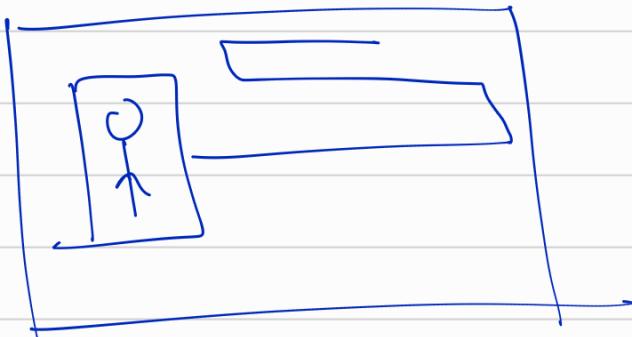
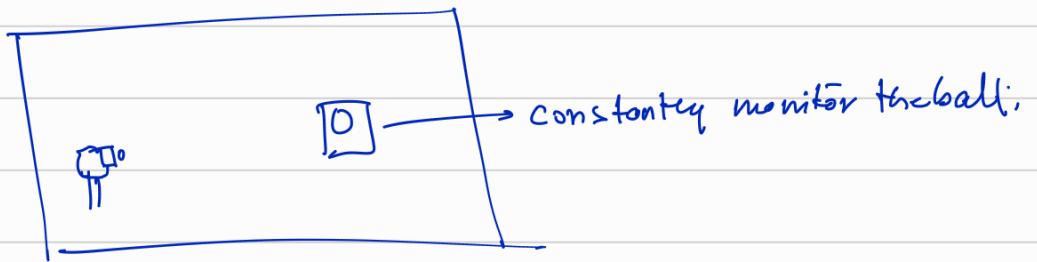
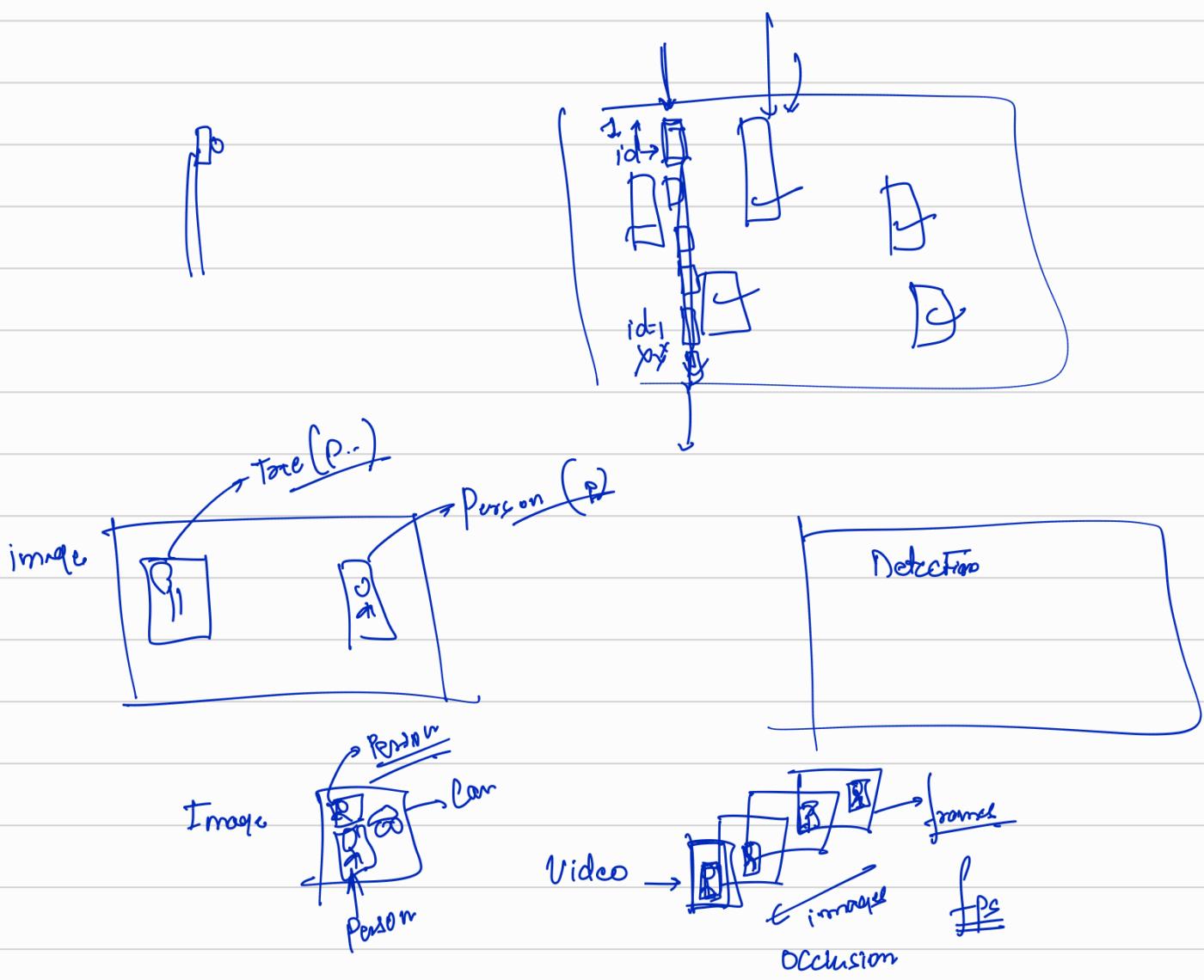


