LAM : Luminance Attenuation Map for Photometric Uniformity in Projection Based Displays

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Abstract

Large area multi-projector displays show significant spatial variation in color, both within a single projector's field of view (FOV) and also across different projectors. Recent research in this area [8] has shown that the color variation is primarily due to luminance variation. Luminance varies within a single projector's field of view, across different brands of projectors and with the variation in projector parameters. Further, luminance variation is also introduced by overlap between adjacent projectors. On the other hand, chrominance remains constant throughout a projector's field of view and varies little with the change in projector parameters, especially for projectors of same brand. This indicates that *matching* luminance response of all the pixels of a multi-projector display should help us achieve photometric uniformity [8].

In this paper, we present a method to do a per-channel per-pixel luminance matching. Our process consists of a one-time calibration procedure when a *luminance attenuation map (LAM)* is generated. This LAM is then used to correct any imagery to achieve photometric uniformity. In the one-time calibration step, we first measure the per-channel luminance response of a multi-projector display using a camera and find the pixel with the most "limited" luminance response. Then we generate a per channel LAM for each projector that assigns weight to every pixel of the projector to scale the luminance response of that pixel to match with the most limited response. This LAM is then used to attenuate any image projected using the projector.

This method can be extended to do the image correction in real time on traditional graphics pipeline by using alpha blending and color look-up-tables. To the best of our knowledge, this is the first effort to match luminance across all the pixels of a multi-projector display. Our results show that luminance matching can indeed achieve photometric uniformity as analyzed in [8].

1 Introduction

Large-area, high-resolution multi-projector displays have the potential to change the way we interact with our computing environments. The high resolution and large field-of-view make them extremely useful for visualizing large scientific models. The compelling sense of presence created by such displays make them suitable for creating immersive virtual environments for 3D teleconferencing and entertainment purposes. Several such displays currently exist at Princeton, University of North Carolina at Chapel Hill, University of Minnesota, University of Illinois at Chicago, Stanford, MIT, Fraunhofer Institute (Germany) and United States National Laboratories like Argonne, Sandia and Lawrence Livermore National Laboratories. Recent efforts are directed towards building large displays comprising of $40 - 50$ projectors (Sandia National Labs and National Center for Supercomputing Applications at University of Illinois at Urbana Champaign).

Geometric registration and photometric uniformity of the projected imagery are essential in multi-projector displays to provide the user with the illusion of a single display. There are several algorithms to perform the geometric registration [12, 13, 10, 11]. But, to the best of our knowledge, there is no single solution that takes care of different photometric variations to achieve photometric uniformity in multi-projector displays. The comments in the recent work [5,1,4,6,12] and our experience has led us to believe that this problem is non-trivial and needs to be solved.

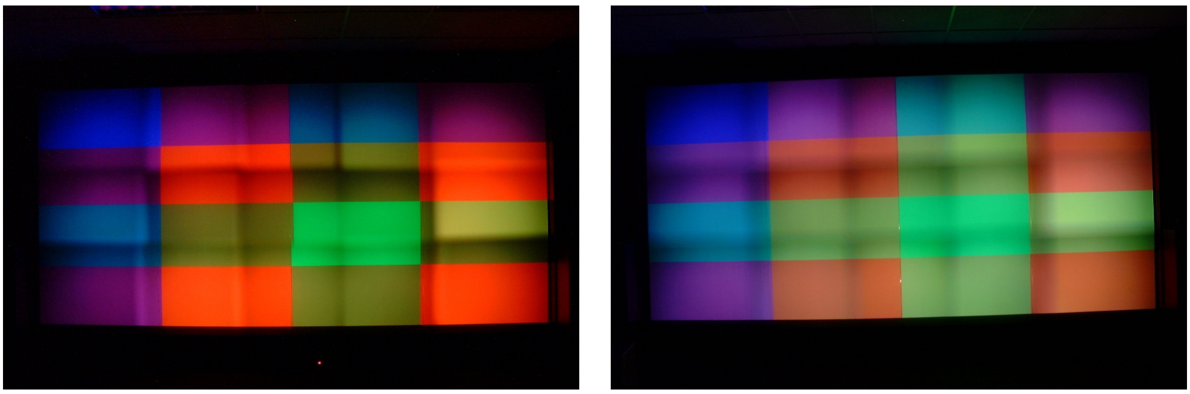

Figure 1: Left : A display of 5×3 array of 15 projectors where the overlap regions are blended using a physical shadow mask on the light path of the projector. Right : The same display with the overlap region blended by a linear ramp in software. For this, it is necessary to have the knowledge of the exact location of the overlap region.

