

SHADOWS AND SILHOUETTES IN COMPUTER VISION

Edited by

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Shadows And Silhouettes In Computer Vision

Reinhard Klette, Azriel Rosenfeld



Shadows And Silhouettes In Computer Vision:

Shadows and Silhouettes in Computer Vision S.A. Shafer, 2013-01-11 **Shadows and Silhouettes in Computer Vision** S.A. Shafer, 2013-03-09 **Computer Vision - ECCV 2002** Anders Heyden, Gunnar Sparr, Mads Nielsen, Peter Johansen, 2003-08-02 Premiering in 1990 in Antibes France the European Conference on Computer Vision ECCV has been held biennially at venues all around Europe These conferences have been very successful making ECCV a major event to the computer vision community ECCV 2002 was the seventh in the series The privilege of organizing it was shared by three universities The IT University of Copenhagen the University of Copenhagen and Lund University with the conference venue in Copenhagen These universities lie geographically close in the vivid Oresund region which lies partly in Denmark and partly in Sweden with the newly built bridge opened summer 2000 crossing the sound that formerly divided the countries We are very happy to report that this year's conference attracted more papers than ever before with around 600 submissions Still together with the conference board we decided to keep the tradition of holding ECCV as a single track conference Each paper was anonymously refereed by three different reviewers For the first time for ECCV a system with area chairs was used These met with the program chairs in Lund for two days in February 2002 to select what became 45 oral presentations and 181 posters Also at this meeting the selection was made without knowledge of the authors identity **Readings in Computer Vision** Martin A. Fischler, Oscar Firschein, 2014-06-28 The field of computer vision combines techniques from physics mathematics psychology artificial intelligence and computer science to examine how machines might construct meaningful descriptions of their surrounding environment The editors of this volume prominent researchers and leaders of the SRI International AI Center Perception Group have selected sixty papers most published since 1980 with the viewpoint that computer vision is concerned with solving seven basic problems Reconstructing 3D scenes from 2D images Decomposing images into their component parts Recognizing and assigning labels to scene objects Deducing and describing relations among scene objects Determining the nature of computer architectures that can support the visual function Representing abstractions in the world of computer memory Matching stored descriptions to image representation Each chapter of this volume addresses one of these problems through an introductory discussion which identifies major ideas and summarizes approaches and through reprints of key research papers Two appendices on crucial assumptions in image interpretation and on parallel architectures for vision applications a glossary of technical terms and a comprehensive bibliography and index complete the volume *Computer Vision of Shadows* Pamela Brigid Lechleider, 1997 **Computer Vision - ACCV 2010** Ron Kimmel, Reinhard Klette, Akihiro Sugimoto, 2011-02-28 The four volume set LNCS 6492 6495 constitutes the thoroughly refereed post proceedings of the 10th Asian Conference on Computer Vision ACCV 2009 held in Queenstown New Zealand in November 2010 All together the four volumes present 206 revised papers selected from a total of 739 Submissions All current issues in computer vision are

addressed ranging from algorithms that attempt to automatically understand the content of images optical methods coupled with computational techniques that enhance and improve images and capturing and analyzing the world's geometry while preparing the higher level image and shape understanding Novel geometry techniques statistical learning methods and modern algebraic procedures are dealt with as well Theory and Applications of Image Analysis II Gunilla Borgefors, 1995 This book contains 31 selected papers out of 136 accepted from the 9th Scandinavian Conference on Image Analysis held in Uppsala Sweden 6-9 June 1995 They represent the very best of what is currently done in image analysis world wide describing very recent work The papers have been both considerably expanded and updated compared to the version in the conference proceedings giving the readers a much better understanding of the issues at hand The papers cover both theory and successful applications There are chapters on Edges and Curves d104ure Depth and Stereo Scene Analysis and 3D Motion thus covering the chain from feature extraction to computer vision Two important application areas are covered Medical and Industrial Dynamic Analysis of Robot Manipulators Constantinos A. Balafoutis, Rajnikant V. Patel, 2012-12-06 The purpose of this monograph is to present computationally efficient algorithms for solving basic problems in robot manipulator dynamics In particular the following problems of rigid link open chain manipulator dynamics are considered i computation of inverse dynamics ii computation of forward dynamics and iii generation of linearized dynamic models Computationally efficient solutions of these problems are prerequisites for real time robot applications and simulations Cartesian tensor analysis is the mathematical foundation on which the above mentioned computational algorithms are based In particular it is shown in this monograph that by exploiting the relationships between second order Cartesian tensors and their vector invariants a number of new tensor vector identities can be obtained These identities enrich the theory of Cartesian tensors and allow us to manipulate complex Cartesian tensor equations effectively Moreover based on these identities the classical vector description for the Newton Euler equations of rigid body motion are rewritten in an equivalent tensor formulation which is shown to have computational advantages over the classical vector formulation Thus based on Cartesian tensor analysis a conceptually simple easy to implement and computationally efficient tensor methodology is presented in this monograph for studying classical rigid body dynamics XII Application of this tensor methodology to the dynamic analysis of rigid link open chain robot manipulators is simple and leads to an efficient formulation of the dynamic equations of motion

