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(54) Title: IMAGE FORMING AND PROCESSING DEVICE AND METHOD FOR USE WITH NO MOVING PARTS CAMERA

(57) Abstract

A video surveillance system (10) has a camera equipped with a fisheye lens (20) having a substantially hemispheric field of view. The system implements operations equivalent to the panning, tilting and zooming of a conventional camera without the use of moving parts. The lens (20) is mounted vertically above a plane under surveillance. The camera produces a fisheye image (14) made up of a plurality of pixels. The fisheye image (14) is distorted due to the properties of the fisheye lens (20). The system corrects the distortion by mapping the pixels of the fisheye image (14) to coordinates produced by selecting a particular part of the fisheye to be viewed.

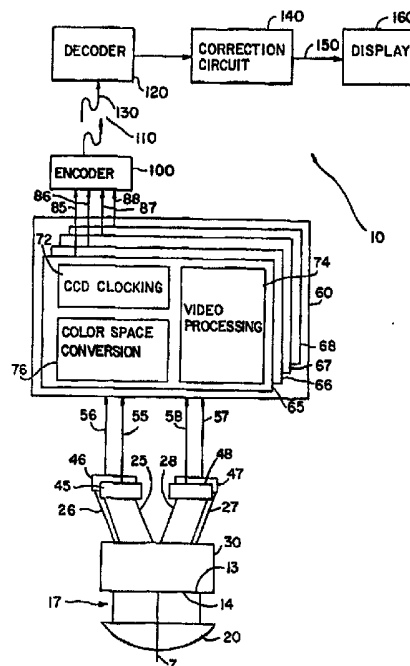


IMAGE FORMING AND PROCESSING DEVICE AND METHOD
FOR USE WITH NO MOVING PARTS CAMERA

BACKGROUND OF THE INVENTION

Field of the Invention:

This invention relates generally to the field of video surveillance systems. More specifically, it relates to an
5 image forming and processing device including a fisheye lens having a substantially hemispherical field of view. The invention allows an operator to view a selected part of the image formed by the fisheye lens as if it were formed by a
10 normal lens by simulating the panning, tilting or zooming of the normal lens. This allows the operations of panning, tilting and zooming to be implemented without the use of moving parts.

Description of Related Art:

Surveillance cameras are commonly used to monitor areas
15 of retail stores, factories, airports and the like. In order to use a single camera to survey a large area, the camera is typically provided with mechanisms to enable it to pan, tilt and zoom. Such mechanisms increase the complexity and hence the cost of the camera and can also adversely affect its
20 reliability. Due to the presence of moving parts, mechanical pan, tilt and zoom devices are subject to damage and degradation brought on by extremes of temperature, moisture and dust. In addition, such mechanical systems consume relatively large amounts of power. A surveillance camera
25 capable of panning, tilting and zooming without the use of moving parts would therefore provide significant advantages over existing surveillance cameras.

In U.S. Patent No. 5,185,667, Zimmermann proposes such a camera having no moving parts. In the device specified in
30 that patent, a fisheye lens is coupled to a video camera such that the camera produces an electronic image. Due to the characteristics of the fisheye lens, the image is distorted. The distortion in the image is corrected by means of an algorithm.

35 One of the limitations of the system proposed by Zimmermann is that the camera is unable to provide sufficient

resolution for effective zooming. Since a fisheye lens renders a distorted image of an entire hemisphere, parts of the image, especially at its peripheries are distorted. The image is formed on a charge coupled device (CCD) having a
5 limited number of pixels. In order to view the image as a normal (non-distorted) image, it is necessary to transform the image electronically. The limited number of pixels in the CCD causes the transformed image to be poorly resolved. In order to provide acceptable resolution, a CCD made of
10 approximately 156,000,000 would be needed.

The best available CCD's have approximately 16,000,000 pixels (4,000 x 4,000) and operate at clocking rates of the order of 10 Mhz. However, in order to satisfy the NTSC sampling rate of 30 samples per second, a clocking rate of
15 480 MHz is needed. Thus, the type of resolution required for an NTSC picture with the desired magnification cannot be achieved using the prior art.

In U.S. Patent No. 5,200,818, Neta et al. describe a system in which a wide angle scene is monitored by means of
20 a plurality of sensor arrays mounted on a generally hemispherical surface. Each sensor array has its own lens system. This allows a wide field to be monitored without the need for moving parts to effect panning and tilting. The resolution of the system would be relatively high due to the
25 plurality of sensor arrays. However a system such as that described by Neta et al. would be very costly to implement due to the large number of high quality components needed.

It is an object of the present invention to provide a surveillance camera apparatus, having a substantially
30 hemispherical field of view and capable of effecting the operations of panning, zooming and tilting without the use of moving parts, while still providing sufficient resolution to allow the desired magnification.

It is a further object of the invention to provide a
35 surveillance camera apparatus, having a substantially hemispherical field which allows an operator to view parts of the field of view as if they were acquired by a camera having a conventional lens and being capable of panning,

tilting or zooming.

These and other advantages are achieved by the invention described herein.

