AFFINE INVARIANT OBJECT

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THESIS

AFFINE INARIANT OBJECT RECOGNITION BY VOTING MATCH TECHNIQUES

by

Hsu, Tao-I

December 1988

Thesis Advisor: Chin-Hwa Lee

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# AFFINE INVARIANT OBJECT RECOGNITION BY VOTING MATCH TECHNIQUES

## Title: Master's Thesis

HSU, Tao-I

**TYPE OF REPORT**: Master's Thesis

**DATE COVERED**: FROM December 1988 TO December 1988

**PAGE COUNT**: 103

### Abstract

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**COSATI CODES**

- Field: Affine transformation
- Group: Hashing function

**SUBJECT TERMS**

- Affine transformation
- Hashing function
Affine Invariant Object Recognition
by Voting Match Techniques

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Submitted in partial fulfillment of the
requirements for the degree of

MASTER OF SCIENCE IN ELECTRICAL ENGINEERING

from the

NAVAL POSTGRADUATE SCHOOL
December 1988

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This thesis begins with a general survey of different model based systems for object recognition. The advantage and disadvantage of those systems are discussed. A system is then selected for study because of its effective Affine invariant matching [Ref. 1] characteristic. This system involves two separate phases, the modeling and the recognition. One is done off-line and the other is done on-line. A Hashing technique is implemented to achieve fast accessing and voting. Different test data sets are used in experiments to illustrate the recognition capabilities of this system. This demonstrates the capabilities of partial match, recognizing objects under similarity transformation applied to the models, and the results of noise perturbation. The testing results are discussed, and related experiences and recommendations are presented.
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ACKNOWLEDGMENTS

I would like to express my deep appreciation to my Thesis Advisor, Dr. Chin-Hwa Lee, for his guidance and counsel in assisting in the completion of this thesis.

I would also like to thank Dr. C.W. Therrien and LT Michael Shields and Mrs. Cindy Shields, and Dan Zulaica who contributed their assistance in the accomplishment of this thesis.

Finally, I wish to express my gratitude to my parents, and my fiancee, Wen-Yao Ko, who helped and supported me through these laborious times to achieve this educational goal.
I. INTRODUCTION

There has been considerable growth of interest in problems of object recognition. This interest has created an increased amount of theoretical methods and experimental software/hardware for the design of object recognition systems. Applications of object recognition include character recognition, target detection, medical diagnosis, analysis of biomedical images, remote sensing, identification of human faces or fingerprints, archaeology, speech recognition, machine part recognition, and automatic inspection.

Object recognition is primarily concerned with the description and classification of measurements taken from some physical or mental process. In general, object recognition may be considered as:

- Observing the attributes or characteristics of the objects,
- Selecting useful features from the set of characteristics that are expected for representation of the objects,
- Performing the matching procedure with respect to a specific goal on the basis of the representation.

It is obvious that the most popular and largely used technique in object recognition is model-based recognition. A model-based recognition system involves comparing the input image with a set of predefined models of objects. The goal
of such a system is to create a description of each of a known set of objects in advance. Then, these object models are used to recognize unknown objects in an image and to specify position and orientation relative to the viewers. A model-based vision system contains three basic phases: feature extraction, object modeling, and unknown object matching. These are discussed in the three subsections that follow.

A. FEATURE EXTRACTION (PREPROCESSING)

Using effective features in object recognition is a very important factor for success. Features can be used to describe or synthesize objects. Features of an object are most often boundaries and geometric measurements derived from boundaries. These features can be roughly classified into three types: global, local, and relational features.

- Global features include area (size), perimeter, centroid, distance of contour points from the centroid, curvature and moment of inertia, and others which provide useful information for object manipulation. The representation of an object with these global features can be stored in a feature lists, and the ordering of the features in the feature list is not important.

- Local features include line segments, arc segments with constant curvature and corner, each describing a portion of the object. They are organized in a highly structured manner, such as an ordered list or a sequence of equations. The ordering of the feature in this highly structured manner is usually related to the object's boundary.

- Relational features include a variety of distance and relative orientation measurements relating substructures and regions of an object. Geometric relations among
local features (e.g., corner and line) may be of particular interest.

Typical feature extraction techniques are the following:

1. **Fourier Descriptor Technique**

Fourier series representation of the parameterized boundary is one of the oldest and most well known transform technique. A finite number of harmonics of the Fourier descriptors are computed from the pattern boundary and compared with a set of reference Fourier descriptors. This description is global in nature, i.e., each coefficient depends on every other point of the boundary. It is therefore not suitable for recognition of partially occluded objects. A minimum-distance classification rule can be used for the recognition of various parts. [Ref. 2]

2. **Moment Techniques**

Moment techniques use parameters calculated from the pattern interior points. In these techniques, coordinates of points belonging to the pattern are used to compute a set of moments. These moments can be normalized to obtain measures that are invariant under scaling and rotation [Ref. 3]. It is difficult to relate higher order moments to the pattern. This requires global feature extraction, so the moment techniques have a shortcoming in recognizing partially occluded objects.
3. Technique of Accumulating Local Evidence by Clustering

Directed edge elements (vectors) are used as one type of primary feature which contains directional, positional, and size information. First, point features (i.e., the head and tail of a vector) are extracted, and then vectors are formed from suitable point pairs. Straight edge detectors, curved edge detectors, circle detectors, and intersection detectors are employed to define vectors between point pairs. Holes are detected by a set of circular masks and curves and intersections are detected by linking edges together [Ref. 4].

Overall, using local features has the following advantages:

- Local features may be cheaper to compute because they are simpler and can be selectively (sequentially) detected;
- If a few local features are missing (due to noise or occlusion), it may still be possible to recognize the object on the basis of the remaining features associated with the object;
- Since a few types of local features are often sufficient to describe a large number of complex objects, it is possible to specify only a few number of local feature detectors which can be applied to the image.

B. MODELING (TRAINING/LEARNING)

Modeling is based on the object's geometric properties such as object's shape and surface relative to the viewing angle. The three basic types of features (the global feature, the local feature, and the relational feature) are then employed to describe or represent objects.
Possible modeling schemes include radius-angle representation, orientation-arc length representation, curvature-arc length representation.

1. Radius-angle

The radius-angle representation requires a reference origin. This is usually taken to be the object's centroid. This representation is obviously scale-dependent. The need for a reference origin (global feature) also makes it unsuitable for recognizing partially occluded objects. Also the need for the representation to be single-valued further restricts the type of shapes that can be modeled in this manner.

2. Orientation-arc Length

The orientation-arc length representation models the angle made between a fixed axis and a tangent to the boundary as a function of the arc length. This representation is scale invariant but not orientation invariant. Straight horizontal lines or this representation correspond to zero curvature (i.e., straight lines in the boundary), and straight non-horizontal lines correspond to segments of circles with the radii or curvature given by the slopes of the lines. (This allows the boundary to be easily segmented into straight lines and circular arcs and is used sometimes in the initial processing for feature matching).
3. Curvature-arc Length

The curvature-arc length representation models the curvature of the boundary as a function of arc length. This representation is orientation-invariant but unfortunately it is not scale independent. (A circle of radius \( r \), for example, has a curvature of \( 1/r \)). Also, curvature is very sensitive to noise. However, curvature is a popular descriptor and this representation is often used to extract the extremas (in curvature) for feature matching [Ref. 5].

A discrete version of orientation-arc length representation has also been used. Commonly called chain codes, this models the boundary in short line segments that lie on a fixed grid with a fixed set of orientations. Although efficient in representation and cross-matching, chain codes are rather sensitive to noise and have other shortcomings that make this representation unsuitable for general shape matching.

It should be noted that none of the representations discussed above is simultaneously scale and orientation-invariant.

C. MATCHING (RECOGNITION)

Given a set of models that describe all aspects of an object to be recognized, the process of model-based recognition consists of matching features extracted from
unknown objects of a given input image with respect to those of the models. Matching techniques using global, local or relational features provide a way to recognize and locate a part on the basis of a few key features. Therefore, the model description dominates other procedures in the model-based matching process. The choice of matching process is highly dependent on the type of model used for object representation.

We divide matching processes into three schemes: statistical matching, graph matching, and syntactic (structural) matching. Models using global features are usually associated with statistical matching techniques. Models based on local features are usually associated with syntactic matching techniques, and models using both local and relational features are usually associated with graph matching techniques. Table 1 summarizes the techniques used in three phases of the model-based matching procedure.

1. **Statistical Matching**

Statistical pattern recognition can be divided into non-parametric and parametric methods. Non-parametric classification uses separation of clusters in feature space and to recognize pattern classes. Parametric classification on the other hand, is based on Bayes rule. It states that the input feature vector belongs to a particular class, say \( j \), if the likelihood ratio \((\lambda)\) between two pattern classes \( i \) and \( j \)
Table 1. The Three Methods Based on 2-D Image Representations.

