Subject Index

Α	shape deviations relative to standard template,
Abstract pattern matching. See Pattern matching	532-533
Active contours. See Segmentation	size measurement requirements,
Active vision, 1	529-530
Advanced driver assistance system (ADAS). See	of steel strips, 538–539
In-vehicle vision systems	of three-dimensional objects, 530
Agriculture example, egomotion and, 653-654	of wood, 538–539
Algorithm design criteria, 76	using X-rays, 546
accuracy, 279-280	Autonomous mobile robots. See Robots,
adaptability, 760	autonomous mobile
cost, 542, 682–683	D
detection sensitivity, 368	В
reliability, 760	Backpropagation algorithm. See Artificial neural
robustness, 315–316	networks
speed, 314-315	Bayes' decision theory, 676-679
tradeoffs, 354	Binary images and shape analysis, 229
Algorithmic parallelism, 744, 745	boundary tracking procedures, 257
Animal tracking, 631	circularity, 229
Articulated objects, 662	compactness, 254
Artificial neural networks (ANNs), 701	complexity, 254
Back-propagation algorithm, 705-708	concavity trees, 255
credit assignment problem, 705	connectedness in, 230-231
cross validation, 711	convex deficiency, 255
fixed increment rule, 702, 703, 704	convex hull, 255
Hebbian learning, 715	crossing number χ , 247–248
multilayer perceptron (MLP) networks,	distance functions, 240-243
708-709	image processing operations on, 257
noise suppression using, 40	measures for shape recognition, 253-254
self-organizing map (SOM), 670	metric properties, 238
spatiotemporal attention (STA), 665	modified crossing number $\chi_{\rm skel}$, 253, 259
validation set, 711, 712	moment approximations, 255
Widrow-Hoff delta rule, 703-704	object labeling and counting, 231–235
Automated visual inspection, 10-12	sigma function σ , 248
applications, 10	size filtering, 238
categories of, 530–532	skeletons and thinning, 245–254
of cereal grains, 553	Binocular images, 393–395
of circular products, 533	Blob size filtering, 659
using radial histograms, 533	Boundary pattern analysis, 266
color, importance of, 546	accuracy of length measures, 279-280
design of inspection systems, 757–760	centroidal profiles, 269-270
in factories, 527	chain code, 281
of food products, 528	Fourier descriptor method, 276
inspection process, 527	occlusion problems, 266
optimized algorithm, 351	(r, θ) plot, 272, 274
of precision components, 528–529	(s, κ) plot, 272, 276
of printed circuit boards, 530	(s, ψ) plot, 274–276
of products with high levels of variability,	Boundary tracking procedures, 269
539-542	Bubble sort, 44, 79

C	Harris operator, 158–166
Cameras, 732	Kitchen-Rosenfeld (KR) operator, 153
digitization and, 732–735	median-based operator, 153-158
line-scan, 731	Plessey operator, 165
Canny operator, 128	second-order derivative schemes, 151–153
use of hysteresis thresholding, 128, 129	SUSAN operator, 181
Centroidal profile. See Boundary pattern analysis	template matching, 150–151
Cereal grains, inspection of, 553	Zuniga—Haralick (ZH) operator, 153
dark contaminants, 555–560	Corner properties, 149
high-speed grain location, 566–572	bluntness, 151
insects, 560–566	contrast, 154
linear feature detection, 560	location, 166–167
rodent droppings, 555-557	orientation, 166–168
using sets of template masks, 572–575	pointedness, 151
Chord-tangent method. See Ellipse detection	sharpness, 151
Circle detection, 314	Counting, object, 231–238 Cross ratio, 439
accurate center location, 311-314	Chasles' theorem, 450–452
applications, 304-305	cross ratio spectra, 475
Hough transform and, 305-308	cross ratio spectra, 475
speed problem, overcoming, 314-320	5-point configuration, 447–449
unknown radius problem, 308-311	ratio of ratios, 441–445
Circles, egomotion and centers of, 460-462	Crossing number χ , 247–248
Circular operators, 118–119	Crossing number χ , 247 240
Circular products, inspection of, 533-537	D
Cluster analysis. See Statistical pattern recognition	
Color, 19	Data parallelism, 744, 745
channel, 22, 52, 75, 590, 739	Detection, 15
Color processing, 38	See also Circle detection; Corner Detection;
color bleeding, 52, 76	Edge detection; Ellipse detection; Eye
conversion to HSI, 547	detection; Facial feature detection;
distance-weighted median filter, 77	Insect detection; In-vehicle vision systems; Iris detection; Line detection;
image filtering, 74–76	Surveillance
mode filter, 65–67	contaminant, 555
principal components analysis (PCA),	crack, 92
695–699	defect, 109, 193
use in inspection, 546–548	foreign object, 539–541
value of, 20, 21, 22 vector median filter, 76, 78	hole, 327–328
Computational load, calculating, 339–342	interest point, 149
generalized Hough transform, 334–335	laparoscopic tool, 297–298
maximal cliques, 361, 371–373	line segment, 300, 560, 561
reducing, 54–55	linear feature, 560–563
Computer vision, 13	optimal, 353
Connectedness, in binary images, 230–231	parabola, 330, 640
Convolutions, 32–34	people, 662
Corner detection, 149	polygon, 335
See also Feature, invariant	salient feature, 378-379
Beaudet operators, 152	shadow, 721–724
DET operator, 152	vanishing point, 458-460
determining orientation, 166–168	Diameter bisection method. See Ellipse detection
Dreschler-Nagel (DN) operator, 153	Differential invariants, 452-454
generalized Hough transform, 369	Digitization, cameras and, 732-735

Dilation, 186 duality between erosion and, 189–190 inspection of cereal grains, 556, 557 properties of operators, 190–193	comparison of methods, 347–348, 349 determining parameters, 323–325 diameter bisection method, 320–322 generalized Hough transform method, 343–347
Discrete model of median shifts, 62–65	reducing computational load for, 347–348
Discrete model of rank order filters, 52–53	superellipse, 321, 322, 329
Discrete relaxation, 376	triple bisection algorithm, 570–571
Distance functions, 240–244	Ellipses, perspective and centers of, 460–462
Distortion, 733	Epipolar lines, 396
barrel, 488	generalized epipolar geometry, 491–492
edge shift, 78	Erosion, 186
foreshortening, 469	duality between dilation and, 189–190
optical, 769	inspection of cereal grains, 556, 557
perspective, 359–360	properties of operators, 190–193
pincushion, 489	Essential matrix, 492–495
radial, 488–490	Euclidean metric, 245
Driver assistance system. See In-vehicle vision	Extrinsic camera parameters, 486
systems	Eye detection, 463–465, 475
E	F
Edge, 111	Face recognition, 462-464, 475
planar, 112, 113	Facial feature detection, 224, 325-326, 330,
roof, 113	463-465, 645-647
step, 112, 113	Fast Fourier transform (FFT), 39, 754
Edge detection, 111	Feature, invariant, 168
advantages of, 111	affine invariant, 173
alternative schemes, 123-126	gradient location and orientation histogram
basic theory of, 113-115	(GLOH), 177
in binary images, 230	Harris-based, 170–173
Canny operator, 128–134	Hessian-based, 173
difference of Gaussians (DoG), 173–174	intensity extrema-based region detector
differential gradient (DG), 117-118	(IBR), 177
integrated directional derivative (IDD), 125	maximally stable extremal region (MSER),
Kirsch operator, 111	176–177
Laplacian of Gaussian (LoG), 171	scale invariant, 178
Laplacian operator, 134–135	scale-invariant feature operator (SFOP), 177, 179
Marr-Hildreth operator, 125-126, 146	scale invariant feature transform (SIFT),
morphological gradient operator, 201	173-174
non-maximum suppression, 153, 157, 158	speeded-up robust features (SURF),
orientation, 111, 114	174–176
Prewitt operator, 117–118, 124	use for wide baseline matching, 519-521
Reeves moment-based operator, 124	Feature collation, 369–371
Roberts operator, 117	Feature detection, 560
Robinson 3-level operator, 115	corner, 149
Robinson 5-level operator, 115	edge, 113
Sobel operator, 117–118, 121, 129, 135	hole, 327–328
template matching (TM), 115–116	interest point, 149
Yuille—Poggio operator, 146	line segment, 560
Egomotion See In-vehicle vision systems; Robots,	salient, 378–379
autonomous mobile	Filters, 38
Ellipse detection, 303, 320–325	anisotropic diffusion, 552
chord—tangent method, 322—323	applications, 74
chord—tangent method, 322—323	applications, 74

Filters (Continued)	Gaussian smoothing, 40-42
color, 74–76	Gaussian sphere, vanishing point detection and,
color bleeding and, 56, 76	457-458
computational load, reducing, 54-55	Generalized Hough transform (GHT), 334-335
distance-weighted median, 77	basic, 334–335
edge-preserving smoothing, 552	computational load, 370-371
Gaussian, 41, 54	feature collation and, 369-370
hybrid median, 77	gradient versus uniform weighting, 339-342
Kalman, 517-519	line detection and, 285–288
limit, 43	polygon detection and, 335
low-pass, 39-43	problems and setting up, 336
matched, 336	reducing computational load, 54-55
maximum, 53	sensitivity and computational load, calculating
mean, 68	339-342
median, 43–45	spatial matched filtering, 336-338
corner detector, based on, 81	Genetic algorithms (GAs), 109, 207
minimum, 53	Gradient weighting versus uniform weighting,
mode, 45–52	339–342
noise suppression by Gaussian smoothing,	Gray-level co-occurrence matrices, 202
