

로봇 팔에 부착된 카메라를 이용한 3차원 측정 방법 (Axial Motion Stereo Model)

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Abstract

This paper describes a method of extracting the 3-D coordinates of feature points of an object from two images taken by one camera. The first image is from a CCD camera before approaching the object and the second image is from the same camera after approaching the object along the optical axis.

In the two images, the feature points appear at different position on the screen due to image enlargement. From the change of positions of feature points their world coordinates are calculated. In this paper, the correspondence problem is solved by image shrinking and correlation.