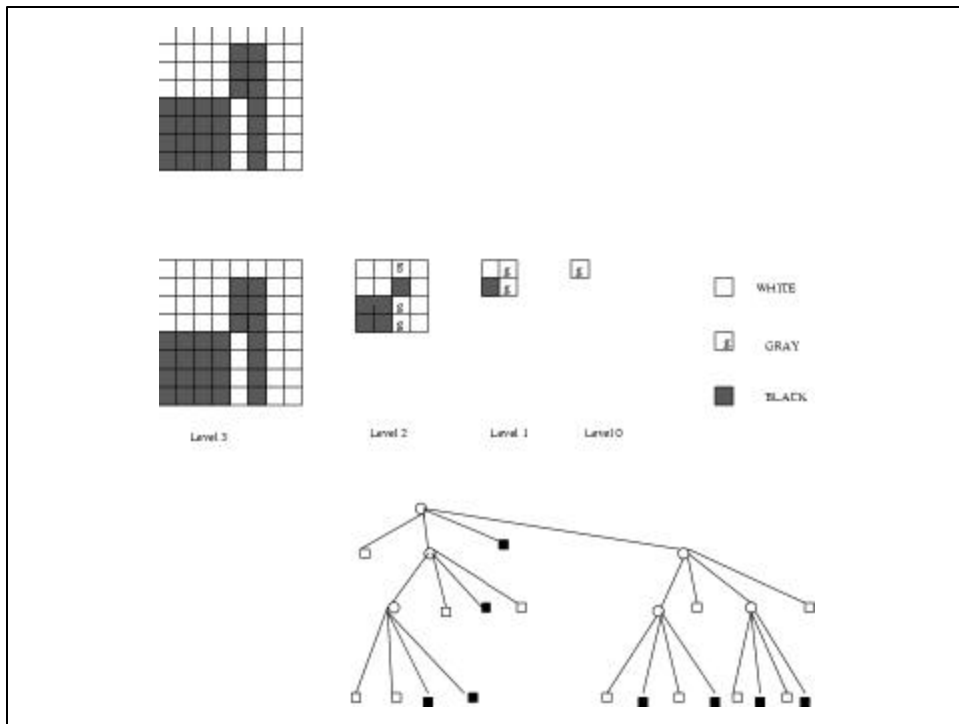


## Lecture-15

Quad Trees, Chain Code, Shape  
number & Moravec's interest  
operator

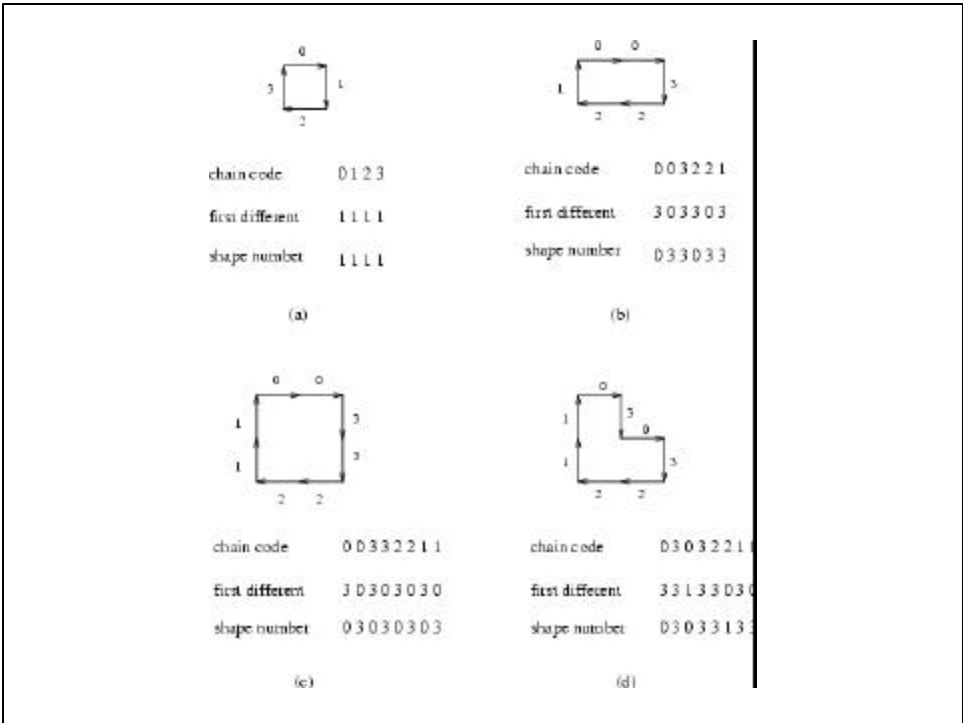
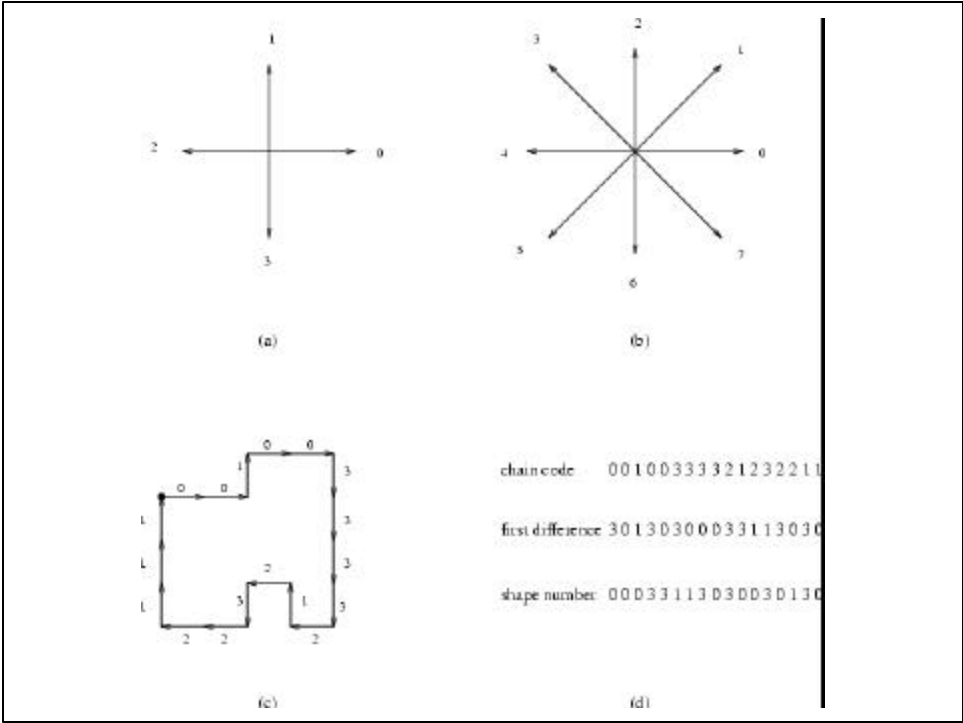
### Quad Trees

