

Temporal shape super-resolution by intra-frame motion encoding using high-fps structured light

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Abstract

One of the solutions of depth imaging of moving scene is to project a static pattern on the object and use just a single image for reconstruction. However, if the motion of the object is too fast with respect to the exposure time of the image sensor, patterns on the captured image are blurred and reconstruction fails. In this paper, we impose multiple projection patterns into each single captured image to realize temporal super resolution of the depth image sequences. With our method, multiple patterns are projected onto the object with higher fps than possible with a camera. In this case, the observed pattern varies depending on the depth and motion of the object, so we can extract temporal information of the scene from each single image. The decoding process is realized using a learning-based approach where no geometric calibration is needed. Experiments confirm the effectiveness of our method where sequential shapes are reconstructed from a single image. Both quantitative evaluations and comparisons with recent techniques were also conducted.

1. Introduction

Active depth imaging systems for capturing dynamic scenes have been intensively investigated in response to strong demands from various fields. Previous work on dynamic scene-capture mainly used light projectors which project a static structured light pattern onto the object. Recently, time of flight (TOF) sensors have improved the capability of real-time and high resolution capturing [13]. However, from the wide variety of real-time 3D scanning systems available, including commercial products, it is still a difficult task to realize high-speed 3D scans of fast-moving objects. One main reason for this difficulty comes from severe limitations on the light intensity of pattern projectors to sufficiently expose all the pixels of the image sensor in a short period of time. This is a common problem for all active scanning systems including both structured light and TOF sensors. Another reason is that it is still not common for imaging sensors to be capable of high speed capturing due to hardware limitations.

On the other hand, based on recent progress on pre-

cision devices fundamental to Digital Light Processing (DLP) technology, such as micro-electromechanical systems (MEMS), extremely high fps (e.g. 10,000fps) is readily available. Therefore, in general, the switching speed of patterns on a projector is much faster than that of a camera. Based on this fact, we propose a new solution to reconstruct 3D shapes of fast moving objects by projecting multiple patterns onto the object with a higher fps than that of a camera. Since it is possible to alter patterns with extremely high fps, the projected pattern on a moving object is not easily blurred out and a sharp patterns are effectively preserved (Fig. 1(b)). By using these sharp patterns with our reconstruction algorithm, not only a single shape, but also sequential shapes can be recovered; we call this temporal shape super-resolution.

The basic idea of a reconstruction algorithm is straightforward; we simultaneously search the depth as well as the velocity of the object's surface in order to best describe the captured image for each pixel by synthesizing the image using an image database which is captured in advance. This is a multi-dimensional search of all pixels and the calculation time becomes enormous if brute-force search is applied. To reduce the computational time, we first obtain initial depth and velocity estimation under constant velocity assumption, then, we refine the estimation allowing varying velocities.

Several experiments were conducted using an off-the-shelf DLP projector module [24] to confirm the effectiveness of our method with quantitative and qualitative evaluation, proving that our system can recover the shape of a fast moving object with better accuracy than previous techniques. This paper proposed the following:

1. Multiple patterns projected into a single frame to encode both depth and motion information, in order to recover sequential shapes of fast moving objects from a single captured image.
2. Learning-based reconstruction algorithm to avoid geometric calibration as well as efficient search algorithm to reduce calculation time.
3. An actual system be built with an off-the-shelf DLP projector module with an ordinary camera to realize 1,800fps reconstruction. Note that no special setup, synchronization nor extra devices are required.

In section 2, we explain the related work. Then, in section 3, system configuration and overview of the algorithm are explained followed by a detailed explanation in section 4. Finally, we evaluate the accuracy of the method followed by limitations, and conclude the paper.