The color of the multi-projector displays show significant spatial variation which can be distracting enough to be the sole cause of breaking the illusion of having a single display. Both *intra (within a single projector's field-of-view)* and *inter (across different projectors)* projector variation are the cause of such photometric non-uniformity. Further, adjacent projectors are overlapped to avoid rigid geometric alignment at the cost of introducing color variation. Some existing solutions try to reduce the higher brightness in the overlap regions by blending techniques [12] implemented either in software or hardware. But since this does not account for either intra or inter projector variations, the seams between projectors are still visible and one can easily notice the boundaries of the projectors that make up the display, as shown in Figure 1. The solution presented in [7] matches the luminance across multiple projectors but does not account for the variation within a single projector's field of view and hence fails to generate photometrically uniform displays.

Current research on analysis of the photometric variation [8,9] shows that the complexity of this problem may be reduced by the fact that the color variation across a multi-projector display is primarily due to luminance variation while chrominance variation is negligible. The luminance drops by almost 80% at fringes from the center of a single projector, but the chrominance remains constant. The chrominance of projectors of the same brand are so close to each other that the difference can be ignored for all practical purposes. Even for projectors of different brands, luminance difference is much more significant than the chrominance difference. It has also been shown [8] that it is the luminance that changes significantly with the change in projector parameters like position, zoom, brightness, contrast and lamp-age. Further, luminance difference is introduced by overlapping projectors to avoid rigid geometric alignments. These indicate that matching the luminance response of all the pixels of a multi-projector display may be sufficient to achieve the desired photometric uniformity.

In this paper we present a method to achieve a luminance matching across all pixels of a multi-projector display which results in photometrically uniform displays. We use a camera as measurement device for this purpose. Our method comprises of a one-time calibration step that generates a *per-channel per-projector luminance attenuation map (LAM)* that can then be used to correct any image projected by the projector.

1.1 Main Contributions

Following are the main contributions of the paper.

1. To the best of our knowledge, this is the first effort that solves for the both intra and inter projector color variation and also the variation introduced by the overlaps. All of these variations are taken care of by a single algorithm in an automated unified manner which is completely transparent to the user. In the past, assumption was made that color variation exists only across different projectors but not within a single projector and hence methods were devised [7] to achieve photometric uniformity by accurately measuring the photometric response at only one location per projector. As shown by the extensive studies in [8,9], this assumption is not true. Further, because of the same assumption, a different algorithm was needed to take care of the overlap.

2. To the best of our knowledge, this is the first effort to achieve photometric uniformity in multi-projector displays that uses a commodity off-the-shelf product like an inexpensive digital camera to measure the spatial luminance variation across the display. Previous work in this direction [7] uses a high precision expensive radiometer for measurement which is impractical when we want to measure the response of potentially every pixel on the display.

3. The use of a camera to accurately measure the luminance variation across the multi-projector display and the one-time calibration process to generate the LAM, makes this method easily scalable, practical and general purpose. Further, this method has the potential to be used in traditional graphics pipelines to achieve this correction in real-time.

In Section 2, we give the overview of our algorithm. In Section 3, we discuss the implementation of each step of the algorithm in details. Then we present the results in Section 4. In Section 5, we discuss several pertinent issues that would affect the quality of the results achieved by our algorithm. Finally, we conclude with future work in Section 6.

2 Algorithm Overview

In this section, the algorithm will be described for a single channel. All the three channels are treated similarly and independently.

The method comprises of two step. The first step is a one time calibration step where a per projector luminance attenuation map is generated. In the second image correction step, this LAM is used to correct any image content.

2.1 Calibration Step

The calibration step consists of three stages.

1. **Luminance Response Measurement :** The *luminance response* of any pixel is defined as the variation of luminance with input at that pixel. We measure the luminance response of every pixel of the display with a camera.

2. **Finding the Common Achievable Response:** We find the common response that can be achieved at every pixel of the display. The goal is to achieve this *common achievable response* at every pixel.

3. **Luminance Attenuation Map Generation:** We find a luminance attenuation function that transforms the measured luminance response at every pixel to the common achievable response.

If we assume a linear response for the projectors, then each of the above stages gets simplified. By linear response we mean that the luminance of black is zero, the maximum luminance occurs for the maximum input, and luminance response for every other input is a linear interpolation between these two values. First, the luminance measurement stage is simplified with this asumption since instead of measuring the luminance response of every input, we can now measure the luminance of only the maximum input. Second, the common achievable response can now be defined as the linear response with minimum luminance range. Finally, the luminance attenuation function is just a scaling function which is encoded in the luminance attenuation map (LAM). Hence, we assume that every display pixel has a linear luminance response. In Section 3 we show how we satisfy this assumption in the real implementation.

2.1.1 Luminance Response Measurement

Let us assume that the display D of resolution $W_d \times H_d$ is made up of n projectors each of resolution $W_p \times H_p$. Let us refer to the projectors as $P_i, 0 \leq i < n$. We use a static camera C of resolution $W_c \times H_c$ to measure the luminance of D. Let us denote the luminance response for the *maximum input* of the channel at a display location (x_d, y_d) as $L_d(x_d, y_d)$. The light at (x_d, y_d) can come from one or more projectors. If it comes from more than one projector, then (x_d, y_d) is in the region of the display where multiple projectors overlap. We want to find $L_d(x_d, y_d)$ for all pixels (x_d, y_d).