- Data structure to represent regions
- Three types of nodes: gray, black and white
- First generate the pyramid, then:
- If type of pyramid is black or white then return else
  - Recursively find quad tree of SE quadrant
  - Recursively find quad tree of SW quadrant
  - Recursively find quad tree of NE quadrant
  - Recursively find quad tree of NW quadrant
  - Retrun



## Chain Code

- A simple technique to represent a shape of boundary.
- Each directed line segment is assigned a code.
- Chain code is integer obtained by putting together the codes of all consecutive line segments.
- Shape number is a normalized chain code, which is invariant to translation and rotation.



## Moravec's Interest Operator

### Algorithm

- Compute four directional variances in horizontal, vertical, diagonal and anti-diagonal directions for each 4 by 4 window.
- If the minimum of four directional variances is a local maximum in a 12 by 12 overlapping neighborhood, then that window (point) is interesting.

|           |           |           |           |
|-----------|-----------|-----------|-----------|
| $F_{0,0}$ | $F_{0,1}$ | $F_{0,2}$ | $F_{0,3}$ |
| $F_{1,0}$ | $F_{1,1}$ | $F_{1,2}$ | $F_{1,3}$ |
| $F_{2,0}$ | $F_{2,1}$ | $F_{2,2}$ | $F_{2,3}$ |
| $F_{3,0}$ | $F_{3,1}$ | $F_{3,2}$ | $F_{3,3}$ |

(a)

|           |           |           |           |
|-----------|-----------|-----------|-----------|
| $P_{0,0}$ | $P_{0,1}$ | $P_{0,2}$ | $P_{0,3}$ |
| $P_{1,0}$ | $P_{1,1}$ | $P_{1,2}$ | $P_{1,3}$ |
| $P_{2,0}$ | $P_{2,1}$ | $P_{2,2}$ | $P_{2,3}$ |
| $P_{3,0}$ | $P_{3,1}$ | $P_{3,2}$ | $P_{3,3}$ |

