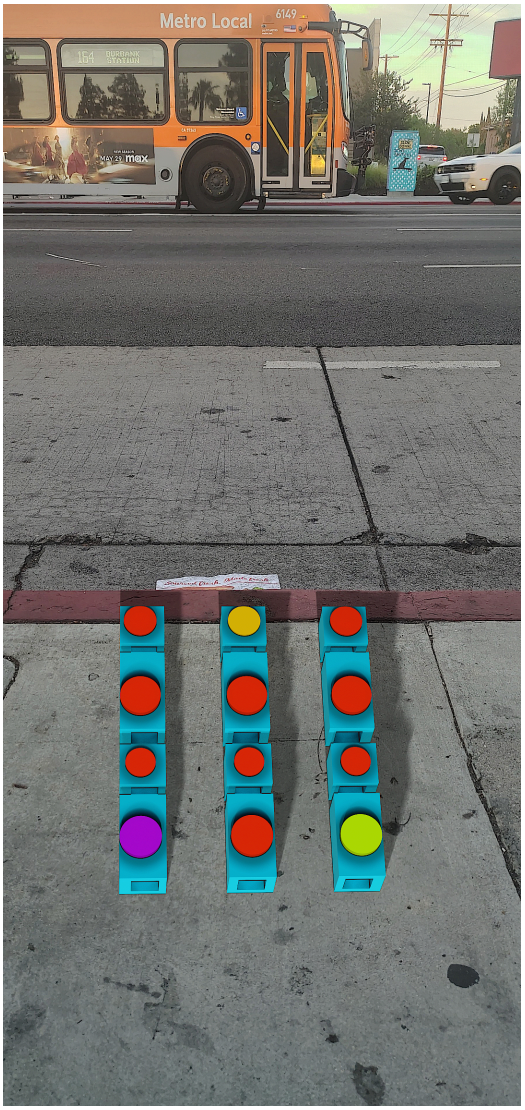
Metro Local
6149
154
BURBANK
STATION
max

For the algorithmic execution logic first the light sources will need to be determined if from a source of light detection using the camera lens hardware or lidar or infrared but primarily for this purpose were focusing on a camera lens if light hitting that lens is to be determined to for that color spectrum to all come from the same source and analysis of this should show that to be determined to be a light source that entire color spectrum from that source that point will need to show pure generation of the color spectrum and not degeneration this will separate it from objects that can reflect multiple colors through generation or degeneration these will not be light sources only light sources can be purely generative of one color spectrum.

The algorithmic execution logic for pathfinding lidar laser projection in the real world and then interpreting that data when it bounces back into the sensor it's so forth a process in which the first brightest white point from a given light source and the brightest band of white light will be determined to be the single light source secondly the first medium green light source in the scene will be determined and will be selected as the pivoting for path analysis this light source will then divide the remaining colors in the scene and separate itself by picking the ones out brighter than its medial that are not its same color and the ones that are dimmer than its medial and are not the same color, we're a single light ray breaks up on a surface this will be the habitat in which analysis for separation of scattering and what's causing the scattering begins first the obstruction of light scatter for the brightest white light detected or if there is no white light the next brightest light gray in the lightest color spectrum will be selected as the starting point and then for this habitat in which it scatters within this habitat and it scatters or is determined that scattering continues are calls variations of color lengths or color waves which is determined by the difference between the green medial and the brightest light source that was the starting point if scattering continues breaks up and repeats again in the same manner these objects must be determined as separate subhabitats because there is a break in the consistency of pattern of scatter secondly this will first primarily be determined before things are separated into subhabitats by determining if the surface in which the brightest light source is breaking upon that potential sub-object of its own habitat will be determining if the medial green source is generative when it reflects or bounces on the surface if it has a -1 and progresses towards degeneration on part of that surface but is generative and then increases by +1 from the same source this will be an object that has its own subhabitats in the primary objects subhabitat itself of the primary habitat in which all light sources are found but if multiple light sources of the green spectrum are bouncing on the same area they will first be compared against the medial green sources spectrum to separate theirs from its own but once that is achieved then the object will continue subcategory razzation of its habitats of the object's own attributes and for every other object and there its own subhabitat in the same group but it meets the same pattern but is not within the same position they will proceed to be their own habitat with their own sub habitat of the attributes in which are pawn that object such as that if all the objects are the same color but on the object there's different colored patterns those patterns will be attributes of that object and return those attributes or sub habitats of the object and its habitat further the medial green wavelength will determine the consistency in which all remaining light sources define the habitat subhabitat and attribute habitats by median and average for an object not to be confused