Geometric Calibration : First, we perform a geometric calibration procedure that defines the geometric relationships between the projector pixels (x_{P_i}, y_{P_i}), camera pixels (x_c, y_c) and the display pixels (x_d, y_d). This geometric calibration procedure uses the static camera to take pictures of some known static patterns put up on the display. By processing these pictures, the geometric calibration procedure defines two warps : $T_{P_i \rightarrow C}(x_{P_i}, y_{P_i})$ which maps a pixel (x_{P_i}, y_{P_i}) of projector P_i to the camera pixel (x_c, y_c), and $T_{C \rightarrow D}(x_c, y_c)$ which maps a camera pixel (x_c, y_c) to a display pixel (x_d, y_d). The concatenation of these two warps defines $T_{P_i \rightarrow D}(x_{P_i}, y_{P_i})$ which maps a projector pixel (x_{P_i}, y_{P_i}) directly to display pixel (x_d, y_d). These three warps give us the geometric information we need to find $L_d(x_d, y_d)$.

Data Capture for Luminance Correction : Keeping the camera in the same position, we take the image of each projector P_i projecting the maximum input for the channel. From these images we extract the luminance image for each projector P_i in the camera coordinate space denoted by I_i.

Generating the Luminance Surface : Next we generate the luminance surface $L_{P_i}(x_{P_i}, y_{P_i})$ for every projector P_i. For this, we first transform every projector pixel (x_{P_i}, y_{P_i}) by $T_{P_i \rightarrow C}$ into the camera coordinate space and read the luminance at that transformed pixel from I_i. Hence

$$L_{P_i}(x_{P_i}, y_{P_i}) = I_i(T_{P_i \rightarrow C}(x_{P_i}, y_{P_i})) \tag{1}$$

Once we have the luminance surface L_{P_i} for every projector P_i, we find the contribution of every projector at (x_d, y_d) by the inverse warp of $T_{P_i \rightarrow D}$ denoted by $T_{D \rightarrow P_i}(x_d, y_d)$ and add them up.

$$L_d(x_d, y_d) = \sum_{i=1}^{n} L_{P_i}(T_{D \rightarrow P_i}(x_d, y_d)) \tag{2}$$

2.1.2 Finding the Common Achievable Response

The common achievable response is defined as a linear response for which the luminance response for the maximum input is minimum of all $L_d(x_d, y_d)$ and this minimum luminance is denoted by L_{min}. Conceptually, this is equivalent to finding a common response that every pixel can achieve. Figure 2 illustrates this.

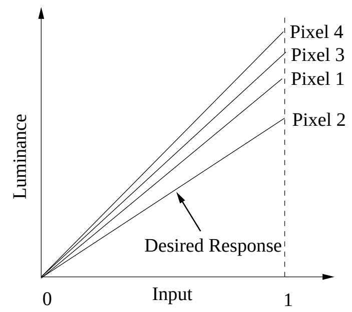

Figure 2: The common achievable response with four sample pixel response. The response with the least range is the common achievable response.

2.1.3 Luminance Attenuation Map Generation

The LAM, denoted by $A_d(x_d, y_d)$, is first generated in the display coordinate space and is given by

$$A_d(x_d, y_d) = \frac{L_{min}}{L_d(x_d, y_d)} \tag{3}$$

Thus A_d signifies the pixel-wise scale factor (less than 1.0) by which L_d should be scaled down to achieve luminance matching.

The next step is to generate the per projector luminance attenuation maps $A_{P_i}(x_{P_i}, y_{P_i})$ from A_d. Since we know the warp $T_{P_i \rightarrow D}$, this is achieved by

$$A_{P_i}(x_{P_i}, y_{P_i}) = A_d(T_{P_i \rightarrow D}(x_{P_i}, y_{P_i})) \tag{4}$$

2.2 Image Correction Step

Once this per-projector LAM is generated, it is used to attenuate any image. When putting up an image $M(x_d, y_d)$ of resolution $W_d \times H_d$ on the display wall, the warp $T_{P_i \rightarrow D}$ is used to the generate $M_{P_i}(x_{P_i}, y_{P_i})$ which is the part of M that projector P_i should project.

$$M_{P_i}(x_{P_i}, y_{P_i}) = M(T_{P_i \rightarrow D}(x_{P_i}, y_{P_i})) \tag{5}$$

Finally, M_{P_i} is multiplied by A_{P_i} to create the final image for projector P_i denoted by F_{P_i}.

$$F_{P_i}(x_{P_i}, y_{P_i}) = M_{P_i}(x_{P_i}, y_{P_i}) \times A_{P_i}(x_{P_i}, y_{P_i}) \quad (6)$$

3 Implementation

In this section we will give details of how exactly this method is implemented. The implementation is done on two wall configuration. The first one is a wall of resolution 1200×800 made up of 2×2 array of 4 projectors. Later we extended this to a wall of resolution 4500×2000 made of 5×3 array of 15 projectors.