<table>
<thead>
<tr>
<th>PHASE</th>
<th>Feature extraction</th>
<th>Modeling</th>
<th>Matching</th>
</tr>
</thead>
<tbody>
<tr>
<td>T E C H N I Q U E S</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Global scalar</td>
<td>Global scalar</td>
<td>Feature vector (unordered)</td>
<td>Statistical pattern recognition</td>
</tr>
<tr>
<td>Local</td>
<td>Local</td>
<td>Ordered string of features or abstract description of feature string</td>
<td>Syntactical or voting verification of string description</td>
</tr>
<tr>
<td>Local and relational</td>
<td>Local and relational</td>
<td>Relational graph</td>
<td>Graph searching</td>
</tr>
</tbody>
</table>

is greater than the ratio of the probabilities of occurrence of the pattern classes \( j \) over \( i \).

For example, consider two classes \( w_1 \) and \( w_2 \) with \( \text{a priori} \) probabilities \( P_1 \) and \( P_2 \) where \( (P_1 + P_2 = 1) \). The Bayes discriminant function \( f_{12}(x) \) defining the decision boundary between class 1 and 2 has the form

\[
f_{12}(x) = \frac{1}{p(x)}[P_1 L(w_1, d_2)p(x/w_1) - P_2 L(w_2, d_1)p(x/w_2)] \geq 0
\]  

(1)

where

\[
L(w_i, d_j) \text{ } i, j = 1, 2,
\]  

(2)
is the loss incurred with the decision $d_i$ when the $i$-th class is true, and

$$p(x) = \sum_{i=1}^{2} P_i p(x/\omega_i)$$  \hspace{1cm} (3)$$

and $p(x/\omega_1)$ and $p(x/\omega_2)$ represent the conditional probability densities associated with measurement $x$, given the unknown pattern that came from class $\omega_1$ or $\omega_2$ respectively. If $f_{12}(x) \geq 0$, we decide that $x$ belongs to the 1st class; if $f_{12}(x) < 0$, decide the 2nd class.

It is evident that Bayes rule is based on a priori knowledge. In practice, the collection of all the priori statistical data becomes a serious problem.

2. Syntactic/Structural Technique

In syntactic methods, an object model is represented by using abstracted and precise geometric primitives such as arcs, lines and corners. These primitives are local in nature, each describing a portion of the object. They are organized in a highly structured manner, such as an ordered list or a sequence of equations. The ordering of primitives in this type of method is usually related to the object's boundary in such a way that following the entire primitive list sequentially is equivalent to tracing the boundary of the object. Recognition uses a hypothesis-verification procedure. The structural local primitives of the model are used to predict where objects are located in the scene. Then,
primitives of the hypothesized object are measures on the basis of the prediction hypothesized in the model, in order to verify and find the match.

In this type of matching, the local primitives are transformed into primitives which are organized into strings (sentences) by some highly structured grammatical rules. Matching is performed by parsing. A major problem with the grammatical model is the construction of a grammar that is comprehensive enough to generate all the possible types of shapes of interest and yet discriminatory enough to reject others. The grammatical model is inherently one-dimensional. Noise perturbation of the model is also detrimental. A number of grammars have been developed over the years. A good description of these can be found in Reference 6.

3. Relational Graph Method

Objects can be represented structurally by graphs. In this method, relationships among local geometric primitives are represented by a graph. In the graph each node represents a local geometric primitive and is labeled with a list of properties (e.g., size) of the geometric primitive. Arcs represent relational primitive linking pairs of nodes and are labeled with lists of relation values (e.g., distance and adjacency). Recognition of the object becomes a graph-matching process. A disadvantage with this type of method is the fact that a large number of geometric primitives must be
detected and grouped together to recognize an object. Thus the matching algorithm used with these models must be more complex and may be slower than matching algorithms used with the other methods. Noises in the geometric primitives may change the graph of the unknown object. No precise analytic treatment of the noise problem is currently known.

4. Voting Match Techniques

A technique which is different from the traditional techniques discussed above is the Voting Match techniques. In this technique an object's model is defined first by transforming the object's local features into an abstract vector set. That is, the model representation is condensed to lower dimensional vector sets which preserve the geometrical characteristics corresponding to the original feature vectors. Matching is done using an accumulator cell to collect the strength of instances of occurring objects, that is, to increment a vote whenever a match between the unknown scene and the model occurs. The procedure matches all possible instances of the image and the model features on the basis of local evidence. From the peak strength in the accumulator cell the candidacy of the model can be picked up. Then, for verification, a line-drawing version of the object will be performed. This method is believed to be more robust because the voting procedure integrates all local information before any recognition decision is made.
There are two typical voting match techniques. These are Hough transform method and Affine transform method. Both use geometric transformations to map instances of a given pattern into peaks of a transform space.

The Hough transform method was originally developed to handle simple pattern such as straight lines and circles, but it was recently extended to arbitrary shapes [Ref. 7]. This technique can be summarized as follows. For the reference pattern, code the boundary with respect to a fixed reference point. For the test pattern, use this coding to reconstruct the possible locations of the reference point. The possible locations are thus obtained. If the two patterns are identical, there would be a peak at the location of the original reference point.

In this form, the Hough transform method has several limitations. It requires the reference and test objects to be of the same scale and orientation. To account for orientation, the above procedures must be repeated for every orientation to be distinguished. Thus computational complexity increases rapidly if it is necessary to deal with variations in scale and orientation. A more serious objection is that the transform suffers from false peaks in the accumulator array due to random matches caused by noise or distortion.
In the Affine transform method, the same voting technique is used as that in the Hough transform method. However, it does not have the shortcomings such as translation, orientation and scale variant problems, or misrecognition due to false peaks. Therefore the Affine transform method is often preferred. The Affine transformation mathematically is an automorphism. An automorphism of a mathematical structure is always a one-to-one mapping of that structure onto itself which preserves its structural properties. Therefore, Affine geometry could be called the geometry of parallelism, that is, Affine geometry has the characteristics of parallelism and the preserving of the ratio of parallel line.

In object recognition terms, any two different top view images of the same flat object are in an Affine 2-D correspondence. The Affine transform method involves a nonsingular $2 \times 2$ matrix $A$ and 2-D (translation) vector $b$, such that each point $x$ in the first image is translated to the corresponding point $Ax + b$ in the second image. Our problem in this thesis is to find the identity of objects in the scene and the Affine transformation between their locations in the scene and the stored models. The study is concentrated on recognition of flat rigid objects. However, this method can be extended to general and 3D objects. More detail about the
Affine transformation method will be addressed in the following chapters.

In Chapter II there is a discussion of the basic concept of Affine invariant transform illustrated through translation, rotation and enlargement of an arbitrary incoming sensed pattern. Motivated by this concept, a model-based object recognition system was developed. Chapter III details the algorithm and the system implementation that consists of three general object recognition phases: feature extraction (preprocessing), object modeling and object matching (recognition). Chapter IV discusses possible ways to improve the system performance and discussion of topics for further study. The Pascal-like pseudo code programs are included in Appendix A to explain the implementation. Appendix B contains the entire Affine invariant object recognition system source codes.
II. AFFINE INVARIANT MATCHING

The occluded or overlapped object recognition problem has received more attention recently in the object recognition community. A recognition technique that can identify an occluded object is discussed in this chapter. To understand many of the concepts involved in this work, a basic background for the Affine transformation is presented. The application of Affine transformation in the object recognition through match and voting techniques is also discussed.

A. PARTIAL MATCHING

In the industrial robotic vision application, parts often appear to be occluded to the sensor. Occluded objects are difficult to recognize by using the traditional or global feature recognition method. Object recognition techniques using global feature need to know the complete information representing or describing the objects. Once some portions are covered by other objects, the information will cause the recognition to fail. Accordingly, it is necessary to describe our objects by a set of local features. This situation is applicable to the human vision system, which is also capable of recognizing the object in the presence of considerable
occlusion. The local features can be points, line segments, curve segments, borders, or other structures obtained from feature extraction.

Initially, attention is restricted to the use of special points of the boundary, which we denote as interesting points. The point sets of the various objects are matched against the point set of the composite overlapping test object using a small number of corresponding points. To elaborate upon these views, one particular geometrical transformation with a unique mapping characteristic is used. That is the Affine coefficient invariant transformation discussed below.

B. AFFINE TRANSFORMATION AND VOTING TECHNIQUE

1. Affine Coefficient

The interesting point set can be transformed to an Affine coefficient pair \((\xi, \eta)\). Any three non-collinear points can uniquely specify a plane. The rest of the points of that plane can be expressed in terms of these three points. This representation is in terms of the Affine coefficient pair \((\xi, \eta)\).

The objects to be recognized in our system are assumed to be planar objects. The known objects are stored as models in the data-base in advance. Recognition of test object by comparing it to the models is based on two different sets of Affine coefficients which are obtained from the test object and the models respectively. Figure 1 shows this concept graphically.
AFFINE COEFFICIENT MATCHING

MODEL FEATURE

TEST OBJECT FEATURE

NON-COLINEAR INTERESTING POINT SET

NON-COLINEAR INTERESTING POINT SET

AFFINE TRANSFORM

AFFINE COEFFICIENT

AFFINE COEFFICIENT

MATCH??