SUMMARY OF THE INVENTION

5

According to the invention there is provided a method of video surveillance comprising the steps of:

providing a video camera having an image plane and a fisheye lens, the fisheye lens having a lens constant indicative of distortion caused by the fisheye lens, a primary
10 axis and a substantially hemispheric field of view and the camera having an image plane, the image plane having a center point through which the primary axis passes;

mounting the camera at a mounting point vertically above a surveillance plane such that the primary axis of the fisheye lens lies substantially perpendicular to the surveillance plane;

15 causing the video camera to form a fisheye image, the fisheye image being distorted by the fisheye lens and comprising a plurality of pixels, each pixel having unique fisheye coordinates;

generating a corrected image of sub-area in the field of view by the steps of:

providing angular coordinates of an object in the field of view by simulating a
20 hypothetical camera having a hypothetical axis and such that the hypothetical axis passes through the center point and the object in the field of view at specific pan and tilt angles;

selecting an area of the fisheye image, wherein the area comprises a subset of
the plurality of pixels, each pixel of the subset being displaced from the specific pan
25 angle by an angle "a";



- 3a -

$$X_d = f \cdot \cos^{-1}(\cos(a) \cdot \cos(b)) \cdot \cos(\tan^{-1}(\tan(a)/\sin(b)))$$

$$Y_d = f \cdot \cos^{-1}(\cos(a) \cdot \cos(b)) \cdot \sin(\tan^{-1}(\tan(a)/\sin(b))),$$

where "f" is the lens constant and X_d and Y_d are the unique fisheye coordinates, and

- 5 mapping the pixels in the subset of the plurality of pixels to normal coordinates, thereby forming the corrected image of the sub-area.

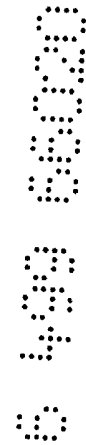
BRIEF DESCRIPTION OF THE DRAWINGS

Fig. 1 is a block diagram of a system embodying the invention;

Fig. 2 is a plan view of the image plane of the fisheye lens showing a distorted

- 10 fisheye image;

Fig. 2A is a diagram of a selected part of the fisheye



image, corrected using the present invention;

Fig. 3 is a perspective view of the image splitter of the invention;

Fig. 4 is a perspective view of the fiber optic bundles in the image splitter;

Fig. 5 is a block diagram of the fisheye distortion correction system of the invention;

Fig. 6 is a diagram showing the projection of a point C at tilt angle b on the Y axis of the image plane as a result of the fisheye distortion;

Fig. 7 is a diagram of the image plane X-Y showing the projection of a point C on the image plane; and

Fig. 8 is a three dimensional diagram showing the primary axis of the fisheye lens, the primary axis of a hypothetical camera panned and tilted to point at point C.

DETAILED DESCRIPTION

The following is a description of the preferred embodiment of the present invention. It is intended to be illustrative of the invention and not limiting. The full scope of the invention is to be determined by the appended claims and their equivalents.

The invention is shown in block diagram form in Fig. 1. Typically the invention is used in the surveillance of premises such as warehouses, stores, bus or train stations and the like. To this end, system 10 is provided with a lens 20 which has a substantially hemispherical field of view, for example a fisheye lens. It is preferable to have an azimuthal view of 180° , a zenithal view of 90° and an infinite depth of field. This produces the desired substantially hemispherical field. The preferred lens is a commercially available equidistant fisheye lens having a focal length of 1.9 mm, and an f stop of 1.8. Lens 20 has a primary axis Z and forms a circular image 14 on image plane 13.

Due to the properties of lens 20, image 14 is distorted. Specifically, the orientation of objects in image 14 is altered relative to their real orientation. For example, an object 11 in the field of view of lens 20 (See Fig. 8) will

appear on the periphery of image 14 in distorted form as shown in Fig. 2.

Image 14 is preferably split into four separate components by splitter 30. Image 14 could be split into any
5 number of components, depending on the resolution required and the available technology. When image 14 is split into four components, each component respectively contains an image 15, 16, 17 or 18 made up of one quadrant of circular image 14. (See Fig. 2). Splitter 30 is made up of four
10 light conduits 25, 26, 27 and 28. Light conduits 25, 26, 27 and 28 respectively contain coherent fiber optic bundles 35, 36, 37 and 38 (See Fig. 4). Images 15, 16, 17 and 18 are thus respectively carried in conduits 25, 26, 27 and 28 by fiber optic bundles 35, 36, 37 and 38.

15 Splitter 30 is shown in greater detail in Figs. 3 and 4. Splitter 30 is made up of a housing 32 to which are attached conduits 25, 26, 27 and 28. Optical fiber bundles 35, 36, 37 and 38 housed in conduits 25, 26, 27 and 28 respectively, branch off from a major bundle of fibers, terminating at
20 image plane 13 in a polished surface. See Fig. 4. Optical fiber bundles 35, 36, 37 and 38, are each made up of a plurality of optical fibers. Each optical fiber carries a sample of image 14 formed by fisheye lens 20 and has a diameter of approximately 10 μm .