3.1 Luminance Response Measurement

In this section, we describe in details the luminance response measurement procedure.

3.1.1 Geometric Calibration

We need an accurate geometric calibration method for the purpose of our photometric calibration method. Several geometric calibration algorithms have been designed in the past [13, 11, 10]. Any geometric calibration algorithm that can define accurately the two warps $T_{P_i \to C}$ and $T_{C \to D}$ can be used for our method. For our implementation, we use a geometric calibration procedure that defines two *cubic non-linear* warps $T_{P_i \to C}$ and $T_{C \to D}$. These non-linear warps include the radial distortion correction for both the camera and the projectors. This warp can be implemented in real time on traditional graphics pipeline using texture mapping. The details of this algorithm is available in [3].

3.1.2 Data Capture for Luminance Correction

As mentioned in the previous section, we need to capture images for every projector P_i when it is projecting the maximum input for each channel. During this time we turn off all the projectors that overlap with P_i to capture the luminance contribution solely from P_i accurately. To capture the data for all projectors in the display, we need to take a total of four pictures per channel. In each picture alternate projectors are turned on so that none of them overlap with each other. The pictures taken for the two different wall configurations are shown in Figure 3.

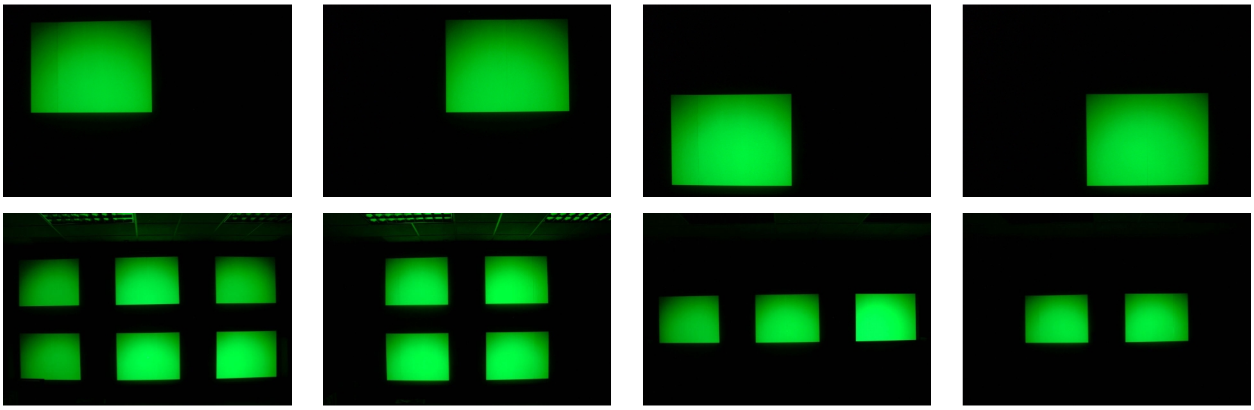

Figure 3: Top : The four pictures taken for green channel to do the luminance attenuation for a display made of 2×2 array of 4 projectors. Bottom : The four pictures taken for green channel to do the luminance attenuation for a display made of 5×3 array of 15 projector.

In the previous section, we assumed linear devices for our algorithm. To satisfy this assumption, we find the camera's non-linear response and linearize it using a color look up table. For our implementation we use a Fujifilm MX-2900 camera. We use the method presented in [2] to reconstruct its non-linear response. This method also generates a per-channel color look-up-table(LUT) that linearizes the per channel luminance response of the camera. Every image captured by the camera is linearized using this LUT.

3.1.3 Generating the Luminance Surface

In this section, we describe in details the generation of luminance response surface for the display.

Generating the Luminance Surface in Camera Coordinate Space : First, we find the luminance surface in the camera coordinate space corresponding to linearized images generated in the previous section. For this we use the standard linear transformation usually used to convert RGB colors to YUV space given by

$$Y = 0.299R + 0.587G + 0.114B \quad (7)$$

Generating Per-Projector Luminance Surface : In this step, we generate L_{P_i} for each projector P_i. For every pixel of the projector we find the corresponding camera coordinate using $T_{P_i \rightarrow C}$ and then interpolate bilinearly the corresponding luminance from the luminance of the four nearest neighbor in