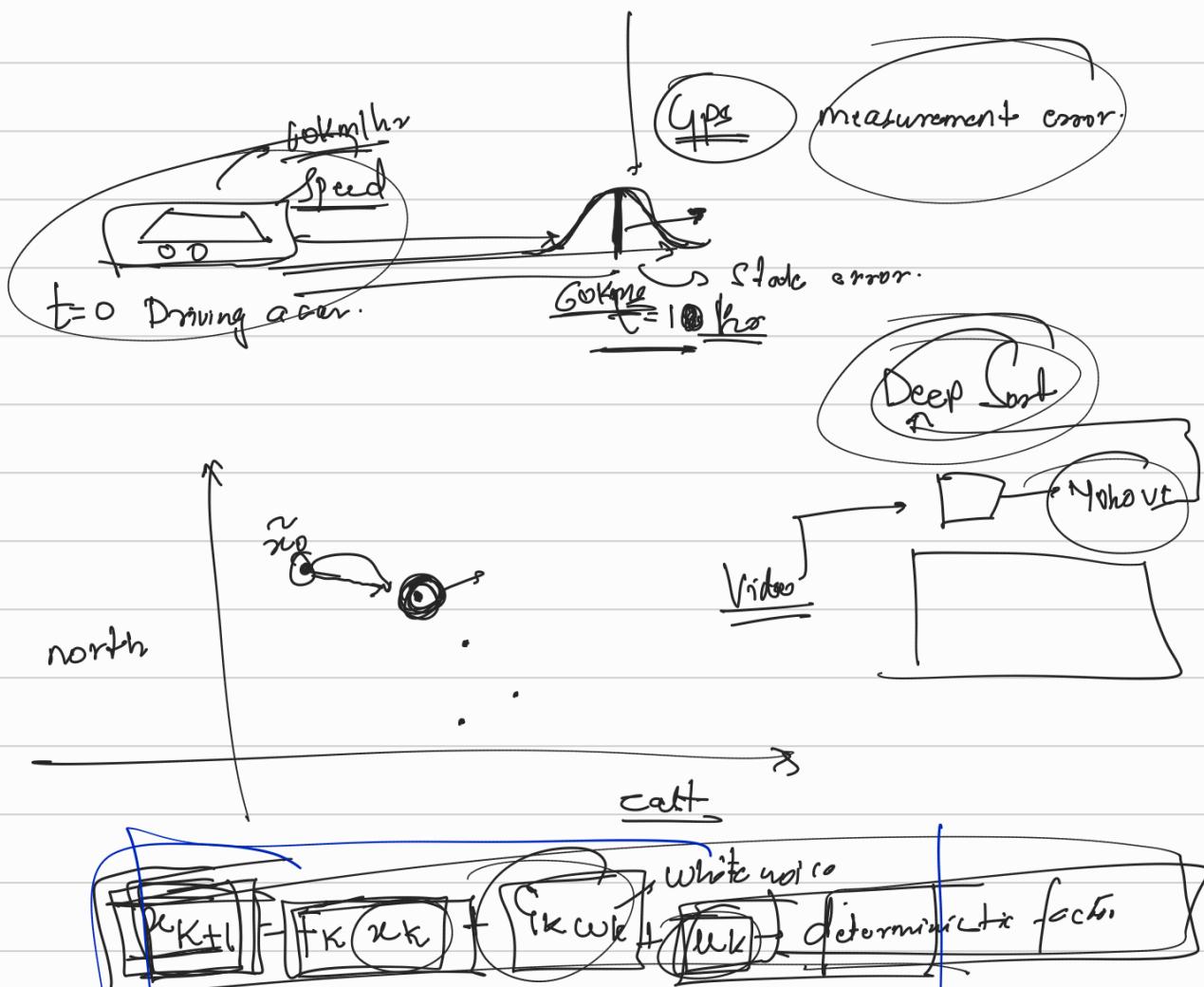
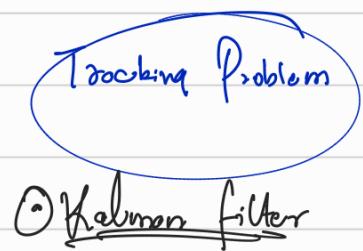
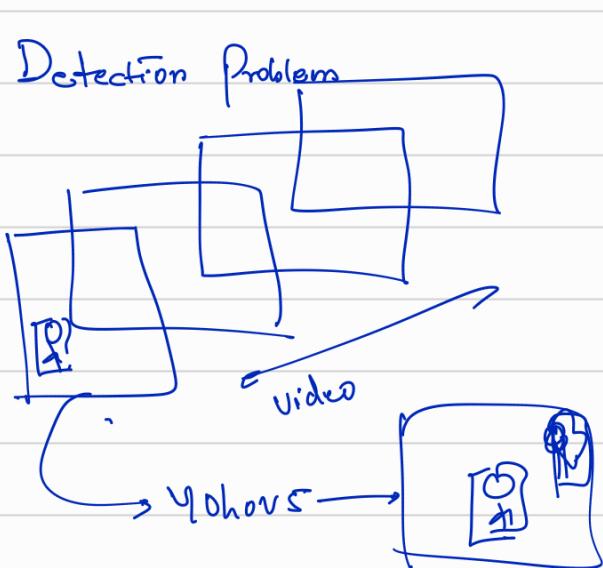
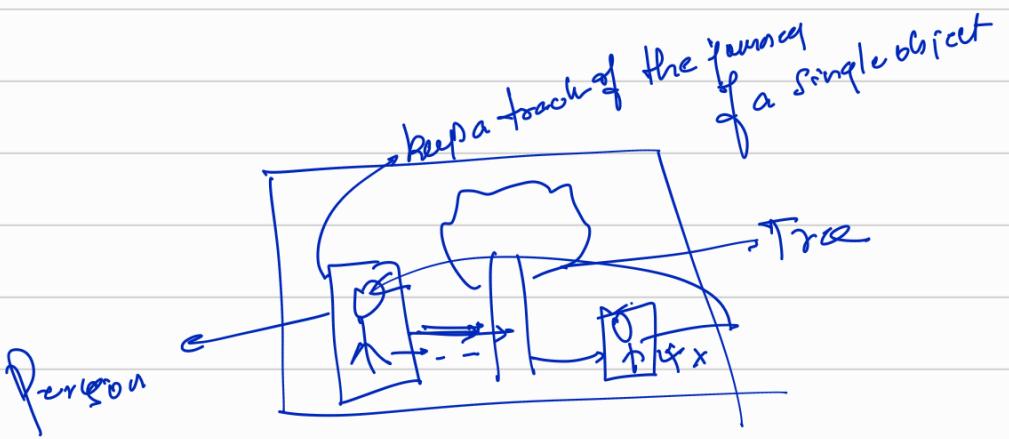
Object detection