40-42	Gray-tone (gray-scale) images, 18
particle. See Tracking moving objects	discrete model of median shifts, 62–65
rank order, 52–53	generalized morphology, 59–60
sharp-unsharp masking, 55-56	image processing operations on, 23–32
shifts introduced by, 67	versus color, 19–22
mean and Gaussian filters, 67–68	
median filters, 56–62	Н
discrete model of, 62-65	
mode filters, 65–67	Hamming distance, 7, 674, 675
rank order filters, 68–74	Hardware, 11
spatial, 336	design of inspection systems, 757–760
spatial frequency, 40–41	digital signal processing (DSP) chip, 754, 756
switched, 78	field programmable gate array (FPGA), 754,
truncated median, 48, 50	756
vector median, 52, 76	dynamic reconfigurability, 764
Feature location. See Feature detection	Flynn's classification, 748–750
Focus of contraction, 509	graphics processing unit (GPU), 757, 765
Focus of expansion (FoE), 509, 510,	Kinect human motion capture system, 766
511–512, 521	multiple instruction, multiple data (MIMD)
Food products, inspection of, 528	stream, 748–749
cereal grains, 553	multiple instruction, single data (MISD)
color, importance of, 546–548	stream, 748–749
nematode worms in fish, 739	optimal implementation, 750–754
Foot-of-normal method, 288–290	options, 754–755
Frame store, 23–24, 35	pipelined processor, 747–748
Full perspective projection, 418, 429, 435, 436,	N processors, speed gain using, 747–748
461	real-time, 754–755
Fundamental matrix, 495–496	single instruction, multiple data (SIMD)
Tulidamentai matrix, 453—450	stream, 745–747
G	single instruction, single data (SISD) stream,
-	746, 748
Gaussian distributions, 47, 88, 296-297, 548,	specification and design, 751-752
779, 780, 783	very large scale integration (VLSI), 757, 763,
Gaussian filters. See Filters	764

Harris interest point detector, 158–166	suppressing noise, 38
Hole detection, 327	on binary images, 38
Homogeneous coordinates, 478, 481	on gray-scale images, 39
Homography, 466, 467, 475, 497, 611–613, 617,	Image segmentation. See Segmentation
618, 795	Imaging modalities, 718
Hough transform (HT), 285	color, 547-548
See also Generalized Hough transform	HSI, 547
agriculture application, 658	RBG, 547
fast, 351	hyperspectral, 577, 738-739
Gerig-Klein back-projection technique,	infra-red (NIR), 576, 577, 635, 666, 698,
352-353	738-739
nature of, 333–342	multispectral, 698, 738
uses, 304	thermal, 577, 634, 635, 666, 668
circle detection, 304-308, 328	visible, 397
corner detection, 166-168	X-ray, 540
ellipse detection, 320-325, 328	dual-emission X-ray absorptiometry
line detection, 285–288	(DEXA), 546
superellipse detection, 329	In-vehicle vision systems, 636
vanishing point detection, 456–458	See also Robots, autonomous mobile;
<i>xy</i> -grouping, 290–291	Surveillance; Tracking moving objects
Human—computer interaction, HCI, 765	advanced driver assistance system (ADAS),
Human gait analysis, 626–628	663-671
Hyperspectral cube, 738	all hours-all weathers, 666
Hyperspectral imaging, 577, 738–739	catadioptric cameras, 669
	convoy, 638
I	global positioning system (GPS), 638, 670
	ground plane, location and use of, 653–654
Illumination schemes, 719–732	licence plate location, 647–649
infinite parallel strip lights example,	omnidirectional cameras, 669
726–729	pedestrian location, 650-653
line-scan cameras, 730–731	chamfer matching, 650
overview of uniform illumination, 729–730	skin color, 652
producing uniform illumination, 724–726	road lane marking location, 640-641
shadows, eliminating, 721–724	RANSAC, 641
Image acquisition, 718	road sign, location, 641-644
cameras and digitization, 732–735	chamfer matching, 644
illumination schemes, 719–732	matched filter, 643
sampling theorem, 735–738	roadway location, 638-640
Image differencing, 506, 521 Image filters (filtering). See Filters	use of vanishing points (VPs), 458-460
Image inters (internig), see Pitters Image parallelism, 745–746	vehicle location, 644-645
Image parametrism, 743–746 Image processing, 6, 13, 15	under-vehicle shadow, 645
applying convolutions, 32–34	Industrial parts, location of, 415-417
	Insect detection, 576
applying logical operations, 287 brightening, 17	Inspection. See Automated visual inspection
6 6	Intrinsic camera parameters, 486
clearing, 24 displaying, 24	Invariant feature. See Feature, invariant
1 , 0	Invariants, 439
expanding, 29 inverting, 24, 27	See also Feature, invariant
C	cross ratio, 441-445
sequential versus parallel operations, 34–35	functions, symmetric, 454–456
shifting, 17	5-point configuration, 654
shrinking, 28 size filtering, 238–240	spectra, 475
512c Hitching, 230-240	

Invariants (Continued)	defined, 768
defined, 441	future for, 768-769
differential and semidifferential,	importance of, 768–770
452-454	tradeoffs, 770-772
for noncollinear points, 445-449	Mathematical morphology, 187
for points on conics, 449-452	closing, 193-195
reasons for using, 439	connectivity-based analysis, 195-196
Inverse graphics, 9–10	dilation
Iris detection, 224, 325-326, 330, 463, 645	generalized, 187-188
use to estimate eye Gaze direction, 325	duality between dilation and erosion, 189-190
	erosion
J	generalized, 188-189
Junation orientation technique, 411, 415	gray-scale processing, 197–201
Junction orientation technique, 411–415	maximum, 199
V	minimum, 199
K	morphological analysis, 537, 552, 555, 558,
Kalman filter. See Tracking moving objects	576, 577, 589, 590, 592, 619, 663, 670,
	764, 776
L	morphological gradient, 201-205
	noise, effects of, 201–205
Labeling, 231–238	opening, 193–195
object, 231–238	residue function, 193
relaxation, 379	template matching, 206
Laparoscopic tools, 297–298	top hat operator, 193
location of tips, 298	black, 193
location using RANSAC, 297–298	white, 193
Laplacian operator, 134–135	umbra homomorphism theorem, 199–200
Laws' texture energy approach, 217–220	Matrix (matrices), 497
Learning See Artificial neural networks; Statistical	essential, 492-495, 496-497
pattern recognition	fundamental, 495–497
Least median of squares, 787–790	gray-level co-occurrence, 214–217
Least squares analysis, 779	Maximal clique, 355, 361
Light emitting diode (LED) light sources,	algorithm, 367
731-732	computational load, 370–371
Light striping, 396	concept, 361–362
Line detection, 284	generalizing, 371–373
final line fitting, 292–293	Mean filters. See Filters
foot-of-normal method, 288-290	Median filters. See Filters
generalized Hough transform and, 285-288	Metric properties, in digital images, 393
Hough transform and, 285–288	Mobile robots. See Robots, autonomous mobile
longitudinal localization, 290-292	Mode filters. See Filters
RANSAC, 293–297	Moment approximations, 255
slope-intercept equation, 285-286	Moore's law, 754, 772–773
Line-scan cameras, 730–731	Morphology. See Mathematical morphology
Linear feature detection, 560-563	Motion, 504
Local maximum operation, 293	See also Surveillance; Tracking moving
Local minimum operation, 199, 201	objects
Longitudinal line localization, 290-292	aperture problem, 506
	focus of expansion (FOE), 511–512
M	human gait analysis, 626–628
	Kalman filters, 517–519
Machine vision, 12	optical flow, 506–509
See also Automated visual inspection	
applications, 769	snakes, 633

stereo from, 515-517	Particle filter. See Tracking moving objects
time-to-adjacency analysis, 513-514	Pattern matching, 358
traffic flow monitoring, 614-618	affine matching, 380
Multiple-view vision, 490-491	Hausdorff distance, 381
	cream biscuits example, 363-366
N	feature collation and use of generalized Hough
Nasty realities, 768	transform, 354
clutter, 768	local-feature-focus (LFF), method, 368
glint, 769	graph matching, 358
noise, 768	maximal clique algorithm, 367
Gaussian, 769	maximal clique concept, 371
impulse, 769	reproducible kernel Hilbert space (RKHS),
white, 336–337	380
occlusion, 621	spectral graph theory, 380
shadow, 721–722	relational descriptors, 373-376
Navigation, robots. See Robots, autonomous	relaxation labeling, 376
mobile	search space, 376-377
Near infra-red (NIR), 576	similarity measures, 379, 380
Nearest neighbor algorithm, 674–676	Bhattacharyya coefficient, 604
Neighborhood parallelism, 745–746	Pattern recognition. See Statistical pattern
Noise, 40	recognition
morphological grouping operations and effects	People tracking, 579
of, 201–205	applications, 579
spike, 42	basic techniques, 620
white, 336–337	from vehicles, 620
	Performance measures, 177-179, 183, 686
Noise suppression, 40	accuracy, 688
artificial neural networks and, 701–705 Gaussian smoothing, 40–42	area under curve (AUC), 688, 717
3	discriminability, 688
median filters, 43–45	F-measure, 688, 716
mode filters, 45–52	false negative (FN), 687
rank order filters, 52–53	false negative rate (fnr), 687
Noncollinear points invariants for, 445–449	false positive (FP), 687
0	false positive rate (fpr), 687
	precision, 688
Object labeling and counting, 231–238	recall, 687
Object location. See Detection	receiver operating characteristic (ROC), 147,
Object recognition schemes, 3-D, 410–411	667, 688, 716