Figure 1. The Concept of Recognition in Affine Coefficient Space.
2. **Affine Coefficient Transform**

Affine coefficient matching is one of the important matching techniques. It is motivated by the fact that any Affine transformation of a plane [Ref. 8] is uniquely defined by knowledge of three non-collinear points (or triplet) in the plane. The Affine transformation is always unique; it maps any non-collinear triplet in one plane to another non-collinear triplet.

To illustrate the "invariant" characteristic of the Affine transformation, consider the following example. For the pattern of Figure 2, there are four vertices A=(0,0), B=(0,1), C=(1,0) and D=(1,0). Point D can be expressed by points A, B and C (i.e., triplet), through the representation.

\[
D = \xi (B - A) + \eta (C - A) + A
\]

i.e.,

\[
(1,0) = \xi [(0,1) - (0,0)] + \eta [(1,2) - (0,0)] + (0,0)
\]

Solving for the unknown variables \( \xi \) and \( \eta \), we get

\[
\xi = -2, \eta = 1
\]

To show the characteristic of this transformation, let us examine the following cases.

a. **Case I: Translation**

Assume that there is a translation applied to the original pattern in Figure 2. The translation of the original pattern is accomplished by adding 1 to the coordinate of each vertices and results in Figure 3. In Figure 3, points \( A', B', \)
Figure 2. Original Pattern.

Figure 3. Translated Pattern.
C', and D' correspond to A, B, C and D respectively and have coordinates $A' = (1,1)$, $B' = (1,2)$, $C' = (2,3)$ and $D' = (2,1)$. Point $D'$ can also be expressed by $A'$, $B'$ and $C'$ as:

$$D' = \xi (B' - A') + \eta (C' - A') + A'$$

(6)
i.e.,

$$(2,1) = \xi [(1,2) - (1,1)] + \eta [(2,3) - (1,1)] + (1,1)$$

(7)
Solving for the unknown we again obtain

$$\xi = -2, \eta = 1$$

It is seen that the Affine coefficient pair remains the same in this case.

b. Case II: Rotation

Figure 4 shows the result of adding 1 and rotating the original pattern by $90^\circ$. Now, $A' = (2,3)$, $B' = (2,2)$, $C' = (1,1)$ and $D' = (1,3)$. Point $D'$ can again be expressed in terms of $A'$, $B'$ and $C'$ as:

$$D' = \xi (B' - A') + \eta (C' - A') + A'$$

(8)
i.e.,

$$(1,3) = \xi [(2,2) - (2,3)] + \eta [(1,1) - (2,3)] + (2,3)$$

(9)
Solving for the unknowns again, we get

$$\xi = -2, \eta = 1$$

The Affine coefficient pair is still the same as before.

c. Case III: Enlargement-Scale Change

The combined effect of translation, rotation, and enlargement, which is generated from the original pattern by adding 1 (translation), rotating $90^\circ$, and multiplying by 2

20
Figure 4. Pattern After Rotation.

(enhancement) is shown in Figure 5. Here, the vertices are
\( A' = (4,6) \), \( B' = (4,4) \), \( C' = (2,2) \) and \( D' = (2,6) \). Point \( D' \) can also be expressed by \( A' \), \( B' \), and \( C' \) as:

\[
D' = \xi (B' - A') + \eta (C' - A') + A' \tag{10}
\]

i.e.,

\[
(2,6) = \xi [(4,4) - (4,6)] + \eta [(2,2) - (4,6)] + (4,6) \tag{11}
\]

Again we find

\[
\xi = -2, \eta = 1
\]

In all those four cases, \( \xi \) and \( \eta \) are exactly the same. We have illustrated the invariant property of the transformation in the above cases. That means that the Affine coefficient pair \((\xi, \eta)\) does not change in those four cases. The Affine invariant matching technique studied in this thesis is based on this property.
Figure 5. Pattern After Translation, Rotation and Enlargement.

For a test object in the scene, we can exploit this property to represent those points of the test object in terms of their Affine coefficients which are invariant to similarity transformations. That is, we change the object representation from the interesting point representation of the original plane (the higher dimension representation) to a representation based on the non-collinear triplet (the lower dimension representation). In this coefficient space, it is possible to apply search and voting techniques to recognize the test objects.

C. AFFINE INVARIANT RECOGNITION ALGORITHM

The Affine coefficient invariant property was illustrated in section II.B.2. It is possible to exploit this property
to recognize planar objects. We divide the recognition process into two separate procedures. The first procedure is Modeling (encoding). The second procedure is the Recognition (Matching). The Modeling procedure has two phases: preprocessing and data-base setup. The recognition procedure has three phases: Preprocessing, Data-base access and Voting match. The purpose of the Preprocessing is to extract a set of interesting points from the object. It is used both in the Modeling procedure and the recognition procedure. The Date-base setup includes choosing three arbitrary non-collinear points (triplet) as an Affine basis and generating the coefficients $\xi$ and $\eta$. These are used as index keys to create a search table with the triplet as its content. In the Recognition procedure the Affine coefficient of the interesting points of the test object ($\xi, \eta$) is also used as the index keys to search the previously created table. When there is a match, we increment a vote. The total vote will be used to decide whether the basis of the test object is the one corresponding to that of the model.

1. **Preprocessing (Feature Extraction)**

   This phase is done to extract features for either the models in the date-base or the test patterns. These features can be points, line segments, curve segments, etc., as mentioned in Chapter I. In general, the more features extracted, the more detail it is possible to describe a model. Hopefully, with more features, more accurate recognition can
be achieved. However, this approach will increase computation complexity. Using the extracted features, a model approximation is formed, using the set of interesting points for each object model. Since the image is assumed to be flat, only one set of interesting points is involved. For 3-D objects, it may be necessary to extract several sets of interesting points, one for each orthogonal projection of the object. Smoothing and data reduction are also two of the primary effects in feature extraction. The thesis work studied here will not emphasize the feature extraction phase. The processing steps will be discussed in more detail in section III.A.

2. Data-Base Setups (Modeling)

This phase is the second step in the Modeling (encoding) procedure where creation or update of the model data-base is accomplished. The objective of this phase is to encode models in the data-base and to create the search table. Each model object is represented by a set of local feature interesting points which were obtained from the Preprocessing. A total of \( m \) interesting points are extracted from the model, (i.e., the model points). These model points approximate the object in a special form. For each ordered non-collinear triplet of model points the coefficient \((\xi, \eta)\) of all the rest of the \( m-3 \) model points are computed. Taking this triplet as an Affine basis in the 2-D plane, the other points can be represented as
\[ \mathbf{v} = \xi (\mathbf{e}_{10} - \mathbf{e}_{00}) + \eta (\mathbf{e}_{01} - \mathbf{e}_{00}) + \mathbf{e}_{00} \]  

(12)

where \( \mathbf{e}_{00}, \mathbf{e}_{01}, \mathbf{e}_{10} \) are the three selected non-collinear points.

Application of an Affine transformation \( T \) described in section II.B.2. will change the point \( \mathbf{v} \) to

\[ T\mathbf{v} = \xi (T\mathbf{e}_{10} - T\mathbf{e}_{00}) + \eta (T\mathbf{e}_{01} - T\mathbf{e}_{00}) + T\mathbf{e}_{00} \]  

(13)

Hence, \( T\mathbf{v} \) still has the same coefficient \((\xi, \eta)\) on the new triplet basis \( T\mathbf{e}_{00}, T\mathbf{e}_{10}, T\mathbf{e}_{01} \). Each such coefficient is used as an index to access the search table. The entry of this search table may have a variable number of ordered pair, \((\text{modelid, basis-tripletid})\). The ordered pairs helps to access the vote array to register the basis-triplet by which the coefficient was obtained. Some detail of the search table is shown in Table 2. This is a conceptual table mainly used to illustrate the algorithm. The actual implementation is different in detail. That will be discussed in the next chapter.

3. Voting Match

In the recognition procedure a test object is given in a scene. First, the interesting points of this test object (say we have \( n \) interesting points) have to be extracted. An arbitrary ordered test triplet of the interesting points of the test object is selected. Based on the test triplet, the Affine coefficient of the other points can be calculated. The search
Each entry has a variable number of records of ordered pair \((modelid, basis-tripletid)\).

<table>
<thead>
<tr>
<th>Table 2. CONCEPTUAL SEARCH TABLE FORMAT.</th>
</tr>
</thead>
<tbody>
<tr>
<td>1ST AFFINE COEFFICIENT (KEY1,KEY2)</td>
</tr>
<tr>
<td>(MODELID,TRIPTID)</td>
</tr>
<tr>
<td>VOTE</td>
</tr>
<tr>
<td>(MODELID,TRIPTID)</td>
</tr>
<tr>
<td>VOTE</td>
</tr>
<tr>
<td>...</td>
</tr>
<tr>
<td>...</td>
</tr>
<tr>
<td>...</td>
</tr>
</tbody>
</table>

| 2ND AFFINE COEFFICIENT (KEY1,KEY2)      |
| (MODELID,TRIPTID)                        |
| VOTE                                    |
| (MODELID,TRIPTID)                        |
| VOTE                                    |
| ...                                     |
| ...                                     |
| ...                                     |

| 3RD AFFINE COEFFICIENT (KEY1,KEY2)      |
| (MODELID,TRIPTID)                        |
| VOTE                                    |
| (MODELID,TRIPTID)                        |
| VOTE                                    |
| ...                                     |
| ...                                     |
| ...                                     |

tripletid), where the model field is an integer for model identification and the basis-triplet field is the model triplet used as the Affine basis for the model. Associate with each record of ordered pairs is a vote array called "vote." This is initialized to zero.