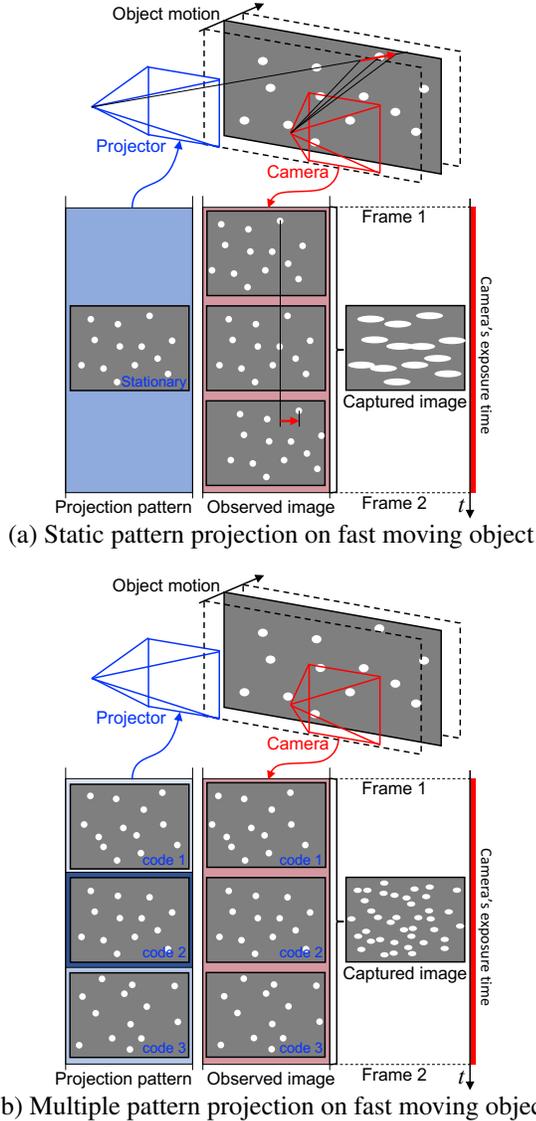


Figure 1. Differences between motion blur and intra-frame motion encoding.

2. Related work

In general, high frame rate of the input image is essential for analyzing rapidly moving objects. Since the sampling theory [21] determines the upper bound of recoverable temporal frequency for given sampling rates, specially designed image sensors [8, 9] have been intensively explored to achieve higher temporal resolution of input im-

age sequences. However, we cannot ignore the fundamental trade-off between temporal and spatial resolution caused by the limited performance of analog-to-digital (AD) conversion, and by the storage capacity of the captured images. To overcome this trade-off, redundancy of the moving scenes has been exploited. Gupta et al [4] synthesized high-resolution videos by combining low-resolution videos and a limited number of high-resolution key frames. In order to efficiently preserve the motion information of the scene in a single captured image, a technique using a coded aperture, in which aperture shape changes faster than shutter speed, has been proposed [15, 1]. Similarly, Hitomi [5] reconstructed a short video from a single coded exposure image, which sampled the scene randomly in terms of both spatial and temporal aspects, whereas Nagahara and Lull [14, 10] change exposure time for each pixel faster than shutter speed. In those cases, the single input image can also be regarded as a temporal sequence of sparsely sampled images. In other words, the corrected array of pixel values is not an instantaneous image but a culled version of the temporal image sequence. Similar techniques that encode temporal information in a limited number of images have been proposed [18, 16, 20, 11, 22]. However, these methods still share the unavoidable critical issue of costly special sensors with controllable exposure timing specified independently for each pixel.

Temporally coded light blinking faster than the sensor rate is also effective to increase the temporal information in a video with a limited frame rate [26]. In this case we can use ordinary imaging devices, but from the viewpoint of the sampling scheme of the redundant spatio-temporal array, it is far from optimal since all pixels are sampled simultaneously. In other words, the effect of homogeneous blinking light has similarity to the technique of coded exposure [17] so it is difficult to recover motion picture from a single input image as with Hitomi’s method [5] using pixel-wise individual exposure coding. Also blinking illumination is not versatile in daily-use cameras.

Contrary to the existing work listed above, our method of temporal super-resolution of 3D shapes is not only efficient in terms of sampling scheme and minimum cost for ordinary imaging devices, but is also natural in a shape-measuring context, because the method of projecting artificial light onto the object is not eccentric for active depth measurement [19, 25]. The proposed pattern of projected light is encoded spatially and temporally to maximize the exploitation of the motion information of the moving shape.

There are several papers, which use multiple patterns to reconstruct a moving object [23, 27], however, they capture each pattern in individual frames and do not capture multiple exposure of patterns into a single frame, it is difficult for them to achieve reconstruction of faster motion than camera fps nor temporal super-resolution.

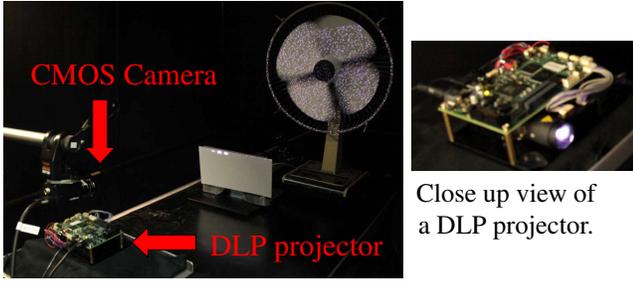


Figure 2. System configuration. Only a off-the-shelf camera and a projector are used.

3. Overview

3.1. Configuration of the system

The system setup for our experiment is the same as for any common active stereo setup and does not require special setup. Nor do we require synchronization between the projector and the camera. The only difference from conventional systems is that temporally coded patterns are projected onto the object. Thus, if a fast-changing pattern can be projected, most previous structured light systems can be used with our method; such simplicity and generalities of the methodology are important considerations of our work. Fig. 2 shows an example setup using a high-fps DLP projector, which is used for real experiments.

