VISIBLE LIGHT THERMAL IMAGING FUSION

Team 11 Senior Project CS 426 Spring 2012

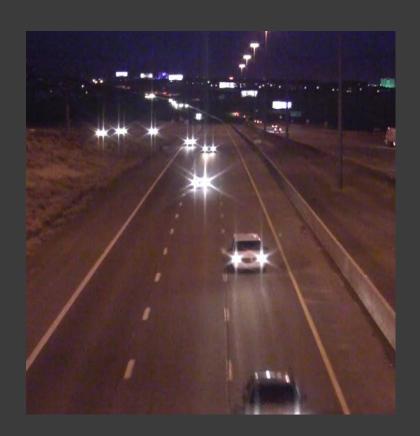
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PROJECT GOALS

Core:

- Detect any vehicles in image regardless of external conditions
- Accurately count vehicles passing through intersections regardless of external conditions

Potential:

- Generic classification based on type of vehicle (truck, sedan, sports utility vehicle)
- Discrimination between vehicles, pedestrians, cyclists
- Behavioral analysis (vehicles improperly parked in emergency zones, suspicious activity, etc.)



First came timers...





...followed by inductive loop sensors to detect if vehicle present

PROBLEM SOLVED?







And overall, the potential data collection from loop sensors is very limited.

WHAT IS A
BETTER
SOLUTION?

CAMERA BASED TRAFFIC MONITORING SYSTEMS



Easy to use and maintain...

Existing products with over \$100 million in annual sales...





PROBLEM SOLVED?

LIMITATIONS OF EXISTING SYSTEMS

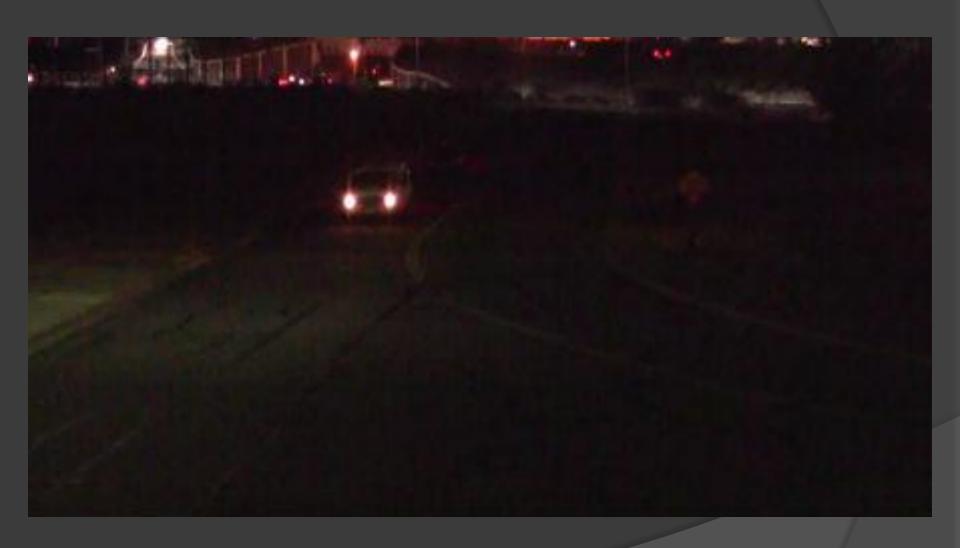






- Rely on a single color camera as input sensor
- Good performance is limited to
 - Daylight
 - Clear weather







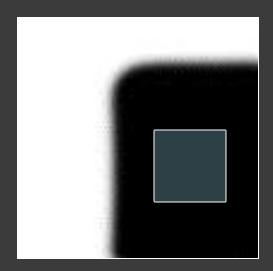
Traffic monitoring using thermal and visible light fusion.

Changes in lighting, occlusion, texture, and orientation greatly affect object recognition algorithms in computer vision.

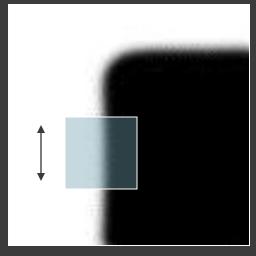


Humans are much better at pattern recognition with partial data.