↳ Object Tracking



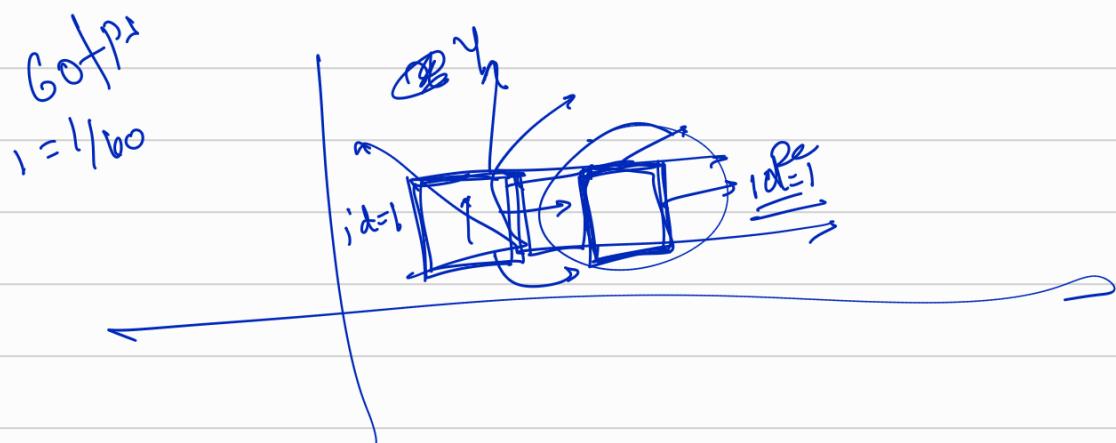
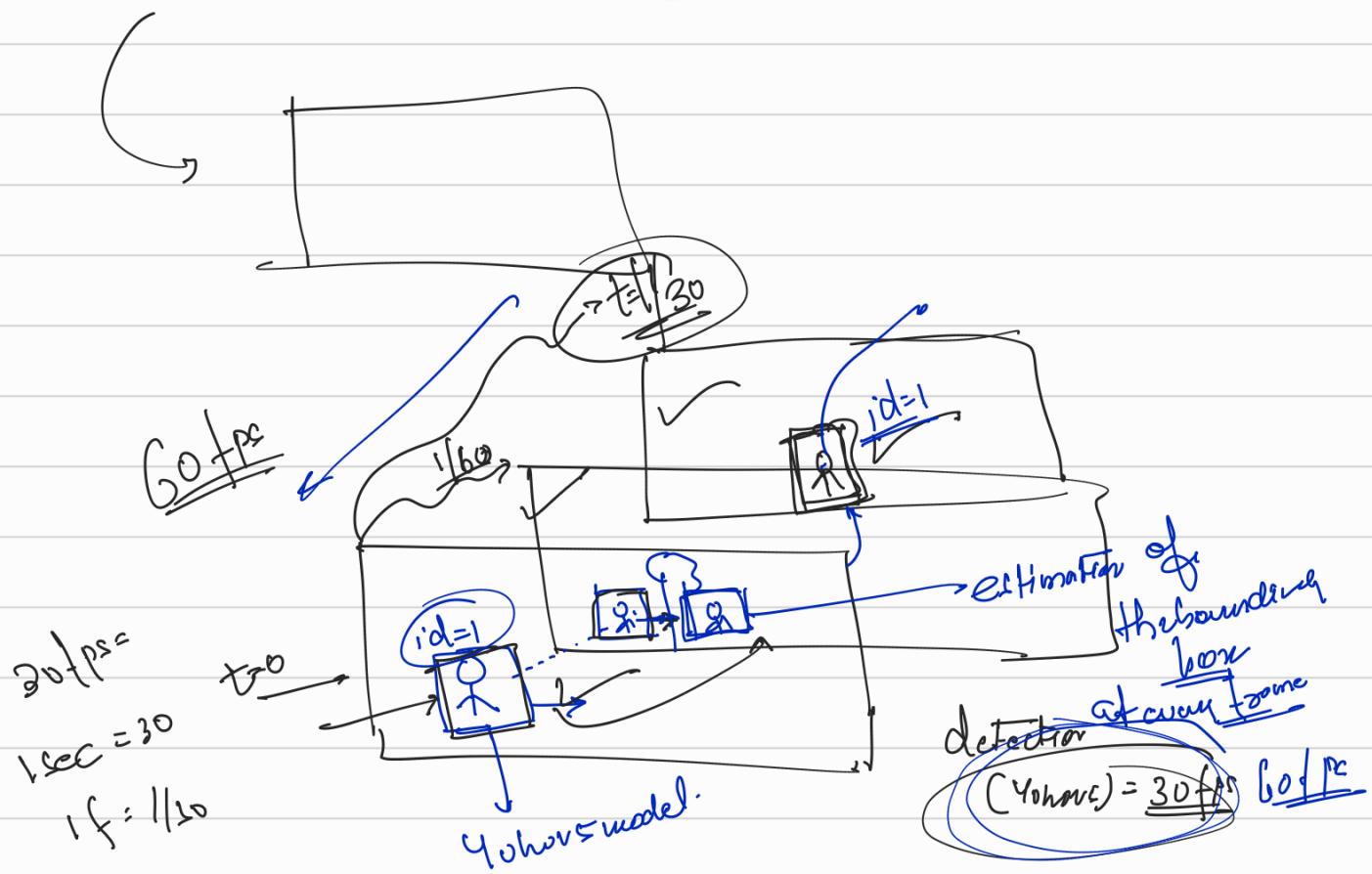
CCV footage → Traffic cone

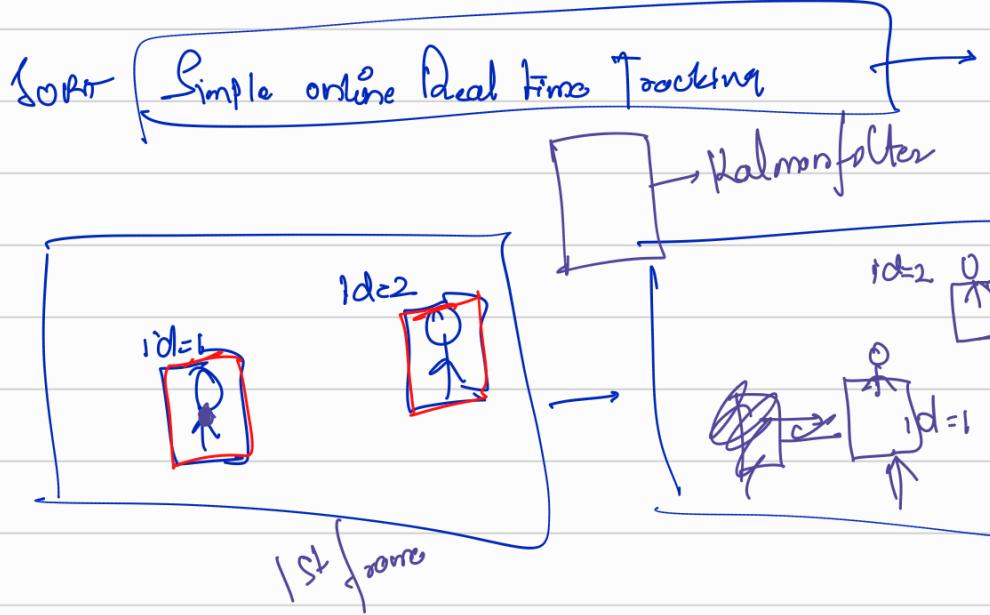




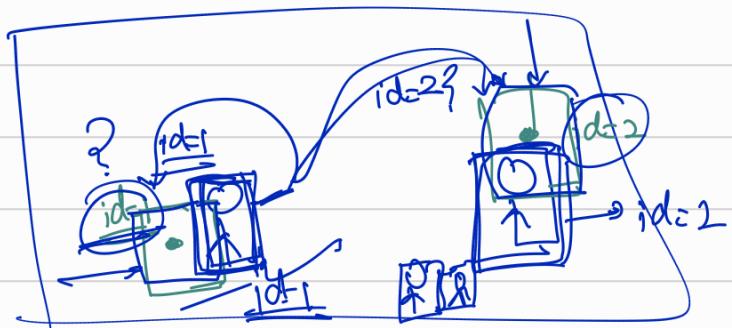
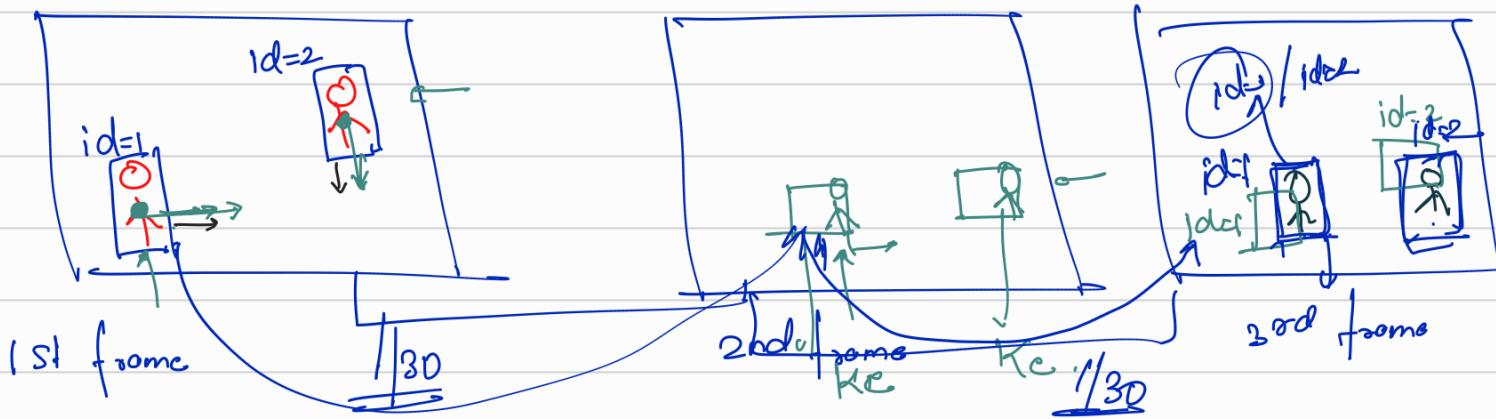
$$z_k = H_k x_k + v_k \rightarrow \text{measurement/noise}$$