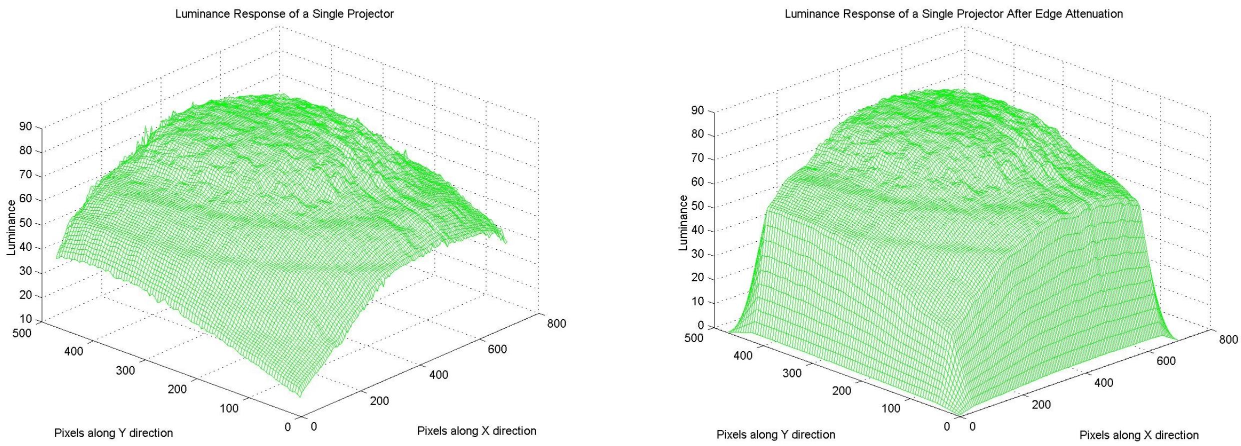

Figure 4: Left : The luminance surface generated for one projector. Right : The same luminance surface after edge attenuation.

the camera coordinate space. An example of the luminance surface thus generated for a projector is shown in Figure 4.

Edge Attenuation : Usually, in most projection based displays, adjacent projectors are overlapped to avoid rigid geometric alignment. However, the luminance in the overlap region is much higher than the luminance in the non-overlapped region and this spatial transition is very sharp. Theoretically, in order to reconstruct this edge between the overlapped and non-overlapped region we would need a camera resolution at least twice the display resolution. Given the resolution of today's display walls, that is a pretty strict restriction.

Instead, we smooth out this sharp transition by attenuating a few pixels at the edge of each projector. We do this attenuation in software. After generating the luminance image for each projector, we attenuate the $40-50$ pixels at the edge of the projector using a linear function. However, the width of this attenuation can be changed as long as it is less than the width of the overlap region. Similarly, a different function can be used like a cosine ramp. Figure 4 shows the luminance after such an edge attenuation. Note that we do not need information about the exact location of the overlap regions for this purpose but just an approximate idea about the width of the overlap so that the attenuation width is less than the width of the overlap.

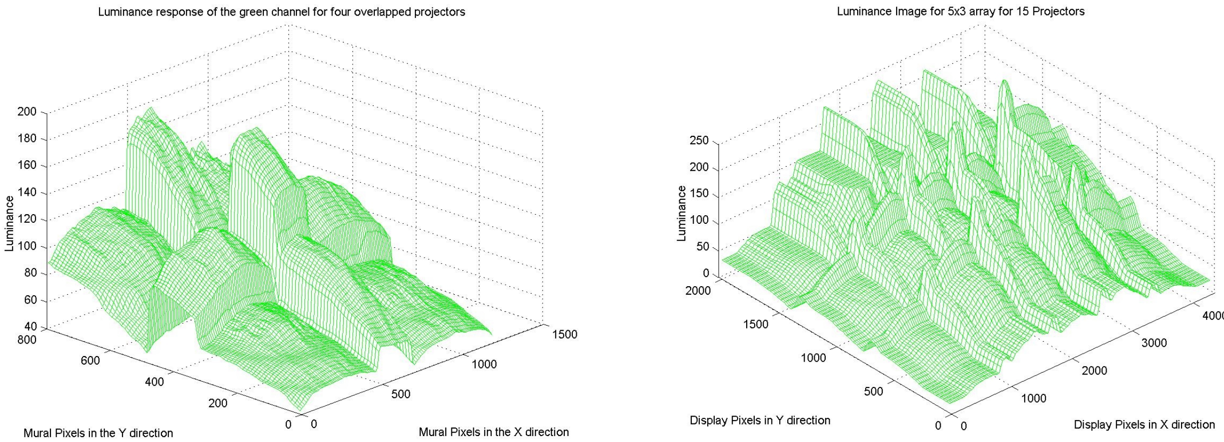

Figure 5: Left : The luminance surface generated for 2×2 array of four projectors. Right : The luminance surface generated for 5×3 array of 15 projectors.

Adding Them Up : Now, we have got the luminance image for each projector. The next step is to add them all up in the display coordinate space to generate L_d. For every projector pixel, we use $T_{P_i \rightarrow D}$ to find the corresponding display coordinate and the add the contribution of the luminance to the nearest four display pixels in a bilinear fashion. The generated luminance surface for the 2×2 array of four projectors and the 5×3 array of 15 projectors is shown in Figure 5.

3.2 Luminance Attenuation Map Generation

Now, we define the common achievable response as the minimum of L_d designated by L_{min}. Then we generate the luminance attenuation map A_d, in the display coordinate space by dividing L_{min} by L_d. This is shown in Figure 6. Notice how the LAM is dimmer to compensate for the brighter regions of the luminance surface.

