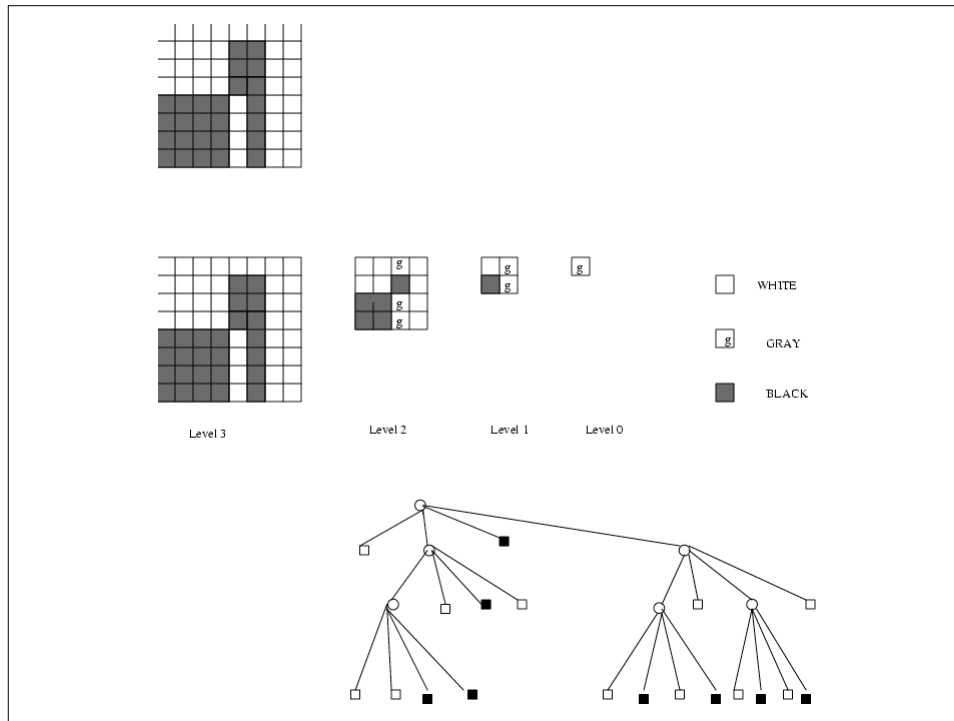


Lecture-15

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

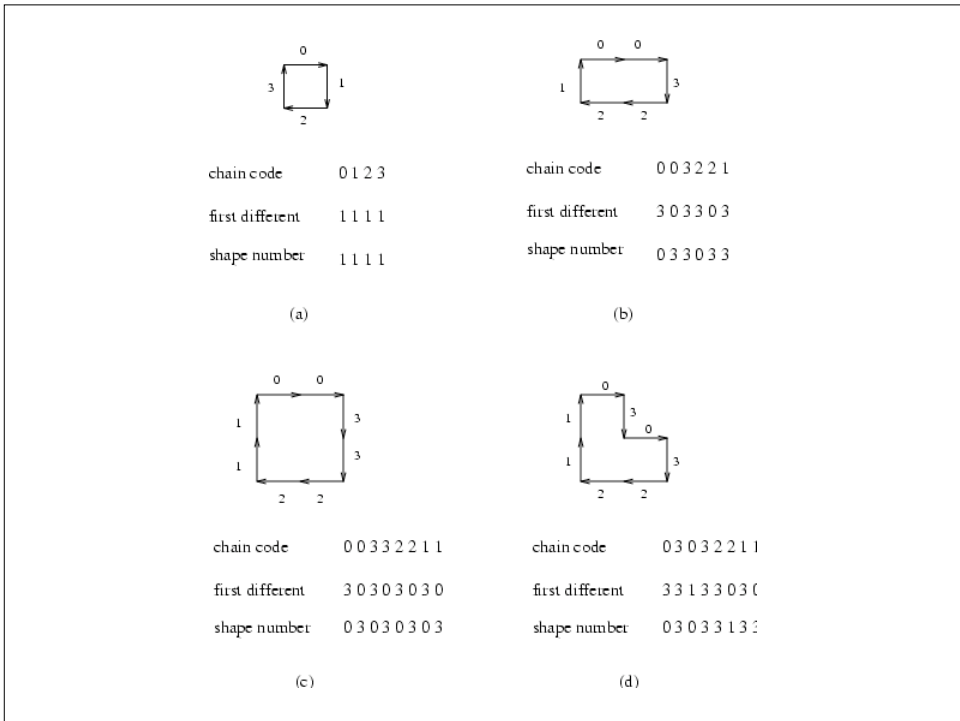