measurement / observed position



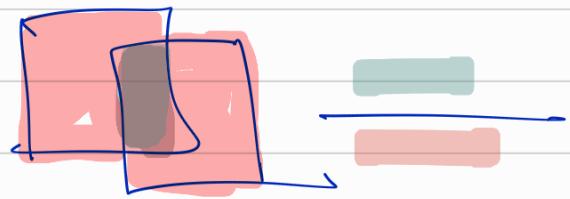


→ Ke → YD



Intersection Over Union

Deep SORT

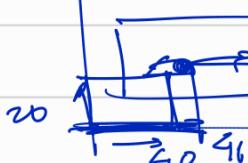


60 FPS

1st frame

2nd frame

~~global tracker~~



1:1 m

150 Km/hr

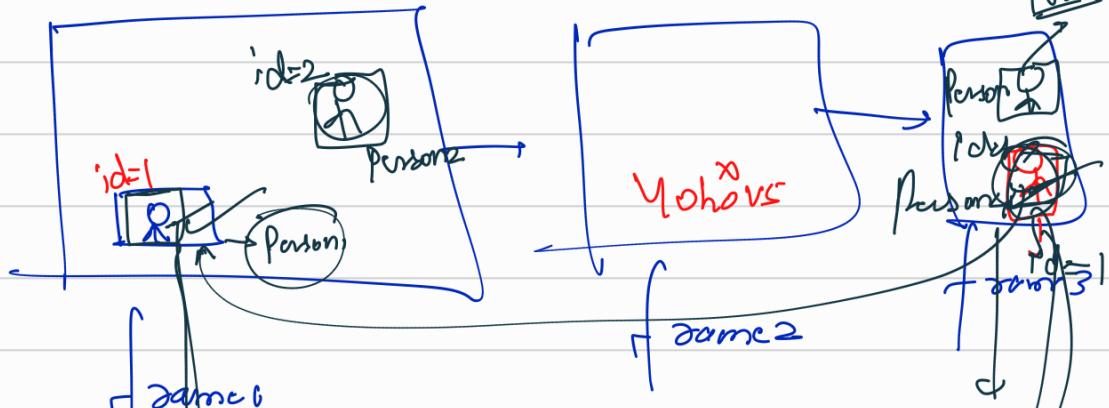
1/60 of seconds

$$\frac{150 \text{ Km}}{3600} \times \frac{1}{60}$$

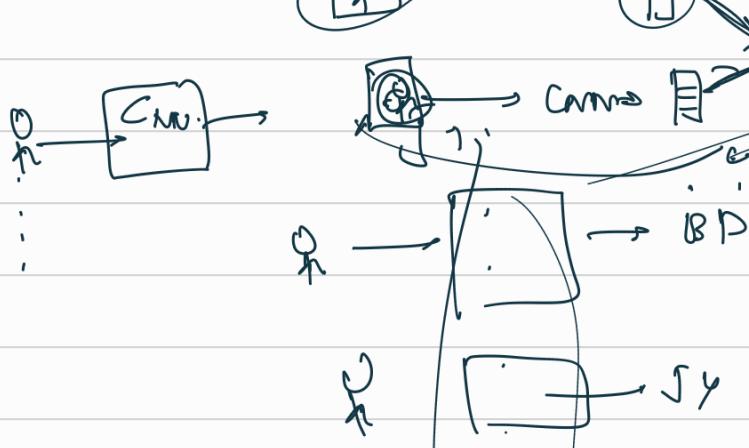
+ 0.001

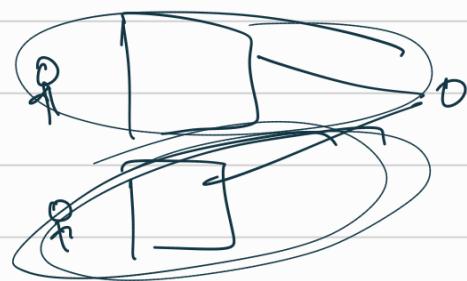
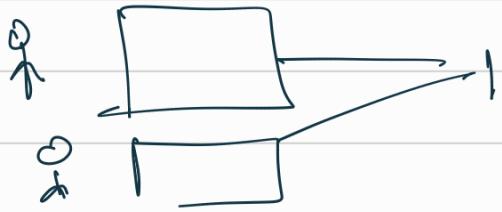
1 m