To generate the per-projector attenuation map A_{P_i}, for every projector pixel we use $T_{P_i \rightarrow D}$ to convert it to display coordinate space and then interpolate bilinearly the value of A_d from the nearest four neighbors.

Finally, we put in the edge attenuation in the luminance attenuation map for each projector by attenuating the same number of edge pixels in the same way as was done while generating the luminance image in the previous section. Figure 7 shows an example LAM for one projector. The 15 projector

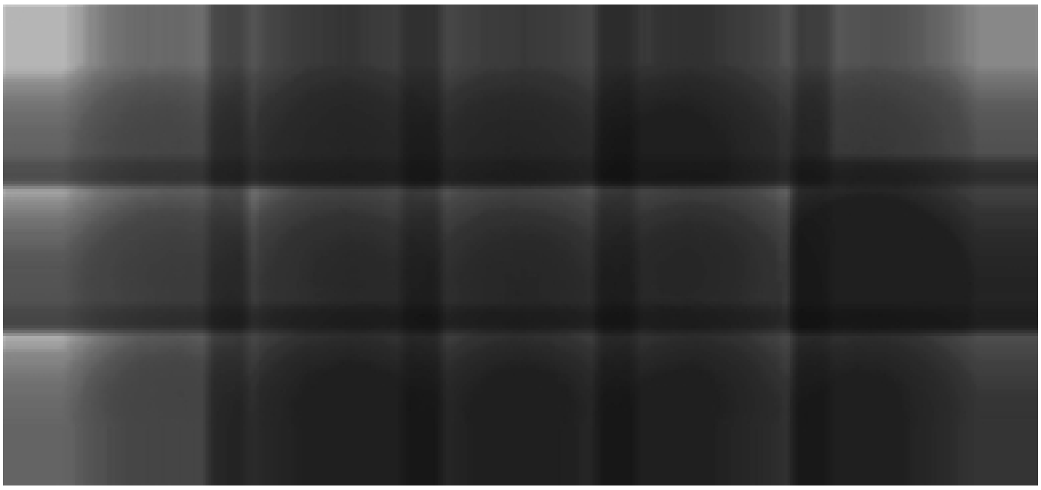

Figure 6: LAM for a display made of the 5×3 array of 15 projectors.

wall had larger luminance variation with some of the projectors having very low luminance response. Hence the attenuation in the 15 projector display is higher than that in the four projector display.

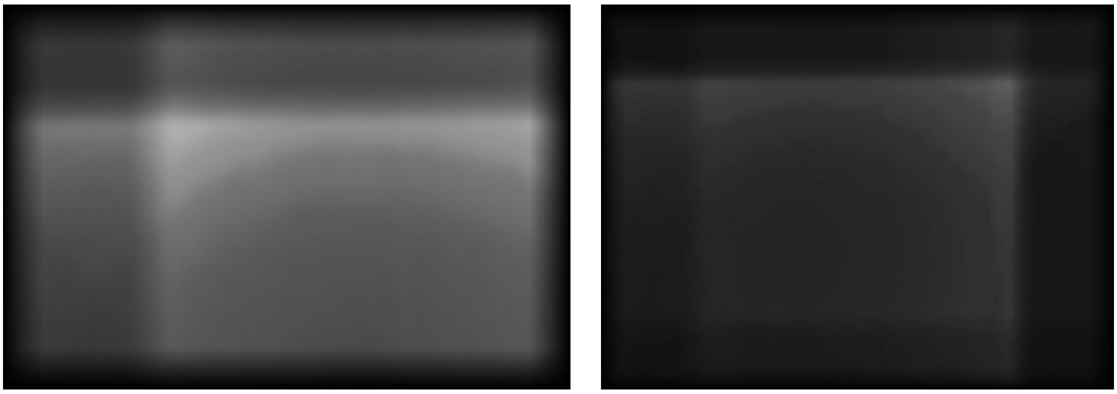

Figure 7: Left : LAM for a single projector in the four projector display. Right : LAM for a single projector in the 15 projector display.

3.3 Image Correction

The image correction is done in two steps.

Image Attenuation : The LAM is multiplied with the image to be rendered. This can be extended to an interactive application using the traditional graphics hardware, where the LAM can be used as an alpha mask which is blended with the rendered image.

Linearization of Projectors : Finally, since we have assumed linear response for the projectors, we have to linearize the projectors. This is done by a LUT. These per projector LUTs are pre-generated. It is shown in [8] that the projector non-linearity response does not vary spatially. Hence, we use a photometer to measure the per channel non-linear luminance response at the center of every projector. Then we find a LUT that would linearize this luminance response and use this for all pixels of the projector.

4 Results

In this section we present and discuss our results in the four and 15 projector display walls. Figure 8 and 9 shows the results on the four projector wall. These images are taken by a digital camera using the same exposure so that they can be compared. The worst test patterns for this algorithm are images with flat test colors. Figure 9 shows our algorithm on such images. A faint vertical line that can be seen in the images is not the projector boundaries but is the physical crack between the vertical planks that make our display wall.

