Stereo Abort of Unmanned Aerial Vehicle Deliveries

ABSTRACT

A method includes, during a delivery process of an unmanned aerial vehicle (UAV), receiving, by an image processing system, a depth image captured by a downward-facing stereo camera on the UAV. One or more pixels are within a sample area of the depth image and are associated with corresponding depth values indicative of distances of one or more objects to the downward-facing stereo camera. The method also includes determining, by the image processing system, an estimated depth value representative of depth values within the sample area. The method further includes determining that the estimated depth value is below a trigger depth. The method further includes, based at least on determining that the estimated depth value is below the trigger depth, aborting the delivery process of the UAV.

Figure 1A