Deep SORT

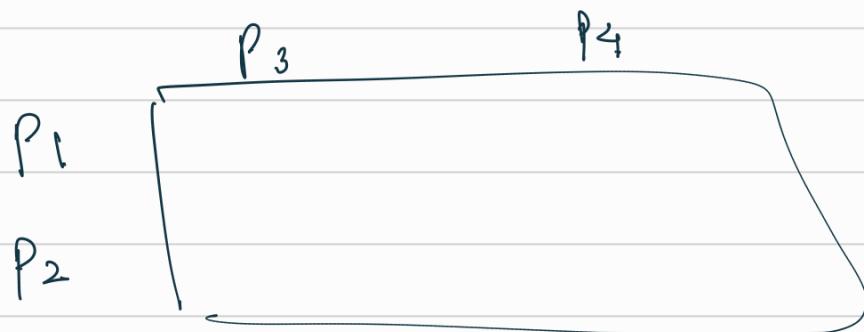


id assignment
problem





$id=1$



$P_2, P_3 \quad P_2 P_4$

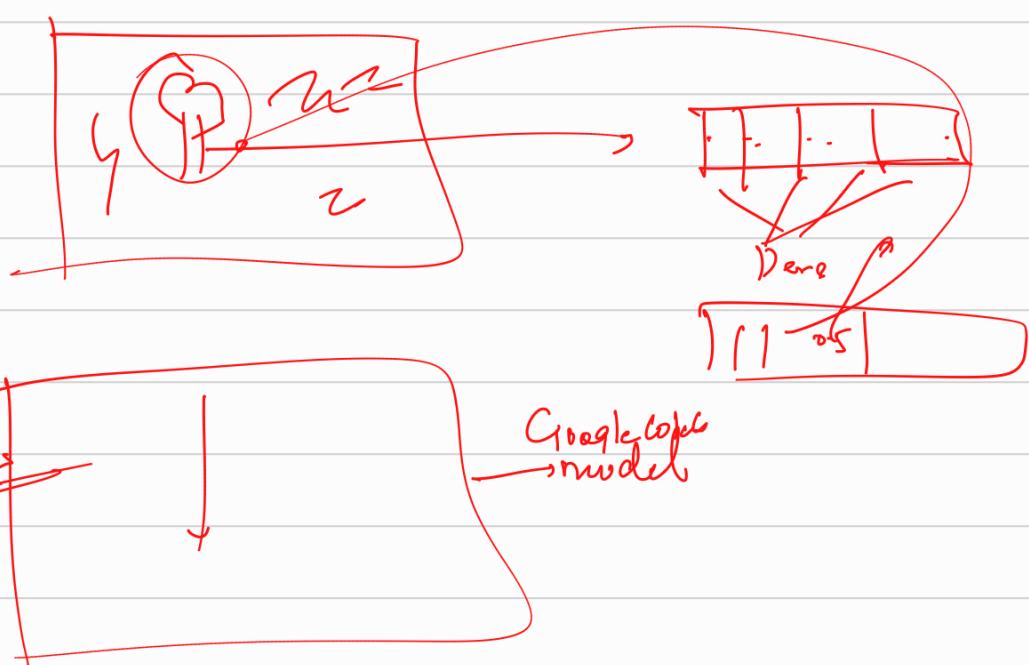
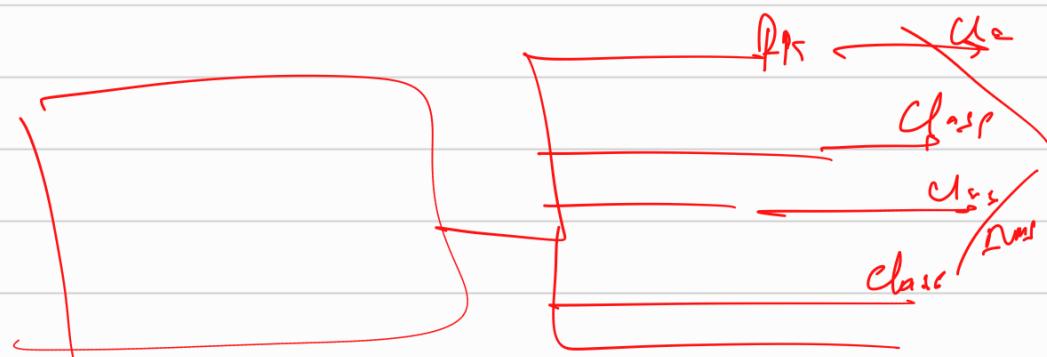
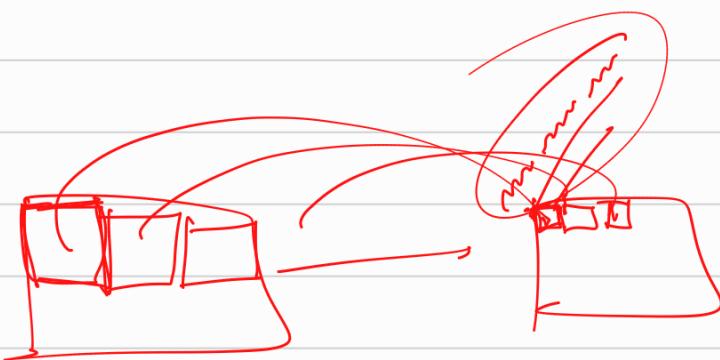
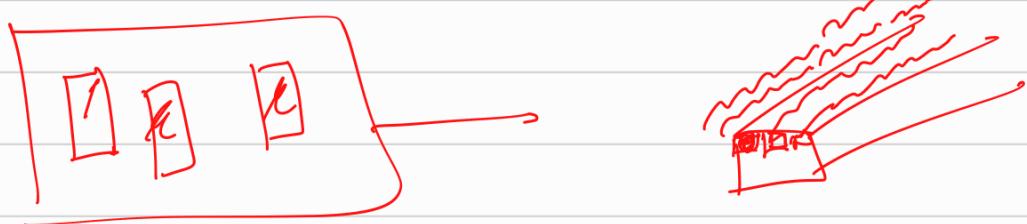
Deep Sort T
Combined output (IOT + Euclidean dist.)