25 Images 15, 16, 17 and 18 respectively travel along each of conduits 25, 26, 27 and 28 and impinge respectively upon sensors 45, 46, 47 and 48. Sensors 45, 46, 47 and 48 are 768 x 480 CCD's with fiberoptic windows formed from a fiberoptic faceplate which allows for direct coupling of the CCD's to
30 the optical fibers. Suitable fiberoptic faceplates are available from Galileo Electro-optics Corporation of Sturbridge, Massachusetts under the name "CP Series." Images 15, 16, 17 and 18 are respectively converted by the sensors into representative electrical signals 55, 56, 57 and 58.

35 Signals 55, 56, 57 and 58 are fed into CCD control processor 60 which is made up four identical off the shelf video camera sensor image controllers 65, 66, 67 and 68, each corresponding respectively to one of signals 55, 56, 57 or

58. Each of the control processors contains a CCD clocking circuit 72, a video processing circuit 74 and a color space converter 76. Color space conversion circuit 76 produces chrominance and luminance signals Cr, Cb and Y for each signal 55, 56, 57 and 58.

Control processors 65, 66, 67 and 68 respectively produce video outputs 85, 86, 87 and 88 in the form of luminance and chrominance components suitable for compression by encoder 100. Compression of the video signals 85, 86, 87 and 88 allows a very large number of image samples to be transmitted over a channel having limited bandwidth. The video outputs are therefore compressed if the lens is at a location remote from correction circuit 140. Encoder 100 compresses the video signals 85, 86, 87 and 88 by compressing them in accordance with a compression scheme, for example, MPEG or H. 261. Alternatively, a sub-band coding scheme can be used. Encoder 100 packetizes the video signals into a serial data stream for transmission over high speed network 110 such as coaxial cable or optical fibers. The compressed video signals are received by decoder 120 which performs a transform on the compressed video signals which is the inverse of the transform performed by encoder 100.

Decoder 120 produces a decoded video signal 130 which is fed into correction circuit 140. The purpose of correction circuit 140 is to correct the distortion introduced by fisheye lens 20. This correction is performed in accordance with the algorithm described below. Correction circuit 140 produces a corrected signal 150 which is displayed on display 160.

The following is a description of the system for correcting the fisheye distortion of image 14. For the sake of simplicity, it will be assumed that the entire fisheye image 14 is formed on the surface of a single CCD 180 and that splitter 30 is not used. CCD 180 has axes X and Y. Lens 20 is mounted at a mounting point 17 vertically above surveillance plane 19, preferably such that principal axis Z is perpendicular to surveillance plane 19. Surveillance plane 19 is the floor of a room 15. Mounting point 17 is on

the ceiling of room 15. Axes X, Y and Z intersect at center point I on the surface of CCD 180. The surface of CCD 180 forms image plane 13 which is parallel to surveillance plane 19.

- 5 Mounting the camera and fisheye lens above the surveillance field (i.e. on ceiling rather than on a wall) has several advantages. Firstly, with the camera on the ceiling, the field of view covers a full 360°. This allows the simulation of a pan through 360° rather than a pan range
10 limited by the presence of the wall. In the case of a ceiling mounted lens, the hypothetical (simulated) pan axis is the primary axis Z of the fisheye lens, rather than an axis perpendicular to the primary axis in the case of a wall mounted lens. The angle about the primary axis Z is
15 maintained from the object to the image. This facilitates the calculation of radial coordinates because the pan axis is already in radial form and no conversion is needed.

When any object is viewed on monitor 240, the vertical center line of the image intersects the center point I of the
20 image plane. The primary axis Z of the lens passes through this center point. There is therefore no need to rotate the images to view them in their correct orientation. In the correction algorithm set forth in U.S. Patent No. 5,185,667, rotation of the image is separately calculated. Such a
25 separate operation is not needed with the present invention.

When the lens is placed on a wall, objects of interest and objects which are furthest away tend to be at the center of the fisheye image. The greatest resolution is needed to view the details of those objects. When the fisheye lens is
30 placed vertically above the surveillance plane, objects in the center are usually closest to the lens. Viewing of such objects does not require high resolution and those objects are the least distorted. Objects which are furthest away from the lens appear at the peripheries of the fisheye image.
35 However, the image formed by a fisheye lens has a higher density and therefore a lower CCD image resolution at the center than at its peripheries. Consider a part of a fisheye image having a radius of "R." The density of the

pixels in the CCD on which the image is formed is uniform. Along a line passing through the center of the CCD, the image is spread over $2R$ pixels. At the circumference of the image, the image is spread over πR (half the circumference) - $\pi/2$ more pixels than for objects appearing at the center of the image. Thus placing the lens vertically above the surveillance plane provides far better resolution for distant objects than if the lens is placed perpendicular to the surveillance plane.

The following description refers to Fig. 5. Fisheye lens 20 has a 180 degree field of view covering area "A." With lens 20 is mounted on the ceiling of room 15, area A includes the floor and walls of the room. Fisheye lens 20 forms a fisheye image A_d of area A on image plane 13. Any point in area A represented by unique coordinates $(x;y)$, is displaced to point $(x_d;y_d)$ in the fisheye image A_d in accordance with the characteristics of fisheye lens 20. Image plane 13 (the surface of CCD 180) is made up of a matrix comprising a plurality of pixels 182. Each pixel has unique fisheye coordinates. CCD thus produces an electronic representation of area A. This representation is fed into CCD control processor 250 (identical to control processor 60) which produces chrominance and luminance values for each pixel in CCD 180. Those chrominance and luminance values are stored in dual ported image memory ("DPIM") 200. The present invention allows the user to manipulate the fisheye image electronically in order to implement the operations of panning, tilting and zooming. Thus a sub-area α of area A can be examined in detail by the transformation of sub-area α_d of area A_d from a distorted fisheye image into a normal image.

