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-- 3.2 Hierarchical Motion Estimation with CSMFB -- 4 Results -- 4.1 Motion Estimation -- 4.2 Motion Correction -- 4.3 Phase Shift Correction -- 4.4 Motion Correction in Magnetic Resonance Imaging -- 5 Conclusions -- Fast and Robust Variational Optical Flow for High-Resolution Images Using SLIC Superpixels -- 1 Introduction -- 2 Existing Work Using (Over)Segmentation -- 3 Existing Superpixel Methods -- 3.1 gSLIC Superpixels -- 3.2 (g)SLIC in Our Proposed Workflow -- 4 Variational Optical Flow on the Superpixel Grid -- 5 Experiments and Results -- 6 Conclusion -- 7 Future Work -- References -- Depth-Based Filtration for Tracking Boost -- 1 Introduction -- 2 Proposed Approach -- 2.1 Pixel Filtration. 2.2 Tracking Stage -- 2.3 Detection Stage -- 2.4 Occlusion Handling -- 2.5 Recenter and Resize -- 2.6 Learning Stage -- 3 Experimental Results -- 3.1 Success Rate -- 3.2 Precision -- 3.3 Efficiency -- 4 Conclusion -- Robust Fusion of Trackers Using Online Drift Prediction -- 1 Introduction -- 2 Related Work -- 3 Our Approach -- 3.1 Drift Predictor -- 3.2 Computation of the Fusion Bounding Box -- 3.3 Object Model Reinitialization or Update -- 4 Fusion Experiments and Results -- 4.1 Video Dataset -- 4.2 Evaluation Protocol -- 4.3 Implementation -- 4.4 Results -- 5 Conclusion -- References -- Bootstrapping Computer Vision and Sensor Fusion for Absolute and Relative Vehicle Positioning -- 1 Introduction -- 2 Fusion Approach -- 3 Visual Features -- 4 Improved GPS Method -- 5 Dynamic Map -- References -- Detection of Social Groups in Pedestrian Crowds Using Computer Vision -- 1 Introduction -- 2 Proposed Methodology -- 3 Bottom up Hierarchical Clustering -- 4 Experimental Results -- 5 Conclusions -- References -- Single Image Visual Obstacle Avoidance for Low Power Mobile Sensing -- 1 Introduction -- 2 Navigating Around Obstacles -- 2.1 Relative Focus Maps -- 2.2 Obstacle Avoidance -- 2.3 Implementation -- 3 Evaluation -- 4 Conclusions and Future Work -- References -- ROS-Based SLAM for a Gazebo-Simulated Mobile Robot in Image-Based 3D Model of Indoor Environment -- 1 Introduction -- 2 System Setup -- 2.1 Choice of a Robot for Simulation in Gazebo -- 2.2 PR-2 Robot Description and Simulation -- 2.3 AR-601M Robot Description and Simulation -- 3 Camera-Based 3D Model of Indoor Environment -- 3.1 Indoor Environment Shooting with Camera -- 3.2 Image-Based 3D Modeling of Indoor Environment -- 4 ROS-Based SLAM Using Gazebo in Image-Based 3D Model of Indoor Environment -- 4.1 Robot Simulation in Gazebo -- 4.2 ROS-Based SLAM Simulation in Gazebo -- References.

Security, Forensics and Biometrics.

Sommario/riassunto

This book constitutes the thoroughly refereed proceedings of the 16th International Conference on Advanced Concepts for Intelligent Vision Systems, ACIVS 2015, held Catania, Italy, in October 2015. The 76 revised full papers were carefully selected from 129 submissions. AcivS 2015 is a conference focusing on techniques for building adaptive, intelligent, safe and secure imaging systems. The focus of the conference is on following topic: low-level Image processing, video processing and camera networks, motion and tracking, security, forensics and biometrics, depth and 3D, image quality improvement and assessment, classification and recognition, multidimensional signal processing, multimedia compression, retrieval, and navigation.