Figure 10 shows results of the 15 projector display. You will see two types of artifacts in these results. Some contours are visible and some of the projector edges are faintly visible. These artifacts are due to insufficient sampling or limited camera dynamic range and will be explained in details in the next section. The bright spots you see in the center are due to light leaking through the cracks between the planks making up the display. Due to larger variation in luminance, the attenuation in larger for the 15 projector display. Hence, the images of the corrected display are taken at a higher exposure than the images of the uncorrected display.

The LAM can be implemented using the conventional graphics pipeline in real time by alpha blending. However, for the final linearization in the image correction step, we need a LUT. Usually all off-the-shelf projectors have in-built hardware LUT which would be ideal for this purpose since this would not incur any extra computation overhead. However, most commercial projectors do not give the user complete access to this hardware LUT. Hence we had to implement this using the software LUT in OpenGL. Unfortunately, this becomes the bottleneck stage in terms of achieving interactive

Figure 8: The left column shows the image before correction and the right column shows the image after luminance matching.

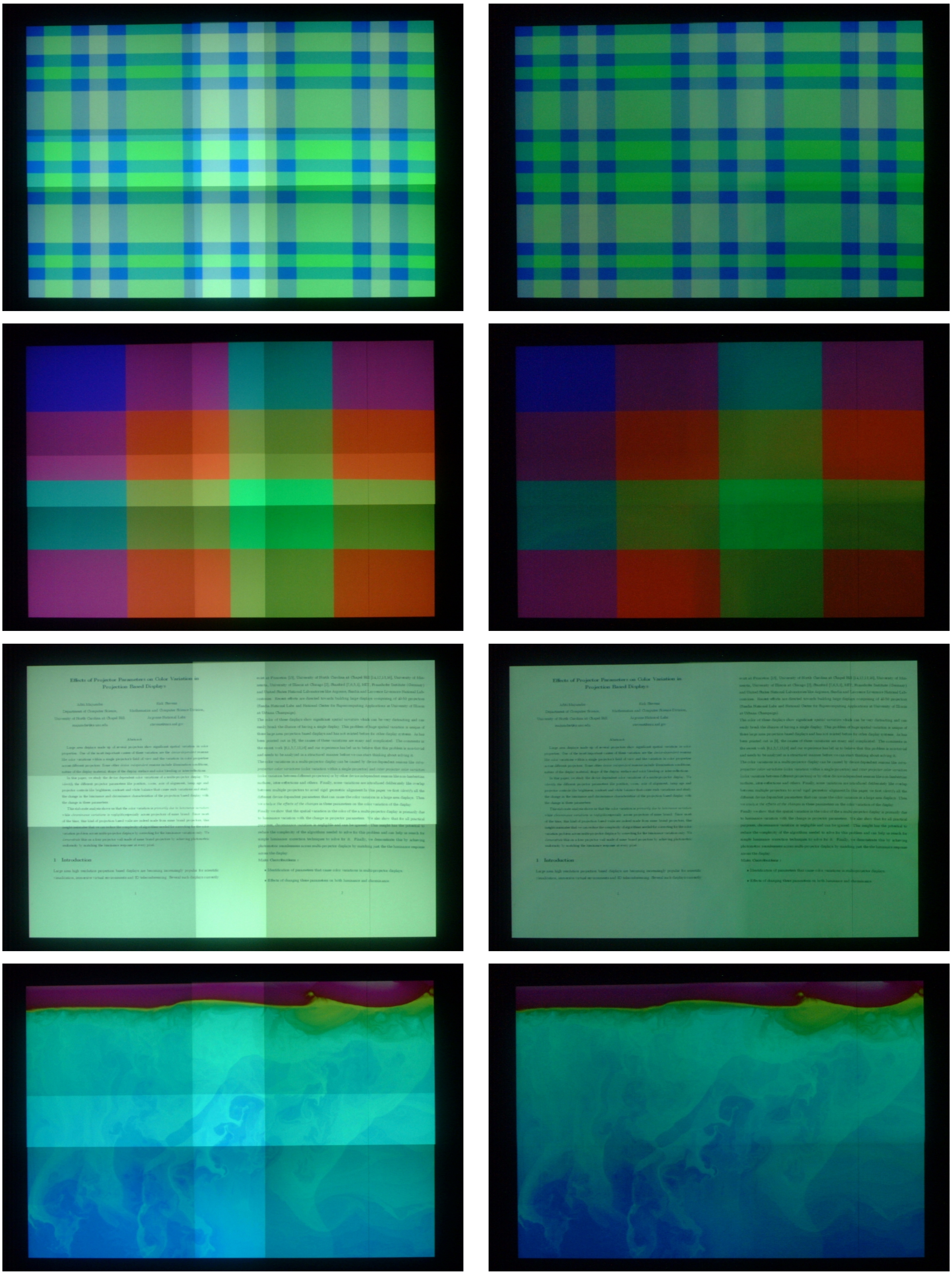

Figure 9: The left column shows the image before correction and the right column shows the image after luminance matching.