3.2. Basic idea

With our technique, motion information is embedded into the accumulation of multiple patterns. Then a series of shapes are temporally super-resolved by extracting the individual pattern from the pattern set. The basic theory and overview of the technique is explained in Fig. 1. If there is no motion in the scene, a sharp pattern is observed by the camera. If there is motion in the scene, the position of the projected pattern on the object surface will move depending on the depth and velocity of the object, and thus, the observed image subsequently degrades as shown in Fig. 1(a). In this process, if the scene motion is fast, motion blur increases because of a large position change of the pattern on the object surface, and less motion blur will be observed if the motion is slow.

To overcome the problem, we project multiple patterns with a higher fps than that of the camera, as shown in Fig. 1(b). With the method, the projected pattern is rapidly switched to the next pattern, thus several patterns are integrated on the object surface and captured by image sensors in one frame. Unlike the static pattern projection where pattern is blurred, high frequency patterns, which consist of multiple patterns with different codes, are captured without blur. Since the integrated pattern varies depending on which patterns are used, how fast the object moves and how deep the object exists, it is necessary to estimate those param-

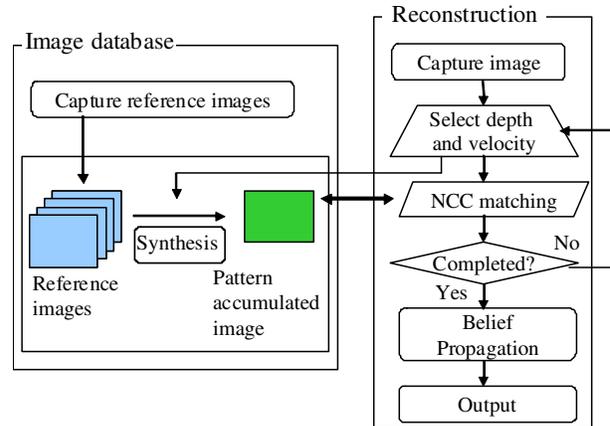


Figure 3. Algorithm overview

eters simultaneously. Also, projected patterns are significantly affected by defocus and aberrations. We solve those issues by taking a simple approach as follows: First, we create a pattern database which stores independent patterns projected on a flat white board set at varying depth. Once the database has been created, it can be used as the basis for comparison with the image capturing the moving target object. Thus, the image of the moving target object can be measured for depth and velocity by seeking the corresponding pattern combinations from a vast database.

3.3. Algorithm overview

Fig.3 shows the diagram of the algorithm. The technique mainly consists of two parts: image database creation and shape reconstruction. Note that image database creation is an offline process performed only once. To this end, reference images are captured by changing the depth of a planar board with a known position on which the set of randomly distributed dense dot patterns are projected. This process is repeated for all the independent patterns respectively. Since such a database approach can solve open problems such as strong defocus blur, etc. for a projector-camera system, its efficacy is currently being intensively researched [7, 2, 6].

During the shape reconstruction phase, we captured the target object by alternating projection patterns faster than camera fps. Then, the velocity and the shape of the object is recovered through two steps; the first is an initial depth estimation assuming a constant velocity for each pixel, and the second is a re-optimization step estimating the independent velocity according to a non-linear optimization method; note that errors accumulated by an assumption of constant velocity are efficiently decreased by the next re-optimization step. Both steps conduct stereo matching between the captured image and the image database, for estimation. Reference image patches are synthesized by using values of velocities and depths of the object, and the patches of the captured image are compared with the reference patches using normalized cross correlation (NCC). In

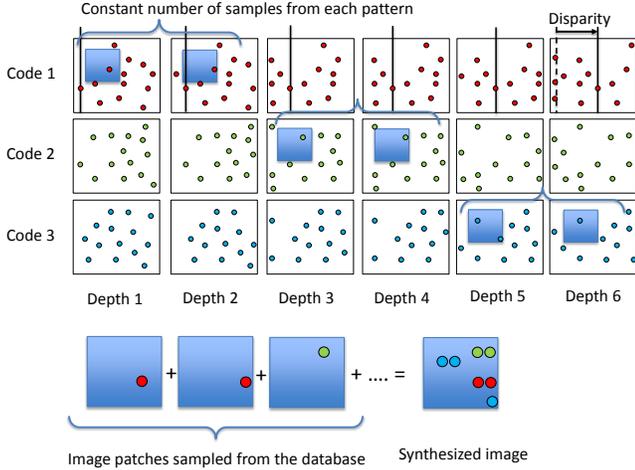


Figure 4. Synthesis of reference image patches for constant velocities.

our experiments, 16x16 and 24x24 pixels windows are used for calculation. As for the pattern design, we adopted a standard dense random dot pattern used by real-time scanning systems [12].

4. Implementation

4.1. Motion compensation database construction

In our method, learning-based approach is adopted instead of geometric calibration. As mentioned in Sec.3.3, the huge data size for learning-based approach is not just simply a weakness, but should be considered with a trade-off between accuracy, and we take accuracy in our method.