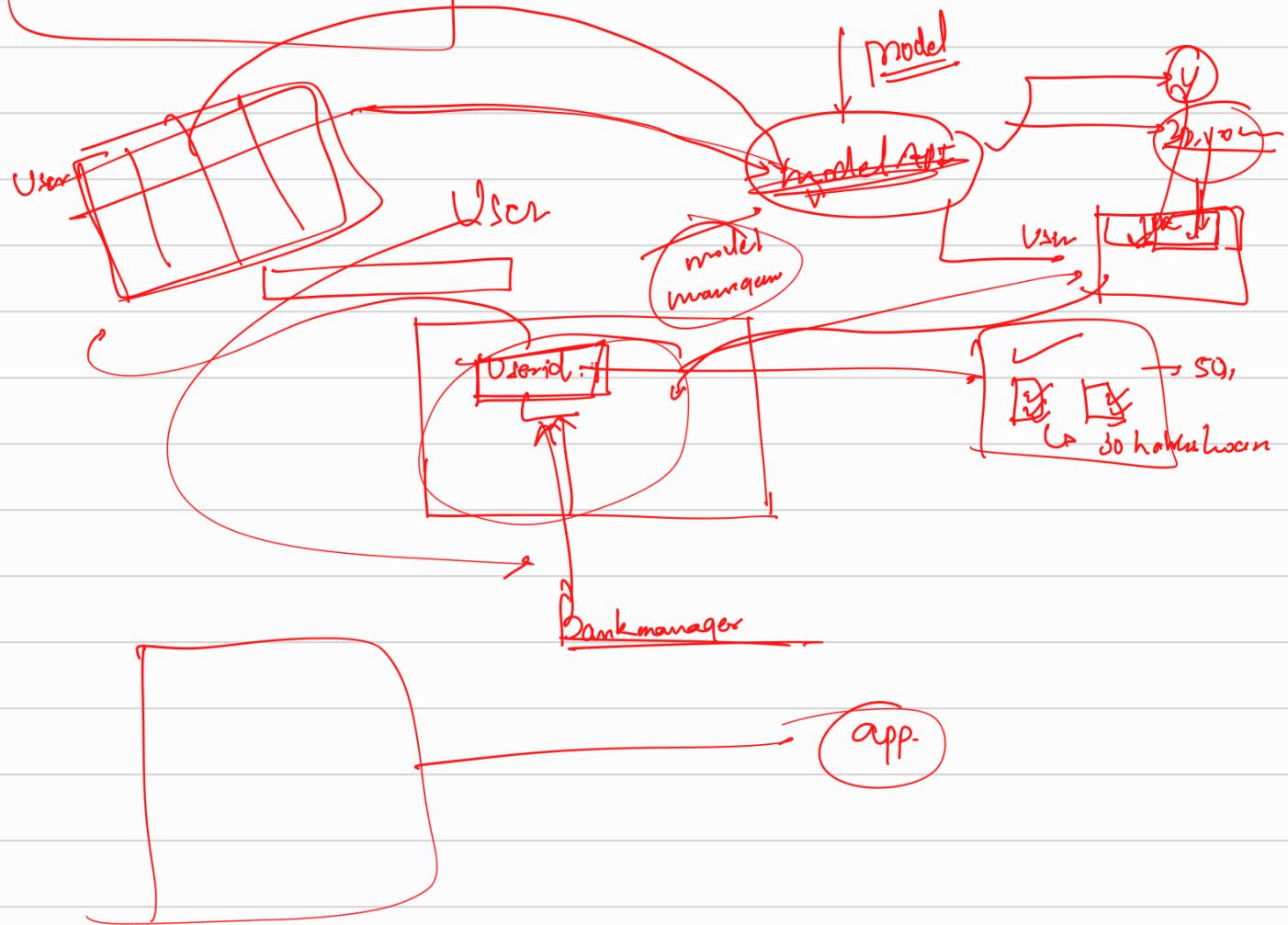
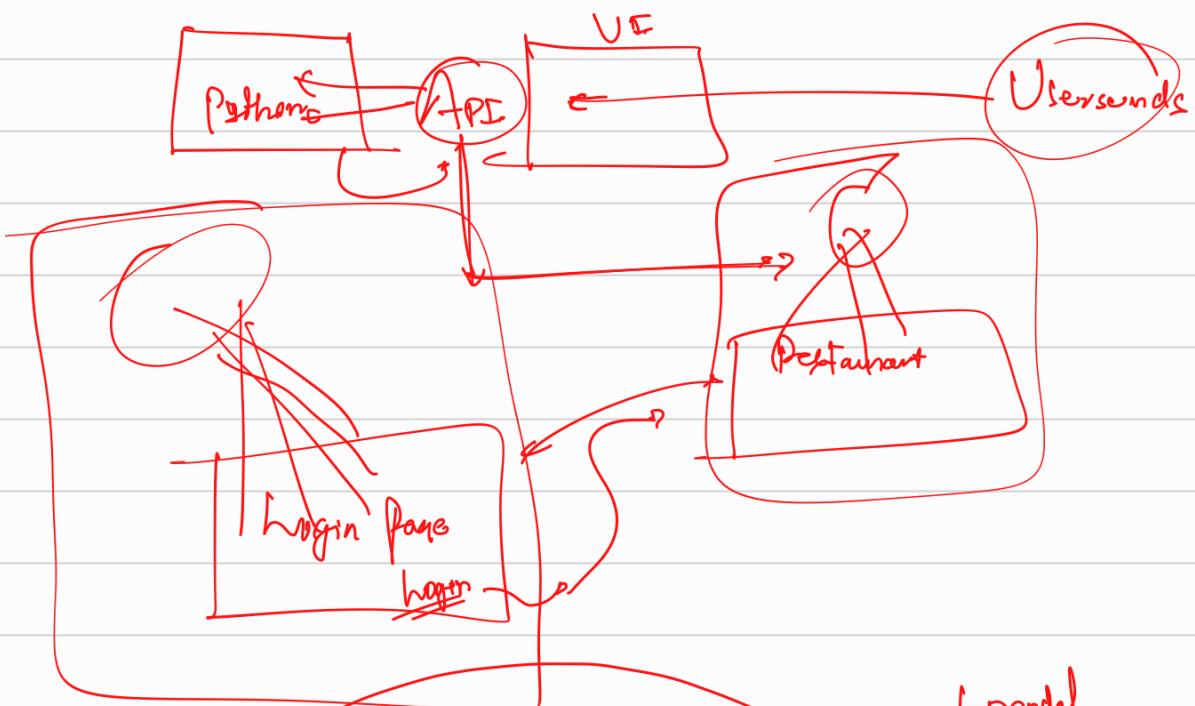
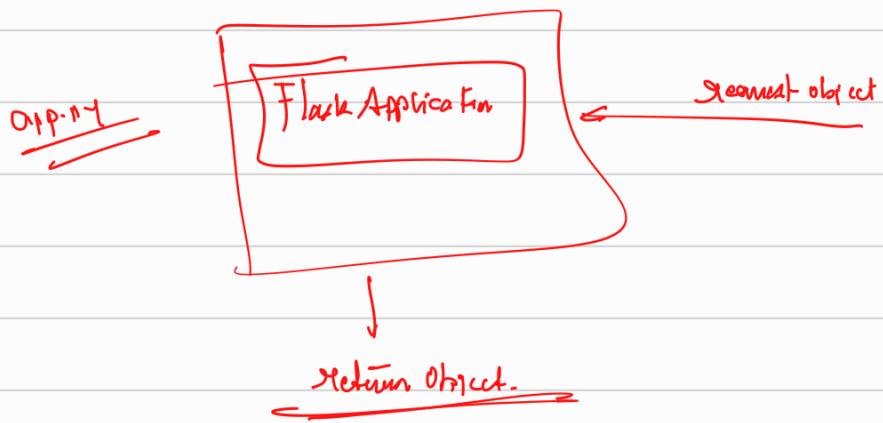
9:20 pm → 9:30 pm
9:30 → 10:15 Code.