Figure 10: The left column shows the image before correction and the right column shows the image after luminance matching.

speeds. We can render a movie using OpenGL at 15 frames per second just with the alpha mask. Note that this speed is limited by the time required to load the movie and not to render it. However, it does not look right without the final linearization. But, if we use the OpenGL LUT for this purpose, it takes $2-3$ seconds per frame on nVidia GeForce cards. Currently we are trying to find some projectors that would give us complete access to their hardware LUTs so that we can implement an interactive version of this algorithm.

5 Issues

Accuracy of Geometric Calibration : Our geometric calibration algorithm gives us an accuracy of 0.2 pixels. Each display pixel is about $2.5mm$ is size. Even with this accuracy, a misalignment of even a couple of pixels in the reconstructed luminance response can cause perceived discontinuities without the edge attenuation. The edge attenuation alleviates the situation and we can tolerate greater errors of about $5-6$ pixels in the display space.

Sampling Density : Sampling density decides the accuracy of the reconstruction of the luminance surface for the display. As it is clear from the results, having two times the resolution of the display is ideal and would get rid of any sampling artifacts. However, the important thing is the minimum sampling density required to reconstruct the surface correctly. Obviously, this will be different from wall to wall depending on the nature of the variation. But to get an approximate idea, we did the following experiment. We reconstructed the luminance response of a four projector region of the wall sampled at the ideal sampling density. The frequency content of the luminance of this region is representative of that of a larger display since the larger display is made of several such four projector configurations. The fourier analysis of this luminance image after the edge attenuation showed that the required sampling resolution is about 1/5 of the display resolution. In our 15 projector implementation, the wall is sampled at 1/3 the display resolution and still we see some artifacts since there may be places in the wall which were not properly represented by the small region we used to decide on the minimum sampling density.

Dynamic Range of the Calibration Images : It is important for the brightness of each projector to be well within the dynamic range of the camera. This can be verified by simple under or over saturation tests of the camera images. In display walls made of many projectors there may be large brightness variation across projectors. In such cases, the camera exposure should be adjusted to accommodate for this variation. This change in exposure should be taken into account by appropriate scaling factors while generating the luminance surface [2]. Using same exposure for all projectors leads to contouring artifacts as seen in right most middle projector in Figure 10.

Camera Properties : It is important that the camera does not introduce additional luminance variation than is already present in the wall. Hence, the camera must produce flat fields when it is seeing a flat color. It is mentioned in [2] that most cameras satisfy this property at lower aperture settings, especially below $F8$. Our camera had a standard deviation of $2-3\%$ for flat field images. These flat field images were generated by taking pictures of planar nearly-diffused surfaces illuminated by a studio light with a diffusion filter.

Black Offset : In our method we assume that black produces zero luminance. However, this is not true in case of the projectors. Due to several leakages in the light path, the projectors have a non-zero black luminance which is called the *black offset*. Hence, if the image content is near black, we can see faint seams. However, from our experience, we find that the black offset has less effect on images with high frequency contents.

White Balance : Our method generates a per-channel LAM for every pixel. Since each channel may get attenuated differently, the grays may not be retained as grays when transformed by the LAM. This may lead to faint color blotches in the results. Hence, we use the LAM generated for the green channel for all channels. Since the nature of luminance variation is similar across the three channels, the small inaccuracy introduced by this do not show any visible artifacts.

6 Conclusion

In summary, we presented a camera based method to achieve photometric uniformity in multi-projector displays. Our one time calibration procedure generates a luminance attenuation map which is then used to correct any images. The LAM achieves a luminance matching across all the display pixels.

We believe that this is the first step towards achieving photometric uniformity across projection based displays but much more still needs to be done. Following are some of the things we are working on currently.

- Though this method removes the seams, the dynamic range of the display reduces dramatically since we are matching the response of all the pixels to the response of the worst pixel. This leads to under-utilization of system capabilities, especially in the overlap regions which have higher brightness and range. We are currently developing algorithms which can remove seams and at the same time make better use of the resources thus leading to higher dynamic range displays.

- It is important to evaluate the results of algorithms based on some photometric or perceptual metric. This metric should quantify the different display properties that are improved or degraded by the proposed algorithms. We are in process of designing such a metric.

- It is evident that as we move towards bigger display walls, the limited camera resolution will be insufficient to sample the luminance surface adequately leading to sampling artifacts in the corrected images. Hence, there is a necessity to design scalable solutions that can correct parts of the wall at a time and then stitch together the results. We are also investigating such scalable algorithms.

- The proposed method does not depend on the image content. But, if content of the image is considered as an input to the algorithm, the compression in the input range may be reduced leading to higher dynamic range images. We are investigating such content based corrections which may be more suited for canned movies as is used for entertainment purposes.

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