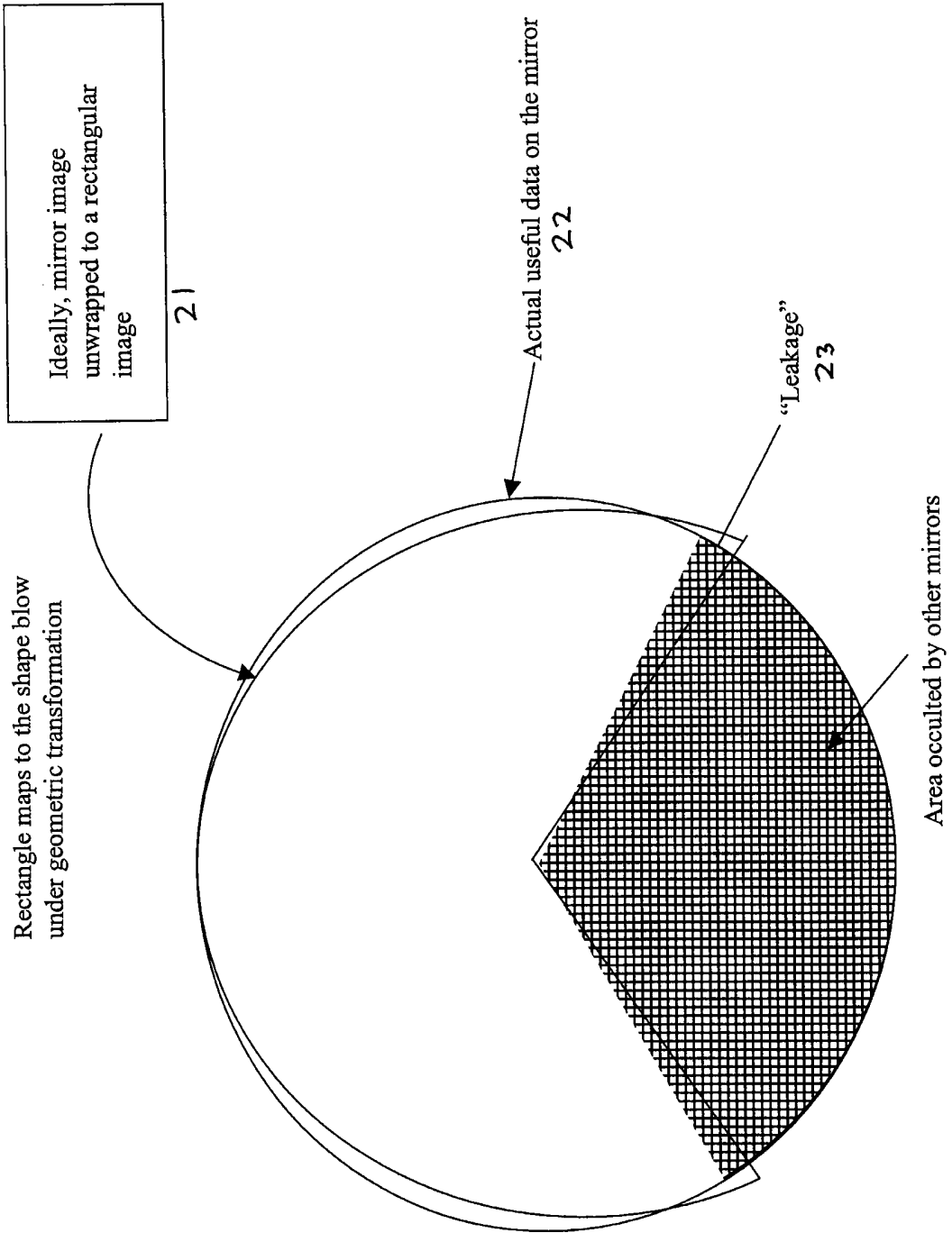


Three 'Left View' segments can be stitched to make a 360° left view

Three 'Right View' segments can be stitched to make a 360° Right view

Figure 10A

Mirror from top

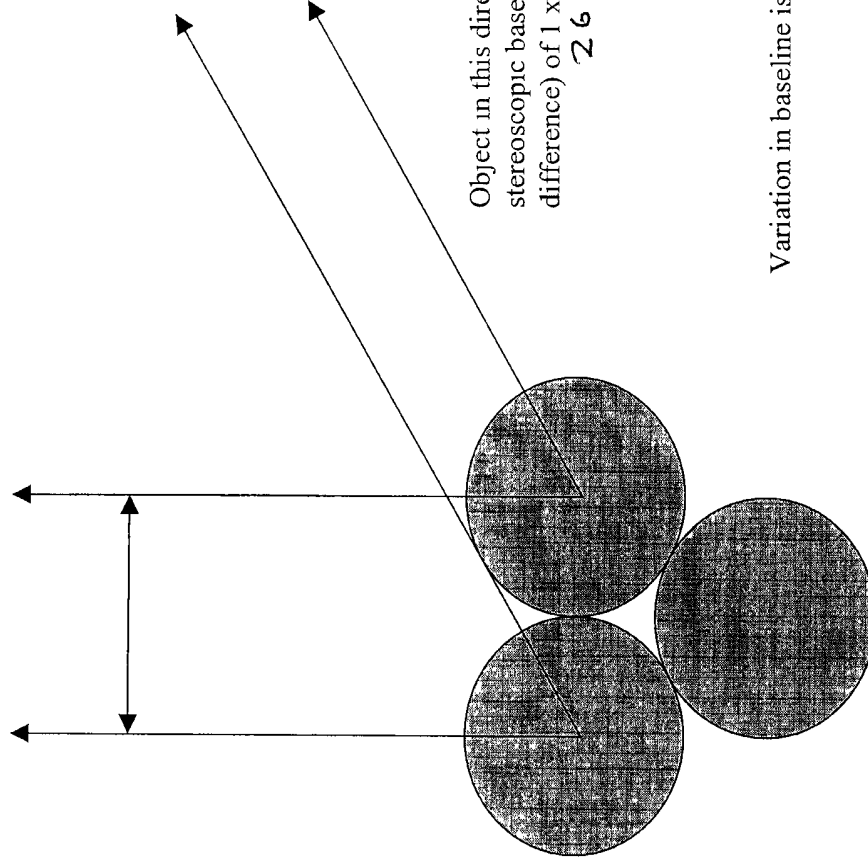


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Figure 10B

25

Object in this direction has a stereoscopic baseline (viewpoint difference) of 2 x (mirror radius)



Object in this direction has a stereoscopic baseline (viewpoint difference) of 1 x (mirror radius)

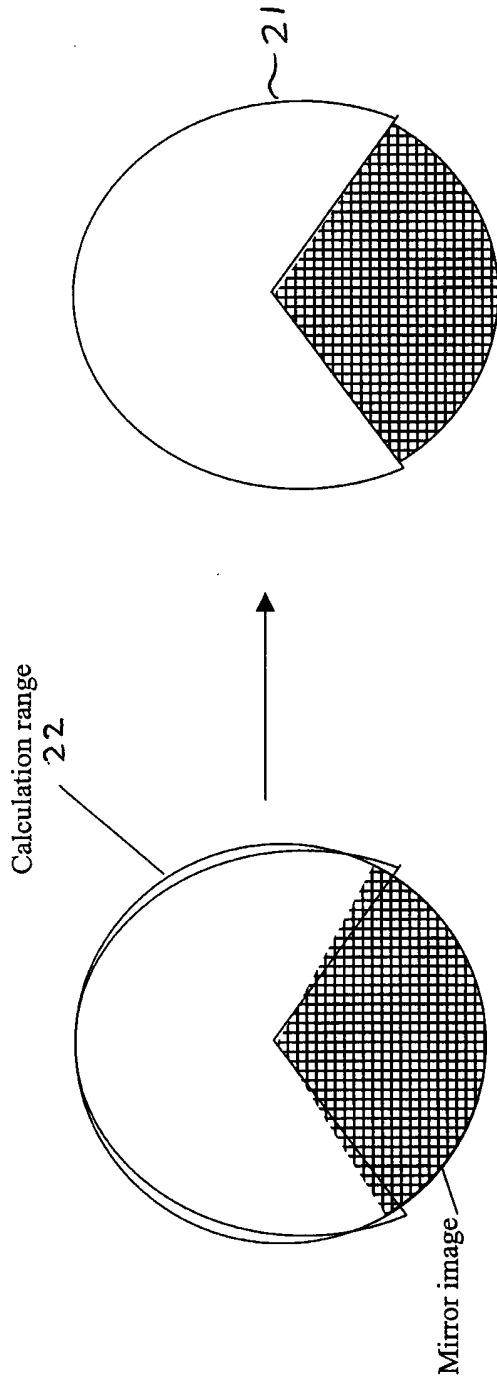
26

Variation in baseline is 50%.