The image database is created by capturing the actual scene where a planar reference board on a motorized stage is moved from d_{min} to d_{max} between the projector and the camera. Each pattern is projected on the board and captured each time the board is moved one predefined unit length (0.5 mm in our experiment for sufficient accuracy in relation to data size), thus the captured static reference images do not involve motion blur. Because of the baseline between the projector and the camera, the observed pattern is shifted with disparities depending on the distance to the board. This capturing process is repeated $N_{p_{max}}$ times.

As for the projection pattern, we use multiple dense random dot patterns to make the projected pattern as unique as possible and to make blur clearly visible in all directions.

4.2. Initial depth and velocity estimation assuming constant velocity

The proposed technique simultaneously estimates depth and velocity using a multidimensional search with the reference image database. The reference images that can be observed depends on depths and velocity. However, generating reference image patches in advance requires huge amounts of memory and computational time for matching

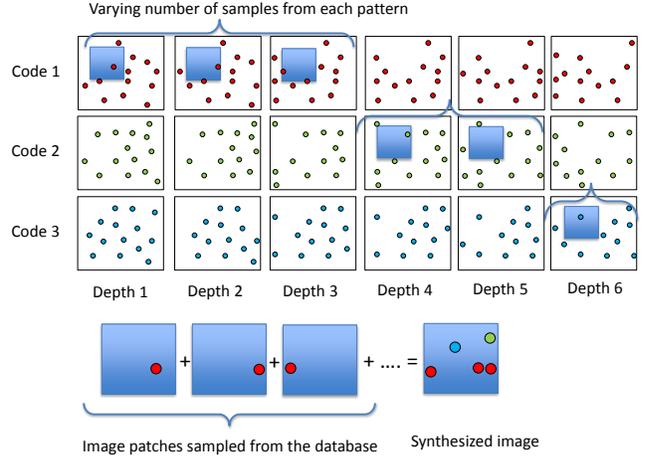


Figure 5. Synthesize of reference image patches for varying velocities.

because the combination of depth ($|d_{max} - d_{min}|$ levels) and velocity (v_{max} levels) creates enormous amounts of data, even if constant velocity is assumed.

To reduce the computational cost, we first obtain coarse initial solution by assuming constant velocity of the surface. The initial solution is refined later. The velocity is changed from $-v_{max}$ to v_{max} and the depth is changed from d_{min} to d_{max} . In total, $2 \times v_{max} \times |d_{max} - d_{min}|$ the reference image patches are generated for the captured pattern set.

In the initial estimation process, reference image patches $I^{const}(v, d_0)$ of depth at the start point d_0 and constant velocity v are generated by collecting image patches from the image database and integrating them as shown in Fig. 4. Note that, since constant velocity is assumed, the same number of patches are sampled from each pattern code. We calculate $I^{const}(v, d_0)$ by:

$$I^{const}(v, d_0) = \frac{1}{N_p} \frac{T_E}{T_E^{ref}} \sum_{n=1}^{N_p} \sum_{d=d_0+(n-1)\Delta d}^{d_0+n\Delta d} \frac{I_{p(n+N_{start}),d}^{static}}{\Delta d + 1} \quad (1)$$

where T_E and T_E^{ref} are exposure time at measurement and database construction, respectively. $p(n)$ is n -th observed pattern, $I_{p(n),d}^{static}$ is static reference image of pattern $p(n)$ at depth d in the image database, and Δd is the moving distance while the pattern is projected, i.e., $\Delta d = v \frac{T_E}{N_p}$. Then, all the generated reference images are compared to the captured image, and initial estimated values of depth and velocities are computed by

$$d, v = \operatorname{argmax}_{d,v} NCC(I^{const}(v, d), I^{cap}) \quad (2)$$

where I^{cap} is a captured image.

4.3. Refinement of depth and velocity estimation

After obtaining the initial solution, the depth and velocity estimation is further refined. In the refinement pro-

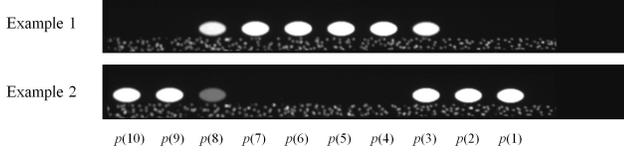


Figure 6. Captured image examples of projected pattern markers, *e.g.* examples 1 and 2 involve $p(3), p(4), \dots, p(8)$ and $p(8), p(9), \dots, p(3)$, respectively. In example 2, $p(8)$ is captured with about 25% of $\frac{T_E}{T_{ref}}$, respectively.