Occlusion, 606	sensitivity, 687
apparent occlusion, 620	sorting optimization curve (SOC), 716
dynamic occlusion, 620	specificity, 688
occlusion reasoning, 616	true negative (TN), 686
problems, 276–279, 616	true negative rate (tnr), 686
scene occlusion, 620	true positive (TP), 686
Optical flow, 506–509	true positive rate (tpr), 686
interpretation of, 509-511	Personal computers, 756
problems with, 514-515	Perspective, 466
Optimizing network architecture, 764	in art, 466–472
Overfitting training data, 709–712	vanishing point, 456-458
_	Perspective inversion, 425–427
P	Perspective projection, 392
Parallel image processing operations, 34–35	full, 429, 431
Parallel thinning, 250	3-point problem, 433-434

Perspective projection (Continued)	Robust statistics, 778
symmetric trapezia problem, 434	N adjacent points sample consensus
weak, 425, 427–429, 431	(NAPSAC), 794
Phong model, 402	beta [distribution] sampling consensus
Photometric stereo, 402–405	(BetaSAC), 795
Plan view of ground plane, 654	breakdown point, 780-782
constructing, 654	features from accelerated segment test
Point-line duality, 285	(FAST), 177
Point pattern matching. See Pattern matching,	group sampling consensus (GroupSAC), 795
graph matching	Hough transform and, 778
Point spread functions (PSFs), 32–34	importance sampling consensus (IMPSAC),
Principal components analysis (PCA), 695-699	794-795
Principal point, 486	influence function, 783-787
Probabilistic relaxation, 376	inlier, 782, 791
Probability and image analysis, 699	L-estimator, 782, 789
Projection schemes, 3-D, 392–398	least median of squares (LMedS), 787-790
PROLOG, 376	least squares regression, 782, 787, 790
Propagation, 231	M-estimator, 782, 789
T. C.	outlier, 782, 783, 784, 785, 793, 795
R	progressive sample consensus
	(PROSAC), 795
Radial distortions, 479, 495	R-estimator, 782, 789
correcting, 488–490	random sample consensus (RANSAC),
Rank order filters, 52–53	791–792
shifts introduced by, 68–74	relative efficiency, 781
RANSAC (random sample consensus) approach,	Robustness, 179, 315–316, 790
292–297, 301, 640, 641, 668, 791–792	
Raw pixel measurements, 495	S
Real-time operation, 523, 602, 670	
Receiver operating characteristic (ROC), 684–688	Salt and pepper noise, 30, 31
Recognition. See Statistical pattern recognition	Sampling theorem, Nyquist, 735–738
Region-growing methods. See Segmentation	Scaled orthographic projection, 425, 427, 435
Region of interest (RoI), 325	Scene analysis, 8–9
Relational descriptors, 373–376	Schmitt trigger, 126
Relaxation labeling, 376, 379	Search space, 269, 310
(r, θ) plot. See Boundary pattern analysis	Semidifferential invariants, 452–454
Road, 640, 668	Segmentation, 82
lane markings, 640, 641, 642, 766	See also Thresholding (threshold)
location, 640–644	active contour, 136
signs, 641–644	maximum a posteriori (MAP) modeling,
Robots, autonomous mobile, 653	147–148
active vision, 1	deformable contour, 136
agriculture application example, 656	graph cuts, 421
applications, 74	min flow-max cut theorem, 142
centers of circles and ellipses, 460	residual network, 144
cross ratios, 474	level set, 140–141
distance function	fast marching method, 141
navigation for, 479	region-growing, 83–84
plan view of ground plane, constructing, 654	scattergrams, use of, 86–87
safety issues, 579	snake, 136, 614
vanishing point detection, 474	greedy algorithm, 138
vehicle guidance, 656	Sequential image processing operations, 34–35
Robust estimator. See Robust statistics	Sequential labeling 235

Sequential pattern recognition, 699	multiple classifiers, 688-691
Sequential thinning, 249	naïve Bayes, 678-679
Shading, shape from, 398–402	nearest neighbor (NN) algorithm, 674-676
Shadows, 474	optimum number of features, 681-682
detecting, 719	overfitting to training data, 709–712
eliminating, 721–724	principal components analysis, 695-699
Shape recognition, 254	probability, relevance of, 699
See also Binary images and shape analysis	supervised learning, 691–692
from angle, 411	support vector machine, 700–701
moment approximations, 255	undertraining, 710
from shading, 398–402	unsupervised learning, 691–692
simple measures for, 229	Stereo from motion, 515–517
skeletons and, 253–254	Stitching photographs, 439, 441, 470–472,
from texture, 407–408	475
(s, κ) plot. See Boundary pattern analysis	Straight edge detection, 288
(s, ψ) plot. See Boundary pattern analysis	Stretching image contrast, 114, 156
Simplex algorithm, 630	Structured lighting, 408
Singular value decomposition (SVD), 380, 497	Subgraph—subgraph isomorphism, 360, 378
Skeletons and thinning, 244	Sudden step-edge response, 112, 113
crossing number χ , 247–248	Support vector machine (SVM), 700–701
defined, 244	Surveillance, 10, 578
guided, 251	
_	See also In-vehicle vision systems; Tracking
modified crossing number $\chi_{\rm skel}$, 253	moving objects
nature of skeleton, 251	articulated bodies, analyzing motions of, 634
node analysis, 251–253	iterative parsing, 634
shape analysis using, 253	background modeling, 585
sigma function σ , 248	expectation maximization (EM) algorithm,
thinning implementations, 248–251	589
Snakes. See Active contours	fluttering vegetation, 586, 587, 589
Spatial matched filtering, 336–337	Gaussian mixture model (GMM), 588
Speed gain using N processors, 747–748	non-parametric model, 593
Statistical pattern recognition (SPR), 672	parametric model, 590–593
See also Artificial neural networks;	field of view (FoV), 583, 609
Performance measures	foreground detection, 584
AdaBoost, 715	ghost, 586, 590, 591, 632
bag-of-words, 521	ground plane, location and use of, 609, 610,
bagging, 714	611
Bayes' decision theory, 676–678	in-plane rotation, 600
boosting, 714	licence plate location, 618–620
cluster analysis, 691, 692	monitoring traffic flow, 614-618
agglomerative algorithms, 693, 694	motion distillation, 623
divisive algorithms, 693, 694	rigidity parameter, 624, 625
iterative self-organizing data analysis	multiple cameras, 609
(ISODATA), 694, 713	non-overlapping fields of view, 613-614
MacQueen's k-means algorithm, 695	overlapping fields of view, 613
noniterative clustering algorithms, 695	transition probability, 595
conditional risk, 682	occlusion reasoning, 607–609, 620–623
cost functions, 682–683	out-of-plane rotation, 600
distinct class based splitting measure (DCSM),	pedestrian location, 651, 652, 662
716	chamfer matching, 607-609
error-reject tradeoff, 682-683	histogram of orientated gradients (HOG),
face recognition, 462-463	668

Surveillance (Continued)	spatial gray-level dependence matrix
human gait analysis, 626-628	(SGLDM) approach, 214
minimum description length (MDL)	structural approaches to, 221-222
approach, 607	Thermal imaging, 526, 577
people location, 613	Thinning, 244
shadow suppression, 590	crossing number χ , 247–248
stationary background problem, 590	guided, 251
traffic flow monitoring, 614	implementations, 248–251
Bascle method, 614–615	modified crossing number $\chi_{\rm skel}$, 253
Koller method, 615-618	sigma function σ , 248
transient background problem, 590	Three-dimensional (3-D) analysis, 389
use of color, 599	ambiguity, 390
chromaticity coordinates, 592	Ballard—Sabbah method, 420
chrominance parameters, 601	camera calibration, 418
color histograms, 599–603	eight-point algorithm, 497
color indexing, 599–600	essential matrix, 492
vehicle location, 644–646	fundamental matrix, 495
Symmetry, 115, 322	generalized epipolar geometry, 491–492
mirror symmetry, 356	homogeneous coordinates, 481, 483
reflection symmetry, 645	homography, 611
rotation symmetry, 360	Horaud's junction orientation technique,
symmetric object, 366	411–415
symmetry detection, 645	image reconstruction, 500
System design, 451, 638	image rectification, 498–499
inspection systems, 538, 757	image transformations, 479
optimization, 742	industrial parts, location of, 415–417
1	intrinsic and extrinsic camera parameters, 486
_	methods for studying, 359
Т	multiple-view vision, 490-491
Template matching (TM), 7, 8, 112, 115	object recognition schemes, 410–411
boundary pattern analysis and, 269	perspective <i>n</i> -point (PnP) problem, 301, 436
coarse–fine, 273–274	photometric stereo, 402-405
corner detection and, 150-151	pose estimation, 437, 794
design of directional masks, 575	use of coplanarity, 493
edge detection and, 115-116	projection schemes, 392–393
equal area rule, 576	radial distortions, correcting, 488–490
hole detection and, 327	shape from angle, 411
matched filter, 378	shape from shading, 398-402
multistage, 774	bidirectional reflectance distribution function
2-stage, 771-772, 775	(BRDF), 421
tradeoffs, 771–772	smoothness, surface, 405-407
Texture, 201-202, 209	shape from texture, 407-408
defined, 210	Silberberg method, 420
fractal-based measures of, 223	structure from motion, 514, 521
Markov random field models of, 223	structured lighting, 408-410
shape from, 223	surface smoothness, 405-407
texel, 210-211	transformation parameters, 484
Texture analysis	triangulation, 500
