In almost every service-robotics task, that requires cooperating with people or working in human environment, one of the key aspects is object recognition. In contrast to structured factory environments, where objects are placed in specific places (e.g. on conveyors) objects in house may be placed virtually anywhere. They can be also occluded (by other objects), distorted (e.g. creased box or bag) or deformed in anyway. Thus, robust object recognition methods are required.

A lot of objects, that people cope with every day, contain distinct texture. For textured objects the existing recognition and localization methods rely on matching feature point sets of object's model to the points extracted from current scene. There is, however, crucial problem in this approach – measurement distortions (scaling, rotation, perspective). Current algorithms cope with some of those problems, but there are no universal methods for distortion removal in object recognition task. The biggest problem is, undoubtedly, perspective distortion. In case, when measurements are supplemented with depth maps (aligned with color image) it is possible to calculate surface characteristics of the object around the keypoint. This information can then be used to apply perspective correction either to image itself or, if possible, inside feature descriptor algorithm. This additional step, in general, can be applied to any RGB descriptor, making them robust against perspective distortions and, as a result, making object detection and localization algorithms work better.

Research in the project will start from recreation of already carried out feasibility studies (described in following section) and creation of initial algorithm version working with planar or nearly planar surfaces. Next, more surface types will be added, with spherical and cylindrical for example. For every surface types mathematical models of reprojection to camera frame and rejection of unstable points will be created. In parallel to those tasks, preparation of testing environment will be carried out. This includes preparation of simulator and gathering multiple test images (extension of object database). Last task is algorithms testing itself. This will be interleaved with theoretical and implementation works.