When the system is powered up a default corrected sub-area α_c appears on monitor 240. The user selects sub-area α by means of area select unit 210 - a control station having a keyboard and a pointing device. This is done by using pointing device 214 to simulate the panning and a tilting of a hypothetical conventional camera. The image on monitor 240 appears to have been formed by a conventional camera. In

reality, it is formed by correction of part of fisheye image 14. The selection of sub-area α provides the normal (non-fisheye) coordinates of an object in the center of sub-area α . This operation simulates the pointing of the primary axis 5 (IC in Fig. 8) of hypothetical conventional camera at the object. The hypothetical camera is mounted at mounting point 17 with its primary axis IC passing through center point I and through the center of sub-area α . Pointing this hypothetical camera by means of input device 214 such that a 10 sub-area α appears on monitor 240 also causes area select unit 210 to generate the pan and tilt angles which would be associated with the hypothetical camera positioned at hypothetical pan and tilt angles so that it points at an object in sub-area α .

15 When the user selects sub-area α the system automatically converts α_d (the distorted fisheye image of area a) into a corrected image α_c . This allows the user to view the sub-area α on monitor 240 as if it were formed by the hypothetical (non-fisheye) camera which had been panned and 20 tilted to point at sub-area α .

Each of the pixels in the fisheye image A_d is stored at a unique address in DPIM 200 in the form of the intensity and color data generated by CCD 180 via control processor 250. DPIM 200 thus contains a digital electronic representation of 25 the distorted fisheye image A_d of area A. For any sub-area α of area A, DPIM 200 contains an electronic representation of the corresponding distorted sub-area α_d .

Image plane 13 is the plane formed by the X and Y axes as shown in Figs. 6, 7 and 8. Primary axis Z of lens 20 is 30 perpendicular to the X and Y axes. If a user wished to view in detail the scene centered around point C (i.e sub-area α -the image shown in Fig. 2) with a hypothetical non-fisheye lensed camera, the user would instruct the camera to tilt by an angle b relative to the primary axis Z. Doing so would 35 orient the hypothetical camera such that the hypothetical primary axis (center line IC) passes through the center point I of image plane 13 and through point C.

Had it been captured by the hypothetical conventional



camera, area a would appear on CCD 180 as an image 300 centered at line 320 and made up of a large number of horizontal lines of pixels 310. (See Fig. 2A). Each pixel on a particular horizontal line is displaced from center line 320 by a particular distance x. That distance corresponds to an angle "a" relative to center line IC (See Fig. 8) or angle a' about primary axis Z.

Each pixel in image 14 can be described by reference to a set of rectangular or polar coordinates. Thus, referring to Figs. 7 and 8, the pixel at point C on center line IC can be located by reference to polar coordinates in the form of tilt angle b (See Fig. 6) and angle a - the displacement of the pixel from center (for point C, a is equal to zero since C lies on the X axis). Similarly, moving along a horizontal line in CCD 180 (i.e., moving parallel to the Y axis), a pixel at point S can be described by reference to tilt angle b' relative to principle axis Z and pan angle a' relative to center line IC. The corresponding rectangular coordinates are x_d and y_d .

Referring again to Fig. 2, it can be seen that due to the nature of the fisheye lens, the fisheye image is distorted. Objects located close to the principal axis of fisheye lens 20 appear on CCD 180 substantially normally (See area 182), whereas, objects further from the principal axis are progressively more distorted (See area 184). The information carried by a pixel located at point (x;y) in a non-fisheye image will, in the fisheye image, be located at $(x_d;y_d)$, where $(x_d;y_d)$ are displaced from (x;y) by an amount dependent on the properties of fisheye lens 20.

It is a fundamental property of a fisheye lens that the image of a point located at an angle of rotation b' relative to the primary axis will be projected on the image plane a radius r from the primary axis in accordance with the formula:

$$r = f.b'$$

where r is the distance from center point I;

f is a lens constant in mm/radian indicative of the distortion caused by the fisheye lens; and



b' is the angle of an incident ray from an object to the primary axis (in radians).

It is also a fundamental property of a fisheye lens that the angle from a point in the field of view to its projection
5 on the image plane is maintained.

These two properties are used to derive a new formula which allows selected parts of the fisheye image to be viewed as if they were formed by a conventional camera panned, tilted or zoomed in on an area of interest in the field of
10 view. This formula relates the pan and tilt angles of a hypothetical camera described above to the rectangular coordinates of a corrected image. The following is a description of how that formula is derived and applied to achieve the objects of the invention.