During the recognition procedure, for each Affine coefficient pair \((\xi, \eta)\) the search table created in the Data-Base Setup phase is accessed and those vote fields are also tallied. For each entry of the table, different \((modelid, basis-tripletid)\) pairs with the same \((\xi, \eta)\) are accessed and the entries of "vote" are incremented by one. If the entry of the search table scores a large enough number of votes, all ordered pairs of this entry become possible candidates to match the test
object. The next step is to decide which of the ordered pairs (i.e., which model) will be the real matched one. The selection process is based on the fact that the model with the maximum accumulated vote is the matched model. The model triplet of the ordered pair of the maximum accumulated vote then corresponds to the one chosen for the test object. The uniquely identified Affine transformation, between the model triplet and the test triplet, is the selected transformation between the model and the object. Using the selected model triplet and all entry of the pairs \((\xi,\eta)\) associated with this selected maximum vote model triplet, it is possible to reconstruct the recognized model in the scene. If the selected model triplet and all of the associated pairs \((\xi,\eta)\) do not match the dimension of the model, the second maximum vote model triplet and its associated pair \((\xi,\eta)\) is checked in the same way. Because of this checking procedure the test object can be reconstructed even when there is occlusion.
III. ALGORITHM IMPLEMENTATION

A. SEARCHING

Searching plays an important role in the Affine recognition procedure. It is necessary to search the table shown in Table 2. Search is dependent on the index or search key. This is a content dependent search. The objective of the search is to collect the instances (basis-triplet) of the models which occurred in the test object. The more instances of the model occurring in the test object, the more confident will be the decision which shows what part of the test object resembles the model. Content dependent search is inherently slow. Therefore, special techniques are needed to speed up this procedure.

B. HASH TECHNIQUE

In the recognition procedure, the result of the Affine transformation of the interesting points is actually a pair of real coefficient, i.e., $(\xi, \eta)$. By multiplying it with a constant, this pair of coefficients can be added to generate the key, i.e., inkey, in this system. Since the quantized real coefficient is somehow random, it is not desirable to use sequential array data structure like those shown in Table 2.
The storage overhead and speed reduction will be too severe. The Hashing technique is a preferred technique. The inkey is associated with a location of an accumulator cell. The accumulator cell is used to store the instance of the occurrence of the candidacy model.

Hashing is a many-to-one mapping that does not usually preserve the order of the keys of a list. Hashing is achieved by deriving a hash key from the inkey which indicates to which sublist or neighborhood a record belongs. This sublist is called a bucket. The biggest problem is Hashing is the difficulty in producing a relatively uniform number of records in the bucket. When the keys, inkey1 and inkey2, of two distinct records are converted to the same hash key, there is a collision. To solve this problem in this system, it is necessary to use a linked list to append the collided record after the last record in the bucket. The linked list is used to link all records in the same bucket together with the same hash key.

There are several possible Hashing implementations. One of the best general purpose methods is the division method [Ref. 9]. Our system is based on this method. In this method an inkey is divided by a number which is the table size in this system. Then, the record is assigned to the bucket that is associated with the remainder, i.e., the hash key. Table size is determined by the possible number of ($\xi, \eta$) pairs generated.
from the interesting points of the model for all bases. Figure 6 shows hash key generation by division.

1. Hashing Implementation

The algorithm implementation is divided into two separate procedures. The first procedure is Modeling (encoding). The second procedure is Recognition (Matching). The Modeling procedure has two phases: preprocessing and data-base setup. The recognition procedure has three phases: preprocessing, data base access, and voting match. The implementations for each of these modules are described in sequence. In preprocessing the interesting points of the boundary are formed. In data base setup the Affine coefficient pairs \((\xi, \eta)\) are calculated which are
used to generate the "Hash" table. In voting match the test object and models in the data base are compared in terms of (modelid, basis-tripletid) pair.

C. PREPROCESSING

The preprocessing is shown in Figure 7, which consists of a number of steps. All the modules in this phase are adopted from the commercial package SPIDER [Ref. 10] on a VAX 11/780 system. SPIDER is an image processing utility software package. There are five routines written in FORTRAN used for preprocessing.

1. Laplacian Operator EGLP [Ref. 10]

The Laplacian function $f(X,Y)$ of two independent variables is defined as

$$\nabla^2 f(X,Y) = \frac{\partial^2 f(X,Y)}{\partial X^2} + \frac{\partial^2 f(X,Y)}{\partial Y^2}$$  \hspace{1cm} (14)

The image intensities change sharply at places where $\nabla^2 f(X,Y)$ is large. The outline is detected and obtained from the Laplacian image plane.

2. Threshold Operation SLTH

This operation thresholds the output data of the Laplacian operator and generates the input data for the boundary tracing operation conducted later. That is,

$$g(x,y) = \begin{cases} 256 & \text{if } \nabla^2 f(X,Y) > \text{THRESHOLD} \\ 0 & \text{otherwise} \end{cases}$$  \hspace{1cm} (15)
3. Boundary Thinning THNG [Ref. 10]

The boundary outline of the image is thinned to a width of 3 pixels.

4. Tracing Boundary BDFL [Ref. 10]

Boundary tracing is the conversion from boundary coordinates to chain codes [Ref. 11]. The line is represented by the coordinates of the starting point and a series of codes indicating the slope of the line segments (or links).
BDFL algorithm primarily involves raster scan and tracking of the data.

5. Maximum Curvature Finding MAXCUR

The interesting points are taken at places where the chain code slope is greater than a certain threshold.

At the end of the preprocessing phase, the interesting points of the boundary are selected from either the model or the test object.

D. DATA-BASE SETUP

The data-base setup phase is shown in Figure 8. In the data-base setup phase of the modeling or encoding procedure, two steps are involved. They are discussed in the following.

1. Affine Transformation

AFFINE is the first step in the data-base setup phase. From the interesting points, a set of non-collinear triplets is chosen as an Affine basis. Then the Affine coefficient pair \((\xi, \eta)\) of the other points are calculated. The Affine coefficient pair \((\xi, \eta)\) is then converted from real data type to integer type by multiplying it by a constant. For example, if there are four interesting points \((X_1,Y_1), (X_2,Y_2), (X_3,Y_3)\) and \((X_4,Y_4)\), the fourth point is expressed using the other three as a triplet basis,

\[
X_4 = \xi(X_1 - X_2) + \eta(X_2 - X_3) + X_3 \tag{16}
\]

\[
Y_4 = \xi(Y_1 - Y_2) + \eta(Y_2 - Y_3) + Y_3 \tag{17}
\]
and $\xi$ and $\eta$ are solved from the above equations. That is

$$
\begin{pmatrix}
\xi \\
\eta
\end{pmatrix} = \begin{pmatrix}
(X_1 - X_2)(X_2 - X_3) \\
(Y_1 - Y_2)(Y_2 - Y_3)
\end{pmatrix}^{-1} \begin{pmatrix}
(X_4 - X_3) \\
(Y_4 - Y_3)
\end{pmatrix}
$$

(18)
This procedure is repeated for all different ordered triplets (i.e., permutations and combinations) as basis until every possibility is exhausted. This will generate an output file \((\text{hashkeydata})\). (The format of this data file is described in Table 3.) The main Affine program reads the interesting point data from the input file \(\text{interestingdata}\) and invokes the following modules to accomplish the task. The Pascal-like pseudo code and source program of all modules are listed in Appendix A.

Table 3. HASHKEY DATA FILE FORMAT.