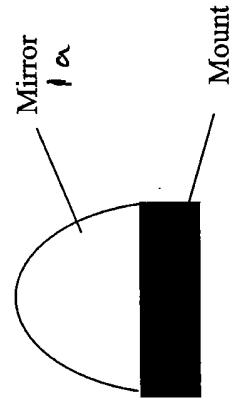
9119

Figure 11A

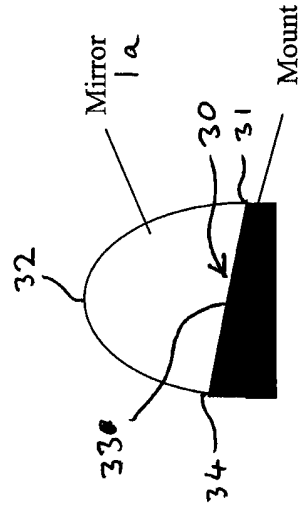
View of mirror on camera CCD



Original mirror view



New design of mirror



Actual mirror shape

Figure 11B

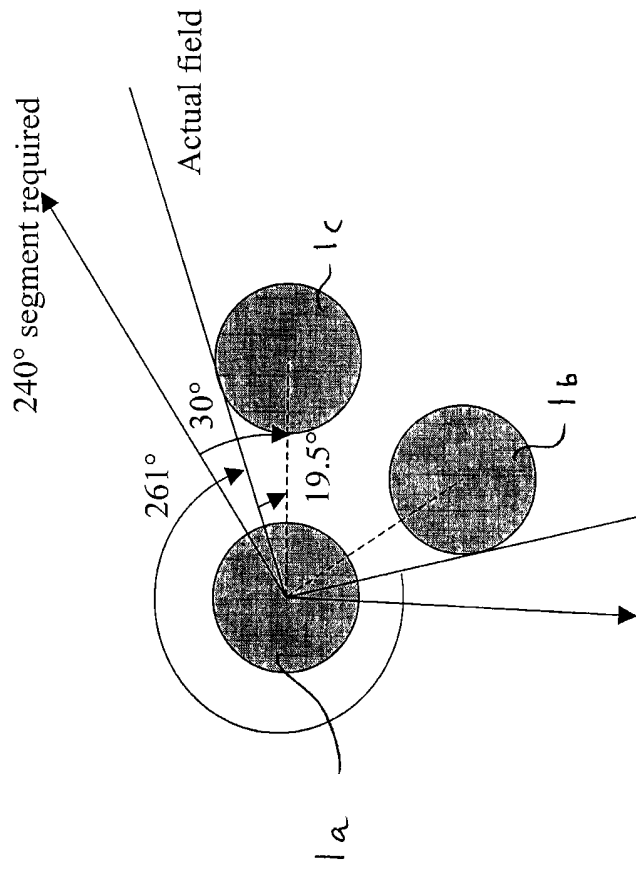
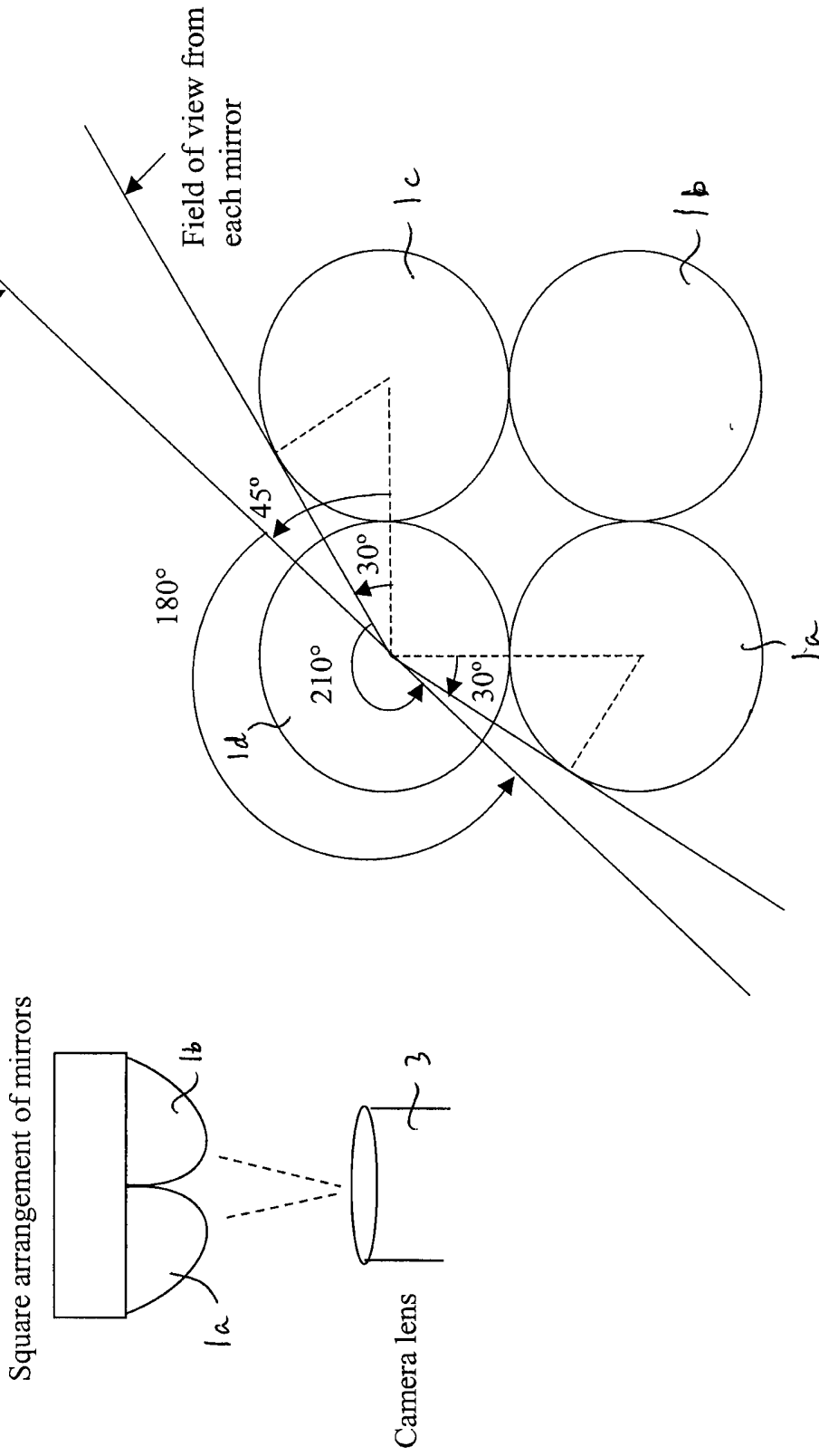
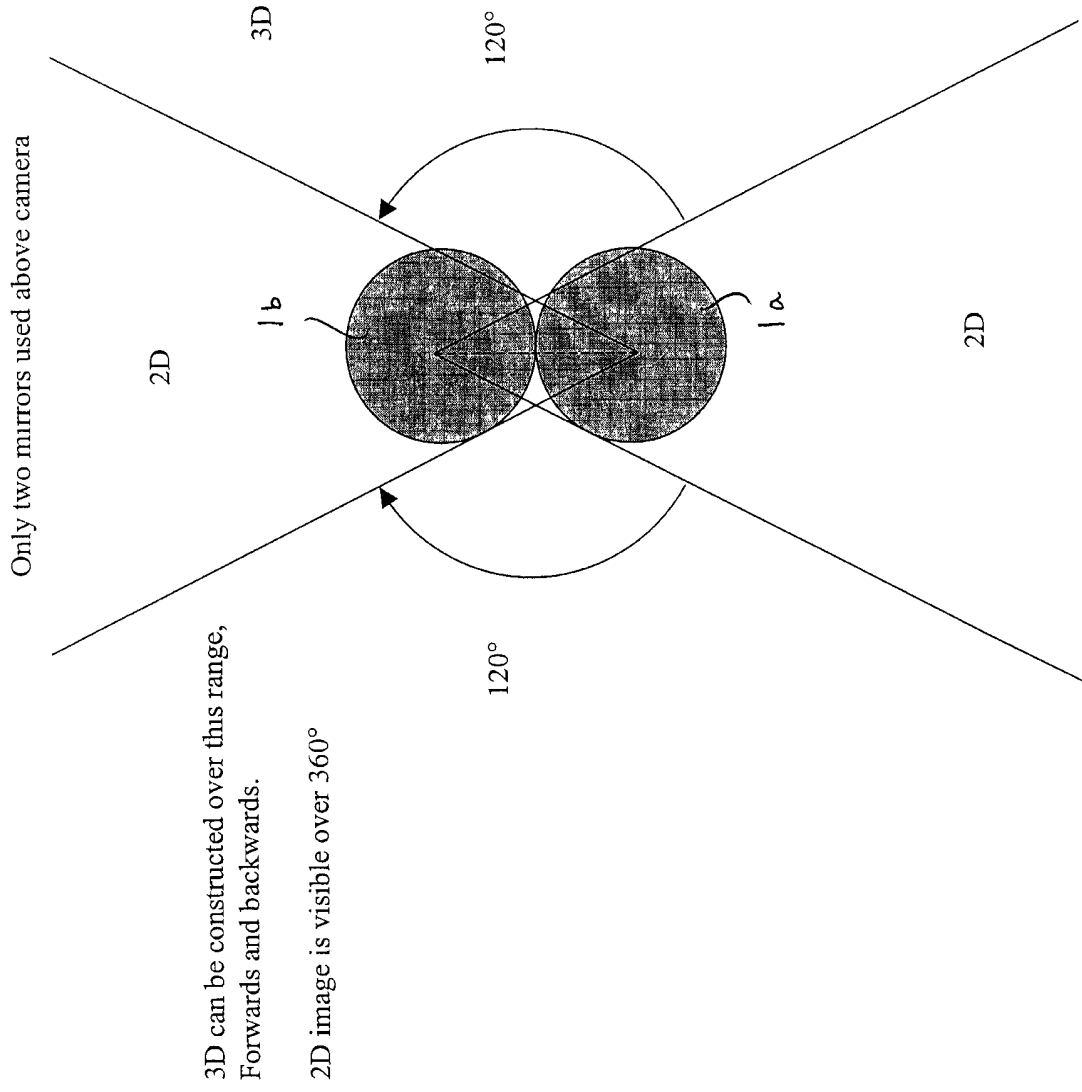