Ade's eigenfilter approach, 220-221	Three-dimensional (3-D) objects, 530
autocorrelation approach, 213	inspection of, 410
gray-level co-occurrence matrices, 214-217	Thresholding (threshold), 82
Laws' texture energy approach, 217-220	See also Segmentation

Top-hat operator, 193 Tracking moving objects, 517 See also Surveillance animal tracking, 631 Kalman filter, 517–519 mean shift algorithm, 599 monitoring traffic flow, 578 particle filter, 594–599 auxiliary particle filter (APF), 597 Condensation, 597 cumulative distribution function (CDF), 597 iCondensation, 597 iterated likelihood weighting (ILW), 598 kernel particle filter, 598 Epanechnikov kernel, 599 sample impoverishment, 596 sampling importance resampling (SIR), 596 sequential importance sampling (SIS), 595 people tracking, 579 Leeds people tracker, 579 Siebel—Maybank tracker, 633 from vehicles, 580 Traffic flow monitoring. See Surveillance Training data, overfitting to, 709–712 Robots, autonomous mobile Video analytics. See Surveillance Vision, 1 See also Automated visual inspection; Machine vision active, 2 human, 1–2, 663 multiple-view, 490–491 Vision, nature of, 2 inverse graphics, 9–10 object location, 6–8 recognition, 4 scene analysis, 8–9 W Weak perspective projection, 427–429 White noise, 336 Wide baseline, 519 matching, 519 use of invariant feature detector, 521 views, 520 Window operation, 26, 35, 38, 147, 196	adaptive, 88	Euclidean, 452
bias when selecting, 86–87 Chow and Kaneko approach, 91 dynamic, 88, 91 entropy-based, 96 finding a suitable, 85–86 global valley method (GVM), 98–101 hysteresis, 93 images, 83, 91 local, 92–93 maximum likelihood, 97 in unimodal distributions, 91 concavity analysis, 106 variance-based, 95 Time-to-adjacency analysis, 513–514 Top-hat operator, 193 Tracking moving objects, 517 See also Surveillance animal tracking, 631 Kalman filter, 517–519 mean shift algorithm, 599 monitoring traffic flow, 578 particle filter, 594–599 auxiliary particle filter (APF), 597 Condensation, 597 iterated likelihood weighting (ILW), 598 kernel particle filter, 598 Epanechnikov kernel, 599 sampling importance resampling (SIR), 596 sequential importance sampling (SIS), 595 people tracking, 579 Leeds people tracker, 579 Siebel–Maybank tracker, 633 from vehicles, 580 Traffic flow monitoring. See Surveillance Training data, overfitting to, 709–712 Transform (Transformation), 479 See also Hough transform affine, 498 maintenance of convexity, 380	between-class variance method (BCVM),	Fourier, 39-40, 736, 754
Chow and Kaneko approach, 91 dynamic, 88, 91 entropy-based, 96 finding a suitable, 85–86 global valley method (GVM), 98–101 hysteresis, 93 images, 83, 91 local, 92–93 maximum likelihood, 97 in unimodal distributions, 91 concavity analysis, 106 variance-based, 95 Time-to-adjacency analysis, 513–514 Top-hat operator, 193 Tracking moving objects, 517 See also Surveillance animal tracking, 631 Kalman filter, 517–519 mean shift algorithm, 599 monitoring traffic flow, 578 particle filter, 594–599 auxiliary particle filter (APF), 597 Condensation, 597 iCondensation, 597 iCondensation, 597 iCrated likelihood weighting (ILW), 598 kernel particle filter, 598 Epanechnikov kernel, 599 sample impoverishment, 596 sequential importance resampling (SIR), 596 sequential importance resampling (SIS), 595 people tracking, 579 Leeds people tracker, 579 Siebel-Maybank tracker, 633 from vehicles, 580 Traffic flow monitoring. See Surveillance Training data, overfitting to, 709–712 Transform (Transformation), 479 See also Hough transform affine, 498 maintenance of convexity, 380	95-96, 106	Radon, 300
dynamic, 88, 91 entropy-based, 96 finding a suitable, 85–86 global valley method (GVM), 98–101 hysteresis, 93 images, 83, 91 local, 92–93 maximum likelihood, 97 in unimodal distributions, 91 concavity analysis, 106 variance-based, 95 Time-to-adjacency analysis, 513–514 Top-hat operator, 193 Tracking moving objects, 517 See also Surveillance animal tracking, 631 Kalman filter, 517–519 mean shift algorithm, 599 monitoring traffic flow, 578 particle filter, 594–599 auxiliary particle filter (APF), 597 Condensation, 597 iCondensation, 597 iCondensation, 597 iCondensation, 597 iterated likelihood weighting (ILW), 598 kernel particle filter, 598 Epanechnikov kernel, 599 sample impoverishment, 596 sampling importance resampling (SIS), 595 people tracking, 579 Leeds people tracker, 579 Siebel-Maybank tracker, 633 from vehicles, 580 Traffic flow monitoring. See Surveillance Training data, overfitting to, 709–712 Transform (Transformation), 479 See also In-vehicle vision systems detection, 458–460 See also In-vehicle vision systems detection, 456–458 use to find circle and ellipse centers, 460–462 Vehicle guidance. See In-vehicle vision systems Robots, autonomous mobile Video analytics. See Surveillance Vision, 1 See also Automated visual inspection; Machine vision active, 2 human, 1–2, 663 multiple-view, 490–491 Vision, nature of, 2 inverse graphics, 9–10 object location, 6–8 recognition, 4 scene analysis, 8–9 W Weak perspective projection, 427–429 White noise, 336 Wide baseline, 519 matching, 519 use of invariant feature detector, 521 views, 520 Window operation, 26, 35, 38, 147, 196 X X-ray inspection, 542–546 dual-emission X-ray absorptiometry (DEXA 546, 552	bias when selecting, 86-87	similarity, 170
dynamic, 88, 91 entropy-based, 96 finding a suitable, 85–86 global valley method (GVM), 98–101 hysteresis, 93 images, 83, 91 local, 92–93 maximum likelihood, 97 in unimodal distributions, 91 concavity analysis, 106 variance-based, 95 Time-to-adjacency analysis, 513–514 Top-hat operator, 193 Tracking moving objects, 517 See also Surveillance animal tracking, 631 Kalman filter, 517–519 mean shift algorithm, 599 monitoring traffic flow, 578 particle filter, 594–599 auxiliary particle filter (APF), 597 Condensation, 597 iCondensation, 597 iCondensation, 597 iCondensation, 597 iterated likelihood weighting (ILW), 598 kernel particle filter, 598 Epanechnikov kernel, 599 sample impoverishment, 596 sampling importance resampling (SIS), 595 people tracking, 579 Leeds people tracker, 579 Siebel-Maybank tracker, 633 from vehicles, 580 Traffic flow monitoring. See Surveillance Training data, overfitting to, 709–712 Transform (Transformation), 479 See also In-vehicle vision systems detection, 458–460 See also In-vehicle vision systems detection, 456–458 use to find circle and ellipse centers, 460–462 Vehicle guidance. See In-vehicle vision systems Robots, autonomous mobile Video analytics. See Surveillance Vision, 1 See also Automated visual inspection; Machine vision active, 2 human, 1–2, 663 multiple-view, 490–491 Vision, nature of, 2 inverse graphics, 9–10 object location, 6–8 recognition, 4 scene analysis, 8–9 W Weak perspective projection, 427–429 White noise, 336 Wide baseline, 519 matching, 519 use of invariant feature detector, 521 views, 520 Window operation, 26, 35, 38, 147, 196 X X-ray inspection, 542–546 dual-emission X-ray absorptiometry (DEXA 546, 552	Chow and Kaneko approach, 91	trace, 355-356
finding a suitable, 85–86 global valley method (GVM), 98–101 hysteresis, 93 images, 83, 91 local, 92–93 maximum likelihood, 97 in unimodal distributions, 91 concavity analysis, 106 variance-based, 95 Time-to-adjacency analysis, 513–514 Trop-hat operator, 193 Tracking moving objects, 517 See also Surveillance animal tracking, 631 Kalman filter, 517–519 mean shift algorithm, 599 monitoring traffic flow, 578 particle filter, 594–599 auxiliary particle filter (APF), 597 Condensation, 597 cumulative distribution function (CDF), 597 iterated likelihood weighting (ILW), 598 kernel particle filter, 598 Epanechnikov kernel, 599 sample impoverishment, 596 sampling importance esampling (SIR), 596 sequential importance sampling (SIS), 595 people tracking, 579 Leeds people tracker, 579 Siebel—Maybank tracker, 633 from vehicles, 580 Traffic flow monitoring. See Surveillance Training data, overfitting to, 709–712 Transform (Transformation), 479 See also Hovehicle vision systems detection, 458–460 See also In-vehicle vision systems Robots, autonomous mobile Video analytics. See In-vehicle vision systems Robots, autonomous mobile Video analytics. See Surveillance Vision, 1 See also Automated visual inspection; Machine vision active, 2 human, 1–2, 663 multiple-view, 490–491 Vision, nature of, 2 inverse graphics, 9–10 object location, 6–8 recognition, 4 scene analysis, 8–9 W Weak perspective projection, 427–429 White noise, 336 Wide baseline, 519 use of invariant feature detector, 521 views, 520 Window operation, 26, 35, 38, 147, 196 Transform (Transformation), 479 See also Hovehicle vision systems detection, 456–858 use to find circle and ellipse centers, 460–462 Vehicle guidance. See In-vehicle vision systems detection, 456–868 use to find circle and ellipse centers, 460–462 Vehicle guidance. See In-vehicle vision systems Robots, autonomous mobile Video analytics. See Surveillance Training tracking, 631 W Weak perspective projection, 427–429 White noise, 336 Wide baseline, 519 use of invariant feature detector, 521 views,		