15 From Fig. 6 it can be seen that a point C located at a tilt angle b relative to the principal axis of the lens forms an image on image plane IP at a radius $r=r_c$ from center point I. As stated above, for a particular fisheye lens, the relationship between tilt angle b and the radius at which the
20 image of point C forms is:

$$r=f.b.....(1)$$

In Fig. 8, point C lies in the plane formed by the Y and Z axes and at a tilt angle of b relative to the primary axis Z. The line IC from the center I of the image plane to point
25 C is taken as the primary axis of a hypothetical camera lens pointed at point C. Line CS extends from point C to a point S. CS is parallel to the X axis. CS thus represents a horizontal line of pixels in CCD 180. Consider a pixel at S, at a particular radius r from I, the center of the CCD,
30 and at a pan angle " a " about the primary axis of the hypothetical camera lens and at a tilt angle b' relative to the primary axis of the fisheye lens. The rectangular coordinates of that pixel are:

$$X=f.b'.\cos(a').....(2)$$

35 $Y=f.b'.\sin(a').....(3)$

Equations (2) and (3) convert the polar coordinates of any particular pixel of the fisheye image formed on CCD to rectangular coordinates. The pixel at point S can therefore

be located by reference to tilt angle b' (an angle measured off the principal axis Z) and pan angle a' (the angle of rotation around the principal axis Z).

When the system powers up a default area a is displayed, corresponding to the initial area at which the hypothetical camera is pointing. For convenience, this area lies along the primary axis Z (so the tilt angle b is zero). The pan angle is also zero (i.e., line IC lies along the X axis). The hypothetical camera (with the primary axis of its lens lying along line IC) is then tilted by an angle of " b " relative to the primary axis Z of the fisheye lens so that it points at an object centered at point C . In order to make the operation of the correction system transparent to the user, the panning and tilting of the hypothetical camera is measured relative to the initial position of the hypothetical camera. Thus, the position of a pixel representing a point at S will be expressed in terms of tilt angle " b " and the angle of point S from center line IC - angle " a " the amount of pan from center line IC to point S .

The following is a description of the manner in which the position of a pixel representing point S in the fisheye image can be described by reference to angle a - its displacement from the center line IC and angle b - the tilt angle of a hypothetical normal camera panned and tilted so that it's principal axis is aligned with point C .

Referring to Fig. 8, it is seen that

$$\tan(a') = SC/PC$$

$$SC = IS \cdot \sin(a)$$

$$PC = IC \cdot \sin(b)$$

$$IC = IS \cdot \cos(a)$$

$$\begin{aligned} \text{therefore } \tan(a') &= IS \cdot \sin(a) / IS \cdot \cos(a) \cdot \sin(b) \\ &= \tan(a) / \sin(b) \end{aligned}$$

$$a' = \tan^{-1}(\tan(a) / \sin(b)) \dots \dots \dots (4)$$

$$\cos(b') = IP/IS$$

$$IP = IC \cdot \cos(b)$$

$$IC = IS \cdot \cos(a)$$

$$\begin{aligned} \text{therefore } \cos(b') &= IS \cdot \cos(a) \cdot \cos(b) / IS \\ &= \cos(a) \cdot \cos(b) \end{aligned}$$

$$b' = \cos^{-1}(\cos(a) \cdot \cos(b)) \dots \dots \dots (5)$$

From equations (2) and (3), for a given fisheye lens, $X_d = fb' \cos(a')$ and $Y_d = fb' \sin(a')$. Substituting the values of a' and b' from equations (4) and (5) into equations

5 (2) and (3):

$$X_d = f \cdot \cos^{-1}(\cos(a) \cdot \cos(b)) \cdot \cos(\tan^{-1}(\tan(a)/\sin(b))) \dots (6)$$

$$Y_d = f \cdot \cos^{-1}(\cos(a) \cdot \cos(b)) \cdot \sin(\tan^{-1}(\tan(a)/\sin(b))) \dots (7)$$

These formulas allow the coordinates of the pixels centered around center line IC to be calculated simply from
10 knowledge of angular coordinates in the form of the tilt angle "b" of a hypothetical camera (a measure of the distance of the point from the center of the fisheye image) and the angle "a" of a pixel relative to center line IC. This formula provides a very simple means for effectuating
15 panning, tilting and zooming from the fisheye image.

To effect panning of the hypothetical camera, pan angle p is added to angle a' to form new angle a'' . Thus, $a'' = p + a'$.

Substituting this into equation (4) gives:

$$20 \quad a'' = p + \tan^{-1}(\tan(a)/\sin(b)) \dots \dots \dots (8)$$

Substituting equation (a) into equations (6) and (7):

$$X_d = f \cdot \cos^{-1}(\cos(a) \cdot \cos(b)) \cdot \cos(p + \tan^{-1}(\tan(a)/\sin(b)))$$

(9)

$$25 \quad Y_d = f \cdot \cos^{-1}(\cos(a) \cdot \cos(b)) \cdot \sin(p + \tan^{-1}(\tan(a)/\sin(b)))$$

(10)

As pointing device 214 is moved to simulate panning and/or tilting of the hypothetical camera, the rectangular coordinates (X;Y) of each pixel in each line of pixels in sub-area α are generated by area select unit 210 and stored
30 in look-up table ("LUT") 222. The system also automatically calculates the coordinates ($X_d; Y_d$) of the fisheye image from the using equations (9) and (10). For each set of normal coordinates (X;Y) in sub-area α , the calculated coordinates ($X_d; Y_d$) are stored in LUT 222 as addresses in DPIM 200.