cess, nonuniform motion of the object is estimated. Velocities for each interval between the projected patterns $\mathbf{v} = (v_{p_1}, v_{p_2}, \dots, v_{p_{N_p}})$ are assumed to be inconstant and their values are simultaneously estimated. Reference images for refinement process are generated in the same way as the coarse process with the only difference on time-variant velocity as shown in Fig. 5, except that the number of samples from each code patterns may not be constant. Then, the reference image patch $I^{fine}(\mathbf{v}, d_0)$ at initial depth d_0 and velocities \mathbf{v} are calculated as follows:

$$I^{fine}(\mathbf{v}, d_0) = \frac{1}{N_p} \frac{T_E}{T_E^{ref}} \sum_{n=1}^{N_p} \sum_{d=d_{n-1}}^{d_n} \frac{I^{static}_{p(n+N_{start}),d}}{d_n - d_{n-1} + 1} \quad (3)$$

where $d_n = \sum_1^n v_{p_n} * \Delta t$. Then, the refined depth and velocity of each pattern are determined as follows:

$$d, \mathbf{v} = \operatorname{argmax}_{d, \mathbf{v}} NCC(I^{fine}(\mathbf{v}, d), I^{cap}). \quad (4)$$

To reduce the combination number of velocity values, a constraint between velocities at adjacent intervals is imposed so that the difference between these values should be less than threshold (*i.e.*, continuous velocities).

Finally, belief propagation (BP) [3] is applied to refine the initial shape. The cost volume obtained by NCC is used for data terms and the absolute value of depth difference between adjacent pixels is used for regularization terms.

4.4. Passive synchronization using markers

Although the aforementioned steps work effectively without synchronization, the search space is vast. If the system is synchronized, the search space can be greatly reduced. We propose a simple method to achieve synchronization without any hardware modifications. We impose markers corresponding to each projected pattern in the peripheral region of the projected pattern, which are not used for measurement. The markers are captured as shown in Fig. 6 and the intensity of each marker is calculated in order to accurately estimate which and for how long each pattern is captured. This allows users to use existing structured light systems without special re-configuration.

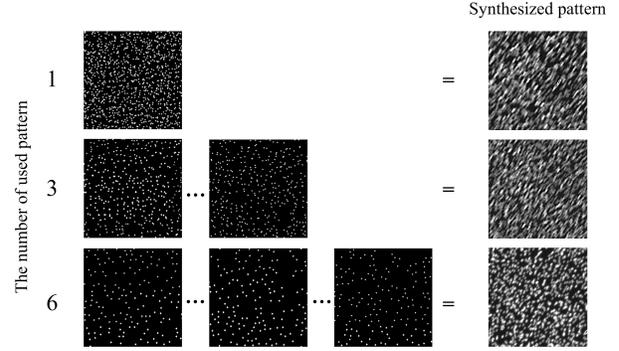


Figure 7. Synthesized patterns with a different number of projected patterns used. Since we assume that the object is moving, motion blurs are observed on the synthesized images; blur is stronger in the single pattern case than the others.

4.5. Temporal super-resolved shape reconstruction

By using the output data from the fine level, the proposed technique produces N_p shapes from a single image. Since the shape of the first frame and a velocity of each pixel at each frame is already estimated, a temporal super-resolved shape at n -th pattern can be reconstructed by accumulating Δd from 1 to $n - 1$ for all the pixels. To reduce accumulation error, we conduct a re-optimization step with reverse direction and average the depths from both directions.

5. Experiment

5.1. Evaluation with planar board

The first experiment was conducted by using a video projector and a CCD camera. Reference database was captured by moving the target screen by motorized stage between 500mm-800mm from the projector and the camera, and the capturing interval was 1.0mm. Fps and a resolution of the camera was 3Hz and 1600*1200 pixels and 30Hz and 1024*768 pixels for the video projector.

For evaluation, we attached a target board onto the motorized stage, and captured it with the camera while the board was moving under different conditions, such as with different numbers of projected patterns, different velocity and different material of the target object. Here, the case of using one pattern is same as the conventional active stereo method, therefore, to equalize the experimental conditions between the measurement using different numbers of patterns, we adjusted pattern density so that the density of the integrated patterns becomes the same, as shown in Fig. 7.

We applied our algorithm to the captured images using the stored database with matching window size 12*12 pixels. The depth value was also estimated by the commercial device Kinect v1 [12] to show the standard ability on scanning moving objects. Results are shown in Fig. 8 and 10.

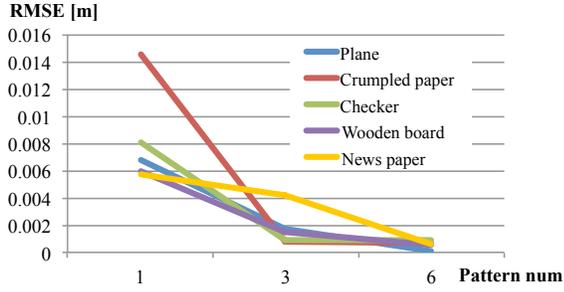


Figure 8. Accuracy evaluation by reconstructing a planar board with different texture using a different number of projected patterns. RMSEs of reconstructed points from the fitted planes are shown. Horizontal axis represents the number of pattern. It is clearly shown that increased number realize better RMSE with all the textures.