Figure 12



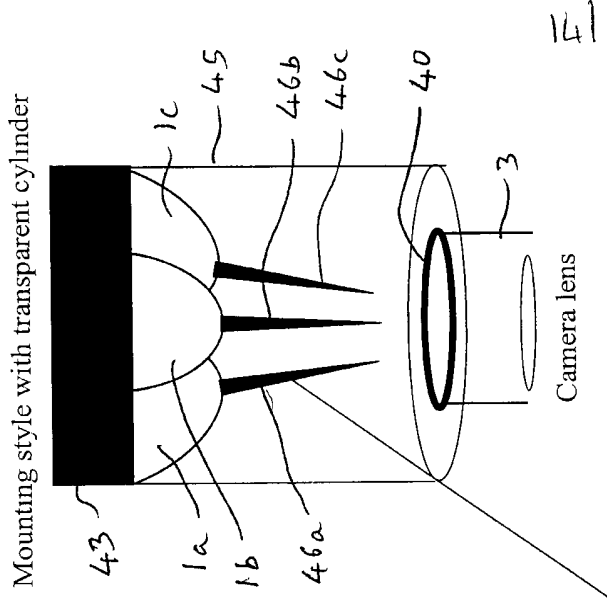
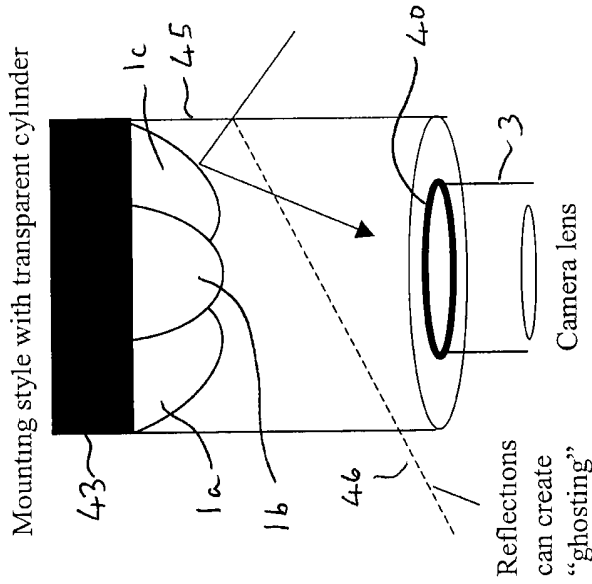
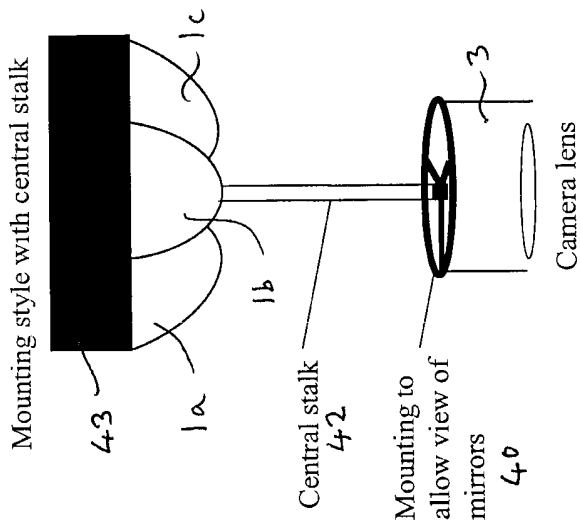
Stereo baseline in the centre is 2 x (radius)
 Stereo baseline at edge of field is $\sqrt{2}$ x (radius)
 Variation in baseline now only 29%.

Figure 13



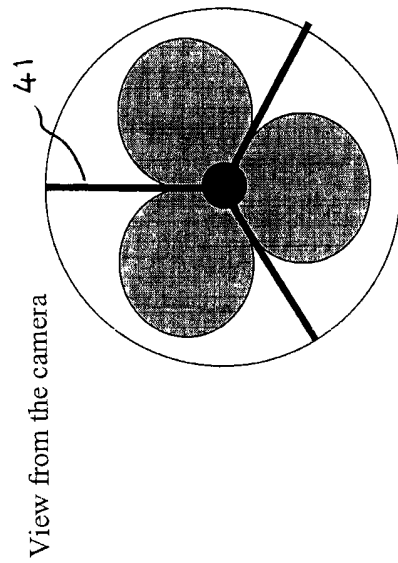
13/19

Figure 14



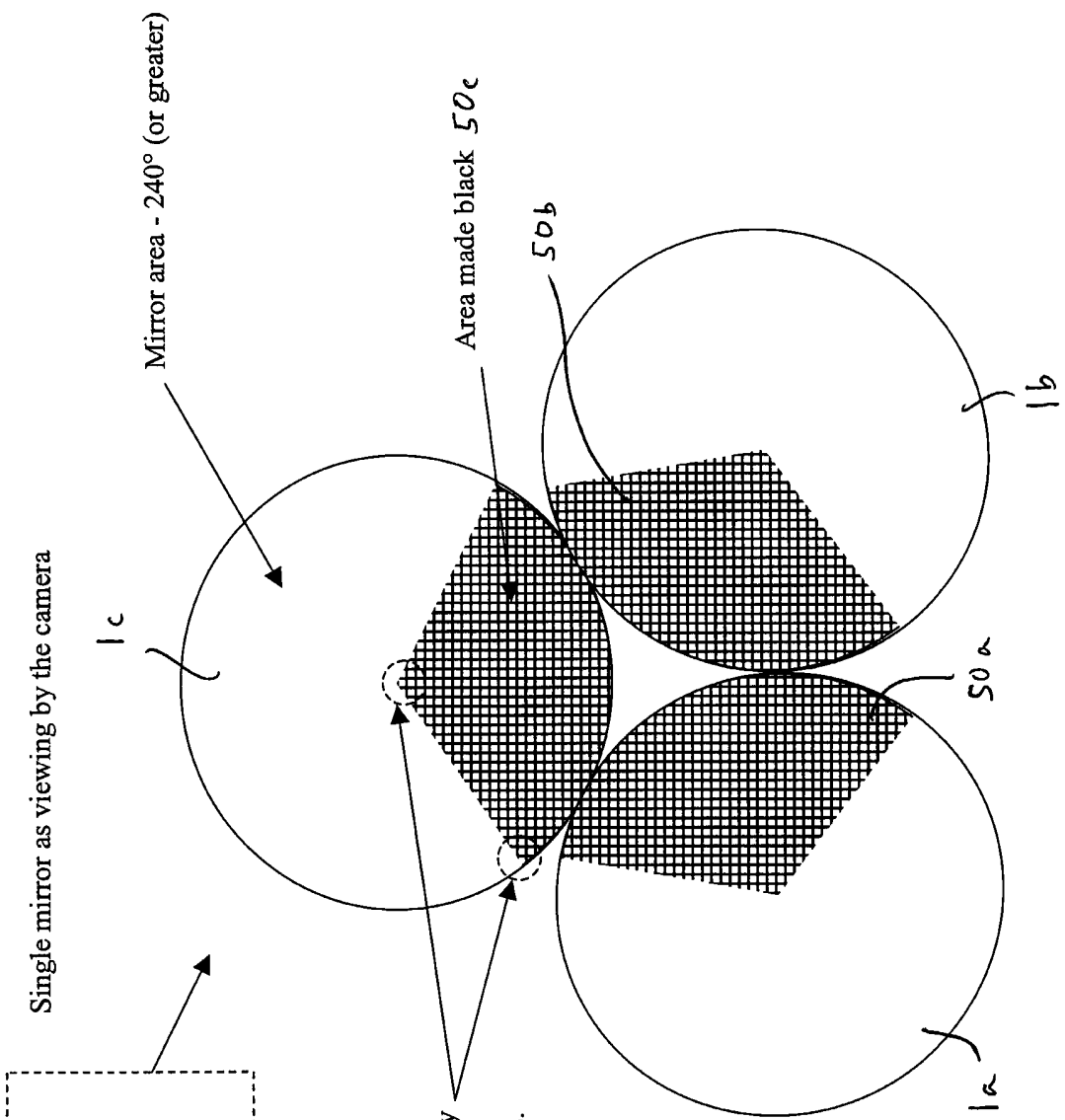
14/19

Blackened "spikes" can eliminate ghosting (Prior art). In this case they will be angled in with the axis of the mirrors.



15/19

Figure 15



Software can now more easily find the circles centre and radius by finding these points. These are needed for processing