Digital Geometry Reinhard Klette, Azriel Rosenfeld, 2004-08-06 The first book on digital geometry by the leaders in the field *Robot Motion Planning* Jean-Claude Latombe, 2012-12-06 One of the ultimate goals in Robotics is to create autonomous robots Such robots will accept high level descriptions of tasks and will execute them without further human intervention The input descriptions will specify what the user wants done rather than how to do it The robots will be any kind of versatile mechanical device equipped with actuators and sensors under the control of a computing system Making progress toward autonomous robots is of major practical interest in a wide variety of application domains including

manufacturing construction waste management space exploration undersea work assistance for the disabled and medical surgery It is also of great technical interest especially for Computer Science because it raises challenging and rich computational issues from which new concepts of broad usefulness are likely to emerge Developing the technologies necessary for autonomous robots is a formidable undertaking with deep interweaved ramifications in automated reasoning perception and control It raises many important problems One of them motion planning is the central theme of this book It can be loosely stated as follows How can a robot decide what motions to perform in order to achieve goal arrangements of physical objects This capability is eminently necessary since by definition a robot accomplishes tasks by moving in the real world The minimum one would expect from an autonomous robot is the ability to plan its own motions

Digital Geometry Algorithms Valentin E. Brimkov, Reneta P. Barneva, 2012-05-20 Digital geometry emerged as an independent discipline in the second half of the last century It deals with geometric properties of digital objects and is developed with the unambiguous goal to provide rigorous theoretical foundations for devising new advanced approaches and algorithms for various problems of visual computing Different aspects of digital geometry have been addressed in the literature This book is the first one that explicitly focuses on the presentation of the most important digital geometry algorithms Each chapter provides a brief survey on a major research area related to the general volume theme description and analysis of related fundamental algorithms as well as new original contributions by the authors Every chapter contains a section in which interesting open problems are addressed

Computer Vision - ECCV 2022 Shai Avidan, Gabriel Brostow, Moustapha Cissé, Giovanni Maria Farinella, Tal Hassner, 2022-11-01 The 39 volume set comprising the LNCS books 13661 until 13699 constitutes the refereed proceedings of the 17th European Conference on Computer Vision ECCV 2022 held in Tel Aviv Israel during October 23-27 2022 The 1645 papers presented in these proceedings were carefully reviewed and selected from a total of 5804 submissions The papers deal with topics such as computer vision machine learning deep neural networks reinforcement learning object recognition image classification image processing object detection semantic segmentation human pose estimation 3D reconstruction stereo vision computational photography neural networks image coding image reconstruction object recognition motion estimation

Data Fusion for Sensory Information Processing Systems James J. Clark, Alan L. Yuille, 2013-03-09 The science associated with the development of artificial sensory systems is occupied primarily with determining how information about the world can be extracted from sensory data For example computational vision is for the most part concerned with the development of algorithms for distilling information about the world and recognition of various objects in the environment e.g. localization of objects from visual images e.g. photographs or video frames There are often a multitude of ways in which a specific piece of information about the world can be obtained from sensory data A subarea of research into sensory systems has arisen which is concerned with methods for combining these various information sources This field is known as data fusion or sensor fusion The literature on data fusion is extensive indicating

the intense interest in this topic but is quite chaotic There are no accepted approaches save for a few special cases and many of the best methods are ad hoc This book represents our attempt at providing a mathematical foundation upon which data fusion algorithms can be constructed and analyzed The methodology that we present in this text is motivated by a strong belief in the importance of constraints in sensory information processing systems In our view data fusion is best understood as the embedding of multiple constraints on the solution to a sensory information processing problem into the solution process