global valley method (GVM), 98–101 hysteresis, 93 images, 83, 91 local, 92–93 maximum likelihood, 97 in unimodal distributions, 91 concavity analysis, 106 variance-based, 95 Time-to-adjacency analysis, 513–514 Top-hat operator, 193 Tracking moving objects, 517 See also Surveillance animal tracking, 631 Kalman filter, 517–519 mean shift algorithm, 599 monitoring traffic flow, 578 particle filter, 594–599 auxiliary particle filter (APF), 597 condensation, 597 cumulative distribution function (CDF), 597 iCondensation, 597 iterated likelihood weighting (ILW), 598 kernel particle filter, 598 Epanechnikov kernel, 599 sample impoverishment, 596 sampling importance sampling (SIR), 596 sequential importance sampling (SIS), 595 people tracking, 579 Leeds people tracker, 579 Siebel–Maybank tracker, 633 from vehicles, 580 Traffic flow monitoring. See Surveillance Training data, overfitting to, 709–712 Transform (Transformation), 479 See also Hovekicles vision systems detection, 458–460 See also In-vehicle vision systems detection, 456–458 use to find circle and ellipse centers, 460–462 Vehicle guidance. See In-vehicle vision systems Robots, autonomous mobile Video analytics. See Surveillance Vision, 1 See also Automated visual inspection; Machine vision active, 2 human, 1–2, 663 multiple-view, 490–491 Vision, nature of, 2 inverse graphics, 9–10 object location, 6–8 recognition, 4 scene analysis, 8–9 W Weak perspective projection, 427–429 White noise, 336 Wide baseline, 519 use of invariant feature detector, 521 views, 520 Window operation, 26, 35, 38, 147, 196 X X-ray inspection, 542–546 dual-emission X-ray absorptiometry (DEXA 546, 552	entropy-based, 96	U
global valley method (GVM), 98–101 hysteresis, 93 images, 83, 91 local, 92–93 maximum likelihood, 97 in unimodal distributions, 91 concavity analysis, 106 variance-based, 95 Time-to-adjacency analysis, 513–514 Trop-hat operator, 193 Tracking moving objects, 517 See also Surveillance animal tracking, 631 Kalman filter, 517–519 mean shift algorithm, 599 monitoring traffic flow, 578 particle filter, 594–599 auxiliary particle filter (APF), 597 Condensation, 597 cumulative distribution function (CDF), 597 iCondensation, 597 iterated likelihood weighting (ILW), 598 kernel particle filter, 598 Epanechnikov kernel, 599 sample impoverishment, 596 sampling importance sampling (SIS), 595 people tracking, 579 Leeds people tracker, 579 Siebel-Maybank tracker, 633 from vehicles, 580 Traffic flow monitoring. See Surveillance Training data, overfitting to, 709–712 Transform (Transformation), 479 See also Hough transform affine, 498 maintenance of convexity, 380 Vanishing point, 458–460 See also In-vehicle vision systems detection, 456–458 use to find circle and ellipse centers, 460–462 Vehicle guidance. See In-vehicle vision systems Robots, autonomous mobile Video analytics. See Surveillance Vision, 1 See also Automated visual inspection; Machine vision active, 2 human, 1–2, 663 multiple-view, 490–491 Vision, atture of, 2 inverse graphics, 9–10 object location, 6–8 recognition, 4 scene analysis, 8–9 W Weak perspective projection, 427–429 White noise, 336 Wide baseline, 519 matching, 519 use of invariant feature detector, 521 views, 520 Window operation, 26, 35, 38, 147, 196	finding a suitable, 85–86	Umbro homomorphism theorem 100, 200
images, 83, 91 local, 92–93 maximum likelihod, 97 in unimodal distributions, 91 concavity analysis, 106 variance-based, 95 Time-to-adjacency analysis, 513–514 Top-hat operator, 193 Tracking moving objects, 517 See also Surveillance animal tracking, 631 Kalman filter, 517–519 mean shift algorithm, 599 monitoring traffic flow, 578 particle filter, 594–599 auxiliary particle filter (APF), 597 Condensation, 597 cumulative distribution function (CDF), 597 iCondensation, 597 iterated likelihood weighting (ILW), 598 kernel particle filter, 598 Epanechnikov kernel, 599 sample impoverishment, 596 sampling importance resampling (SIS), 595 people tracking, 579 Leeds people tracker, 579 Siebel-Maybank tracker, 633 from vehicles, 580 Traffic flow monitoring. See Surveillance Training data, overfitting to, 709–712 Transform (Transformation), 479 See also Hovehicle vision systems detection, 456–458 use to find circle and ellipse centers, 460–462 Vehicle guidance. See In-vehicle vision systems Robots, autonomous mobile Video analytics. See Surveillance Vision, 1 See also Automated visual inspection; Machine vision active, 2 human, 1–2, 663 multiple-view, 490–491 Vision, nature of, 2 inverse graphics, 9–10 object location, 6–8 recognition, 4 scene analysis, 8–9 W Weak perspective projection, 427–429 White noise, 336 Wide baseline, 519 use of invariant feature detector, 521 views, 520 Window operation, 26, 35, 38, 147, 196 X X-ray inspection, 750–456 dual-emission X-ray absorptiometry (DEXA 546, 552 See also In-vehicle vision systems detection, 456–458 use to find circle and ellipse centers, 460–462 Vehicle guidance. See In-vehicle vision systems detection, 456–458 use to find circle and ellipse centers, 460–462 Vehicle guidance. See In-vehicle vision of the centers of the content of the content of the centers of the centers of the centers, 460–462 Vehicle guidance. See In-vehicle vision systems Robots, autonomous mobile Video analytics. See Surveillance Vision, 1 See also Automated visual inspection; Machine visual season	global valley method (GVM), 98-101	Omora nomomorphism theorem, 199, 200
images, 83, 91 local, 92–93 maximum likelihood, 97 in unimodal distributions, 91 concavity analysis, 106 variance-based, 95 Tracking moving objects, 517 See also Surveillance animal tracking, 631 Kalman filter, 517–519 mean shift algorithm, 599 monitoring traffic flow, 578 particle filter, 594–599 auxiliary particle filter (APF), 597 Condensation, 597 cumulative distribution function (CDF), 597 iCondensation, 597 iterated likelihood weighting (ILW), 598 kernel particle filter, 598 Epanechnikov kernel, 599 sample impoverishment, 596 sampling importance sampling (SIS), 595 people tracking, 579 Leeds people tracker, 579 Siebel–Maybank tracker, 633 from vehicles, 580 Traffic flow monitoring. See Surveillance Training data, overfitting to, 709–712 Transform (Transformation), 479 See also In-vehicle vision systems detection, 456–458 use to find circle and ellipse centers, 460–462 Vehicle guidance. See In-vehicle vision systems Robots, autonomous mobile Video analytics. See Surveillance Vision, 1 See also Automated visual inspection; Machine vision active, 2 human, 1–2, 663 multiple-view, 490–491 Vision, nature of, 2 inverse graphics, 9–10 object location, 6–8 recognition, 4 scene analysis, 8–9 W Weak perspective projection, 427–429 White noise, 336 Wide baseline, 519 matching, 519 use of invariant feature detector, 521 views, 520 Window operation, 26, 35, 38, 147, 196 X X-ray inspection, 542–546 dual-emission X-ray absorptiometry (DEXA 546, 552	hysteresis, 93	V
maximum likelihood, 97 in unimodal distributions, 91 concavity analysis, 106 variance-based, 95 Time-to-adjacency analysis, 513–514 Top-hat operator, 193 Tracking moving objects, 517 See also Surveillance animal tracking, 631 Kalman filter, 517–519 mean shift algorithm, 599 monitoring traffic flow, 578 particle filter, 594–599 auxiliary particle filter (APF), 597 condensation, 597 cumulative distribution function (CDF), 597 iCondensation, 597 iterated likelihood weighting (ILW), 598 kernel particle filter, 598 Epanechnikov kernel, 599 sampling importance resampling (SIR), 596 sequential importance sampling (SIS), 595 people tracking, 579 Leeds people tracker, 579 Siebel–Maybank tracker, 633 from vehicles, 580 Traffic flow monitoring. See Surveillance Training data, overfitting to, 709–712 Transform (Transformation), 479 See also Hough transform addetection, 456–458 use to find circle and ellipse centers, 460–462 Vehicle guidance. See In-vehicle vision systems detection, 456–458 use to find circle and ellipse centers, 460–462 Vehicle guidance. See In-vehicle vision systems detection, 456–458 use to find circle and ellipse centers, 460–462 Vehicle guidance. See In-vehicle vision systems Robots, autonomous mobile Vision, 1 See also Automated visual inspection; Machine vision active, 2 human, 1–2, 663 multiple-view, 490–491 Vision, nature of, 2 inverse graphics, 9–10 object location, 6–8 recognition, 4 scene analysis, 8–9 W Weak perspective projection, 427–429 White noise, 336 Wide baseline, 519 use of invariant feature detector, 521 views, 520 Window operation, 26, 35, 38, 147, 196 X X X-ray inspection, 542–546 dual-emission X-ray absorptiometry (DEXA 546–552	images, 83, 91	V