Figure 16

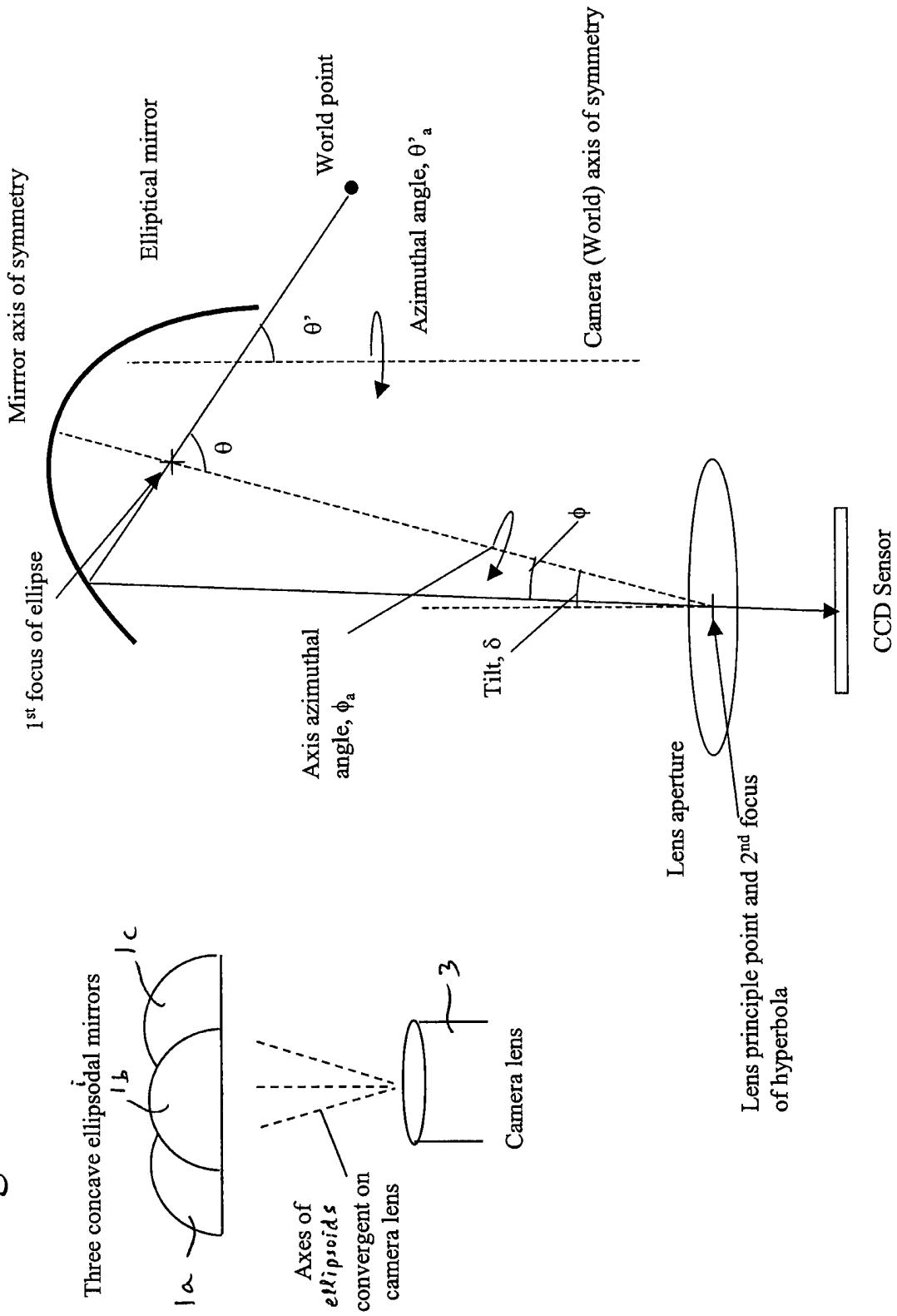
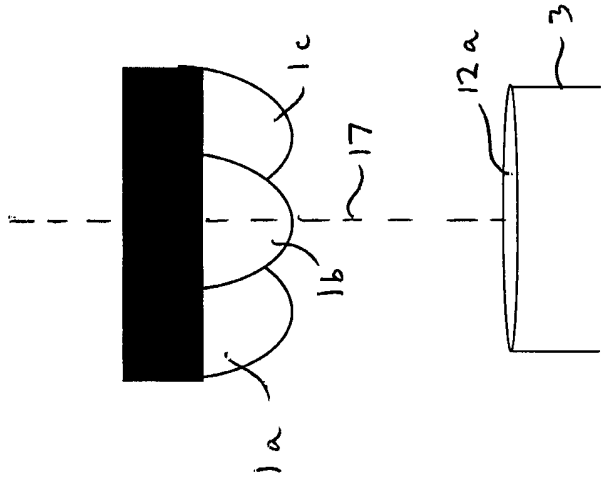
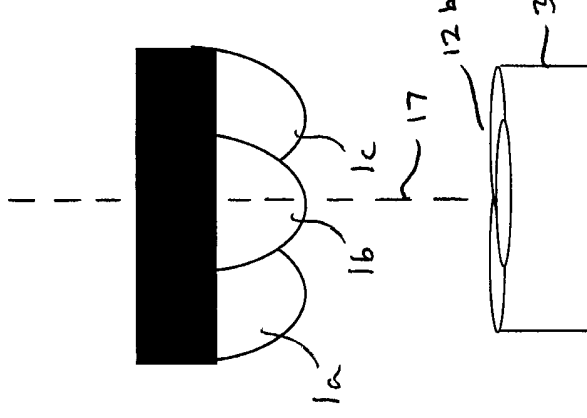


Figure 17 paraboloid mirrors



Three paraboloid mirrors are arranged so that their axes are parallel

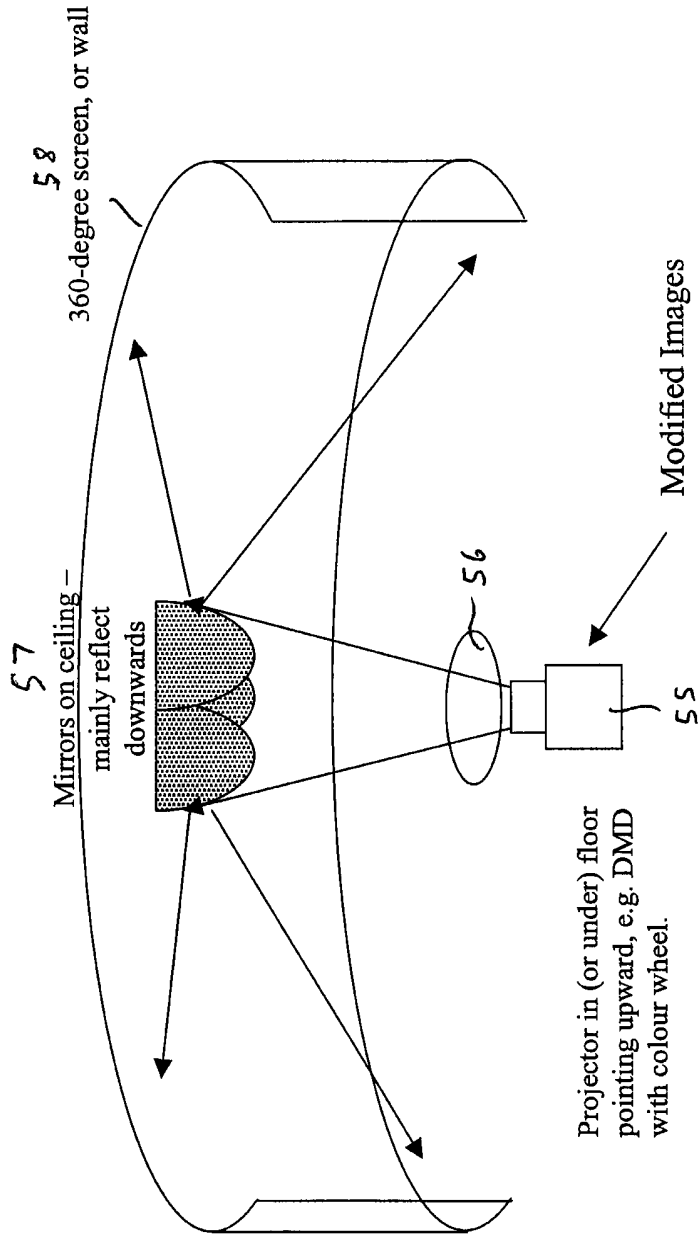
Large telecentric lens system



Custom telecentric lens system

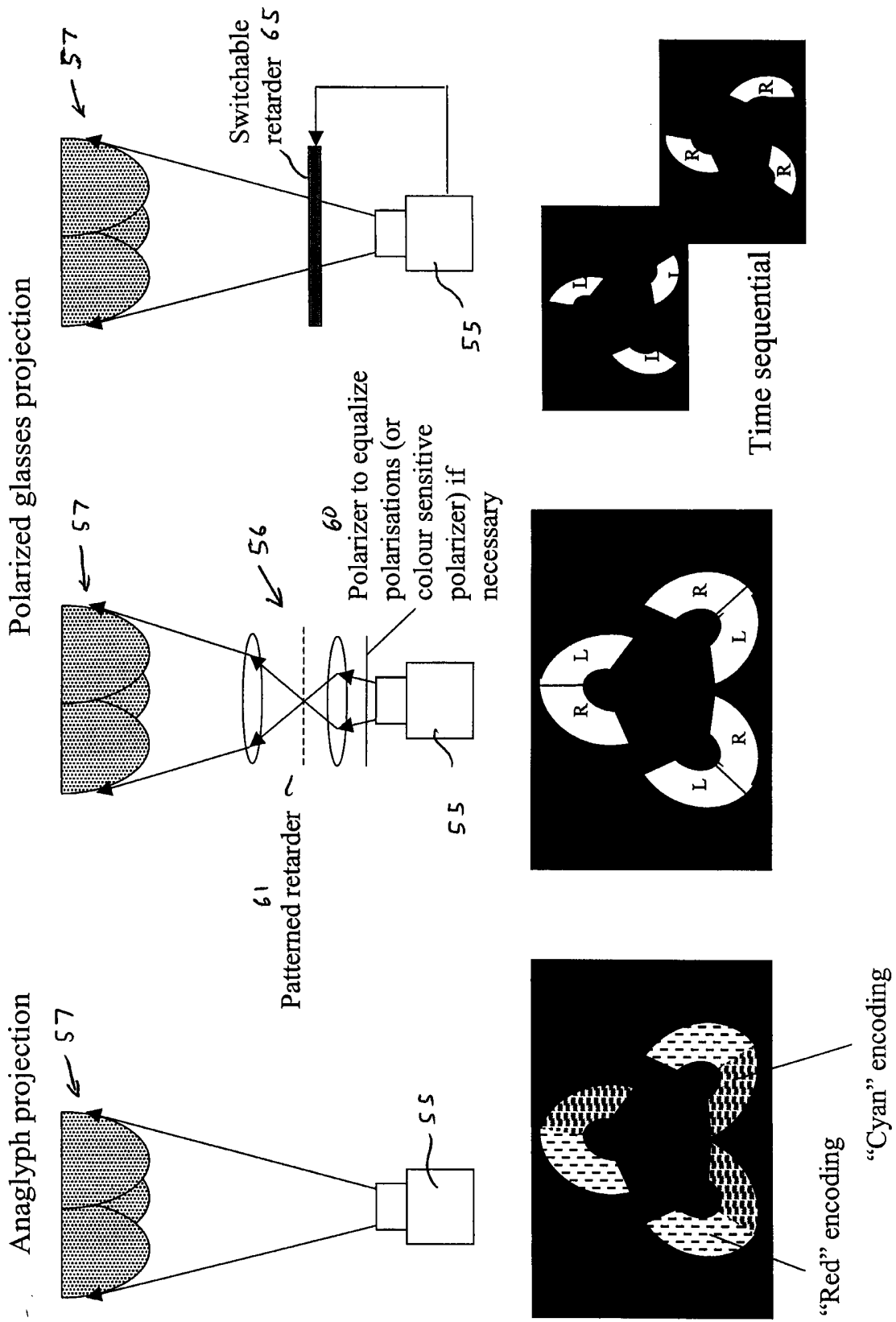
17/19

Figure 18



18/19

Figure 19



19/19.