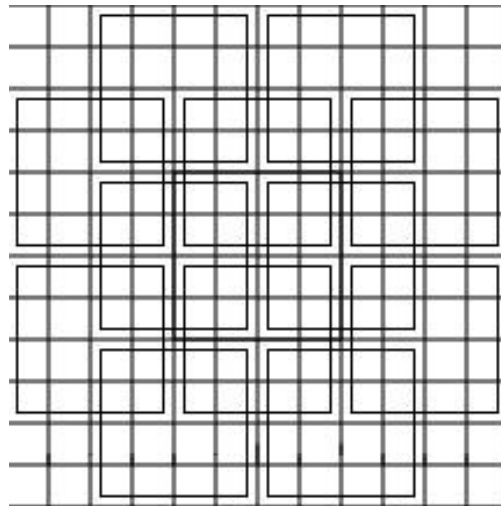
(b)

|           |           |           |           |
|-----------|-----------|-----------|-----------|
| $F_{0,0}$ | $F_{0,1}$ | $F_{0,2}$ | $F_{0,3}$ |
| $F_{1,0}$ | $F_{1,1}$ | $F_{1,2}$ | $F_{1,3}$ |
| $F_{2,0}$ | $F_{2,1}$ | $F_{2,2}$ | $F_{2,3}$ |
| $F_{3,0}$ | $F_{3,1}$ | $F_{3,2}$ | $F_{3,3}$ |

(c)

|           |           |           |           |
|-----------|-----------|-----------|-----------|
| $P_{0,0}$ | $P_{0,1}$ | $P_{0,2}$ | $P_{0,3}$ |
| $P_{1,0}$ | $P_{1,1}$ | $P_{1,2}$ | $P_{1,3}$ |
| $P_{2,0}$ | $P_{2,1}$ | $P_{2,2}$ | $P_{2,3}$ |
| $P_{3,0}$ | $P_{3,1}$ | $P_{3,2}$ | $P_{3,3}$ |

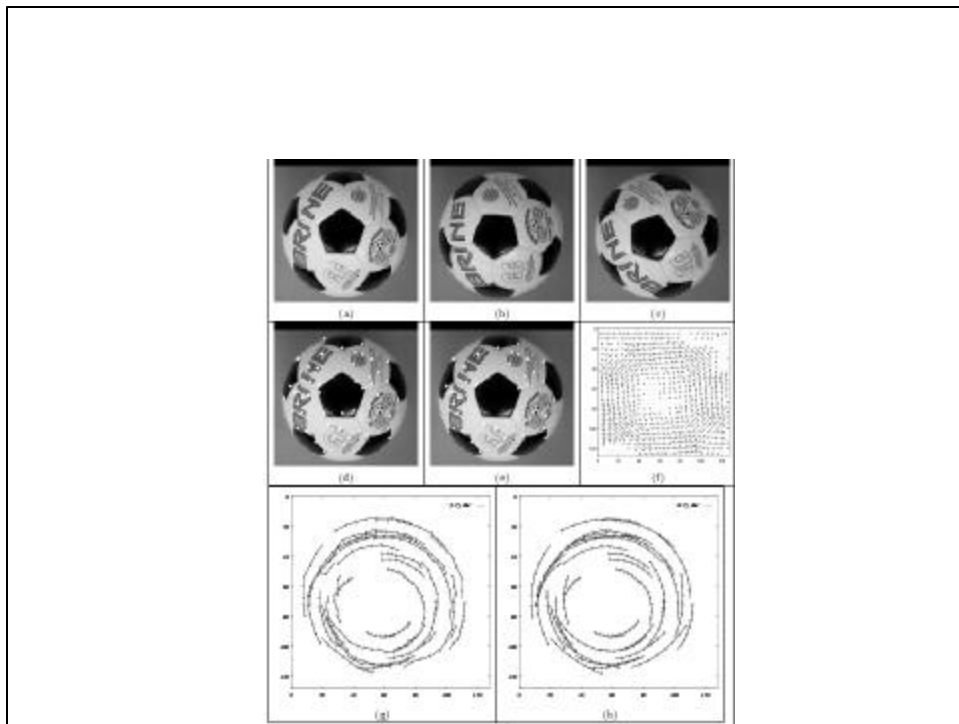
(d)



$$\begin{aligned}
V_h &= \sum_{j=0}^3 \sum_{i=0}^2 (P(x+i, y+j) - P(x+i+1, y+j))^2 \\
V_v &= \sum_{j=0}^2 \sum_{i=0}^3 (P(x+i, y+j) - P(x+i, y+j+1))^2 \\
V_d &= \sum_{j=0}^2 \sum_{i=0}^2 (P(x+i, y+j) - P(x+i+1, y+j+1))^2 \\
V_a &= \sum_{j=0}^2 \sum_{i=1}^3 (P(x+i, y+j) - P(x+i-1, y+j+1))^2
\end{aligned}$$

$$V(x, y) = \min(V_h(x, y), V_v(x, y), V_d(x, y), V_a(x, y))$$

$$I(x, y) = \begin{cases} 1 & \text{if } V(x, y) \text{ local max} \\ 0 & \text{Otherwise} \end{cases}$$