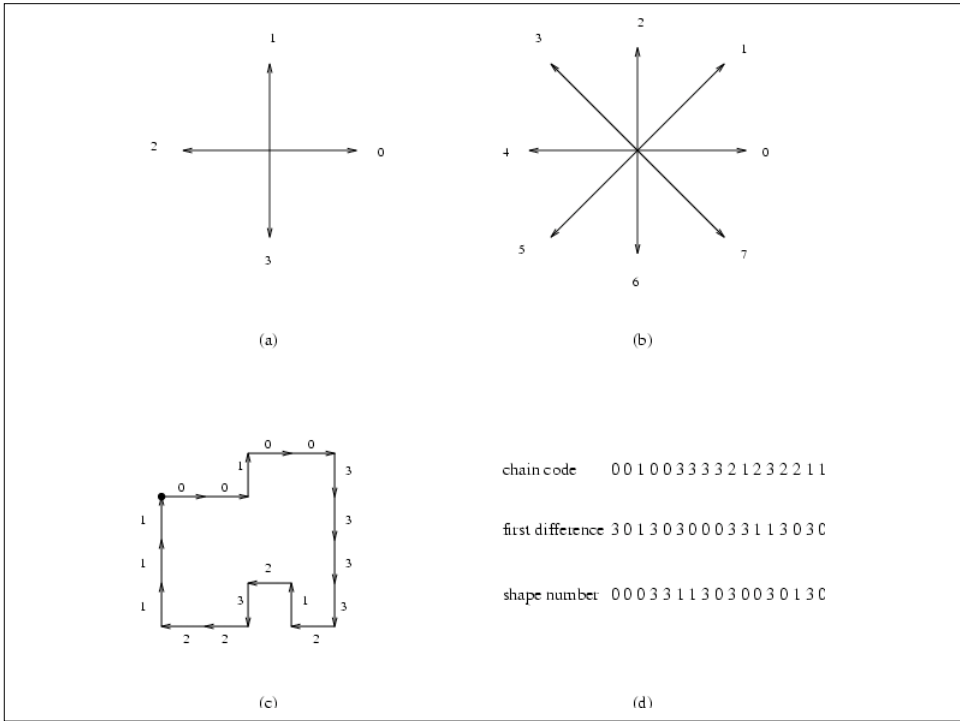
Quad Trees

- 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.