35 All of the coordinates for the fisheye image could be pre-calculated or only the coordinates for a particular area need be calculated as the area is selected. In either case, the coordinates are stored in LUT 222 and the corresponding

pixels are stored in DPIM 200. This allows the pixels corresponding to those calculated coordinates to be fetched from CCD 180. The fetched pixels are then displayed on monitor 240 at locations (X;Y) just as if the image had been
 5 formed by the panning and tilting of a normal camera to coordinates (X;Y).

Zooming can be accommodated by varying the amount that angle a is incremented between pixels and the amount b is incremented between rows when calculating the contents of LUT
 10 222. For example, if there are 400 pixels on a horizontal display line and a is incremented from -20° for the left side of the display in steps of .1°, a 40° horizontal field of view will result. Likewise, to display a 30° vertical field of view that would correctly maintain the 4:3 aspect ratio of
 15 a standard display, the 483 display lines would be obtained by incrementing b by .062° between each horizontal display line.

The contents of LUT 222 and DPIM 200 are represented in the following table:

TABLE I

ADDRESS SEQUENCE FOR BOTH DATA STRUCTURES	FEA GENERATOR LUT CONTENTS	DUAL PORT MEMORY CONTENTS
Starting Address	Address of 1st pixel of 1st row	1st pixel 1st row
Starting Address + 1	Add. of 2nd pixel of 1st row	2nd pixel 1st row
.	.	.
.	.	.
.	.	.
Starting Address + H	Add. of 1st pixel of 2nd row	1st pixel 2nd row
Starting Address + H + 1	Add. of 2nd pixel of 2nd row	2nd pixel 2nd row
.	.	.
.	.	.

	Starting Address + 2H	Add. of 1st pixel of 3rd row	1st pixel 3rd row
5	Starting Address + 2H + 1	Add. of 2nd pixel of 3rd row	2nd pixel 3rd row
	.	.	.
	.	.	.
10	.	.	.

H = Number of pixels per line in display processor.

By retaining multiple images in DPIM 200, a historical log of images over time can also be stored. The oldest image is continually overwritten with the current image as the memory capacity is exceeded, thus maintaining a revolving log of images generated over a predetermined time period. Thus, by appropriate selection of an address in DPIM 200 by fisheye address generator, images captured in the preceding predetermined time interval can be displayed when an alarm event occurs (e.g. an intruder attempting to enter the monitored premises and triggering a sensor).

Using a 360 degree image, this system implements the operations of panning and tilting without any moving parts.

This increases the reliability of the camera while limiting the cost of acquiring and maintaining it. The invention thus enables the monitoring of a large area by means of a single camera covering a wide field of view.

The claims defining the invention are as follows:

1. A method of video surveillance comprising the steps of:

providing a video camera having an image plane and a fisheye lens, the fisheye lens having a lens constant indicative of distortion caused by the fisheye lens, a primary axis and a substantially hemispheric field of view and the camera having an image
5 plane, the image plane having a center point through which the primary axis passes;

mounting the camera at a mounting point vertically above a surveillance plane such that the primary axis of the fisheye lens lies substantially perpendicular to the surveillance plane;

10 causing the video camera to form a fisheye image, the fisheye image being distorted by the fisheye lens and comprising a plurality of pixels, each pixel having unique fisheye coordinates;

generating a corrected image of sub-area in the field of view by the steps of:

providing angular coordinates of an object in the field of view by simulating a



15 hypothetical camera having a hypothetical axis and such that the hypothetical axis passes through the center point and the object in the field of view at specific pan and tilt angles;



20 selecting an area of the fisheye image, wherein the area comprises a subset of the plurality of pixels, each pixel of the subset being displaced from the specific pan angle by an angle "a";



determining the unique fisheye coordinates of each pixel of the subset of the plurality of pixels by means of a formula comprising the lens constant, the specific tilt angle "b" and the angle "a", said formula being given by



$$X_d = f \cdot \cos^{-1}(\cos(a) \cdot \cos(b)) \cdot \cos(\tan^{-1}(\tan(a)/\sin(b)))$$

$$Y_d = f \cdot \cos^{-1}(\cos(a) \cdot \cos(b)) \cdot \sin(\tan^{-1}(\tan(a)/\sin(b))),$$

where "f" is the lens constant and X_d and Y_d are the unique fisheye coordinates, and

- 5 mapping the pixels in the subset of the plurality of pixels to normal coordinates, thereby forming the

8
9
0
1
2
3
4
5
6
7
8
9
0



corrected image of the sub-area.

2. The method of claim 1 wherein the specific tilt angle is taken relative to the primary axis of the fisheye lens.

5 3. The method of claim 1 wherein the specific pan angle is taken relative to a prior pan angle about the primary axis.

4. The method of claim 1 wherein the step of mapping the pixels in the subset to the normal coordinates comprises
10 the steps of:

providing a lookup table containing sets of pre-calculated coordinates calculated in accordance with the formula such that for each pixel in the subset of the plurality of pixels there is a corresponding set of angular
15 coordinates, and such that for each set of angular coordinates, there is a set of pre-calculated pixel coordinates;

providing the angular coordinates to the lookup table and in response, causing the lookup table to output the
20 pre-calculated pixel coordinates.