in unimodal distributions, 91 concavity analysis, 106 variance-based, 95 Time-to-adjacency analysis, 513–514 Top-hat operator, 193 Tracking moving objects, 517 See also Surveillance animal tracking, 631 Kalman filter, 517–519 mean shift algorithm, 599 monitoring traffic flow, 578 particle filter, 594–599 auxiliary particle filter (APF), 597 Condensation, 597 cumulative distribution function (CDF), 597 iCondensation, 597 iterated likelihood weighting (ILW), 598 kernel particle filter, 598 Epanechnikov kernel, 599 sample impoverishment, 596 sampling importance resampling (SIR), 596 sequential importance sampling (SIS), 595 people tracking, 579 Leeds people tracker, 579 Siebel-Maybank tracker, 633 from vehicles, 580 Traffic flow monitoring. See Surveillance Training data, overfitting to, 709–712 Transform (Transformation), 479 See also Hough transform affine, 498 maintenance of convexity, 380 detection, 456–458 use to find circle and ellipse centers, 460–462 Vehicle guidance. See In-vehicle vision systems Robots, autonomous mobile Video analytics. See Surveillance Vision, 1 See also Automated visual inspection; Machine vision active, 2 human, 1–2, 663 multiple-view, 490–491 Vision, nature of, 2 inverse graphics, 9–10 object location, 6–8 recognition, 4 scene analysis, 8–9 W Weak perspective projection, 427–429 White noise, 336 Wide baseline, 519 use of invariant feature detector, 521 views, 520 Window operation, 26, 35, 38, 147, 196 X X-ray inspection, 542–546 dual-emission X-ray absorptiometry (DEXA	local, 92–93	
use to find circle and ellipse centers, 460–462 Vehicle guidance. See In-vehicle vision systems Robots, autonomous mobile Video analytics. See Surveillance Animal tracking, 631 Kalman filter, 517–519 Mean shift algorithm, 599 Monitoring traffic flow, 578 particle filter, 594–599 Auxiliary particle filter (APF), 597 Condensation, 597 Condensation, 597 Condensation, 597 iterated likelihood weighting (ILW), 598 kernel particle filter, 598 Epanechnikov kernel, 599 sample impoverishment, 596 sampling importance resampling (SIR), 596 sequential importance sampling (SIS), 595 people tracking, 579 Leeds people tracker, 579 Siebel–Maybank tracker, 633 from vehicles, 580 Traffic flow monitoring. See Surveillance Training data, overfitting to, 709–712 Transform (Transformation), 479 See also Hough transform affine, 498 maintenance of convexity, 380 use to find circle and ellipse centers, 460–462 Vehicle guidance. See In-vehicle vision systems Robots, autonomous mobile Video analytics. See Surveillance Vision, 1 See also Automated visual inspection; Machine vision active, 2 human, 1–2, 663 multiple-view, 490–491 Vision, nature of, 2 inverse graphics, 9–10 object location, 6–8 recognition, 4 scene analysis, 8–9 W Weak perspective projection, 427–429 White noise, 336 Wide baseline, 519 matching, 519 use of invariant feature detector, 521 views, 520 Window operation, 26, 35, 38, 147, 196 X X X-ray inspection, 742–546 dual-emission X-ray absorptiometry (DEXA	maximum likelihood, 97	See also In-vehicle vision systems
variance-based, 95 Time-to-adjacency analysis, 513–514 Top-hat operator, 193 Tracking moving objects, 517 See also Surveillance animal tracking, 631 Kalman filter, 517–519 mean shift algorithm, 599 monitoring traffic flow, 578 particle filter, 594–599 auxiliary particle filter (APF), 597 Condensation, 597 iCondensation, 599 sample impoverishment, 596 sampling importance resampling (SIR), 596 sequential importance sampling (SIR), 596 sequential importance sampling of invariant feature detector, 521 veix, 520 Window operation, 427–429 White noise, 336 Wide baseline, 519 matching, 519 use of invariant	in unimodal distributions, 91	detection, 456–458
variance-based, 95 Time-to-adjacency analysis, 513–514 Top-hat operator, 193 Tracking moving objects, 517 See also Surveillance animal tracking, 631 Kalman filter, 517–519 mean shift algorithm, 599 monitoring traffic flow, 578 particle filter, 594–599 auxiliary particle filter (APF), 597 Condensation, 597 cumulative distribution function (CDF), 597 iCondensation, 597 iterated likelihood weighting (ILW), 598 kernel particle filter, 598 Epanechnikov kernel, 599 sample impoverishment, 596 sampling importance resampling (SIR), 596 sequential importance resampling (SIS), 595 people tracking, 579 Leeds people tracker, 579 Siebel-Maybank tracker, 633 from vehicles, 580 Traffic flow monitoring. See Surveillance Training data, overfitting to, 709–712 Transform (Transformation), 479 See also Hough transform affine, 498 maintenance of convexity, 380 440–462 Vehicle guidance. See In-vehicle vision systems Robots, autonomous mobile Video analytics. See Surveillance Vision, 1 See also Automated visual inspection; Machine vision active, 2 human, 1–2, 663 multiple-view, 490–491 Vision, nature of, 2 inverse graphics, 9–10 object location, 6–8 recognition, 4 scene analysis, 519 Weak perspective projection, 427–429 White noise, 336 Wide baseline, 519 matching, 519 use of invariant feature detector, 521 views, 520 Window operation, 26, 35, 38, 147, 196 X X-ray inspection; Active, 2 human, 1–2, 663 multiple-view, 490–491 Vision, nature of, 2 inverse graphics, 9–10 object location, 6–8 recognition, 4 scene analysis, 8–9 W Weak perspective projection, 427–429 White noise, 336 Wide baseline, 519 use of invariant feature detector, 521 views, 520 Window operation, 26, 35, 38, 147, 196	concavity analysis, 106	use to find circle and ellipse centers,
Top-hat operator, 193 Tracking moving objects, 517 See also Surveillance animal tracking, 631 Kalman filter, 517–519 mean shift algorithm, 599 monitoring traffic flow, 578 particle filter, 594–599 auxiliary particle filter (APF), 597 Condensation, 597 cumulative distribution function (CDF), 597 icondensation, 597 iterated likelihood weighting (ILW), 598 kernel particle filter, 598 Epanechnikov kernel, 599 sample impoverishment, 596 sampling importance resampling (SIR), 596 sequential importance resampling (SIS), 595 people tracking, 579 Leeds people tracker, 579 Siebel-Maybank tracker, 633 from vehicles, 580 Traffic flow monitoring. See Surveillance Training data, overfitting to, 709–712 Transform (Transformation), 479 See also Automated visual inspection; Machine vision active, 2 human, 1–2, 663 multiple-view, 490–491 Vision, nature of, 2 inverse graphics, 9–10 object location, 6–8 recognition, 4 scene analysis, 8–9 W Weak perspective projection, 427–429 White noise, 336 Wide baseline, 519 matching, 519 use of invariant feature detector, 521 views, 520 Window operation, 26, 35, 38, 147, 196 X X-ray inspection, 542–546 dual-emission X-ray absorptiometry (DEXA		460-462
Tracking moving objects, 517 See also Surveillance animal tracking, 631 Kalman filter, 517–519 mean shift algorithm, 599 monitoring traffic flow, 578 particle filter, 594–599 auxiliary particle filter (APF), 597 Condensation, 597 cumulative distribution function (CDF), 597 iCondensation, 597 iterated likelihood weighting (ILW), 598 kernel particle filter, 598 Epanechnikov kernel, 599 sample impoverishment, 596 sampling importance resampling (SIR), 596 sequential importance sampling (SIS), 595 people tracking, 579 Leeds people tracker, 579 Siebel-Maybank tracker, 633 from vehicles, 580 Traffic flow monitoring. See Surveillance Vision, 1 See also Automated visual inspection; Machine vision active, 2 human, 1–2, 663 multiple-view, 490–491 Vision, nature of, 2 inverse graphics, 9–10 object location, 6–8 recognition, 4 scene analysis, 8–9 W Weak perspective projection, 427–429 White noise, 336 Wide baseline, 519 matching, 519 use of invariant feature detector, 521 views, 520 Window operation, 26, 35, 38, 147, 196 Transform (Transformation), 479 See also Hough transform affine, 498 maintenance of convexity, 380 Video analytics. See Surveillance Vision, 1 See also Automated visual inspection; Machine vision active, 2 human, 1–2, 663 multiple-view, 490–491 Vision, nature of, 2 inverse graphics, 9–10 object location, 6–8 recognition, 4 scene analysis, 8–9 W Weak perspective projection, 427–429 White noise, 336 Wide baseline, 519 use of invariant feature detector, 521 views, 520 Window operation, 26, 35, 38, 147, 196 X X-ray inspection, 542–546 dual-emission X-ray absorptiometry (DEXA	Time-to-adjacency analysis, 513-514	Vehicle guidance. See In-vehicle vision systems;
Tracking moving objects, 517 See also Surveillance animal tracking, 631 Kalman filter, 517–519 mean shift algorithm, 599 monitoring traffic flow, 578 particle filter, 594–599 auxiliary particle filter (APF), 597 Condensation, 597 cumulative distribution function (CDF), 597 iterated likelihood weighting (ILW), 598 kernel particle filter, 598 Epanechnikov kernel, 599 sample impoverishment, 596 sampling importance resampling (SIR), 595 sequential importance resampling (SIS), 595 people tracking, 579 Leeds people tracker, 579 Siebel-Maybank tracker, 633 from vehicles, 580 Traffic flow monitoring. See Surveillance Training data, overfitting to, 709–712 Transform (Transformation), 479 See also Automated visual inspection; Machine vision active, 2 human, 1–2, 663 multiple-view, 490–491 Vision, nature of, 2 inverse graphics, 9–10 object location, 6–8 recognition, 4 scene analysis, 8–9 W Weak perspective projection, 427–429 White noise, 336 Wide baseline, 519 matching, 519 use of invariant feature detector, 521 views, 520 Window operation, 26, 35, 38, 147, 196 X X-ray inspection, 542–546 dual-emission X-ray absorptiometry (DEXA)	Top-hat operator, 193	Robots, autonomous mobile