**Panoramic Three-Dimensional Adapter for an Optical Instrument and a
Combination of such an Adaptor and such an Optical Instrument**

The present invention relates to a panoramic three-dimensional (3D) adapter for an optical instrument and a combination of such an adaptor and such an optical instrument. For example, such an optical instrument may comprise a camera which, when including or mounted to such an adapter, may be used as a stereoscopic panoramic camera. As an alternative, the optical instrument may comprise a projector which, when mounted to or including such an adapter, may be used to form a panoramic stereoscopic projection display.

Examples of applications of such arrangements include:
Video conferencing/lecturing (video presence applications);
Support for Immersive 3D display applications: 3D image acquisition for desktop/large area screen displays, IMAX-style 3D cinemas in the home, 3D-CAD acquisition;
VRML room/building reproduction – single 2D/3D “walkthrough” photographs of rooms in museums, shops, external street/building photography – for websites, motion video etc, estate agents, retailers;
Image acquisition for virtual environments – VR, games, military and civilian aerial reconnaissance, real world data for training simulators, 3D model reconstruction;
Vehicle active cruise/parking control;
All-around 3D home security and monitoring cameras.

There are several known types of wide field or panoramic stereoscopic cameras. A first type uses a plurality of cameras, usually a multiple of 6 cameras, disposed in a circular or spherical arrangement. Such an arrangement typically provides good quality images but is complex and expensive to set up. Also, because several cameras are used to capture the images, there may be brightness and matching errors when the panoramic stereoscopic images are constructed from the individually captured images. Such a problem is typical of any multiple camera system, whether 2D or 3D, in which images captured by different cameras are combined together to form a composite image.

It is also possible to generate panoramic stereoscopic images using a rotating head camera of well-known type. Such an arrangement is capable of providing good results but a significant amount of computer processing of the captured images is necessary in order to provide stereoscopic viewing. Also, because of the nature of such a rotating
5 head camera, different vertical slices of the image are captured at different times and this may result in substantial visible errors if there is any significant movement in the scene or object whose image is being captured.

Another known type of stereoscopic camera arrangement makes use of wide angle lens
10 systems such as "fisheye" lenses. However, such arrangements generally require more than one camera in order to provide a full panoramic view. Also, the resolution of the captured images is generally relatively low.

A known type of 2D system of the "catadioptric" type uses a conic section mirror,
15 generally disposed above a camera, which may be of the "emulsion" or "opto-electric" type and which may capture still or moving images. US3505465 discloses an arrangement of this type for providing a full 360° panoramic 2D view, for example for use by tank commanders. As shown in Figure 1 of the accompanying drawings, the reflecting surface 2 of a conic mirror 1 is axially symmetric around a vertical axis and is
20 in the shape of a surface of rotation based on a hyperbolic section. The mirror 1 is disposed above a video camera 3 so that the axis of symmetry of the mirror 1 coincides with the optical axis of the camera 3.

The image captured by the camera 3 can be processed by means of a coordinate
25 transformation, for example, as described hereinafter, to provide a 360° 2D panoramic image of the scene, for example around the tank. However, such an arrangement is only capable of providing 2D image capture.

EP0989436 discloses a panoramic 3D camera arrangement comprising faceted plane
30 mirrors cooperating with a plurality of separate cameras. As shown in Figure 2 of the accompanying drawings the faceted mirror 1 has the shape of a pyramid, whose base is a regular polygon having any desired number of sides. The group of cameras 3 is

arranged such that, for each facet, at least two of the cameras 3 capture homologous images from a direction defined by the orientation of the cooperating facet. A full panoramic 3D image may then be formed by “stitching” the individual images together. However, such an arrangement using multiple cameras 3 has the difficulties and problems of matching, synchronisation and alignment as mentioned hereinbefore. Also, the relatively large non-symmetric mirror arrangement 1 is bulky and relatively expensive.

JP11095344 discloses an arrangement similar to that disclosed in EP0989436. However, the arrangement differs in that a single camera is directed towards each facet and each facet is split and angled so that the corresponding camera captures slightly different views from the direction defined by the facet.

JP11095344 also discloses an arrangement as illustrated in Figure 3 of the accompanying drawings. This arrangement comprises a single camera 3 pointing upwardly along the axis of symmetry of a mirror having two separate “conic” sections 3a and 3b. The conic sections are of the same type, for example hyperbolic, but are of different sizes and shapes and are spaced apart vertically and connected together by a section 4 which has no optical function. The camera 3 thus capture a composite image in the form of two circular areas for images reflected from the sections 3a and 3b.

The foci of the two conic mirror sections 3a and 3b are separate in space and this provides a stereo baseline from which a 3D panoramic image may be extracted. However, because the separation between the mirrors is vertical rather than horizontal, the disparity between the separate images is vertical and does not provide a horizontal baseline to permit horizontal stereoscopically related images to be extracted directly. In order to correct this and to provide stereoscopic images with horizontal disparity, additional processing including feature matching has to be performed. Such processing can be unreliable and may leave dark areas in the final images where there is no image data. Also, the captured images are of different sizes and resolutions and are therefore difficult to process together without loss of resolution or loss of quality.

WO03/054625 discloses a 3D camera arrangement as shown in Figure 4 of the accompanying drawings. This arrangement uses three catadioptric cameras 3a, 3b and 3c of the type shown in Figure 6 of the accompanying drawings. The cameras are arranged at the apices of an equilateral triangle and have effective fields of view for image capture illustrated at 5a, 5b and 5c limited by the positions of the cameras. A system of this type is also disclosed by Barton et al, Proc SPIE vol.3835, "Three-dimensional imaging, optical metrology, and inspection V", 1999, p.84-92. However, such an arrangement requires three cameras and has the problems of the optical system matching, synchronisation and alignment as mentioned hereinbefore and, again, is difficult to set up.

Peleg et al, IEEE Transactions on Patent Analysis and Machine Intelligence, vol.23 no.3, March 2001, p.279-90 ISSN: 0162-8828 discloses another technique for capturing panoramic stereoscopic images as illustrated in Figure 5 of the accompanying drawings. This document is mainly concerned with using rotating panoramic cameras and simulations thereof. One of the disclosed techniques uses two spiral shaped mirrors 1a and 1b for use with a single camera to provide capture of a wide field stereoscopic composite image. However, such a mirror arrangement is difficult to make and it is not possible to provide a full 360° panoramic view in a single shot.

According to a first aspect of the invention, there is provided a panoramic three-dimensional adapter for a single optical instrument, comprising a plurality of mirrors, each of which has a reflective surface whose shape is at least part of the shape formed by rotating a curved non-circular conic section about an axis of symmetry and which has a first focus, each first focus being spaced perpendicularly from a longitudinal axis of the adapter, the first foci being angularly spaced around the longitudinal axis.

The reflective surfaces may have substantially the same shapes and sizes.

The first foci may be disposed in a common plane extending perpendicularly to the longitudinal axis.

The first foci may be spaced by substantially the same distance from the longitudinal axis.

The first foci may be substantially equiangularly spaced around the longitudinal axis.

5

The axes of symmetry may converge towards the longitudinal axis. The axes of symmetry may intersect the longitudinal axis substantially at a common point. The common point may be arranged substantially to coincide with the front principal point of a lens of the optical instrument when the adapter is mounted to the instrument. Each
10 of the mirrors may have a convex substantially hyperboloidal reflective surface. As an alternative, each of the mirrors may have a concave substantially ellipsoidal reflective surface. The reflective surface may have a second focus substantially at the common point.

15 The axes of symmetry may be substantially parallel to the longitudinal axis. Each of the mirrors may have a convex substantially paraboloidal reflective surface.

The adapter may comprise a substantially non-reflective shield behind the mirrors.

20 Each of the mirrors may have an edge which extends further from an apex of the reflective surface at a point of the edge furthest from the longitudinal axis than at at least one other point of the edge. The edge of each mirror may be in a plane which is non-perpendicular to the axis of symmetry.

25 Each of the mirrors may be spaced from the or each other mirror. Each mirror may be spaced from the or each adjacent mirror by a distance substantially equal to the mirror radius at the edge thereof.

The adapter may comprise three mirrors.

30

The adapter may comprise four mirrors.

The adapter may comprise a mounting for mounting the adapter to the instrument and connected to the mirrors by a rod extending along the longitudinal axis. The mounting may comprise a plurality of spokes radiating from an end of the rod. The number of spokes may be equal to the number of mirrors. Each plane containing a first focus and
5 the longitudinal axis may substantially bisect the angle between an adjacent pair of spokes.

The adapter may comprise a mounting, for mounting the adapter to the instrument, connected to the mirrors by a substantially transparent cylinder containing the mirrors.
10 The adapter may comprise a substantially non-reflective spike extending along the axis of symmetry from each mirror.

An unused part of each reflective surface may be substantially non-reflective.

15 According to a second aspect of the invention, there is provided a combination of an adapter according to the first aspect of the invention and a single optical instrument.

The adapter may form part of the instrument.