$$V_h = \sum_{j=0}^3 \sum_{i=0}^2 (P(x+i, y+j) - P(x+i+1, y+j))^2$$

$$V_v = \sum_{j=0}^2 \sum_{i=0}^3 (P(x+i, y+j) - P(x+i, y+j+1))^2$$

$$V_d = \sum_{j=0}^2 \sum_{i=0}^2 (P(x+i, y+j) - P(x+i+1, y+j+1))^2$$

$$V_a = \sum_{j=0}^2 \sum_{i=1}^3 (P(x+i, y+j) - P(x+i-1, y+j+1))^2$$

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}

(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}

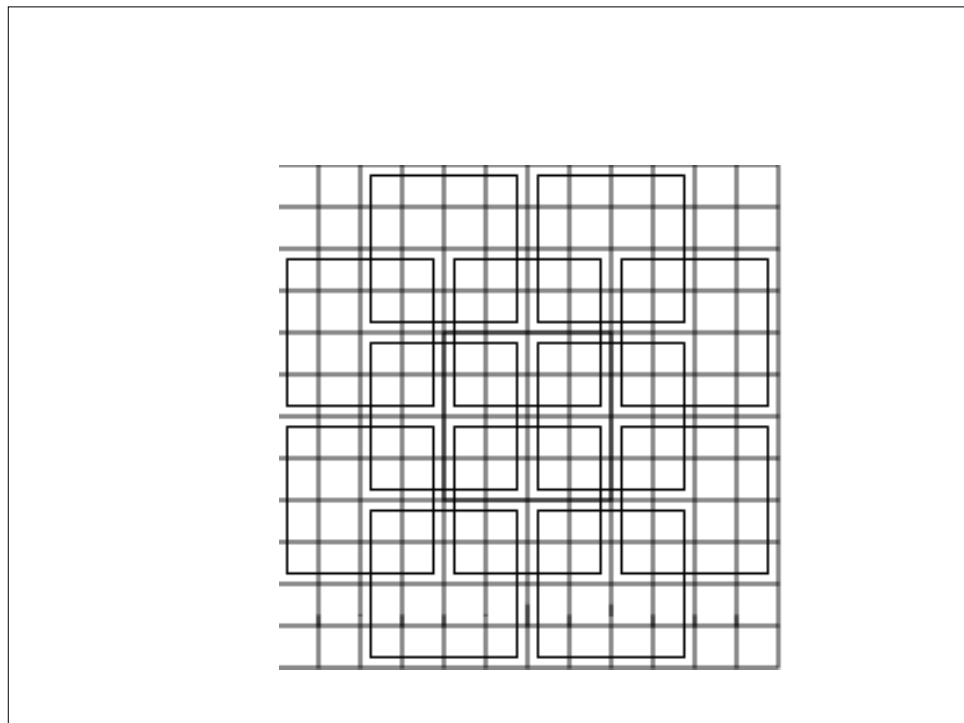
(b)

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}

(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}

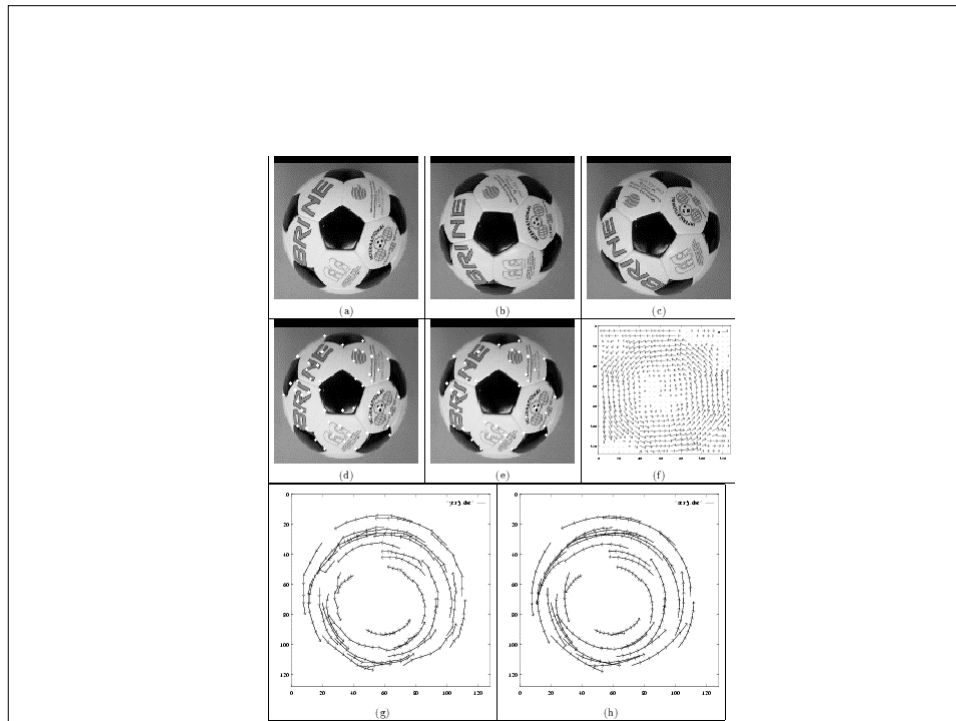
(d)



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

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

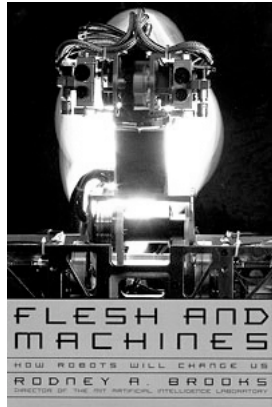
$$I(x, y) = \begin{cases} 1 & \text{if } V(x, y) \text{ local max} \\ 0 & \text{otherwise} \end{cases}$$