see also Automated visual inspection; Machine vision active, 2 human, 1–2, 663 multiple-view, 490–491 Vision, nature of, 2 inverse graphics, 9–10 object location, 498 maintenance of convexity, 380 See also Automated visual inspection; Machine vision active, 2 human, 1–2, 663 multiple-view, 490–491 Vision, nature of, 2 inverse graphics, 9–10 object location, 6–8 recognition, 4 scene analysis, 8–9 W Weak perspective projection, 427–429 White noise, 336 Wide baseline, 519 matching, 519 use of invariant feature detector, 521 views, 520 Window operation, 26, 35, 38, 147, 196 X X-ray inspection; Machine vision active, 2 human, 1–2, 663 multiple-view, 490–491 Vision, nature of, 2 inverse graphics, 9–10 object location, 6–8 recognition, 4 scene analysis, 8–9 W Weak perspective projection, 427–429 White noise, 336 Wide baseline, 519 matching, 519 use of invariant feature detector, 521 views, 520 Window operation, 26, 35, 38, 147, 196 X X-ray inspection; Active, 2 human, 1–2, 663 multiple-view, 490–491 Vision, nature of, 2 inverse graphics, 9–10 object location, 6–8 recognition, 4 scene analysis, 8–9 W X X X-ray inspection; Machine vision active, 2 human, 1–2, 663 multiple-view, 490–491 Vision, nature of, 2 inverse graphics, 9–10 object location, 6–8 recognition, 4 scene analysis, 8–9 W Weak perspective projection, 427–429 White noise, 336 Wide baseline, 519 use of invariant feature detector, 521 views, 520 Window operation, 26, 35, 38, 147, 196 X X-ray inspection;	Tracking moving objects, 517	Video analytics. See Surveillance
Kalman filter, 517–519 mean shift algorithm, 599 monitoring traffic flow, 578 particle filter, 594–599 auxiliary particle filter (APF), 597 Condensation, 597 cumulative distribution function (CDF), 597 iCondensation, 597 iterated likelihood weighting (ILW), 598 kernel particle filter, 598 Epanechnikov kernel, 599 sample impoverishment, 596 sampling importance resampling (SIR), 596 sequential importance sampling (SIS), 595 people tracking, 579 Leeds people tracker, 579 Siebel-Maybank tracker, 633 from vehicles, 580 Traffic flow monitoring. See Surveillance Training data, overfitting to, 709–712 Transform (Transformation), 479 See also Hough transform affine, 498 maintenance of convexity, 380 Machine vision active, 2 human, 1–2, 663 multiple-view, 490–491 Vision, nature of, 2 inverse graphics, 9–10 object location, 6–8 recognition, 4 scene analysis, 8–9 W Weak perspective projection, 427–429 White noise, 336 Wide baseline, 519 matching, 519 use of invariant feature detector, 521 views, 520 Window operation, 26, 35, 38, 147, 196 X X-ray inspection, 542–546 dual-emission X-ray absorptiometry (DEXA	See also Surveillance	Vision, 1
Kalman filter, 517–519 mean shift algorithm, 599 monitoring traffic flow, 578 particle filter, 594–599 auxiliary particle filter (APF), 597 Condensation, 597 cumulative distribution function (CDF), 597 iCondensation, 597 iterated likelihood weighting (ILW), 598 kernel particle filter, 598 Epanechnikov kernel, 599 sample impoverishment, 596 sampling importance resampling (SIR), 596 sequential importance sampling (SIS), 595 people tracking, 579 Leeds people tracker, 579 Siebel-Maybank tracker, 633 from vehicles, 580 Traffic flow monitoring. See Surveillance Training data, overfitting to, 709–712 Transform (Transformation), 479 See also Hough transform affine, 498 maintenance of convexity, 380 Machine vision active, 2 human, 1–2, 663 multiple-view, 490–491 Vision, nature of, 2 inverse graphics, 9–10 object location, 6–8 recognition, 4 scene analysis, 8–9 W Weak perspective projection, 427–429 White noise, 336 Wide baseline, 519 matching, 519 use of invariant feature detector, 521 views, 520 Window operation, 26, 35, 38, 147, 196 X X-ray inspection, 542–546 dual-emission X-ray absorptiometry (DEXA	animal tracking, 631	See also Automated visual inspection;
monitoring traffic flow, 578 particle filter, 594–599 auxiliary particle filter (APF), 597 Condensation, 597 cumulative distribution function (CDF), 597 iCondensation, 597 iterated likelihood weighting (ILW), 598 kernel particle filter, 598 Epanechnikov kernel, 599 sample impoverishment, 596 sampling importance resampling (SIR), 596 sequential importance sampling (SIS), 595 people tracking, 579 Leeds people tracker, 579 Siebel—Maybank tracker, 633 from vehicles, 580 Traffic flow monitoring. See Surveillance Training data, overfitting to, 709–712 Transform (Transformation), 479 See also Hough transform affine, 498 maintenance of convexity, 380 human, 1–2, 663 multiple-view, 490–491 Vision, nature of, 2 inverse graphics, 9–10 object location, 6–8 recognition, 4 scene analysis, 8–9 W Weak perspective projection, 427–429 White noise, 336 Wide baseline, 519 use of invariant feature detector, 521 views, 520 Window operation, 26, 35, 38, 147, 196 X X-ray inspection, 542–546 dual-emission X-ray absorptiometry (DEXA)	•	Machine vision
monitoring traffic flow, 578 particle filter, 594–599 auxiliary particle filter (APF), 597 Condensation, 597 cumulative distribution function (CDF), 597 iCondensation, 597 iterated likelihood weighting (ILW), 598 kernel particle filter, 598 Epanechnikov kernel, 599 sample impoverishment, 596 sampling importance resampling (SIR), 596 sequential importance sampling (SIS), 595 people tracking, 579 Leeds people tracker, 579 Siebel—Maybank tracker, 633 from vehicles, 580 Traffic flow monitoring. See Surveillance Training data, overfitting to, 709–712 Transform (Transformation), 479 See also Hough transform affine, 498 maintenance of convexity, 380 human, 1–2, 663 multiple-view, 490–491 Vision, nature of, 2 inverse graphics, 9–10 object location, 6–8 recognition, 4 scene analysis, 8–9 W Weak perspective projection, 427–429 White noise, 336 Wide baseline, 519 use of invariant feature detector, 521 views, 520 Window operation, 26, 35, 38, 147, 196 X X-ray inspection, 542–546 dual-emission X-ray absorptiometry (DEXA)	mean shift algorithm, 599	active, 2
auxiliary particle filter (APF), 597 Condensation, 597 cumulative distribution function (CDF), 597 iCondensation, 597 iterated likelihood weighting (ILW), 598 kernel particle filter, 598 Epanechnikov kernel, 599 sample impoverishment, 596 sampling importance resampling (SIR), 596 sequential importance sampling (SIS), 595 people tracking, 579 Leeds people tracker, 579 Siebel-Maybank tracker, 633 from vehicles, 580 Traffic flow monitoring. See Surveillance Training data, overfitting to, 709-712 Transform (Transformation), 479 See also Hough transform affine, 498 maintenance of convexity, 380 Vision, nature of, 2 inverse graphics, 9-10 object location, 6-8 recognition, 4 scene analysis, 8-9 W Weak perspective projection, 427-429 White noise, 336 Wide baseline, 519 use of invariant feature detector, 521 views, 520 Window operation, 26, 35, 38, 147, 196 X X-ray inspection, 542-546 dual-emission X-ray absorptiometry (DEXA	monitoring traffic flow, 578	human, 1–2, 663
Condensation, 597 cumulative distribution function (CDF), 597 iCondensation, 597 iterated likelihood weighting (ILW), 598 kernel particle filter, 598 Epanechnikov kernel, 599 sample impoverishment, 596 sampling importance resampling (SIR), 596 sequential importance sampling (SIS), 595 people tracking, 579 Leeds people tracker, 579 Siebel-Maybank tracker, 633 from vehicles, 580 Traffic flow monitoring. See Surveillance Training data, overfitting to, 709-712 Transform (Transformation), 479 See also Hough transform affine, 498 maintenance of convexity, 380 inverse graphics, 9-10 object location, 6-8 recognition, 4 scene analysis, 8-9 W Weak perspective projection, 427-429 White noise, 336 Wide baseline, 519 use of invariant feature detector, 521 views, 520 Window operation, 26, 35, 38, 147, 196 X X-ray inspection, 542-546 dual-emission X-ray absorptiometry (DEXA)	particle filter, 594-599	multiple-view, 490-491
cumulative distribution function (CDF), 597 iCondensation, 597 iterated likelihood weighting (ILW), 598 kernel particle filter, 598 Epanechnikov kernel, 599 sample impoverishment, 596 sampling importance resampling (SIR), 596 sequential importance sampling (SIS), 595 people tracking, 579 Leeds people tracker, 579 Siebel-Maybank tracker, 633 from vehicles, 580 Traffic flow monitoring. See Surveillance Training data, overfitting to, 709-712 Transform (Transformation), 479 See also Hough transform affine, 498 maintenance of convexity, 380 object location, 6-8 recognition, 4 scene analysis, 8-9 W Weak perspective projection, 427-429 White noise, 336 Wide baseline, 519 use of invariant feature detector, 521 views, 520 Window operation, 26, 35, 38, 147, 196 X X-ray inspection, 542-546 dual-emission X-ray absorptiometry (DEXA)		Vision, nature of, 2