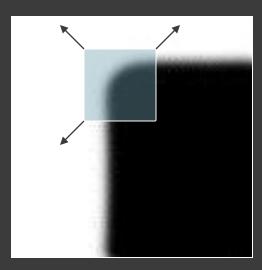
INTEREST POINT CONCEPTS



"flat" region: no change in all directions



"edge": no change along the edge direction

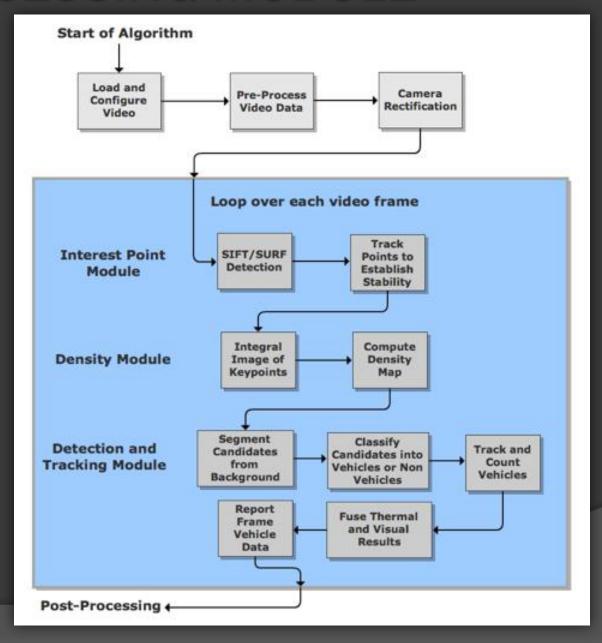


"corner": significant change in all directions

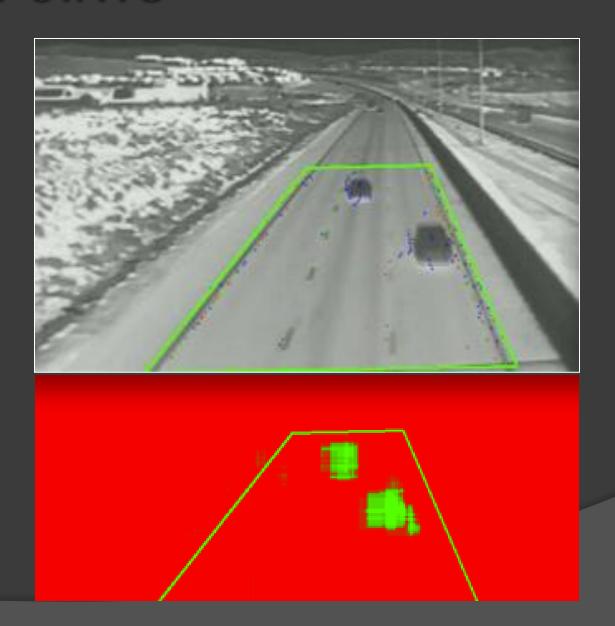
SIFT KEYPOINTS



PROCESSING MODULE



KEY POINTS



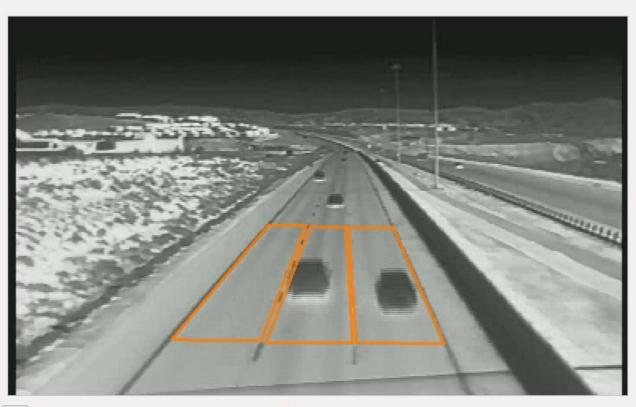
GUI

File Help





Clear Regions



Region 1

Vehicles: 23

Region 2

Vehicles: 13

Region 3

Vehicles: 18

-

DATA COLLECTION

Get thermal and visible cameras working in field Find locations that mimic position of traffic camera (overpasses)