20 The instrument may comprise a camera. The camera may comprise a single lens system. The camera may comprise a single light-sensitive surface.

The combination may comprise a processor for performing a coordinate transformation of the image at the light-sensitive surface to a three-dimensional coordinate frame which
25 is non-coincident with the axes of symmetry. The coordinate frame may be a spherical coordinate frame. The coordinate frame may be an average of the axes of symmetry.

The instrument may comprise a projector.

30 The projector may be arranged to perform anaglyph encoding of left and right images.

It is thus possible to provide an arrangement which is capable of capturing or projecting a panoramic stereoscopic image or sequence of images. In many embodiments, a full 360° horizontal panorama may be captured or projected. Such an arrangement is of the “single shot” type requiring only a single lens or optical system and a single sensor, 5 emulsion film frame, or image generation system so that no optics matching or sensitivity matching is required. Simultaneous homologous images are captured for a full 360° panorama so that, for example, still images of moving scenes may be captured without loss of quality. A camera having this feature is suitable for still recording and video recording.

10

Homologous images of substantially identical sizes and resolution may be captured. Where the system is used to capture horizontal panoramic images, the system is such that only horizontal disparities are present so that no potentially unreliable feature matching or similar processing is required. Instead, global “unwrapping equations” 15 may be used and these are more easily “hard-wired” and are more applicable to “video scenes”. Global unwrapping equations do not depend on distance or size of an object in a scene and may be used because of the single viewpoint condition, which is a consequence of using conic section mirrors. Thus, no object-dependent unwrapping is required so that no object recognition is required.

20

It is possible to provide a relatively simple adapter, which may be used with any standard camera for capturing still or moving images using emulsion film or opto-electronic sensors, for example in high resolution digital cameras or camcorders. Also, a similar or the same adapter may be used with a projector for projecting stereoscopic 25 images to provide panoramic displays. However, the “adapter” may form an integral part of a camera or projector specifically for capturing and displaying panoramic 3D stereoscopic images. Manufacture of the mirrors is relatively easy as all such mirrors may be identical and may be circularly symmetric so that, for example, they may easily be made on a turning machine.

30

The present invention will be further described, by way of example, with reference to the accompanying drawings, in which:

Figure 1 is a cross-sectional view of a known type of 2D panoramic camera;

Figure 2 is a side view of a known type of 3D panoramic camera;

5

Figure 3 comprises diagrammatic perspective and cross-sectional views of a known type of 3D panoramic camera;

Figure 4 is a diagrammatic plan view of a another known type of 3D panoramic camera;

10

Figure 5 is a diagrammatic plan view of a further known type of 3D panoramic camera;

Figure 6 is a cross-sectional diagram of a known type of 2D panoramic camera with a hyperbolic mirror for illustrating the derivation of an unwrapping equation;

15

Figure 7 is a diagrammatic side view of an adapter and camera constituting an embodiment of the invention together with a view looking down on mirrors of the adapter;

20 Figure 8 is a diagram illustrating the derivation of an unwrapping equation for the camera shown in Figure 7;

Figure 9 is a diagram illustrating the relative locations of right and left image views on a sensor of the camera shown in Figure 7;

25

Figure 10a is a diagram illustrating areas of useful data and leakage on a camera sensor for one of the mirrors;

Figure 10b illustrates variation in stereoscopic baseline for different directions;

30

Figure 11a is a diagram illustrating a technique for correcting at least partially for the effect illustrated in Figure 10a;

Figure 11b illustrates an alternative arrangement of non-touching mirrors;

5 Figure 12 shows views similar to Figure 7 of another adapter and camera constituting another embodiment of the invention;

Figure 13 is a diagram illustrating a mirror arrangements of an adapter constituting a further embodiment of the invention;

10 Figure 14 shows various views of mounting arrangements for mounting an adapter to a camera;

Figure 15 is a diagram illustrating a modification of the mirrors shown in Figure 7;

15 Figure 16 is a diagrammatic side view of an adapter and a camera constituting another embodiment of the invention together with a diagram illustrating the derivation of an unwrapping equation;

20 Figure 17 shows diagrammatic side views of adapters and cameras constituting further embodiments of the invention;

Figure 18 is a diagram illustrating an adapter and projector constituting another embodiment of the invention; and

25 Figure 19 illustrates diagrammatically various techniques for encoding left and right views for projection by an arrangement of the type shown in Figure 18.

Like reference numerals refer to like parts throughout the drawings.

30 Figure 6 illustrates the derivation of an unwrapping equation in the case of a simple known type of catadioptric camera system with a convex hyperboloid mirror 1 for a 2D panoramic camera including a conventional or standard camera 3. Such an arrangement

is disclosed, for example, in “Panoramic Vision, Sensors, Theory and Applications”, Ed. Benosman and Kang, Springer, 2001.

The system comprises a convex hyperbolic mirror 1 which is axisymmetric about an axis 9 and with a first focus of the hyperbola at 10. The mirror 1 is disposed above a camera 3 comprising a lens aperture 12 and a charge-coupled device (CCD) sensor 13. The second focus of the hyperbola is located at the principal point 11 of the lens aperture 12. The camera 3 thus “sees” a reflection from the mirror 1 of a scene extending through 360° around the camera axis, which is coincident with the axis of symmetry 9, and with a vertical field dependent on the design of the mirror 1.

It is necessary that the mirror be a conic section with two foci (one of which is at infinity for a paraboloid) because of the property that a light ray incident on one focus will be reflected through the other focus. In the case of a hyperboloid, the far focus is positioned coincident with the front nodal (principal) point 11 of the lens. Thus, the scene on the camera sensor 13 will appear to have been taken from a single point, i.e. the first focus 10 of the hyperboloid. In this case, there is no stereo baseline in the image and thus a simple geometric transformation can be made independent of the scene to reproduce the geometric aspects properly for all objects at different distances from the camera in the resulting panorama. This is known as the single viewpoint condition.

Any curved non-circular conic section can be used in this system; a convex paraboloid mirror can also be used, but this will require a telecentric lens system (principle points at infinity). Also, concave elliptical mirrors can be used, but they have limited vertical field and may be better for downward projection applications. A circular mirror, however, would not be applicable.

In a coordinate system where the lens principle point and far focus 11 of the hyperboloid are coincident and at the origin and the Z axis defines the symmetry axis of the system, the hyperboloid has the surface equation:

$$\frac{\left(\frac{C}{2} - Z\right)^2}{a^2} - \frac{R^2}{b^2} = 1 \quad \text{Eq. 1}$$

where C is the distance between the foci, R is the radial coordinate, and a and b are given by:

5

$$a^2 = \frac{C^2(K-2)}{4K} \quad b^2 = \frac{C^2}{2K} \quad \text{Eq. 2}$$

where K is a modified conic constant defining the shape of the hyperboloid ($K > 2$).

- 10 The unwrapping equations can thus be written simply such that the distance of a point from the axis on the CCD sensor is proportional to $\tan(\phi)$ and is related to the vertical angle of the real world object, θ , by:

$$\tan(\phi) = \frac{K-1 - \sec(\theta)\sqrt{K(K-2)}}{\cot(\theta) - K(K-2)\tan(\theta)}. \quad \text{Eq. 3}$$

15

From this equation, a proper 2D panorama can be constructed.

- Figure 7 illustrates an arrangement for capturing a 3D panoramic set of images permitting full 360° stereoscopic image capture using a single camera 3. This arrangement may comprise a dedicated 3D panoramic camera or may comprise an adapter for adapting a conventional camera to capture 3D panoramic images. The arrangement is shown with a set of three hyperbolic mirrors 1a, 1b, 1c disposed vertically above the camera 3 but other orientations may be used as desired. For example, the camera 3 may be disposed above the mirrors 1a, 1b, 1c or the arrangement may be disposed with the camera optical axis oriented horizontally.
- 20
25

Each of the mirrors 1a, 1b, 1c is axisymmetric about an axis of symmetry 15a, 15b, 15c. The mirrors 1a, 1b, 1c are of identical shapes and sizes and are disposed so as to

touch each other as illustrated at 16 so that the mirrors are effectively arranged at the apices of an equilateral triangle. The first foci are disposed equiangularly around and equidistantly from a longitudinal axis 17 of the adapter. The axis 17 is coincident or coaxial with the optical axis of the lens 12 of the camera 3. The axes of symmetry 15a, 15b, 15c converge towards the camera lens 12 and intersect the longitudinal axis 17 of the adapter at the front principal point of the camera lens 12. The first foci of the hyperbolic mirrors 1a, 1b, 1c are disposed in a plane which is perpendicular to the longitudinal axis 17.

10 The camera 3 may be of any type, for example for capturing single or still images or sequences of moving or video images. Although Figure 6 illustrates the use of a CCD sensor 13, any appropriate light-sensitive device may be used for capturing the or each image. For example, conventional photo-sensitive emulsion film may be used or other types of sensors may be used. Thus, for example, the camera 3 may be a digital camera
15 or a camcorder and may be of conventional type, so that the adapter comprising the mirrors 1a, 1b, 1c is used to allow the capture of stereoscopic 3D panoramic image data in a "single shot" for each image or for each image of a sequence for capturing moving images. Thus, the camera 3 has a single lens (or other optical system) and a single light-sensitive plane and all the image data for each 3D panorama are captured
20 simultaneously by such a camera system.

Each of the mirrors 1a, 1b, 1c maintains the single viewpoint condition separately so that the three images captured by the camera sensor are from three distinct and different viewpoints. Each mirror has a 240° angular field 18 which does not include views of
25 the other mirrors. The three segments can therefore be cut and pasted in to two homologous 3D 360° images because of the separate viewpoints with a baseline which is determined by the mirror foci separation. This results in a 3D image of simultaneous views with horizontal parallax only.