<table>
<thead>
<tr>
<th>entry 1</th>
<th>inkey</th>
<th>model id</th>
<th>triplet id</th>
<th>key 1</th>
<th>key 2</th>
<th>model triplet base (X_1, X_2, X_3)</th>
<th>model triplet base (Y_1, Y_2, Y_3)</th>
</tr>
</thead>
<tbody>
<tr>
<td>entry 1</td>
<td>-20000000</td>
<td>1</td>
<td>1</td>
<td>-1</td>
<td>-1</td>
<td>30,20,40</td>
<td>40,30,30</td>
</tr>
<tr>
<td>entry 2</td>
<td>0</td>
<td>1</td>
<td>1</td>
<td>1</td>
<td>-1</td>
<td>30,20,40</td>
<td>40,30,30</td>
</tr>
<tr>
<td>entry (i)</td>
<td>10000000</td>
<td>2</td>
<td>1</td>
<td>1.5</td>
<td>-0.5</td>
<td>40,30,20</td>
<td>10,10,30</td>
</tr>
</tbody>
</table>

Note: \(\text{inkey} = 10000000 \times (\text{key 1} + \text{key2})\)

entry 1 and entry 2 belong to the same model triplet

a. **COMB Module**

This module is a recursive module which generates all the possible combinations of triplets from the input interesting points. If there are \(m\) interesting points, the total number of combinations will be

\[
mC_3 = \frac{m(m-1)(m-2)}{3!}
\]  

(19)
For each combination this module will call the COLLINEAR module.

b. COLLINEAR Module

This module tests the collinearity of the combinations sent from the COMB module. Slopes among the points are checked to verify the collinearity. If the test of collinearity is not successful, this module then calls the PERM module. If the test is successful, control will be returned to the COMB module for a new combination.

c. PERM Module

Given the combination passed from the COLLINEAR module, this module generates all the permutation. This is again a recursive program. For each permutation it calls the CALCULATE-COORD module.

d. CALCULATE-COORD

This module calculates the base-matrix

\[
	ext{base - matrix} = \begin{pmatrix}
    (X_1 - X_2)(X_2 - X_3) \\
    (Y_1 - Y_2)(Y_2 - Y_3)
\end{pmatrix}
\]  \hspace{1cm} (20)

It then calls the INVERSE module by passing the base-matrix for inversion. Then it calculates the difference for the rest of the interesting points \((X_i, Y_i)\)

\[
\text{difference} = \begin{pmatrix}
    (X_i - X_3) \\
    (Y_i - Y_3)
\end{pmatrix}
\]  \hspace{1cm} (21)

This module then invokes the MATRIX-MULT module to get the final solution, the Affine coefficient pair \((\xi_i, \eta_i)\).
e. **INVERSE Module**

This module calculates the inverse-matrix, for the solution of $\xi$ and $\eta$, that is

$$\text{inverse - matrix} = \left( \begin{array}{c} (X_1 - X_2)(X_2 - X_3) \\ (Y_1 - Y_2)(Y_2 - Y_3) \end{array} \right)^{-1} = \frac{1}{\text{det}} \left( \begin{array}{c} (Y_2 - Y_3)(X_2 - X_3) \\ (Y_1 - Y_2)(X_1 - X_2) \end{array} \right)$$  \hspace{1cm} (22)

f. **MATRIX-MULT Module**

This module calculates the final Affine coefficient pair $(\xi_i, \eta_i)$. That is

$$\left( \begin{array}{c} \xi_i \\ \eta_i \end{array} \right) = \left( \begin{array}{c} (X_1 - X_2)(X_2 - X_3) \\ (Y_1 - Y_2)(Y_2 - Y_3) \end{array} \right)^{-1} \left( \begin{array}{c} (X_i - X_3) \\ (Y_i - Y_3) \end{array} \right)$$  \hspace{1cm} (23)

2. **Hash Table Generation**

**HASH** is the second step in the Data base setup phase. At the end of AFFINE execution, the $(modelid, basis-tripletid)$ pairs are created and stored in a file (hashkeydata) with other support information shown in Table 3. This is an input file to the **HASH** module.

The purpose of the HASH program is to read the input file hashkeydata and create the Hash table with the format as shown in Table 4. The Hash table is a linked list structure.

Each record has extra fields: hashkey, inkey, and link. This structure is the actual implementation used in the experiment; it is different from the search table in Table 2 used for conceptual illustration. The link field is used to link the collided records while the Hash module maps two records with two different values of inkey to the same hashkey. As an
**Table 4: The Hash Table Format.**

<table>
<thead>
<tr>
<th>H1</th>
<th>hashkey</th>
<th>inkey</th>
<th>modelid</th>
<th>tripletid</th>
<th>key 1</th>
<th>key 2</th>
<th>base</th>
<th>basey</th>
<th>link</th>
<th>vote (modelid, tripletid)</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>H2</td>
<td>hashkey</td>
<td>inkey</td>
<td>modelid</td>
<td>tripletid</td>
<td>key 1</td>
<td>key 2</td>
<td>base</td>
<td>basey</td>
<td>link</td>
<td>vote (modelid, tripletid)</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>H3</td>
<td>hashkey</td>
<td>inkey</td>
<td>modelid</td>
<td>tripletid</td>
<td>key 1</td>
<td>key 2</td>
<td>base</td>
<td>basey</td>
<td>link</td>
<td>vote (modelid, tripletid)</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

(1) Entry H1 and entry H3 are in the same bucket

(2) Vote is a two dimensional array indexed by (modelid, tripletid)

(3) $\leftrightarrow$ means association from link list to the 2-D array
example, for a module with four interesting points, the Hash table size is $4 \times 6 = 24$ where 4 is the combinations of three out of four and 6 is the permutations of three out of three. The main task of the HASH module is to generate a consistent Hash table for the recognition procedure. Three modules are called from the HASH program.

a. **INITIALIZE Module**

This is called to initialize the field hashkey and link all of the record to empty label.

b. **HASHING Module**

After initialization, the Hash main program invokes the HASHING module to convert Affine coefficient pair $(\xi, \eta)$ (i.e., $(key1, key2)$) to inkey by adding them and multiplying the sum with a constant multiplier. That is:

$$\text{inkey} = (\text{key1} + \text{key2}) \times \text{multiplier} \quad (24)$$

The HASHING module also generates the hashkey as following:

$$\text{hashkey} = \text{inkey MOD tablesize} \quad (25)$$

The HASHING module then tests if the record accessed by the hashkey in the Hash table has an empty hashkey field. If so, it will insert the current record of the input file (hashkeydata) into the Hash table. Otherwise it will invoke the collision module.
c. **COLLISION Module**

This module tests to see if the accessed record's *link* field of the Hash table is empty. If it is empty, the current record of the input file is the first new-comer into the *bucket* list pointed to by the *link* field. The current record is put in the next available position in the Hash table. The *link* field of the accessed record is updated to point to this new position. If the *link* field is not empty, then using the *link* field, the module can find sequentially the last existing entry of the bucket list and append the current record after the last entry.

E. **RECOGNITION**

Once the *Modeling (encoding)* procedure is accomplished, it is possible to start the recognition procedure of a test object. The flow chart of recognition procedure is shown in Figure 9.

After the preprocessing, a set of $n$ interesting points of the input test object were generated. The *AFFINE* program is invoked to process these points. This program includes modules *COMBINATION, COLLINEAR, CALCULATE-COORD, INVERSE* and *MATRIX-MULT* to obtain the Affine coefficient pairs $(\xi_i, \eta_i)$ $i = 1, 2, \ldots, n - 3$ of the test object. Those Affine coefficient pairs $(\xi_i, \eta_i)$ and the associated test triplet are stored in an output file (*candidatedata*). The format of output file (*candidatedata*) is shown in Table 5. *Inkey* is used to access the
Figure 9. Recognition Procedure Flowchart.

Hash table and the test triplet is used to establish the correspondence between the model triplet of the Hash table,
and the test object at the end of the recognition procedure for reconstruction.

The objective of the tally program is to accumulate incidences of correspondence between one test object's triplet (candidatedata) and one model triplet. Each model has a set of triplets and there could be multiple models in the Hash table. Both of these two set of triplets and the associated interesting points could generate the same Affine coefficient pairs \((\xi_i, \eta_i)\). This represents one incidence of the match. In other words, the Affine coefficient pair \((\xi_i, \eta_i)\) generated by a test triplet is used to access the Hash table. Matching between test triplet and model triplet is done in the Affine

Table 5. CANDIDATE DATA FILE FORMAT.

<table>
<thead>
<tr>
<th>inkey</th>
<th>key1</th>
<th>key2</th>
<th>test triplet base X</th>
<th>test triplet base Y</th>
</tr>
</thead>
<tbody>
<tr>
<td>candidate 1</td>
<td>-20000000</td>
<td>-1</td>
<td>30,20,40</td>
<td>40,30,30</td>
</tr>
<tr>
<td>candidate 2</td>
<td>0</td>
<td>1</td>
<td>30,20,40</td>
<td>40,30,30</td>
</tr>
<tr>
<td>candidate 3</td>
<td>10000000</td>
<td>1.5</td>
<td>40,30,20</td>
<td>10,10,30</td>
</tr>
<tr>
<td></td>
<td>....</td>
<td>....</td>
<td>....</td>
<td>....</td>
</tr>
<tr>
<td>candidate n</td>
<td>....</td>
<td>....</td>
<td>....</td>
<td>....</td>
</tr>
</tbody>
</table>

Note: \(\text{inkey} = 10000000 \times (\text{key1} + \text{key2})\)

candidate 1 and candidate 2 belong to the same test triplet

coefficient domain. During the search, whenever there is a corresponding model triplet in the Hash table with the same Affine coefficient pairs as those of the test triplet, this model triplet in the Hash table is declared to match the test
object. The program *tally* first reads the input file (*candidatedata*) of the test object into a record array (*cand*) and then the hash table data (*hashdata*) into the record array (*model*). Three modules: *SEARCH*, *VERIFY*, and *RECONSTRUCT* are involved in this program.