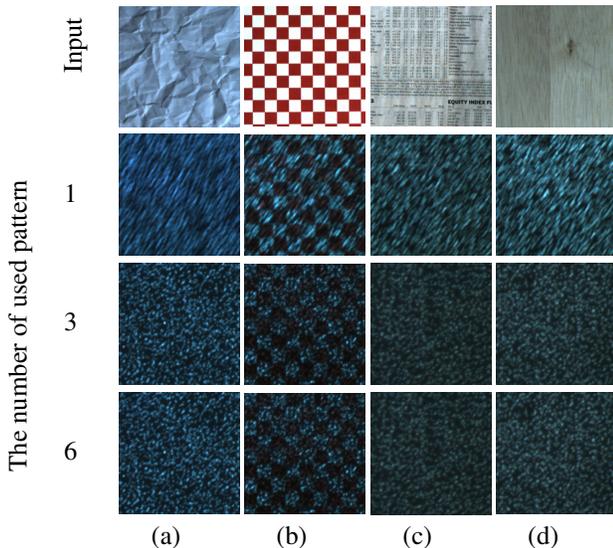


Figure 9. Example input data for the experiment of Fig. 8. (a) crumpled paper, (b) checker pattern, (c) newspaper and (d) wood under the condition of *slow* velocity in Fig. 10.

In the first graph in Fig.8, we can clearly observe that the increase in the number of projected patterns improves the RMSE for all textures and materials. Of all textures and materials, checker pattern has the worst RMSE; we consider that this is caused by the small size of checker pattern used, which is a similar size to the matching window, thus interference occurs during NCC calculation. Fig.9 shows examples of the actual captured images. As can be seen, a larger number of patterns result in a sharper captured image, which in turn results in better RMSE.

In the next graph of Fig.10, we can clearly see that an increase in velocity degrades the RMSE especially when the number of the patterns is small. Since we used an ordinary video projector for this experiment and the fps is just 3Hz, captured patterns are significantly blurred for a single pattern (as shown in Fig. 11,) whereas sharp patterns are preserved with multiple pattern projection. This results in

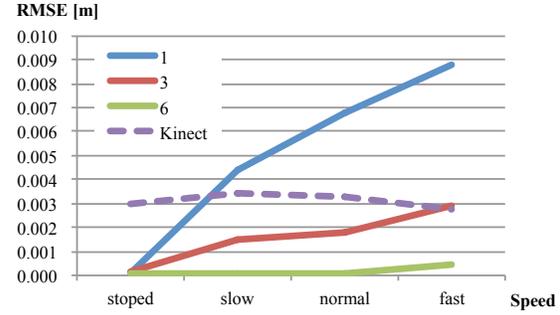


Figure 10. Accuracy evaluation by reconstructing a plane board with different velocity of target object. RMSEs of reconstructed points from the fitted planes are shown. Horizontal axis represents the velocity of the object. It is clearly shown that accuracy degrades when velocity become faster; typically the number of pattern is small.

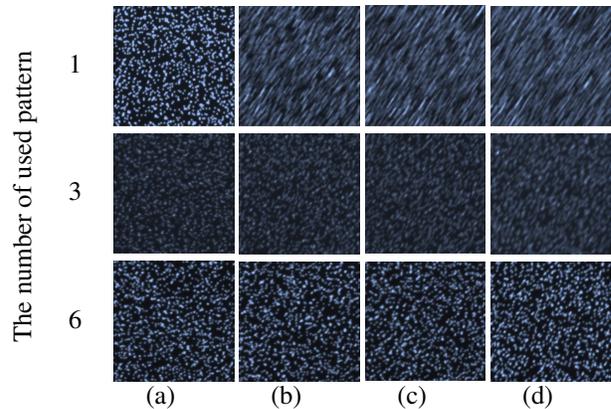


Figure 11. Example input data for the experiment of Fig. 10. (a) stop, (b) slow, (c) normal and (d) fast motion, respectively.

the maintenance of the lowest RMSE of all, at all velocities. The reason why Kinect has almost constant error values at various velocities is that the motorized stage is so slow even at the maximum speed that no motion blur occurred with Kinect.

5.2. Temporal super-resolution of nonuniform velocity

Next, super-resolved shapes were reconstructed from a single image input. To confirm the effectiveness of the refinement algorithm which can estimate nonuniform velocity, we impose a constant acceleration to the target board using the motorized stage. Reconstruction results are shown in Fig.12 and 13. As shown in the figures, we can confirm that the flat boards were not reconstructed at constant intervals, but at squared intervals.