30 Because each mirror 1a, 1b, 1c is tilted at a different angle to the camera 3, each mirror view has to be treated separately. The use of spherical trigonometry to transfer between different axi-symmetric coordinate systems is thus necessary. The conversion

mathematics is still global and the same for all scenes and does not rely on any unreliable feature matching.

The geometry of the conversion mathematics is shown in Figure 8. The definitions of
5 the lines are as follows:

- Line WC defines the axis about which the final image will be produced. It is also the perpendicular to the sensor.
- Line W'C' is parallel with WC passing through the first mirror focus
- 10 • M is the point of intersection of an arbitrary ray from an object with the mirror whose extension passes through the first mirror focus
- F is the focus of the mirror hyperbola
- O is an arbitrary direction defining the zero azimuthal angle.
- P is the ray intersection point with the sensor
- 15 • I is the centre of the mirror image on the sensor
- E is the top edge of the mirror image.
- A and B are arbitrary points on FI and MP, respectively, so that AB is perpendicular to FI
- Line MP defines the ray direction to the sensor
- 20 • Line FI defines the mirror axis of symmetry and the centre of the image circle.
- L is the lens principle point and lies on lines WC, FI and MP.
- O' is a semi-arbitrary point defined within the same plane as A, F and O.
- AB and O'A are both perpendicular to line FI
- The direction M' is defined so that M'F is perpendicular to W'C' and in the same
25 plane as W', C' and M
- MF and FO are both perpendicular to W'C'

and the definitions of the symbols are as follows:

- 30 • Angles WLF, LFC' and ILC are the inclination angle, δ .
- Angle OFM is θ_A'
- Angle LFM is θ .

- Angle C'FM is the world angle θ' .
 - Angle BAO' is ϕ_A
 - Angles MLF and ILP are ϕ
 - Angle CLP is χ
- 5
- Distance IP is the length H
 - Distance IE is the length H_M
 - Angle CIP is χ_A
 - If M is at the edge of the mirror and in the same plane as O, then P is the same as E and the angle MLF is the maximum angle ϕ_0

10

Once the picture is taken of the scene, it is necessary to convert the pixel position of a particular object in the image into an image that conforms to the real-world coordinates. In other words, we wish to relate the image coordinate of a point in one of the circles of
 15 the taken image, defined by a radius H and an azimuthal angle χ_A , to the real world defined by a spherical vertical angle θ' and azimuthal angle θ_A' .

This is done by defining the output image in terms of the real world coordinate (θ', θ_A') and, working backwards to calculate the pixel in the image circle, this corresponds to
 20 (R, χ_A) in pixel coordinates.

The relationships are given by equation group 4, along with equation 3:

$$\cos(\theta) = \cos(\theta')\cos(\delta) - \sin(\theta')\sin(\delta)\cos(\theta'_A)$$

25

$$\cos(\phi_A) = \frac{\cos(\theta') - \cos(\theta)\cos(\delta)}{\sin(\theta)\sin(\delta)}$$

$$\cos(\chi) = \cos(\phi)\cos(\delta) - \sin(\phi)\sin(\delta)\cos(\phi_A)$$

$$H = \sqrt{1 + (\cos(\delta)\sec(\chi))^2 - 2\cos(\delta)\sec(\chi)\cos(\phi)} \quad \text{Eq. 4}$$

$$H_M = \cos(\delta)\tan(\delta + \phi_0) - \sin(\delta)$$

$$R = R_0 \frac{H}{H_M}$$

$$\cos(\chi_A) = \frac{H^2 + \sin^2(\delta) - \cos^2(\delta)\tan^2(\chi)}{2H\sin(\delta)}$$

where R_0 is the radius of the image circle in pixels. This is done for each of the three image circles over the 240° segment of each circle. This produces three 240° images.

5

In order to create a 3D image, each of the three unwrapped 240° segments is “cut” in half vertically as illustrated in Figure 9. The resulting three 120° left hand views are then assembled so as to create one 360° homologous view. Similarly, the three 120° right hand views are assembled, resulting in a full 360° panoramic stereoscopic image.

10

In the embodiment shown in Figure 7, it is typically possible to achieve an angular field of view in a vertical plane on one side of the longitudinal axis of up to 135°. With the orientation illustrated in Figure 7, this can be arranged to extend from substantially directly downwardly to 45° above the horizontal plane.

15

A darkened or substantially non-reflective shield 20 is disposed behind the mirrors 1a, 1b, 1c so as to prevent background light from entering the camera lens 3. Such a shield prevents any light sources behind the mirrors from causing inappropriate exposure settings in cameras equipped with automatic exposure systems. For example, with the camera oriented as illustrated in Figure 7, the shield 20 prevents building lighting, which is typically disposed on ceilings or high up on walls, from undesirably affecting camera exposure settings.

20

As illustrated in Figure 10A, the mathematical mapping from a circular image on the camera sensor to a real world panorama does not match precisely. The ideal mirror image for unwrapping to a rectangular image is illustrated at 21 whereas the useful data on the mirror as illustrated at 22 and this occurs because of the tilting of the axes of symmetry 15a, 15b, 15c relative to the longitudinal axis 17. This is referred to as “artefact leakage” 23 and results in “dark” areas in the corners of each image segment.

As illustrated in Figure 10B the projected stereo baseline varies in length for different azimuth angles. At one extreme as illustrated at 25, the baseline is twice the mirror radius whereas, in the direction illustrated at 26, the baseline is reduced to a minimum of one radius. There is therefore a baseline variation of 50% of the maximum baseline length.

For some applications, these effects are unimportant and do not give rise to unacceptable visual artefacts. However, reducing these effects provides an actual improvement in final image quality and either or both of these effects may be reduced as follows.

Reduction or elimination of the artefact leakage illustrated in Figure 10A may be achieved by restricting the real world angle range and/or by changing the cross-sectional view of the mirrors so that the image of the mirrors on the sensor matches the mapping from a rectangular real world angular range. The latter technique is illustrated in Figure 11A, in which the arrangement at the left hand side of Figure 11A described hereinbefore is changed as illustrated in the right hand side of Figure 11A. In particular, the reflective surface of each mirror such as 1a is modified so that the mirror effectively ends at an edge 30 defined by a plane which intersects the axis of symmetry of the mirror 1a non-perpendicularly. Thus, a point 31 extends further from the mirror apex 32 in the direction of the axis of symmetry than, for example, a point 33 or 34. The resulting useful data match much more closely the ideal data distribution as illustrated at 21 in Figure 11A. The edge 30 of the mirror may be further modified to reduce the artefact leakage.

Figure 11B illustrates the effect of separating the mirrors 1a, 1b, 1c such that they are non-touching. This results in an increased field of view. In the example illustrated where the adjacent pairs of mirrors are separated by a distance substantially equal to the mirror radius at the base thereof, the actual field of view from each camera is 261°, whereas only 240° is actually required. Such an arrangement may thus be used to reduce artefact leakage.

Figure 12 illustrates an adapter and camera comprising four mirrors 1a–1d arranged in a square. In this arrangement, although each mirror provides a 210° field of view, only 180° is needed so that any leakage overlap above 180° does not produce any artefact. Also, the edge of each required angular field is at 45° to the line between the centres as opposed to 30° in the three mirror arrangement illustrated in Figure 11B. Thus, the variation in stereo baseline is reduced from 50% of the maximum value to 29%. Reductions in both artefact leakage and baseline variation are therefore achieved.

Although more than four mirrors may be used, increasing the number of mirrors for a given camera spatial resolution reduces the spatial resolution of each image.

Where three or more mirrors are used, it is possible to capture a full 360° panoramic stereoscopic image. However, if a more restricted angular range in the horizontal plane is sufficient, then two mirrors may be used and this is illustrated in Figure 13. Such an arrangement provides full stereoscopic images over 120° ranges forwards and backwards. In 60° angular ranges to the sides, 2D image data can be captured so that 2D image data are visible over a full 360° angular range in the horizontal plane. In those applications where the restricted 3D image data are acceptable, it is possible to provide a cheaper camera. For example, in security applications, providing image coverage from a wall corner or along a corridor using the front and rear 3D angular ranges will only require a panoramic view which could be provided by two mirrors.

Figure 14 illustrates arrangements for mounting the mirrors 1a, 1b, 1c on the camera lens 3. Each of these arrangements makes use of a mounting 40, which may be of any

suitable type for attaching the adapter in the correct position and orientation on the lens of the camera 3.

5 In the arrangement illustrated in the left diagram of Figure 14, the mounting 40 is fixed to or integral with spokes such as 41, which radiate from and are fixed to or integral with one end of a central stork or rod 42. The rod 42 extends along the longitudinal axis of the adapter and through the middle of the mirrors 1a, 1b, 1c so that its other end is attached to or integral with the mirror mounting arrangement 43.

10 In general, the number of spokes 41 is equal to the number of mirrors, 1a, 1b, 1c and a plane containing the first focus of a respective mirror and the longitudinal axis bisects the angle between adjacent spokes.

The middle diagram in Figure 14 illustrates an alternative mounting arrangement in which the mounting 40 is fixed to the mirror mounting 43 by means of a substantially transparent cylinder 45. Such an arrangement provides protection for the surfaces of the mirrors. However, internal reflections from the cylinder 45 may create ghosting in the captured images as illustrated by the incident ray path 46 and as disclosed in H Ishiguro, "Development of low-costs compact omnidirectional vision sensors", compiled in
 20 "Panoramic Vision", Springer Verlag, 2001, ISBN 0387951113. Such ghosting can be reduced or eliminated by the use of black or non-reflective spikes 46a, 46b, 46c as illustrated in the right hand part of Figure 14. These spikes extend along the axes of symmetry of the mirrors and are convergent towards the principal point of the lens 3 but are not required to extend as far as the principal point.