1. **SEARCH Module**

Given a particular test triplet record from the input file (*candidatedata*), the Affine coefficient pair \((\xi_i, \eta_i)\) and *inkey* are used to perform the access and comparison of the Hash table. That is

\[
\text{hashkey} = \text{inkey} \mod \text{tablesize}
\]  

Using the calculated *hashkey*, a certain entry of the created Hash table is accessed. If there is a match, i.e., a hit occurred in the Hash table, the corresponding 2-dimensional array \(\text{vote(modelid, tripletid)}\) shown in Table 4 with the same \((\text{modelid, tripletid})\) pair is incremented by one. At the same time, the accessed entry of the Hash table is moved to a temporary table. The data format of the *temporary* table is shown in Table 6. This table is needed later to reconstruct the model outline in the test object for graphic presentation. This entire procedure is executed iteratively until all of the interesting points of the test object based on the same test triplet are exhausted.
2. VERIFY Module

This module examines the 2-D array \( \text{vote}(\text{modelid}, \text{tripletid}) \) to select all the model triplets whose accumulated votes are all greater than a given threshold value. Based on the position \((\text{modelid}, \text{tripletid})\) of those that are greater than the threshold value, the model triplets are selected as the one most possibly corresponding to the test object's triplet.

**Table 6. TEMPORARY TABLE DATA FORMAT.**

<table>
<thead>
<tr>
<th>hashkey</th>
<th>inkey</th>
<th>model id</th>
<th>triplet id</th>
<th>key 1</th>
<th>key 2</th>
<th>accessed model triplet</th>
</tr>
</thead>
<tbody>
<tr>
<td>temp1</td>
<td>24</td>
<td>-20000000</td>
<td>1</td>
<td>1</td>
<td>-1</td>
<td>-1</td>
</tr>
<tr>
<td>temp2</td>
<td>72</td>
<td>0</td>
<td>1</td>
<td>1</td>
<td>-1</td>
<td>-1</td>
</tr>
<tr>
<td>......</td>
<td>......</td>
<td>......</td>
<td>......</td>
<td>......</td>
<td>......</td>
<td>......</td>
</tr>
<tr>
<td>temp i</td>
<td>i</td>
<td>10000000</td>
<td>2</td>
<td>1</td>
<td>1.5</td>
<td>-0.5</td>
</tr>
</tbody>
</table>

"i" is the number of the number of the test triplet.

With the selected model triplets, control goes back to the temporary table to collect all those Affine coefficient pairs \((\xi_i, \eta_i)\) for the selected model triplets. Comparison between the \((\text{modelid}, \text{tripletid})\) in the temporary table and the selected \((\text{modelid}, \text{tripletid})\) are necessary in this process.

3. RECONSTRUCT Module

The main purpose of this module is to reconstruct the model outline in the test object and check the squared error and for graphics presentation. Based on the selected model triplets and the collected Affine coefficient pair \((\xi_i, \eta_i)\) from the VERIFY module, an inverse Affine transformation is performed.
to calculate the sets of model coordinates in the model space. With the interesting point data file of the model the order of these points can be established. With the same \((\xi_i, \eta_i)\) and the test triplet, the corresponding interesting points in the test space can be found according to the established order. The square error between each set of the model coordinates and the corresponding interesting points in the test space is measured. If the calculated square error is minimum and it is less than a given threshold, the optimum model triplet can then be determined. Based on the optimum model triplet, the graphics presentation of the model can be displayed in the test scene. In order to recognize all the possible models existing in the test object, after one model is recognized successfully, control goes back to the SEARCH module to find another peak in the array which has a different modelid and the rest of the procedure is repeated. If none of the calculated square error satisfies the given threshold, control goes back to the VERIFY module to use the second test triplet and repeat the procedure.
IV. RESULTS AND PERFORMANCE

A. EXPERIMENT RESULTS

The Affine invariant matching technique via hashing has demonstrated its characteristics of object recognition in several experiments. To concentrate the effort on the study of the Affine invariant technique and the implementation of the technique in software, the model data and test data were artificially created in the experiment. Two different models shown in Figure 10 were stored in the data-base after preprocessing phase.

1. Test For Similarity Transformation

The first unknown test object is fed into the system. The test object and the recognized model are shown in Figure 11. This is a case of recognizing objects under similarity transformations, i.e., rotation, translation and scaling.

The Affine invariant matching is obviously successful in detecting objects under a similarity transformation. Similarity transformation is a special case of a general Affine transformation. The key observation here is that since the similarity transformation is orthogonal, two points are enough to form a basis which spans the 2-D plane. A similarity transformation occurs in the situation when the
Figure 10. Two Different Models in the Data-Base.

Figure 11. Similarity Transformation Case and Recognized Model.

viewing angle of the camera is the same as that of the model. Such a condition usually occurs, for example, in a factory environment where the viewing angle of the camera is kept constant. Consequently, this algorithm can be directly applied to industrial machine vision.
2. Test For Partial Matching

To test the situation where model can be identified partially, a test object of a composite overlapping scene in Figure 12 of the two different models from the database is used. The recognition results are shown on the right hand side of Figure 12.

Figure 12. Composite Overlapping Test Objects Scene and Recognized Model.

Note that the hidden model's interesting point can still be reconstructed due to the partial matching characteristic of the algorithm. In other words, the hidden local feature such as the basis-triplet in our system can be recovered or assisted by the rest of the basis-triplets during the recognition phase.
3. When Numerical Error is Present in the Test Object

If the coordinates of \(c\) and \(d\) are very close to each other as shown in Figure 13, \(c\) and \(d\) cannot be part of the qualified triplets. The collinearity check module will discriminate these cases.

\[
|c-d| < |b-c| \\
\text{OR} \\
|c-d| < |b-d| 
\]

Figure 13. Interesting Point Too Close Case.

If the difference of \(c\) and \(d\) is significant, the triplet with \(c\) and \(d\) may result. A model triplet like this may get a number of votes, which on one hand, are not enough to accept it as a "selected" model triplet, but, on the other hand, do not justify total rejection. It is possible to change this model triplet to another model triplet consisting of points that are more distant from each other than those of the previous model triplet points. Even if a model triplet belonging to some model did not get enough votes due to noisy data, it is still possible to recover this model from another model triplet.
B. ALGORITHM PERFORMANCE AND COMPLEXITY

The performance is highly dependent on the number of interesting points $m$ existing in the test scene. This is true as the data-base model is changed to that shown in Figure 14. The test object scene is shown in the left part of Figure 15 and the recognized model scene is shown on the right part of Figure 15.

![MODEL #1](image)

Figure 14. Changed Data-Base Model.

In this case the cpu time for recognition is increased tremendously. The total number of computation steps for $m$ interesting points in Affine invariant matching is proportional to $m^4$ for the worst case. The Hash table size of order $m^4$ was obtained from

$$m \times \binom{m}{3} \times P_3^3 = 6 \times m \times (m - 1)(m - 2)(m - 3) \approx m^4 \quad (27)$$
where \( \binom{n}{3} \) is the number of different combinations of the Affine basis, and \( \pi^3 \) is the number of permutations of three arbitrary non-collinear points. When the number of interesting points of the models is small, the matching algorithm will be much faster. The computation for Hash table setup in the encoding procedure is usually done off line. If there are \( k \) model points in a test scene of \( m \) points, then the probability of not choosing a model triplet in \( t \) trials is approximately

\[
P = [1 - \frac{k^3}{m^3}]^t
\]  

(28)

where 3 relates to three non-collinear points. Hence, for a given \( \epsilon > 0 \), if we let the probability of missing the correct triplet \( P \) be less than \( \epsilon \), the number of the trials \( t \) is

\[
log \epsilon \geq logP = log[1 - \frac{k^3}{m^3}]
\]  

(29)
that is,

\[ t \leq \frac{\log \epsilon}{\log(1 - \left(\frac{k}{m}\right)^3)} \]  

(30)

In the algorithm, the procedure of recognition repeats itself for each of the selected triplets. The above inequality describes the worst case number of trials before the matching is successful. If one wants the probability of missing the correct triplet to be small, one has to do more triplet selection. Finding the interesting points is also computationally expensive. For example, the outline of a test object is obtained by chain-code in this system. The big curvature change in the linked chain is selected as an interesting point. This choice is pattern dependent. A polyhedral object in the scene naturally suggests the use of polyhedral vertices, deep concavities, and zero curvature points. Sometimes, interesting points do not have to appear physically in the image. For example, an interesting point may be taken as the intersection of two nonparallel lines that do not touch in the test object. Reducing the computation complexity can be achieved by representing a line by only one pair of interesting points if there are some other interesting points on this line. This can help by reducing the order of magnitude \( n \) in the computation. In general, Affine invariant matching is a highly parallel operation. The input test
object can be compared against all the models in the Hash table simultaneously.

C. LIMITATIONS

1. Model Representation

The major limitation of a model based vision system is the low dimensionality in spatial representation or description of models or test objects. This restricts the system's functionality to a limited class of objects observed from a few fixed viewpoints. The system developed here cannot be applied to patterns with both convex and non-convex curves. However, the algorithm still can be performed in these cases by using the footprint method suggested by R. Hummel and H. Wolfson [Ref. 1]. The following description is quoted from that paper.