5.3. Arbitrary shape reconstruction

Then, we applied our method to shapes with curved surfaces and non-uniform texture using off-the-shelf DLP projectors [24] with monochrome CMOS sensor. The fps of the camera was 300Hz with 1024*768 resolution and

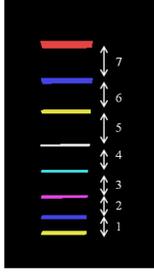


Figure 12. Super-resolved shape of moving board with acceleration. Different intervals are clearly shown.

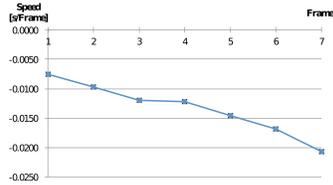


Figure 13. The graph of velocity of each board in Fig.12. Constant acceleration is confirmed.

1800Hz for the projector with 912*1140 resolution. Note that 300Hz is almost the maximum fps among readily available CMOS sensors, whereas potential fps of consumer DLP projector is yet much higher than 1800Hz.

The target objects were placed between 500mm and 800mm from the projector. Captured images are shown in Fig.14(a) and the middle column (b) shows the reconstruction results with depth image. 3D mesh and the cross section of super-resolved multiple shapes are shown in (c) and (d). From the results, we can confirm that the multiple shapes of curved surfaces are recovered accurately.

5.4. Simultaneous estimation of depths and velocities

To show the ability of the proposed system to estimate both depth and velocities simultaneously, we captured two balls in the both hands, shaken as fast as possible. Fig. 15 shows the results, where (a) shows the capturing scene, (b) shows the actually captured image for reconstruction, (c) shows the reconstructed shapes, and (d) and (e) show the color-mapped velocity for the direction along the optical axis. Note that these velocities are estimated from each single frame, rather than from multiple images. From the color maps, we can confirm that the left ball is moving toward the camera, and the right ball is moving from the camera in the frame (d), and the velocities are altered in frame (e).

5.5. Fast motion reconstruction

Finally, we captured the fast moving object by both our technique and Kinect v1 [12]; the board was swung as fast as possible by hand and the same scene was captured by both devices as shown in Fig. 16(a). Since Kinect is not designed for scanning a fast moving object, the purpose of using Kinect is to show the potential of our method compared with standard 3D scanning technique, but not to intend to say that our technique is better than Kinect. The fps of the camera and the projector is as same as the previous experiment, *i.e.* 300Hz and 1800Hz, respectively. As can be seen in Fig. 16(b), there is no blur captured by our method, and accumulated sharp patterns are observed. As

the results shown in Fig. 16(c-e), only corrupted shapes are reconstructed with Kinect, whereas our method can recover the temporally super-resolved shapes with high accuracy as shown in Fig. 16(f-h).

6. Limitations

Since our method detects the change rate of distance on the line of sight corresponding to each pixel, not all object movements can be recovered, especially, the motion perpendicular to the optical axis. One simple solution to detect 3D motion along the optical axis is to use multiple bands; another camera for visible light for estimating optical flow added to the IR pattern and IR camera for our method.

Similar to the previous limitation, if the object shifts in X-Y directions with textures of high spatial frequency and high contrast, negative effects can be caused. However, these are open problems for all the active 3D scanning techniques, and not specific to our method. Using IR illuminations could also be a practical solution.

Another limitation is occluding boundaries in the X-Y direction. With the current implementation, the first and last patterns are fixed for all the pixels, and the shape reconstruction sometimes fails or gets worse. We tested a simple solution of enlarging the search space, however, it significantly increases the processing time and sometimes causes unstable results. Therefore, to prioritize the stability, we did not adopt this technique in the experiments and a finding a practical solution is an important next step in our research.

7. Conclusion

In this paper, we propose a temporal super resolution technique for structured light systems to recover a series of 3D shapes from a single image. To achieve this, we project multiple patterns with higher fps than the camera can capture, to embed temporal information of object depth into a single captured image. Since the projected pattern on the surface varies depending on the depth and motion of the object, those parameters should be estimated simultaneously. Object depth as well as velocity for each pattern are sought to best explain the captured image, by synthesizing the image from an image database which is created in advance. Experiments were conducted to confirm the effectiveness our high-fps multiple pattern projection technique through quantitative evaluation using a planar board with various materials. We also show that temporally super-resolved shapes not captured in between frames can be successfully reconstructed using our method.