Geometric Constraints for Object Detection and Delineation Jefferey Shufelt, 2013-11-11 The ability to extract generic 3D objects from images is a crucial step towards automation of a variety of problems in cartographic database compilation industrial inspection and assembly and autonomous navigation Many of these problem domains do not have strong constraints on object shape or scene content presenting serious obstacles for the development of robust object detection and delineation techniques Geometric Constraints for Object Detection and Delineation addresses these problems with a suite of novel methods and techniques for detecting and delineating generic objects in images of complex scenes and applies them to the specific task of building detection and delineation from monocular aerial imagery PIVOT the fully automated system implementing these techniques is quantitatively evaluated on 83 images covering 18 test scenes and compared to three existing systems for building extraction The results highlight the performance improvements possible with rigorous photogrammetric camera modeling primitive based object representations and geometric constraints derived from their combination PIVOT's performance illustrates the implications of a clearly articulated set of philosophical principles taking a significant step towards automatic detection and delineation of 3D objects in real world environments Geometric Constraints for Object Detection and Delineation is suitable as a textbook or as a secondary text for a graduate level course and as a reference for researchers and practitioners in industry

3D Video and Its Applications Takashi Matsuyama, Shohei Nobuhara, Takeshi Takai, Tony Tung, 2012-05-31 This book presents a broad review of state of the art 3D video production technologies and applications The text opens with a concise introduction to the field before examining the design and calibration methods for multi view camera systems including practical implementation technologies A range of algorithms are then described for producing 3D video from video data A selection of 3D video applications are also demonstrated Features describes real time synchronized multi view video capture and object tracking with a group of active cameras discusses geometric and photometric camera calibration and 3D video studio design with active cameras examines 3D shape and motion reconstruction texture mapping and image rendering and lighting environment estimation demonstrates attractive 3D visualization visual contents analysis and editing 3D body action analysis and data compression highlights the remaining challenges and the exciting avenues for future research in 3D video technology

Computer Vision - ECCV 2006, 2006

Perturbation Techniques for Flexible Manipulators Anthony R. Fraser, Ronald Daniel, 1991-06-30 A manipulator or robot consists of a series of bodies links connected by joints to form a spatial mechanism Usually the links are

connected serially to form an open chain The joints are either revolute rotary or prismatic telescopic various combinations of the two giving a wide variety of possible configurations Motive power is provided by pneumatic hydraulic or electrical actuation of the joints The robot arm is distinguished from other active spatial mechanisms by its reprogrammability Therefore the controller is integral to any description of the arm In contrast with many other controlled processes e.g batch reactors it is possible to model the dynamics of a manipulator very accurately Unfortunately for practical arm designs the resulting models are complex and a considerable amount of research effort has gone into improving their numerical efficiency with a view to real time solution [32, 41, 51, 61, 77, 87, 91] In recent years improvements in electric motor technology coupled with new designs such as direct drive arms have led to a rapid increase in the speed and load carrying capabilities of manipulators However this has meant that the flexibility of the nominally rigid links has become increasingly significant Present generation manipulators are limited to a load carrying capacity of typically 5-10% of their own weight by the requirement of rigidity For example the Cincinnati Milicron T3R3 robot weighs more than 1800 kg but has a maximum payload capacity of 23 kg

Three-Dimensional Object Recognition from Range Images Minsoo Suk, Suchendra M. Bhandarkar, 2012-12-06 Computer Science Workbench is a monograph series which will provide you with an in depth working knowledge of current developments in computer technology Every volume in this series will deal with a topic of importance in computer science and elaborate on how you yourself can build systems related to the main theme You will be able to develop a variety of systems including computer software tools computer graphics computer animation database management systems and computer aided design and manufacturing systems Computer Science Workbench represents an important new contribution in the field of practical computer technology

Tôgiyasu L. Kunii PREFACE The primary aim of this book is to present a coherent and self contained description of recent advances in three dimensional object recognition from range images Three dimensional object recognition concerns recognition and localization of objects of interest in a scene from input images This problem is one of both theoretical and practical importance On the theoretical side it is an ideal vehicle for the study of the general area of computer vision since it deals with several important issues encountered in computer vision for example issues such as feature extraction acquisition representation and proper use of knowledge employment of efficient control strategies coupling numerical and symbolic computations and parallel implementation of algorithms On the practical side it has a wide range of applications in areas such as robot vision autonomous navigation automated inspection of industrial parts and automated assembly

Image Understanding Workshop United States. Defense Advanced Research Projects Agency. Information Science and Technology Office, 1987

Image Understanding Workshop, 1990

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