Film each site in different external conditions (time of day, weather)

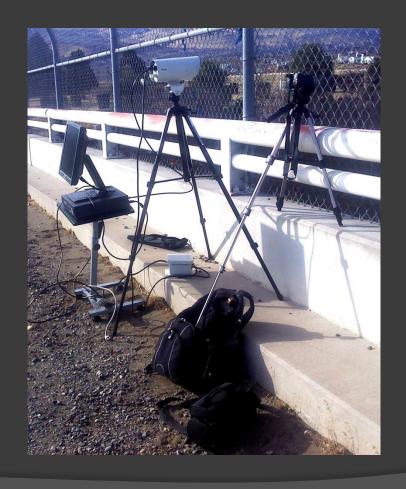
IDEAL DEVICE SETUP





Each device works automatically and is powered by hard work and determination

REAL DEVICE SETUP





Need monitor to observe output and a source to power it all

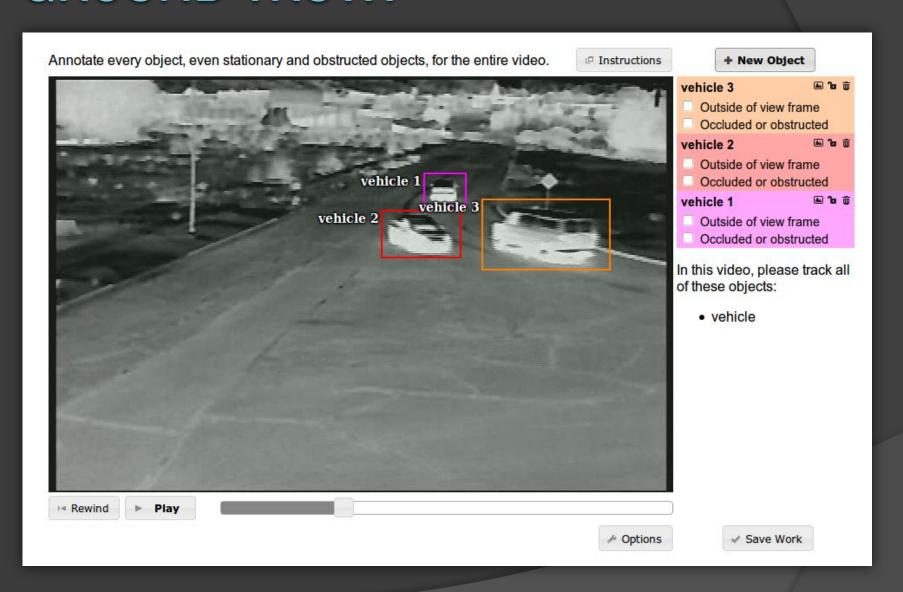
TEAM EFFORT



The roof of the van is sufficiently elevated to see over the fence

Not getting arrested while recording data

GROUND TRUTH



ANALYSIS

In order to evaluate our results, we use an analysis tool which will compute the Precision Recall Curve.

$$Precision = \frac{true positives}{true positives + false positives}$$

$$Recall = \frac{true positives}{true positives + false negatives}$$

Recall: The likelihood that an object is found.

Precision: The likelihood that an object found is accurate.

DEVELOPMENT NOTES

Team Website

Git Distributed Version Control

Github Issue and Bug Tracking

Doxygen Code Management

OBJECTIVES FOR SECOND PRESENTATION

- 1. Develop labeled ground truth using Vatic.
- 2. Finish building segmentation module.
- 3. Integrate Qt GUI with Vision Module.
- 4. Achieve an accuracy of 80% with a PR Curve Area of over 0.6.

- http://sherifftechnologies.com/civilengineering/groundworks-installationcivils/loop-cutting-contracts
- http://www.fhwa.dot.gov/publications/publicroads/07nov/04.cfm
- http://auto.howstuffworks.com/cardriving-safety/safety-regulatorydevices/red-light-camera1.htm

- http://ops.fhwa.dot.gov/freewaymgmt/pu blications/frwy_mgmt_handbook/chapter 15_01.htm
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- http://attackoftheblargg.blogspot.com/2011/ 01/rain-traffic.html
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