cumulative distribution function (CDF), 597 iCondensation, 597 iterated likelihood weighting (ILW), 598 kernel particle filter, 598 Epanechnikov kernel, 599 sample impoverishment, 596 sampling importance resampling (SIR), 596 sequential importance sampling (SIS), 595 people tracking, 579 Leeds people tracker, 579 Siebel—Maybank tracker, 633 from vehicles, 580 Traffic flow monitoring. See Surveillance Training data, overfitting to, 709—712 Transform (Transformation), 479 See also Hough transform affine, 498 maintenance of convexity, 380 object location, 6–8 recognition, 4 scene analysis, 8–9 W Weak perspective projection, 427–429 White noise, 336 Wide baseline, 519 use of invariant feature detector, 521 views, 520 Window operation, 26, 35, 38, 147, 196 X X-ray inspection, 542–546 dual-emission X-ray absorptiometry (DEXA)	Condensation, 597	
iCondensation, 597 iterated likelihood weighting (ILW), 598 kernel particle filter, 598 Epanechnikov kernel, 599 sample impoverishment, 596 sampling importance resampling (SIR), 596 sequential importance sampling (SIS), 595 people tracking, 579 Leeds people tracker, 579 Siebel—Maybank tracker, 633 from vehicles, 580 Traffic flow monitoring. See Surveillance Training data, overfitting to, 709—712 Transform (Transformation), 479 See also Hough transform affine, 498 maintenance of convexity, 380 W Weak perspective projection, 427—429 White noise, 336 Wide baseline, 519 use of invariant feature detector, 521 views, 520 Window operation, 26, 35, 38, 147, 196 X X-ray inspection, 542—546 dual-emission X-ray absorptiometry (DEXA)	cumulative distribution function	object location, 6–8
iterated likelihood weighting (ILW), 598 kernel particle filter, 598 Epanechnikov kernel, 599 sample impoverishment, 596 sampling importance resampling (SIR), 596 sequential importance sampling (SIS), 595 people tracking, 579 Leeds people tracker, 579 Siebel—Maybank tracker, 633 from vehicles, 580 Traffic flow monitoring. See Surveillance Training data, overfitting to, 709—712 Transform (Transformation), 479 See also Hough transform affine, 498 maintenance of convexity, 380 W Weak perspective projection, 427—429 White noise, 336 Wide baseline, 519 use of invariant feature detector, 521 views, 520 Window operation, 26, 35, 38, 147, 196 X X-ray inspection, 542—546 dual-emission X-ray absorptiometry (DEXA)	(CDF), 597	recognition, 4
kernel particle filter, 598 Epanechnikov kernel, 599 sample impoverishment, 596 sampling importance resampling (SIR), 596 sequential importance sampling (SIS), 595 people tracking, 579 Leeds people tracker, 579 Siebel-Maybank tracker, 633 from vehicles, 580 Traffic flow monitoring. See Surveillance Training data, overfitting to, 709-712 Transform (Transformation), 479 See also Hough transform affine, 498 maintenance of convexity, 380 Weak perspective projection, 427-429 White noise, 336 Wide baseline, 519 use of invariant feature detector, 521 views, 520 Window operation, 26, 35, 38, 147, 196 X X-ray inspection, 542-546 dual-emission X-ray absorptiometry (DEXA)	iCondensation, 597	scene analysis, 8–9
Epanechnikov kernel, 599 sample impoverishment, 596 sampling importance resampling (SIR), 596 sequential importance sampling (SIS), 595 people tracking, 579 Leeds people tracker, 579 Siebel-Maybank tracker, 633 from vehicles, 580 Traffic flow monitoring. See Surveillance Training data, overfitting to, 709-712 Transform (Transformation), 479 See also Hough transform affine, 498 maintenance of convexity, 380 Weak perspective projection, 427-429 White noise, 336 Wide baseline, 519 use of invariant feature detector, 521 views, 520 Window operation, 26, 35, 38, 147, 196 X X-ray inspection, 542-546 dual-emission X-ray absorptiometry (DEXA)	iterated likelihood weighting (ILW), 598	
sample impoverishment, 596 sampling importance resampling (SIR), 596 sequential importance sampling (SIS), 595 people tracking, 579 Leeds people tracker, 579 Siebel—Maybank tracker, 633 from vehicles, 580 Traffic flow monitoring. See Surveillance Training data, overfitting to, 709–712 Transform (Transformation), 479 See also Hough transform affine, 498 maintenance of convexity, 380 Weak perspective projection, 427–429 White noise, 336 Wide baseline, 519 use of invariant feature detector, 521 views, 520 Window operation, 26, 35, 38, 147, 196 X X-ray inspection, 542–546 dual-emission X-ray absorptiometry (DEXA)	kernel particle filter, 598	***
sampling importance resampling (SIR), 596 sequential importance sampling (SIS), 595 people tracking, 579 Leeds people tracker, 579 Siebel-Maybank tracker, 633 from vehicles, 580 Traffic flow monitoring. See Surveillance Training data, overfitting to, 709-712 Transform (Transformation), 479 See also Hough transform affine, 498 maintenance of convexity, 380 White noise, 336 Wide baseline, 519 use of invariant feature detector, 521 views, 520 Window operation, 26, 35, 38, 147, 196 X X-ray inspection, 542-546 dual-emission X-ray absorptiometry (DEXA)	Epanechnikov kernel, 599	W
sampling importance resampling (SIR), 596 sequential importance sampling (SIS), 595 people tracking, 579 Leeds people tracker, 579 Siebel-Maybank tracker, 633 from vehicles, 580 Traffic flow monitoring. See Surveillance Training data, overfitting to, 709-712 Transform (Transformation), 479 See also Hough transform affine, 498 maintenance of convexity, 380 White noise, 336 Wide baseline, 519 use of invariant feature detector, 521 views, 520 Window operation, 26, 35, 38, 147, 196 X X-ray inspection, 542-546 dual-emission X-ray absorptiometry (DEXA)	sample impoverishment, 596	Weak perspective projection, 427–429
sequential importance sampling (SIS), 595 people tracking, 579 Leeds people tracker, 579 Siebel-Maybank tracker, 633 from vehicles, 580 Traffic flow monitoring. See Surveillance Training data, overfitting to, 709-712 Transform (Transformation), 479 See also Hough transform affine, 498 maintenance of convexity, 380 Wide baseline, 519 use of invariant feature detector, 521 views, 520 Window operation, 26, 35, 38, 147, 196 X X-ray inspection, 542-546 dual-emission X-ray absorptiometry (DEXA)	sampling importance resampling (SIR), 596	
people tracking, 579 Leeds people tracker, 579 Siebel-Maybank tracker, 633 from vehicles, 580 Traffic flow monitoring. See Surveillance Training data, overfitting to, 709-712 Transform (Transformation), 479 See also Hough transform affine, 498 maintenance of convexity, 380 matching, 519 use of invariant feature detector, 521 views, 520 Window operation, 26, 35, 38, 147, 196 X X-ray inspection, 542-546 dual-emission X-ray absorptiometry (DEXA	sequential importance sampling (SIS), 595	
Leeds people tracker, 579 Siebel-Maybank tracker, 633 from vehicles, 580 Traffic flow monitoring. See Surveillance Training data, overfitting to, 709-712 Transform (Transformation), 479 See also Hough transform affine, 498 maintenance of convexity, 380 use of invariant feature detector, 521 views, 520 Window operation, 26, 35, 38, 147, 196 X X-ray inspection, 542-546 dual-emission X-ray absorptiometry (DEXA)	people tracking, 579	
Siebel—Maybank tracker, 633 from vehicles, 580 Traffic flow monitoring. See Surveillance Training data, overfitting to, 709—712 Transform (Transformation), 479 See also Hough transform affine, 498 maintenance of convexity, 380 views, 520 Window operation, 26, 35, 38, 147, 196 X X X-ray inspection, 542—546 dual-emission X-ray absorptiometry (DEXA)	Leeds people tracker, 579	•
from vehicles, 580 Traffic flow monitoring. See Surveillance Training data, overfitting to, 709–712 Transform (Transformation), 479 See also Hough transform affine, 498 maintenance of convexity, 380 Window operation, 26, 35, 38, 147, 196 X X-ray inspection, 542–546 dual-emission X-ray absorptiometry (DEXA)	Siebel-Maybank tracker, 633	
Traffic flow monitoring. See Surveillance Training data, overfitting to, 709–712 Transform (Transformation), 479 See also Hough transform affine, 498 maintenance of convexity, 380 X-ray inspection, 542–546 dual-emission X-ray absorptiometry (DEXA)	from vehicles, 580	
Transform (Transformation), 479 See also Hough transform affine, 498 maintenance of convexity, 380 X-ray inspection, 542–546 dual-emission X-ray absorptiometry (DEXA)	Traffic flow monitoring. See Surveillance	
See also Hough transform affine, 498 maintenance of convexity, 380 X-ray inspection, 542–546 dual-emission X-ray absorptiometry (DEXA)	Training data, overfitting to, 709-712	
See also Hough transform affine, 498 maintenance of convexity, 380 X-ray inspection, 542–546 dual-emission X-ray absorptiometry (DEXA	Transform (Transformation), 479	Χ
maintenance of convexity, 380 dual-emission X-ray absorptiometry (DEXA)	See also Hough transform	
maintenance of convexity, 380	affine, 498	* *
	maintenance of convexity, 380	
		346, 332