by its attributes and separated into habitats of the same hierarchy this will be avoided by calculating the hierarchy in which the medial light sources find that and the brightest light source starting position found that object as a sub habitat of the primary habitat and if all generative medial green wavelengths and the primary habitat and all the remaining light wave colors average to a mean where they define the genitive and degenerative of the medial green source to be contained by the initial parameters in which the habitat was found this and the objects attributes will become a habitat for those attributes and their subhabitats of the primary habitat of the object within the overall primary habitat this should equally apply to a camera lens in which a light sensor detects light hitting the entire sensor field at once versus where this code will originate on lidar light is sent out to bounce back in to the light sensor and then is analyzed this is an elementary process the same API once this is built should easily feed into both and for infrared sensors when all visible light wavelengths are found the infrared portion will be defined by where the infrared sensing begins and where the visible portion left off and what is not available to analyze but then provided by infrared data will pick up as the remaining flip side to this API and will process in the same manner in reverse position back to the visible spectrums API initial position to meet in the same pattern as a mirror in the mean of this will be the product in which overall lights sources are analyzed for their final result and light scatter two separate objects and their attributes within the overall image field.

As for any light sensing technology whether it be a camera lens a lidar sensor or infrared as more light sources are found within the view of these devices for the brightest color spectrum in its wavelength and the medial green for the green should always be found among all the green habitats of the overall primary habitat for all the the green and if more than one green of the same spectrum is meant the one in which provides the first degenerative or generative enhancement among the same attribute of an object or the object itself in that habitat will be determined the secondary, therefore the other that was in competition will be the primary and will continue the analysis algorithm and the same for the light source that is the brightest it would be determined among any that matches by this generative analysis but will not compare itself to the other light source of its lightness it will be compared against the medial green sources of which is first degenerative or degenerative and the brightest light source that is not green as the starting point that becomes genitive or degenerative will be considered secondary and the other will be the primary brightest light spectrum to continue the analysis of the light scatter and categorization of objects and their attributes among habitats in subhabitats these methods will need to dynamically update as light scattering continues in the view of these devices whether it be a camera sensor a lidar or infrared device. Light sources themselves must be not used to mask the object away for a flight shining on that object it should show that object but if another motion or light source breaks up that scatter of the habitat in which the object in the digital scene is showing then it will be determined which has priority and respecting the difference between the light source not being part of that object's habitat or being part of the habitat and this will be further be determined by any object that passes by the difference of the environment light and the light between where the digital asset measures from where it's mathematically supposed to be distant from the cameras view so any light source that's in between where the measurements of the digital asset is supposed to be located in 3D space away from the cameras view should be a difference of what's on the other side of the object for

the light sources that are detected further away from the cameras view then what's in between the object where it's mathematical settings have it placed from the cameras lens distance. So for an object to have its own habitat and it's attributes of that object to have their own subhabitats of the object's habitat for those colors to be to be determined among the contours of the object and attributes to not be a light source but be the actual color of those objects and attributes will be determined to be the first color that's not part of the medial green in the brightest light spectrum nor part of the first generative and degenerative tags The remaining color that's not part of this will be determined to be a true color of the object or an attribute of that object, this last method in tagging will also be used to as an overall tag proximity area of the habitat and that habitats potential subhabitats of attributes so everything that's marked as its own object and it's uncolor associated with that object that is within proximity of any type to the digital asset but has similarity in the object color or attribute color will dynamically update as the devices light scattering detection filled analyzes the data so that it can be evaluated to be further away or closer to the camera than what the digital asset is and also not part of that digital asset.