The footprint is a numerical Affine invariant shape characteristic that is a representation of the concavity shape. To compute the footprint, we first normalize a concavity by applying the transformation which maps its triplet basis to a standard equilateral triangle. That is, the concavity endpoints are mapped to (-1,0)(1,0), and the third point to (0,30.5). To each such normalized shape we assign a vector of numbers that we call the 'footprint.' One of the footprint schemes that we can use is illustrated in Figure 16.

For some constant s (say 5 ≤ s ≤ 10), we divide the upper half plane by s + 1 rays based at the origin, with angle π/s between two consecutive rays i and i + 1. The footprint will be s-vector \((a_1,a_2,...,a_s)\), where each component is quantized into one of a number of discrete bins.

We now proceed as before to construct a hash table. Each footprint is used as an entry to the hash table, where the model and concavity numbers are recorded. In the recognition phase, each concavity is used to compute a footprint, and the appropriate entry in the hash table is
accessed. For each pair, \((\text{model, concavity})\), appearing in the hash table as the location, we compute the appropriate Affine transformation to the associated model, and attempt to verify an instance of the model in the image.

Basically the same method for handling polygon shapes can be extended to concave shapes.

2. Quantization Problem in Generation of the Hash Key

To convert the Affine coefficient pair to \(\text{inkey}\), we multiply each of the Affine coefficient pair \((\xi, \eta)\) by a large constant and sum them up. This conversion causes most of the \(\text{inkeys}\) to be equal. Therefore, the generated \(\text{hashkeys}\) are not distributed uniformly. These collisions result in a long bucket list. Such a long bucket list is the main disadvantage of the present implementation since it slows down the hash table search speed.

3. Noise Handling

The searching in this implementation is sensitive to the noise. With noisy interesting points the test triplet will lead to the situation where the Affine coefficient pair does not hit the Hash table due to the noise. This is one of the weaknesses of this implementation. However further work
can be done to improve the solution as suggested in Wolfson's paper. [Ref. 1] The following paragraph is adopted from that paper.

An Affine transformation in the plane is uniquely defined by the transformation of three non-collinear points. However, in practical applications this transformation may be somewhat distorted, because of noisy computation of these three points. Knowledge of additional points, which were transformed to each other may help to improve the accuracy of the computed transformation. The incorporating of the Mean Square Error match seems to be one of the solutions. Specifically, assume that we are looking for an Affine match between the sequences of the planar points $u_i$ and $v_i$ where $i = 1, 2, \ldots, n$. By using the MSE method, we could find the optimal Affine match $T$ which will minimize the square of the distance between the sequence $Tu_i$ and $v_i$ where $i = 1, 2, \ldots, n$.

D. IMPRESSIONS OF THE ALGORITHM FEATURE

1. Two Phase Algorithm

A key feature of this algorithm is the division of Modeling (Encoding) and Recognition (Matching) procedures. The modeling is performed off-line. This enables the speed of an on-line recognition procedure to be optimized.

2. Hash Implementation

The method described here differs from other existing model-based matching systems. This method uses hashing technique to search for the Affine coefficient. The speed of on-line recognition depends on the size of the interesting points of the test object. The amount of on-line processing does not depend too much on the total number of models.
existing in the Hash table. In other words, the recognition time is independent of the number of different models in the data-base. This advantage makes the method uniquely attractive as compared to others.
V. CONCLUSION

A. SUMMARY

This thesis begins with a survey of various model-based vision systems. Different feature extraction methods and matching techniques are also discussed. To achieve not only the ability to recognize partial occluded test objects but also to have high processing speed, the Affine invariant transformation technique is preferred. The Affine invariant matching was studied by R. Hummel and H. Wolfson. [Ref. 1] The Affine invariant matching was proposed to provide a high speed and the effective matching technique.

Motivated by this voting match technique, the main objective of this thesis was to develop a local system that can accept an incoming scene and decide where known models exist in it. Affine invariant matching handles the modeling and matching procedures independently. The use of a Hash table indexed by possible Affine coefficient pairs allows for fast content dependent matching. The program developed here is in principle similar to that in Reference 1. Some unique features of this algorithm can be listed as follows.

- Encoding and Recognition procedures are separated.
- Matching can detect objects under Affine transformation.
• Partial matching helps to detect occluded objects.
• The Hashing technique allows us to do content dependent matching efficiently.
• Many operations in the algorithm can be performed simultaneously with parallel processing.

B. EXPERIENCE GAINED

The experience gained in this study can be summarized as follows.

1. Affine Invariant

This is the characteristic of Affine invariant matching. In experiments, the algorithm can detect objects under similarity transformations. The models existing in the scene, can experience translation, rotation, or scaling to some arbitrary degree. The algorithm is able to recognize the existing models.

2. Partial Matching

The triplets used in this algorithm are essential local features. In a composite test scene objects can be recognized in the presence of occlusion due to the hidden interesting points without any problem.

3. Speed and Complexity

The computational complexity of this system is highly dependent on the number of interesting points used after the preprocessing phase. The complexity of this algorithm grows as $m^4$, where $m$ is the number of interesting points. However,
if effective classification of composite local features exists, then it can be incorporated in the Encoding procedure to improve the system performance.

4. Noise Perturbation

The established system is very rigid in calculating the hashkey in the Recognition procedure. If part of the interesting points in the scene are affected by noise, the calculated Affine coefficient pairs based on those affected points will not contribute to the evidence accumulation of the model triplet. This means that the present implementation is still noise sensitive. However if the number of the unaffected interesting points is in the majority, contribution to the voting from other unaffected points still allows recognition of the test object.

C. RECOMMENDATIONS

The main weakness in the present implementation exists in the data structure and the decision-making technique.

- The data structure used in the system is not efficiently utilized due to the redundancy of the record fields of the data file, such as the two dimensional vote array. This is a physical size problem. If there are more than 14 interesting points in the scene, the system implemented here cannot handle them. If more memory is available recompilation of the source code will reduce the limitation.

- On the VERIFY module, the decision-making technique used is not yet mature. The present method just considers the corresponding edge distance between the model and the recognized model. If there are scaled or enlarged models in the test scene, the threshold used in decision-making needs to be changed from one scaled or enlarged model to
another. This needs improvement to obtain a flexible decision-making strategy.

Beside these two problems, possible subjects for future study related to Affine invariant matching could be:

- Find a more effective local feature classification technique in model representation. This can help to reduce the Hash table size and reduce the computation complexity.

- Use the mean square error method to achieve better noise immunity for the Hash table access in the recognition phase.

- Extend Affine invariant matching to handle 3-D object recognition.

- Find some parallel hardware implementation such as Content Addressable Memory (CAM) or others to achieve parallel searching or matching of a test object against various model points.
APPENDIX A

PASCAL-LIKE PSEUDO CODES

This appendix contains those Pascal-like pseudo codes used in the established system. Explanation of each of the modules is discussed in Chapter III.

program affine(interestingdata,hashkeydata)
(* affine finds the affine coefficient pairs *)
(* the input is interesting data file
the output is hashkey data file *)

procedure matrix mult(inverse matrix : array;
var difference,coord :array);
begin
  for i := 1 to 2 do
  for j := 1 to 2 do
    coord[i,j] := coord[i,j] + inverse_matrix[i,n] *
    difference[n,j];
end;

procedure inverse(base matrix : array;
var inverse_matrix :array);
begin
  for i := 1 to 2 do
  for j := 1 to 2 do
    determinent := det (base_matrix[i,j]);
    inverse_matrix[i,j] := (-1`**)^(i+j) * base_matrix[i,j]
    / determinent;
end;

procedure calculate_coord(basex,basey : array);
begin
  for i := 1 to 2 do
    begin
      base_matrix[i,j] := basex[i] - basex[i+1];
      base_matrix[i,j] := basey[i] - basey[i+1];
    end;
  inverse(base_matrix, inverse_matrix);
  difference[i,j] := restbase[i] - base[3];
  matrix_mult(inverse_matrix, difference,coord);
end;

procedure perm(basex,basey :array;
  k : integer);
begin
  if k = 3 then calculate_coord(basex,basey);
  else
    for i := k to 3 do
      begin
        tx := basex[i];
        ty := basey[i];
        basex[i] := basex[k];
        basey[i] := basey[k];
        basex[k] := tx;
        basey[k] := ty;
        perm(basex,basey,k+1);
      end;
  end;
end;

procedure collinear(combinationx,combinationy : array);
begin
  t1 := arctan((combinationx[3]-combinationx[2]) /
                 (combinationx[2]-combinationx[1]))
  t2 := arctan((combinationy[3]-combinationy[2]) /
                 (combinationy[2]-combinationy[1]))
  if t1 = t2 then collinear := true;
  else perm(basex,basey,1)
end;

procedure combination(k,index : integer);
begin
  if index > 3 then collinear(comx,comy)
  else
    for i := k to interestingno do
      begin
        comx[index] := x[i];
        comy[index] := y[i];
        combination(i+1,index+1);
      end;
  end;

(* main affine *)
begin
  while not eof(interestingdata) do
    begin
      readln(interestingdata,x[i],y[i]);
      combination(1,1);
    end;
end;