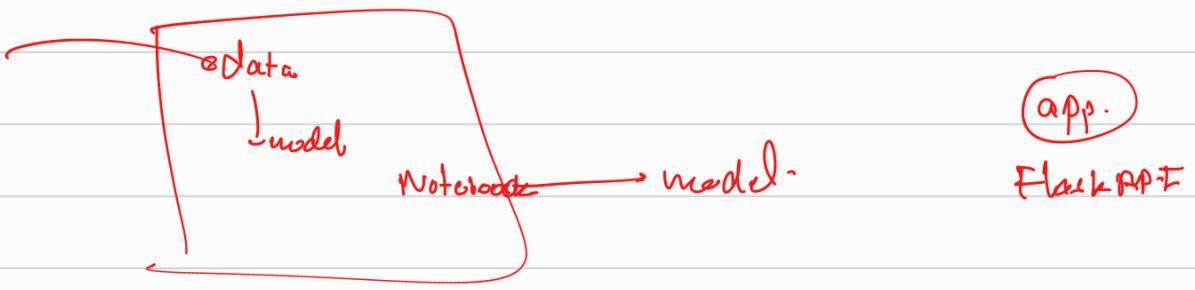
Cv → Image classification

- ① fast run video
- ② less resource for object tracking

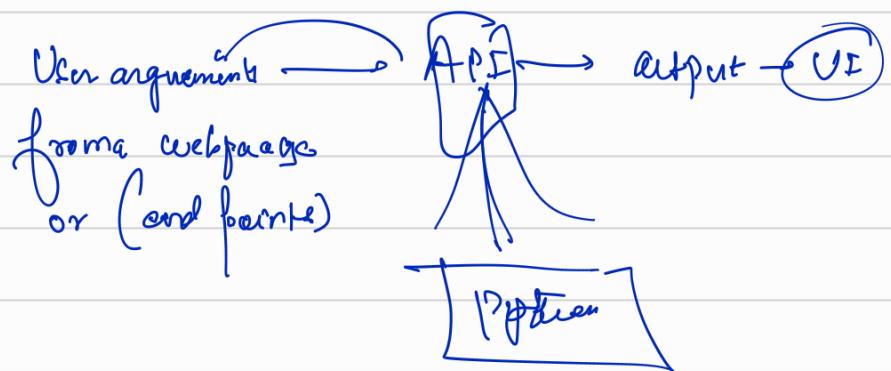




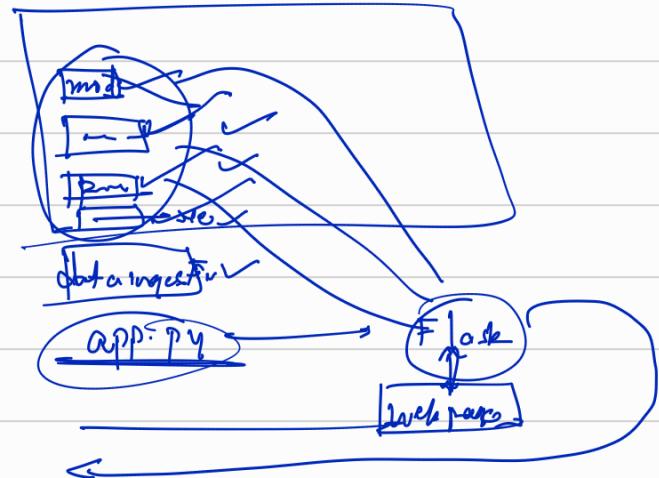


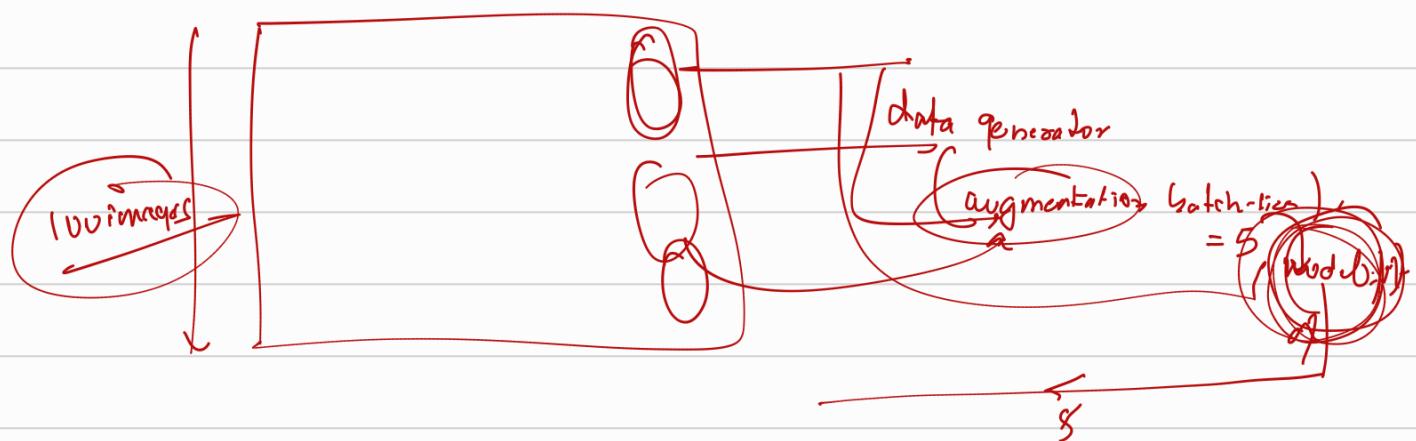
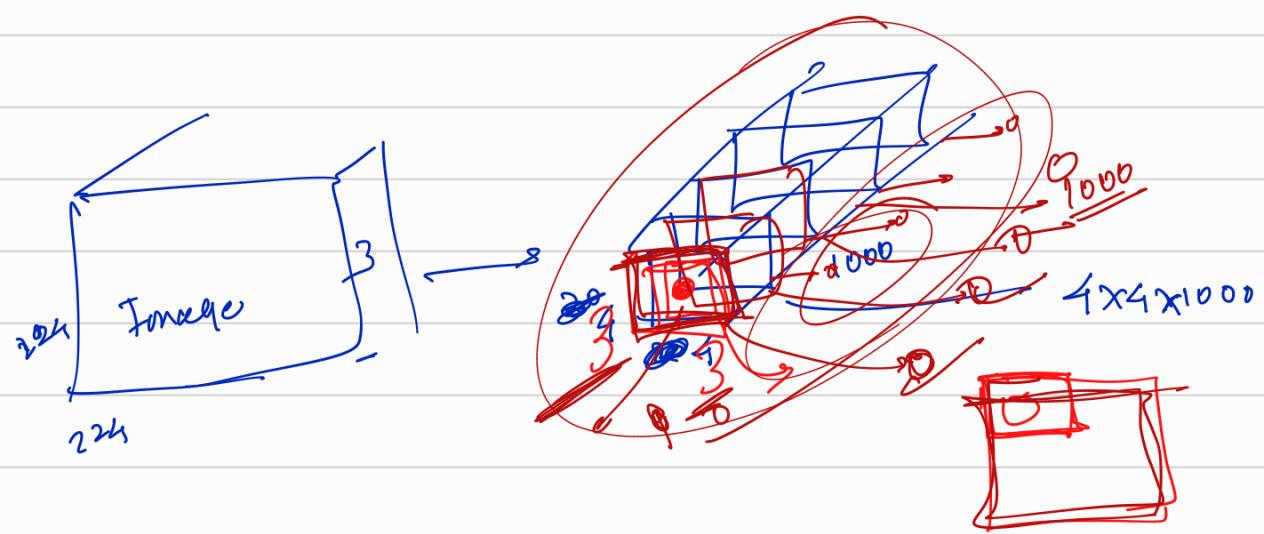