5. The method of claim 4 further comprising the steps of:

storing the plurality of pixels in an image memory, at addresses corresponding to the pre-calculated coordinates,
25 providing the pre-calculated coordinates to the image memory and receiving as an output from the image memory, the pixels in the subset of the plurality of pixels.

6. The method of claim 1 wherein the step of providing the angular coordinates of the object comprises the step of
30 receiving the specific pan and tilt angles via a user input.

7. The method of claim 1 wherein the angular coordinates are polar coordinates and further comprising the step of converting the polar coordinates into the specific pan and tilt angles.

8. The method of claim 1 wherein the step of providing the angular coordinates of the object comprises the step of selecting an area on a video display and calculating the specific pan and tilt angles of the object based on cartesian coordinates of the sub-area.

5

9. The method of claim 1 further comprising the step of displaying the corrected image of the sub-area.

10. The method of claim 1 further comprising the step of zooming the corrected image.

11. The method of claim 10 wherein the step of zooming comprises incrementing angle "a".

12. A method of video surveillance substantially as herein described with reference to the accompanying drawings.

DATED this Twenty-fourth Day of March, 1999

Sensormatic Electronics Corporation

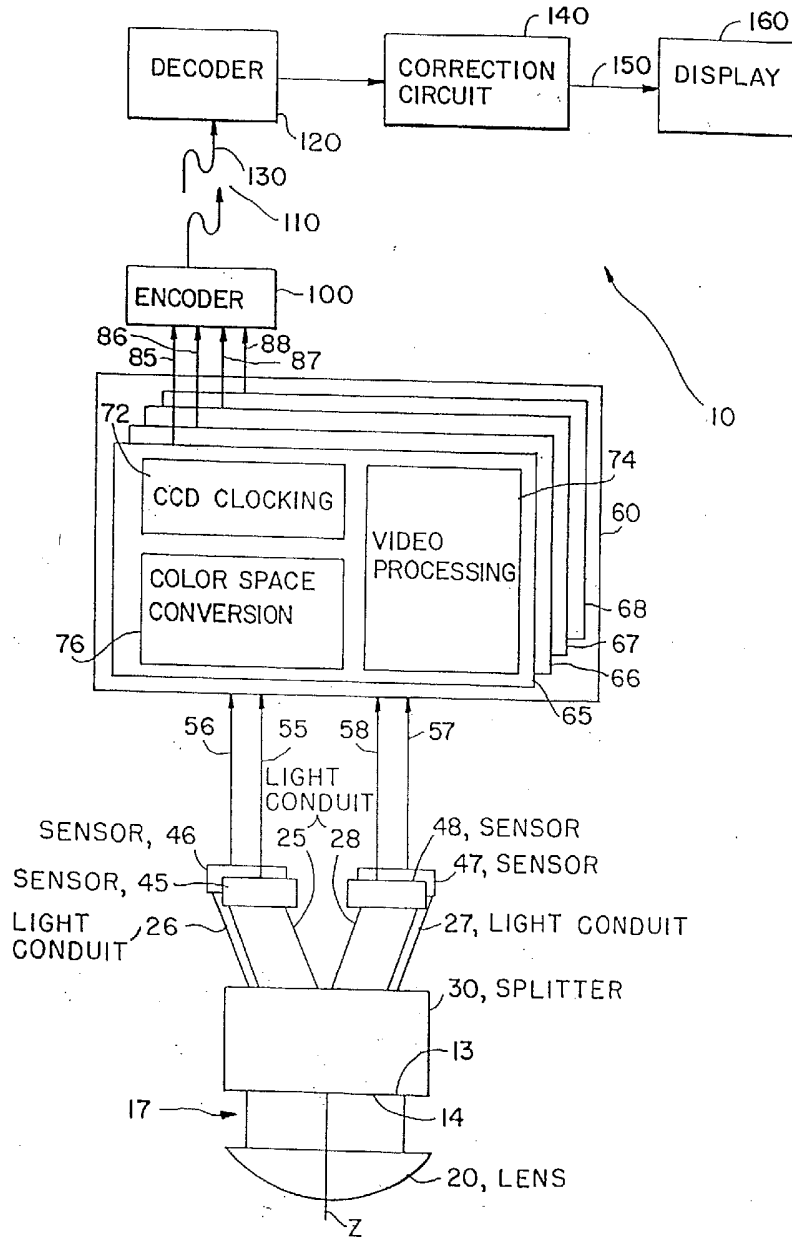
Patent Attorneys for the Applicant

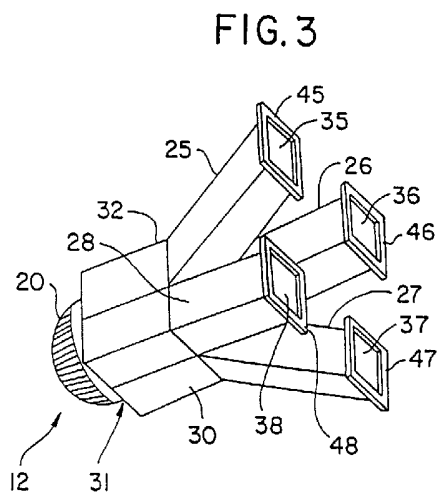
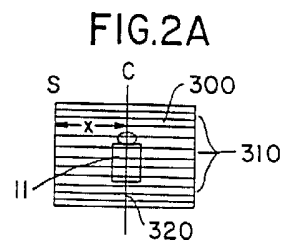
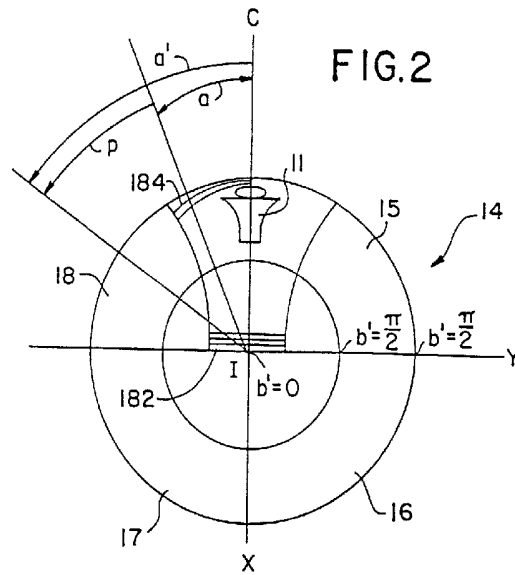
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FIG. 1





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FIG. 5

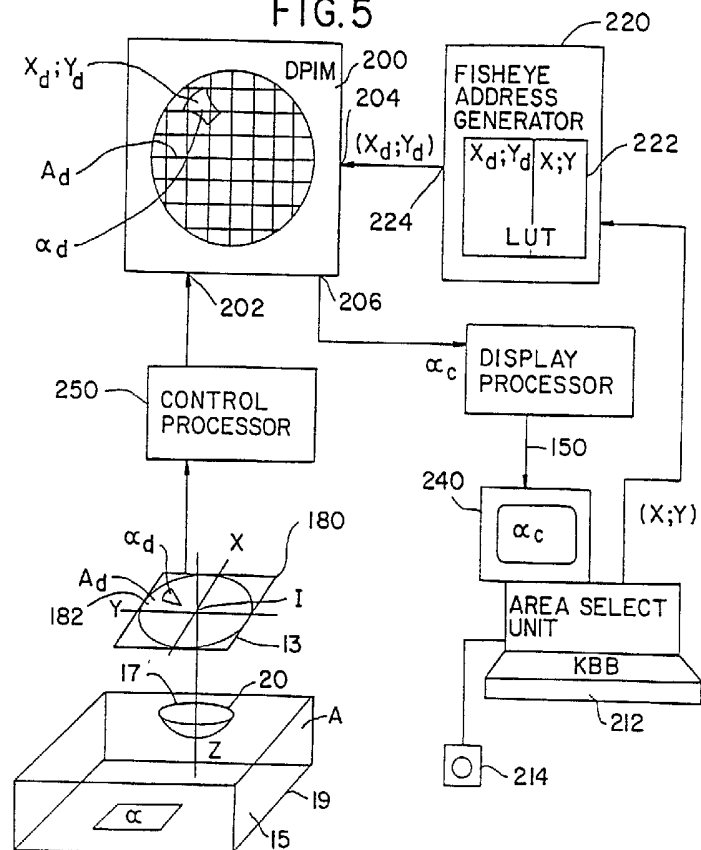
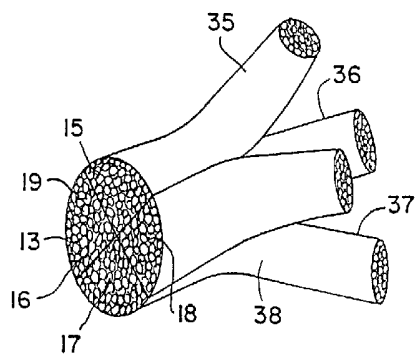


FIG. 4



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FIG.6

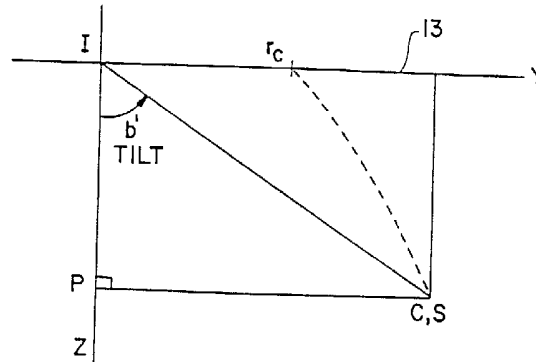


FIG.7

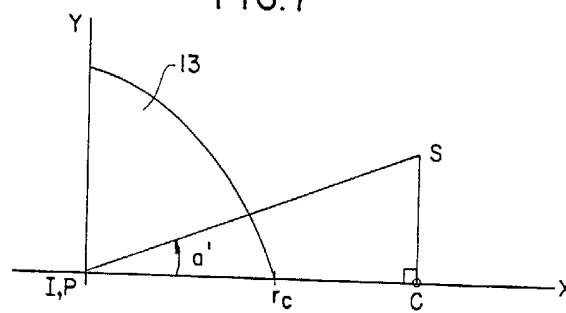


FIG.8