Acknowledgment

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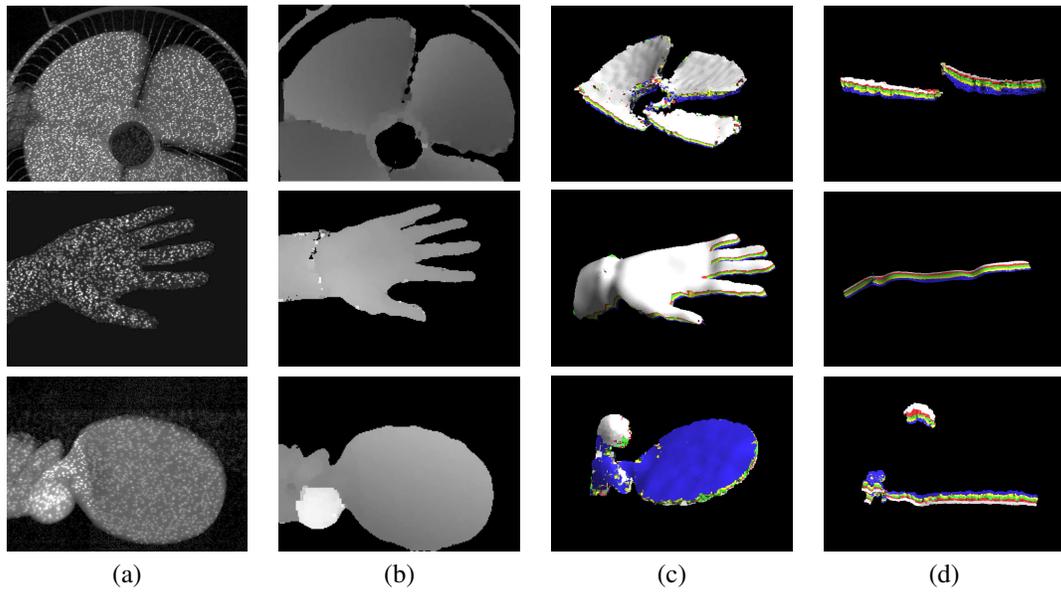


Figure 14. Results of temporal super-resolution of moving objects. (a) captured image, (b) depth image, (c) reconstructed shape and (d) cross section of (c).

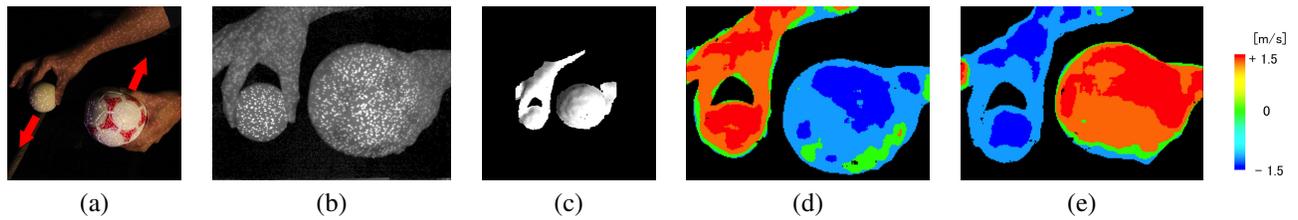


Figure 15. Velocity estimation: (a) the experimental scene, (b) the captured image, (c) the reconstructed shape, (d,e) velocity maps for two frames.

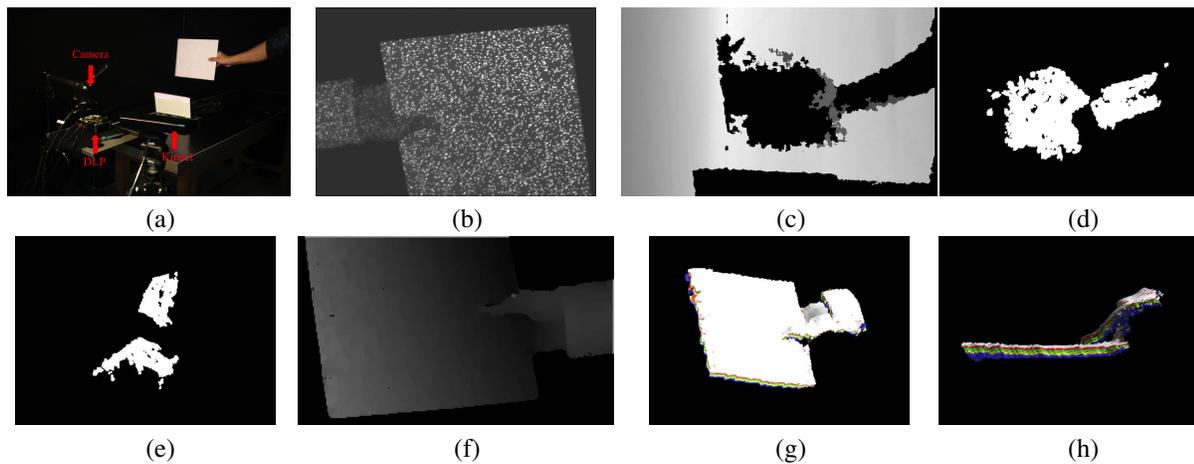


Figure 16. Capturing fast moving object. (a) Actual set-up with Kinect and our system. (b) Captured image of fast moving board with normal CMOS camera of 300 fps and no blur observed. Result of fast motion with Kinect in depthmap (c) and (d,e) 3D shapes. Result of the proposed system in depthmap (f) and (g,h) 3D shapes colored by intra-frames.

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