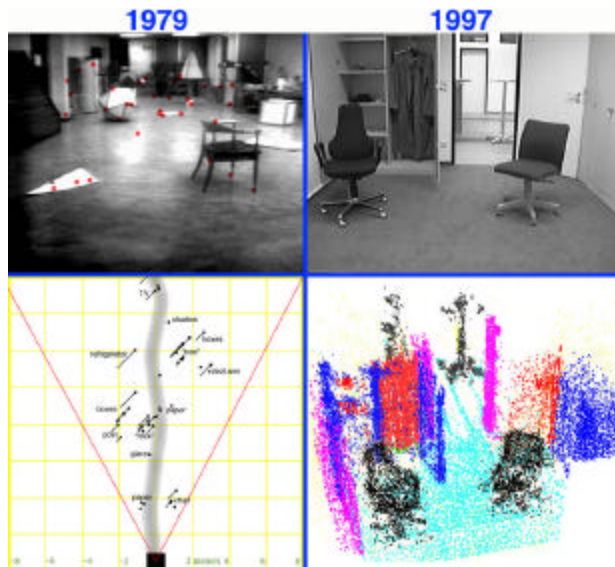
## Books by Hans Moravec

- Robot Rover Visual Navigation
- Mind Children: The future of Robot and Human Intelligence
- Robot, Being
  - Website <http://www.frc.ri.cmu.edu/~hpm/>

## Cart under SAIL



## 1979 and 1997 3D Maps from stereo

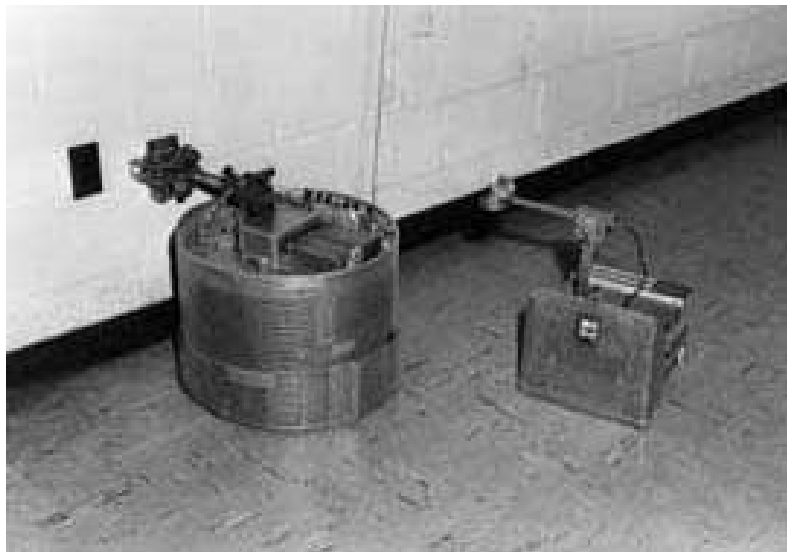




# NAVLABS



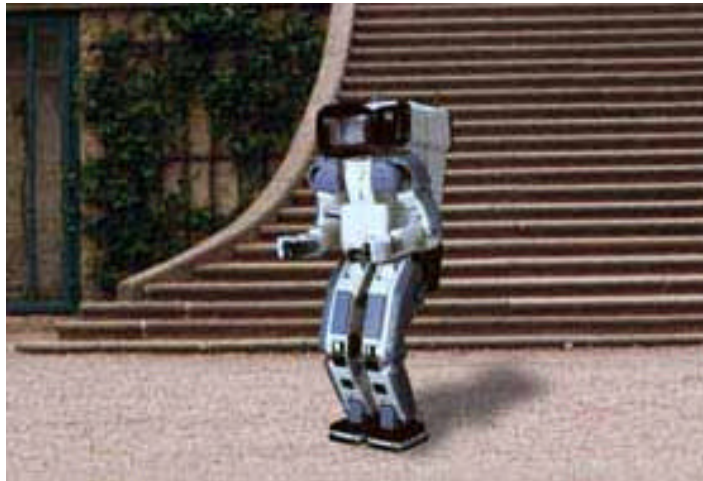
# Beast



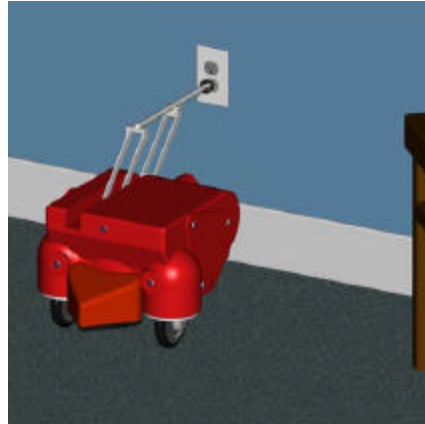
## Universal Delivery



## Potsdam



## Home Vacuum Cleaning Robot (Dustbot)



## Home Vacuum Cleaning Robot (Dustbot)