25

In order to reduce the effects of undesirable reflections, the parts of the mirrors which are not effectively used to form the images may be made non-reflective, for example by being painted matt black. For example, Figure 15 illustrates such blackening of the appropriate areas 50a, 50b, 50c for the three mirror embodiment illustrated in Figure 7.
 30 In this case, the 120° segments of the mirrors facing the longitudinal axis of the adapter are made substantially non-reflective. This also allows processing software for

processing the captured images to determine more easily the centres and radii of the “circular” images formed on the sensor and thus facilitate image processing.

Figure 16 illustrates an adapter and camera which differ from those shown in Figure 7 in that the reflectors 1a, 1b, 1c are concave ellipsoidal reflecting surfaces.

The formulae in this case would then be:

$$\frac{\left(\frac{C}{2} - Z\right)^2}{u^2} + \frac{R^2}{v^2} = 1$$

10

$$u^2 = \frac{C^2(2K'+1)}{4} \quad v^2 = \frac{C^2K'}{2}$$

$$\tan(\phi) = \frac{K'}{(K'+1)\cot(\theta) + \operatorname{cosec}(\theta)\sqrt{(2K'+1)}}$$

15 where K' is a different modified conic constant defining the ellipse shape ($K' > 0$). Equation group 4 still defines the relationship between the tilt angles here.

In a further embodiment as illustrated in Figure 17, convex paraboloidal mirrors may be used. Such mirrors have a first focus, but their second focus is at infinity. In this case, the axes of symmetry of the mirrors are parallel to each other and to the longitudinal axis 17 of the adapter. This requires the use of a telecentric lens system for the camera 3, which may be a large telecentric lens as illustrated at 12a or a custom telecentric triplet lens as illustrated at 12b in order to incorporate the three paraboloid mirrors.

25 The adapter described hereinbefore may also be used with projectors to provide 3D panoramic projection systems and an example of such a system is illustrated in Figure 18. The system comprises a projector 55 of conventional type arranged to project appropriately modified images. For example, the projector may be mounted in or under the floor of a room pointing vertically upwards. An example of a suitable known type

of projector is one which employs a digital micromirror device (DMD) with a colour wheel.

The projector includes a projection lens 56 which directs light upwards and onto a set of
5 conic section mirrors 57, for example disposed on the ceiling of the room. The mirrors
57 reflect light onto a 360° screen or wall 58 for viewing by viewers in the room. Such
a system may be used to provide stereoscopic panoramic images on the screen or wall
58 to be viewed by viewers wearing viewing aids such as spectacles of the appropriate
type. In order for the correct images to be viewed, the images supplied to the DMD or
10 other spacial light modulator or the like in the projector 55 are in a format similar to
those recorded by the cameras and adapters described hereinbefore.

In order for the projected images to be viewed stereoscopically, the left and right images
are encoded so that the viewing aids worn by the viewers can correctly decode the
15 images and ensure that the left and right eye images are visible only to the left and right
eyes, respectively, of each viewer. For example, as illustrated in the left part of Figure
19, the left and right images may comprise red and cyan colour components only for
anaglyph projection. The viewing aids then comprise spectacles with colour filters for
passing only red light to the left eyes and only cyan light to the right eyes of the
20 observers.

Left and right view encoding may alternatively be performed by polarisation encoding
so that the left and right images have orthogonal polarisations and the viewing aids
comprise polarisation analysers. The projection screen 58 is required to be of the
25 polarisation-preserving type. The middle part of Figure 19 illustrates an arrangement
for achieving this and comprises a polariser 60 and a patterned retarder 61 associated
with the projection lens 56. The patterned retarder 61 is arranged to pass all of the parts
of one image with its polarisation unchanged and to convert the polarisation of the parts
of the other image to the orthogonal polarisation.

30

Time-sequential encoding may be used for encoding the left and right views together
with suitably synchronised shutter glasses, for example embodied in liquid crystal

technology. A system which combines this with polarisation encoding is illustrated in the right part of Figure 19. The left and right images are projected time-sequentially and a switchable retarder 65 is switched in synchronism to encode the left and right views with orthogonal polarisations.

CLAIMS:

1. A panoramic three-dimensional adapter for a single optical instrument, comprising a plurality of mirrors, each of which has a reflective surface whose shape is at least part of the shape formed by rotating a curved non-circular conic section about an axis of symmetry and which has a first focus, each first focus being spaced perpendicularly from a longitudinal axis of the adapter, the first foci being angularly spaced around the longitudinal axis.
5
2. An adapter as claimed in claim 1, in which the reflective surfaces have substantially the same shapes and sizes.
10
3. An adapter as claimed in claim 1 or 2, in which the first foci are disposed in a common plane extending perpendicularly to the longitudinal axis.
15
4. An adapter as claimed in any one of the preceding claims, in which the first foci are spaced by substantially the same distance from the longitudinal axis.
5. An adapter as claimed in any one of the preceding claims, in which the first foci are substantially equiangularly spaced around the longitudinal axis.
20
6. An adapter as claimed in any one of the preceding claims, in which the axes of symmetry converge towards the longitudinal axis.
7. An adapter as claimed in claim 6, in which the axes of symmetry intersect the longitudinal axis substantially at a common point.
25
8. An adapter as claimed in claim 7, in which the common point is arranged substantially to coincide with the front principal point of a lens of the optical instrument when the adapter is mounted to the instrument.
30

9. An adapter as claimed in claim 7 or 8, in which each of the mirrors has a convex substantially hyperboloidal reflective surface.
10. An adapter as claimed in claim 7 or 8, in which each of the mirrors has a
5 concave substantially ellipsoidal reflective surface.
11. An adapter as claimed in claim 9 or 10, in which each reflective surface has a second focus substantially at the common point.
- 10 12. An adapter as claimed in any one of claims 1 to 5, in which the axes of symmetry are substantially parallel to the longitudinal axis.
13. An adapter as claimed in claim 12, in which each of the mirrors has a convex substantially paraboloidal reflective surface.
15
14. An adapter as claimed in any one of the preceding claims, comprising a substantially non-reflective shield behind the mirrors.
15. An adapter as claimed in any one of the preceding claims, in which each of the
20 mirrors has an edge which extends further from an apex of the reflective surface at a point of the edge furthest from the longitudinal axis than at at least one other point of the edge.
16. An adapter as claimed in claim 15, in which the edge of each mirror is in a plane
25 which is non-perpendicular to the axis of symmetry.
17. An adapter as claimed in any one of the preceding claims, in which each of the mirrors is spaced from the or each other mirror.
- 30 18. An adapter as claimed in claim 17, in which each mirror is spaced from the or each adjacent mirror by a distance substantially equal to the mirror radius at the edge thereof.

19. An adapter as claimed in any one of the preceding claims, comprising three mirrors.
- 5 20. An adapter as claimed in any one of claims 1 to 18, comprising four mirrors.
21. An adapter as claimed in any one of the preceding claims, comprising a mounting for mounting the adapter to the instrument and connected to the mirrors by a rod extending along the longitudinal axis.
- 10 22. An adapter as claimed in claim 21, in which the mounting comprises a plurality of spokes radiating from an end of the rod.
23. An adapter as claimed in claim 22, in which the number of spokes is equal to the
15 number of mirrors.
24. An adapter as claimed in claim 23, in which each plane containing a first focus and the longitudinal axis substantially bisects the angle between an adjacent pair of spokes.
- 20 25. An adapter as claimed in any one of claims 1 to 20, comprising a mounting, for mounting the adapter to the instrument, connected to the mirrors by a substantially transparent cylinder containing the mirrors.
- 25 26. An adapter as claimed in claim 25, comprising a substantially non-reflective spike extending along the axis of symmetry from each mirror.
27. An adapter as claimed in any one of the preceding claims, in which an unused part of each reflective surface is substantially non-reflective.
- 30 28. A combination of an adapter as claimed in any one of the preceding claims and a single optical instrument.

29. A combination as claimed in claim 28, in which the adapter forms part of the instrument.
- 5 30. A combination as claimed in claim 28 or 29, in which the instrument comprises a camera.
31. A combination as claimed in claim 30, in which the camera comprises a single lens system.
- 10 32. A combination as claimed in claim 30 or 31, in which the camera comprises a single light-sensitive surface.
- 15 33. A combination as claimed in claim 32, comprising a processor for performing a coordinate transformation of the image at the light-sensitive surface to a three-dimensional coordinate frame which is non-coincident with the axes of symmetry.
34. A combination as claimed in claim 33, in which the coordinate frame is a spherical coordinate frame.
- 20 35. A combination as claimed in claim 33 or 34, in which the coordinate frame is an average of the axes of symmetry.
- 25 36. A combination as claimed in claim 28 or 29, in which the instrument comprises a projector.
37. A combination as claimed in claim 36, in which the projector is arranged to perform anaglyph encoding of left and right images.



INVESTOR IN PEOPLE

Application No: GB0507783.9

26

Examiner: Mr Chris Ross

Claims searched: 1-37

Date of search: 28 June 2005

Patents Act 1977: Search Report under Section 17

Documents considered to be relevant:

Category	Relevant to claims	Identity of document and passage or figure of particular relevance
X	1, 28 at least	Applied Optics Vol 36 No 31 1 November 1997 pages 8275-8285 J S Chahl et al "Reflective surfaces for panoramic imaging" Fig 11

Categories:

X	Document indicating lack of novelty or inventive step	A	Document indicating technological background and/or state of the art.
Y	Document indicating lack of inventive step if combined with one or more other documents of same category.	P	Document published on or after the declared priority date but before the filing date of this invention.
&	Member of the same patent family	E	Patent document published on or after, but with priority date earlier than, the filing date of this application.

Field of Search:

Search of GB, EP, WO & US patent documents classified in the following areas of the UKC^X :

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Worldwide search of patent documents classified in the following areas of the IPC⁰⁷

The following online and other databases have been used in the preparation of this search report

Online: WPI, EPODOC