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/>

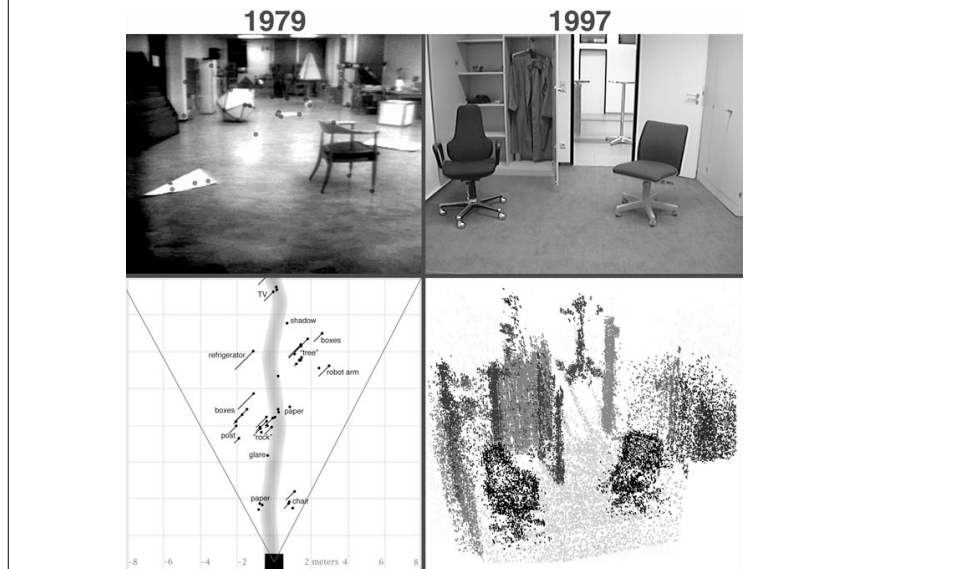
New Book



Cart under SAIL



1979 and 1997 3D Maps from stereo



NAVLABS



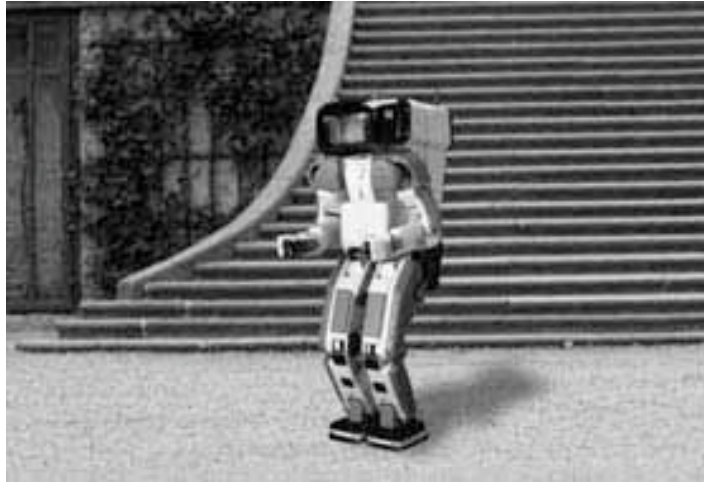
Beast



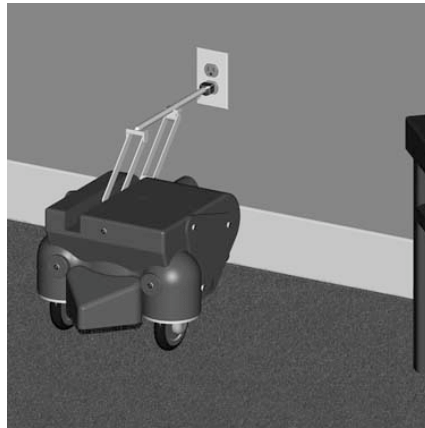
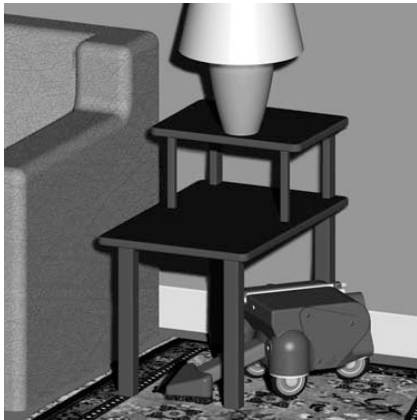
Universal Delivery