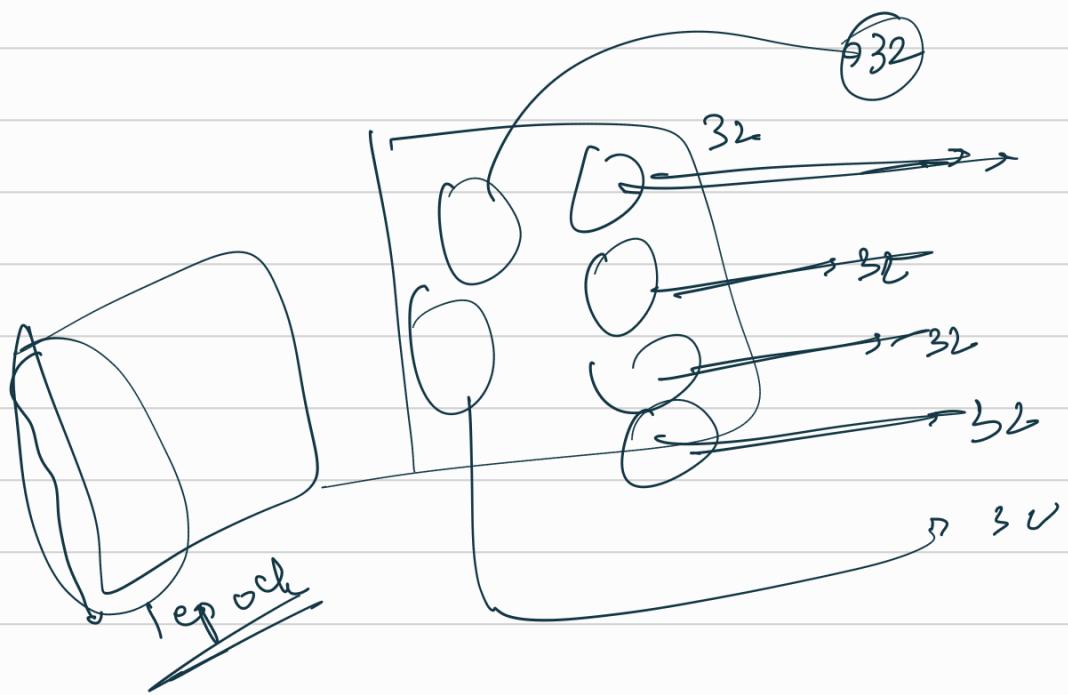
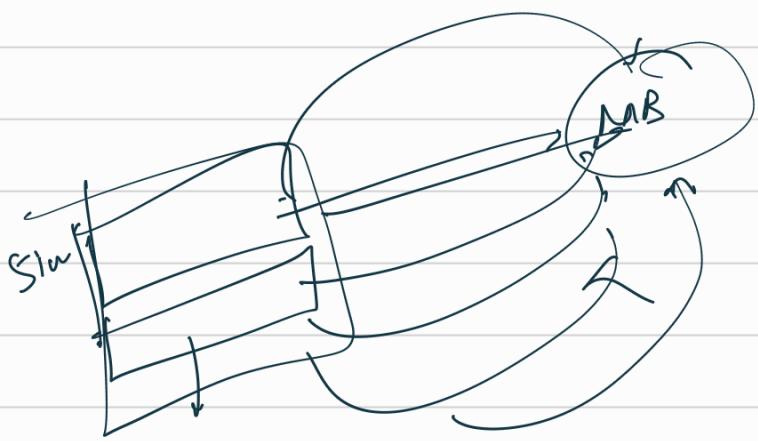
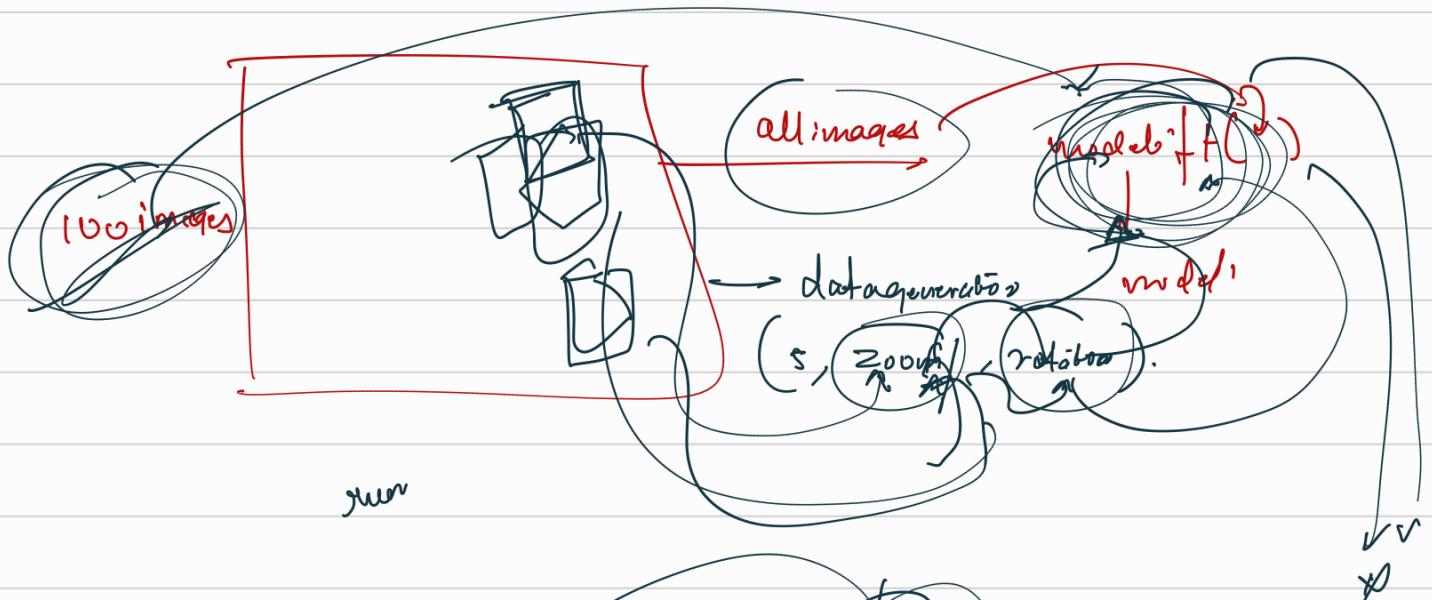
argument → Functions → output

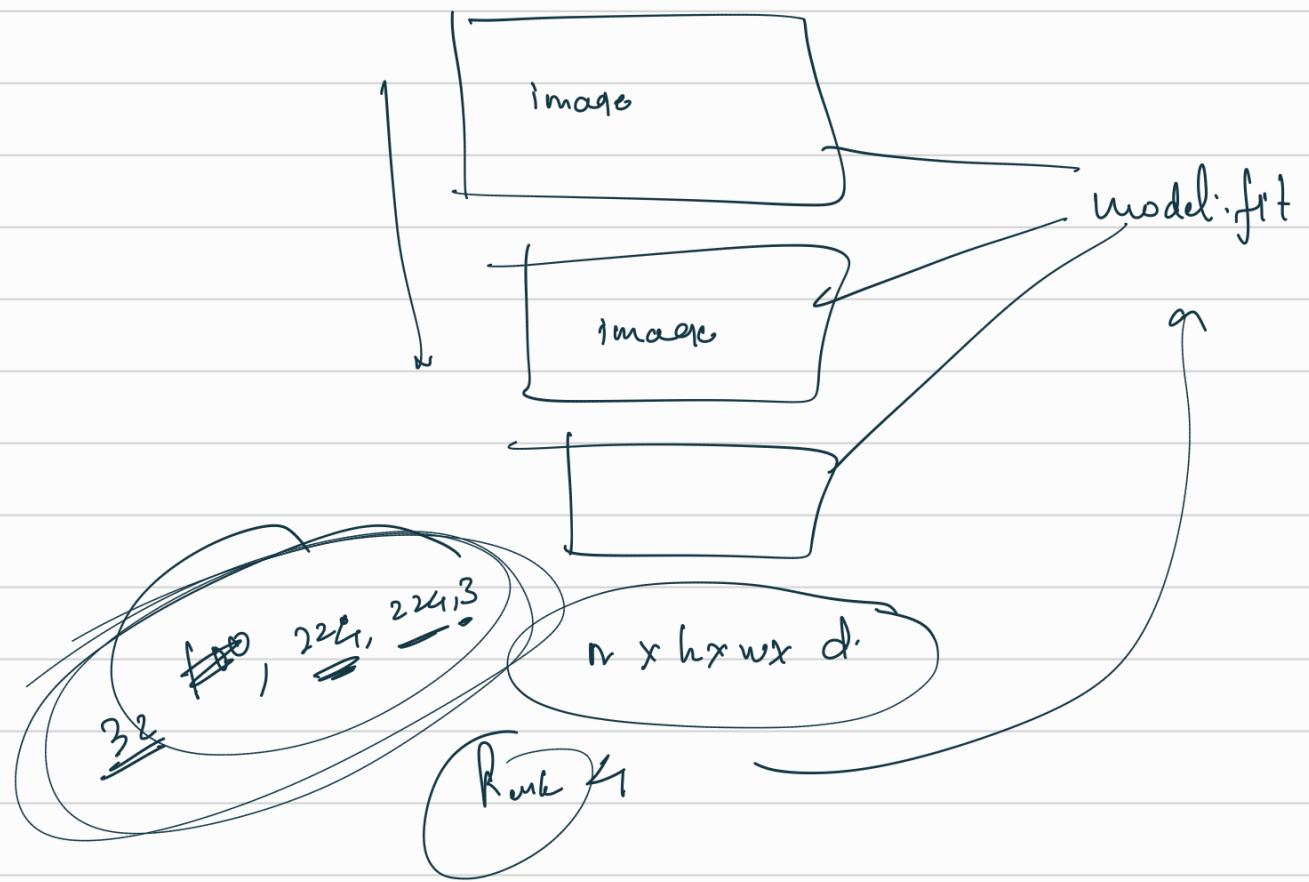


VS code









Keras