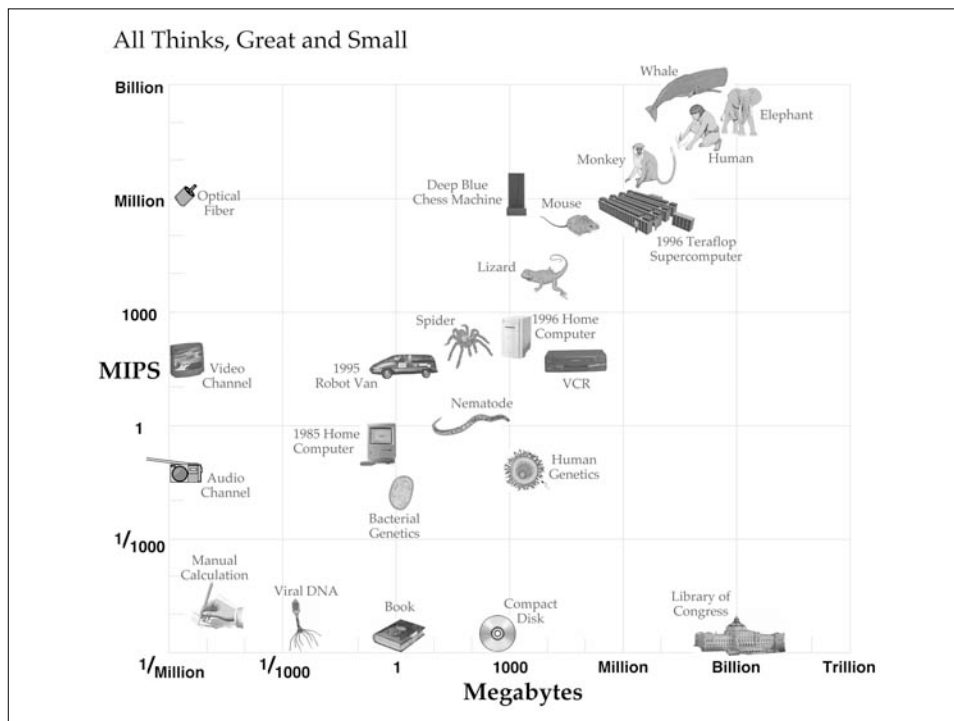
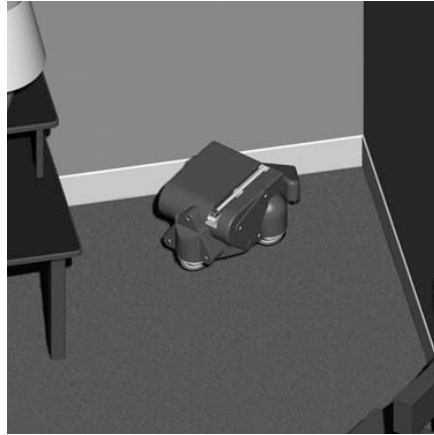
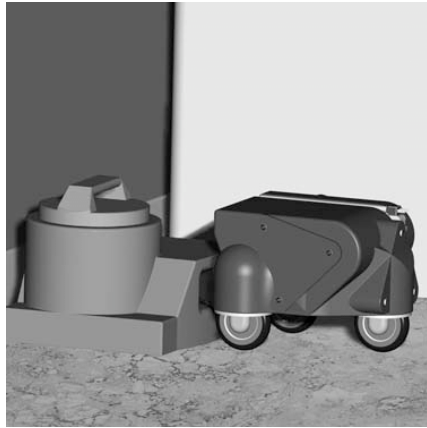
Potsdam

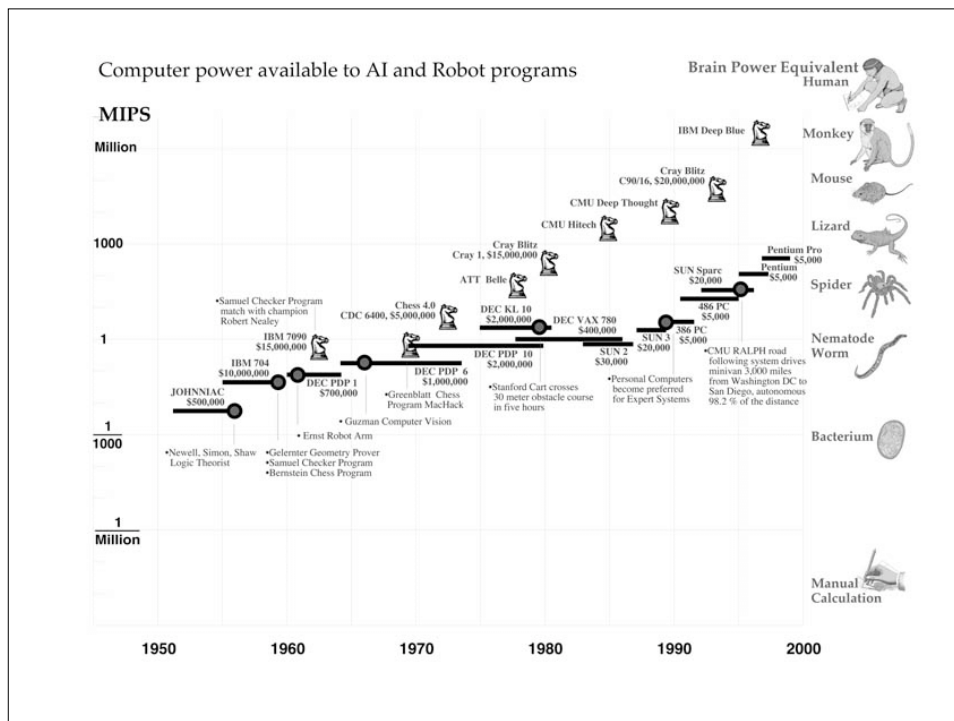
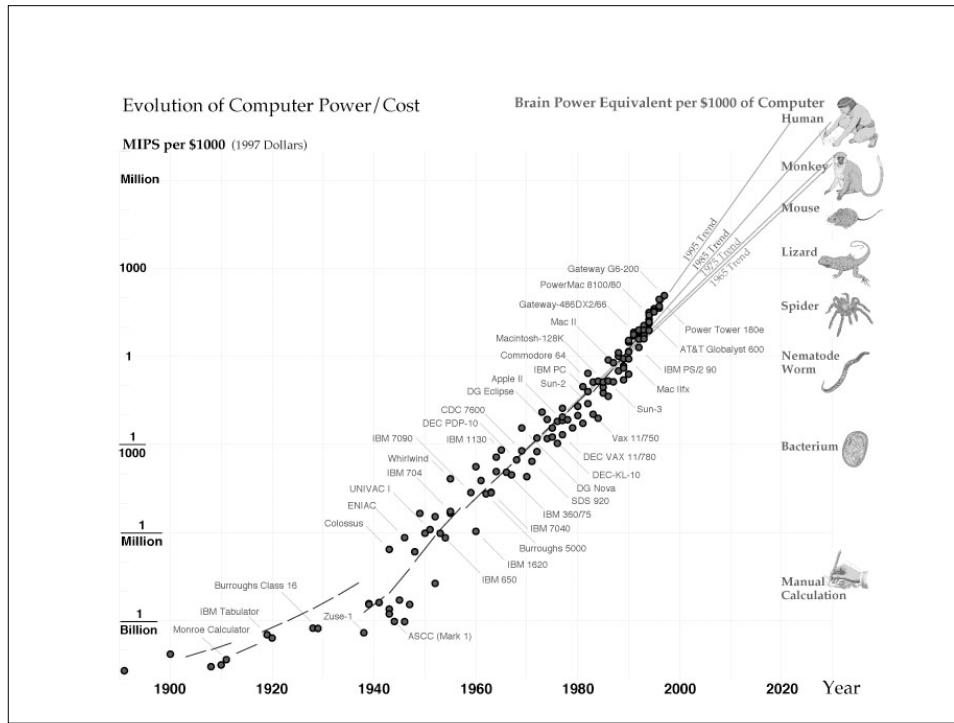


Home Vacuum Cleaning Robot (Dustbot)



Home Vacuum Cleaning Robot (Dustbot)





Chess Machine Performance versus Processing Power