****************************

program hash(hashkeydata,hashdata);
(* hash generates the hash table *)
procedure initialize;
var i : integer;
begnin
    for i := 1 to tablesiz
do
        model[i].hashkey := empty;
        model[i].link := empty;
end;

procedure hashing(var hashkey : integer; inkey : integer);
const   multiplier = 100000;
begin
    inkey := (key1 + key2) * multiplier;
    hashkey := (inkey mod tablesiz);
    if model.hashkey <> empty then
        insert(hashkey)
    else
        collision(hashkey);
end;

procedure collision(hashkey : integer);
var bucket_length : integer;
begnin
    bucket_length := 0;
    while model[hashkey].link <> empty do
        begin
            hashkey := model[hashkey].link;
            bucket_length := bucket_length + 1;
        end;
        insert(model[hashkey]);
    model[hashkey].link := bucket_length;
end;

(* main hash)
begin
    while not eof(hashkeydata) do
        begin
            readln(hashkeydata,model.inkey,model.key1,model.key2);
            initialize;
            hashing(1,model.inkey);
        end.

program tally(interestingdata,cadidatedata,hashdata,plotingdata);

(* tally generates the recognized model interesting data point
  in the test object space *)

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(* the input data files are
  interestingdata: the original information of the model,
  candidatedata: the test triplet, and
  hashdata: the Hash table

the output data file is
  plotingdata *)

procedure search(modelno: integer);
begin
  while (model.modelid = modelno) and (modelno <= total_modelno) do
    begin
      for i := 1 to test_interestingno do
        begin
          cand[i].hashkey := cand[i].inkey MOD tablesize;
          if (cand[i].hashkey = model.hashkey) then
            begin
              vote(modelid, tripletid) := vote(modelid, tripletid) + 1;
              temporary := model;
              (* Temporary is used to collect the accessed entry*)
              temporary_table_size := temporary_table_size + 1;
              end;
            end;
        end;
    verify(l);
  end;
end;

procedure verify(tripletid);
begin
  for i := 1 to temporary_table_size do
    begin
      if (screen_threshold < vote(modelid, tripletid) then
        begin
          selected_tripletid := tripletid;
          number_selected := number_selected + 1;
        end
      else
        begin
          successful := false;
        end;
    (* control goes back to main program for the 2nd test triplet *)
  end;
if (selected.modelid = temporary.modelid) and
  (selected.tripletid = temporary.tripletid) then
begin
  collected.key1 := temporary[tripletid].key1;
  collected.key2 := temporary[tripletid].key2;
  reconstruct(number_selected, collected.key1, collected.key2,
procedure reconstruct(number_selected : integer;
   key1,key2 : real;
   selected_model_triplet,test_triplet : array);
begin
(* perform the Affine transformation on the
   selected_model_triplet
   and the test_triplet respectively to obtain the model interesting
   points and the interesting points exit in the test object *)

for k := 1 to number_selected do
begin
   for i := 1 to interestingpoint do
      (x[i],y[i]) := affine (key1,key2,selected_model_triplet);
   for j := 1 to interestingpoint do
      (x[j],y[j]) := affine (key1,key2,test_triplet);
(* find the order corresponding relationship between (x[i],y[i])
   and (x[j],y[j]) to obtain ordered(x[i],y[i]) *)
(* perform the square error between the ordered(x[i],y[i])
   and the test object interesting coordinate *)

   if (model_triplet[k].square_error < square_error_threshold)
   and (model_triplet[k].square_error <= minimum_square_error)
then
   begin
      optimum_triplet := k;
      minimum_square_error := model_triplet[k].square_error;
   end
else
   begin
      verify(tripletid);
   end;
   display(optimum_model_triplet);
(* the control goes back to the search for the rest of models *)

   end;
end;

(* main tally *)
begin
  readln (interestingdata, total_modelno, interestingno);
  while not eof(hashdata) do
    readln (hashdata, model.hashkey, model.inkey, model.key1, model.key2,
            model.modelid, model.tripletid, model_triplet);
  while not eof(candidatedata) do
    begin
      readln (candidatedata, cand.inkey, cand.key1, cand.key2, test_triplet);
      search(1);
    end;
end.

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Figure A-1. Recognition Procedure Data Flowchart.

1. **Candidate Test Data**
   - Key 1, Key 2
   - Test Triplet

2. **Search**
   - (Key 1, Key 2)

3. **Temporary**
   - Key 1, Key 2
   - Model ID
   - Triplet ID
   - Accessed Entry
     - (Key 1, Key 2)
   - Collect all (Key 1, Key 2) from selected maximum model triplet

4. **Hash Table**
   - Key 1, Key 2
   - Model ID
   - Triplet ID
   - Model Triplet Base X Base Y

5. **Ordered Model Interesting Points Data**
   - Increment Vote Array
     - (Model ID, Triplet ID)
   - Vote (Model ID, Triplet ID)
   - Select Qualified Vote
     - Model Triplet

6. **Model Interesting Point (x, y)**
   - Collected (Key 1, Key 2) and Model Triplet
   - Affine Transformation
   - Reconstructed Interesting Point (x_i, y_i)
   - Model Ordered Interesting Point (x_i, y_i)

7. **Reconstructed Ordered Interesting Point (x_j, y_j)**
APPENDIX B

LISTING OF SOURCE CODES

program gen(interesting);
type ary = array [1..2,1..50] of integer;
var i,j,modelno,interestingno : integer;
    interesting : text;
    x,y : ary;
begin
    open(interesting,'interesting.dat',history := new);
    rewrite(interesting);

        {**************model 1 **************}
        modelno := 1; interestingno := 7;
        x[1,1] := 20; x[1,2] := 30; x[1,3] := 40; x[1,4] := 50;
        x[1,5] := 40; x[1,6] := 30; x[1,7] := 30;
        y[1,1] := 30; y[1,2] := 40; y[1,3] := 30; y[1,4] := 20;
        y[1,5] := 10; y[1,6] := 10; y[1,7] := 20;
        writeln(interesting,modelno,interestingno);
        for i := 1 to interestingno do
            writeln(interesting,x[1,i],y[1,i]);

        {**************model 2 **************}
        modelno := 2; interestingno := 5;
        x[2,5] := 30;
        y[2,5] := 35;
        writeln(interesting,modelno,interestingno);
        for i := 1 to interestingno do
            writeln(interesting,x[2,i],y[2,i]);

close(interesting);
end.

program preproc(interesting,coordinate);
const total = 9999;{user supply}
type ary = array [1..total] of integer;
    aryl = array [1..2,1..2] of real;
    ary2 = array [1..3] of integer;
    ary3 = array [1..2,1..1] of real;
    ary4 = array [1..2,1..2] of integer;
var count,i,j,k,index : integer;
    outmodelno,outinterestingno : array [1..10] of integer;
    modelno,tripletno,interestingno,table_size : integer;
    x,y,rest_basex,rest_basey : ary;
    inverse_matrix : aryl;
    basex,basey,comx,comy : ary2;

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diff, coord : ary3;
base_matrix : ary4;
interesting, coordinate : text;

procedure matrix_mult(inverse_matrix : ary1;
var diff, coord : ary3);

const k = 2;
  l = 2;
  m = 1;
var i, il, n : integer;
begin
  for i := 1 to l do
    for il := 1 to m do
      coord[i, il] := 0;
  for i := 1 to l do
    for il := 1 to m do
      for n := 1 to 1 do
        coord[i, il] := coord[i, il] + inverse_matrix[i, n] * diff[n, il];
end;

procedure inverse(base_matrix : ary4;
var inverse_matrix : ary1);
var det real;
begin
  for i := 1 to 2 do
    det := (base_matrix[1, 1] * base_matrix[2, 2]) -
          (base_matrix[1, 2] * base_matrix[2, 1]);
  inverse_matrix[1, 2] := base_matrix[1, 2] * (-1) / det;
end;

procedure calculate_coord(basex, basey : ary2);
var i, m, il, i2, i3 : integer;
begin
  for i := 1 to 2 do
    begin
      base_matrix[1, i] := basex[i] - basex[i + 1];
      base_matrix[2, i] := basey[i] - basey[i + 1];
    end;
  inverse(base_matrix, inverse_matrix);
  i2 := 1;
  for i := 1 to interesting no do
    begin
      if ((basex[1] <> x[i]) or (basey[1] <> y[i])) and
       ((basex[2] <> x[i]) or (basey[2] <> y[i])) and
((basex[3] <> x[i]) or (basey[3] <> y[i])) then
begin
  rest_basex[i2] := x[i];
  rest_basey[i2] := y[i];
  i2 := i2 + 1;
end;
end;
for i := 1 to (interestingno-3) do
begin
  diff[1,1] := rest_basex[i] - basex[3];
  diff[2,1] := rest_basey[i] - basey[3];
  matrix_mult(inverse_matrix,diff,coord);
  count := count +1;
  i3 := count mod (interestingno-3);
  if i3 = 1 then tripletno := tripletno + 1;
  write(coordinate,modelno,tripletno,coord[1,1],coord[2,1]);
  for i1 := 1 to 3 do
    write(coordinate,basex[i1],basey[i1]);
  writeln(coordinate);
end;
end;
procedure perm(basex,basey : ary2;
  k : integer);
var i,tx,ty : integer;
begin
  if k = 3 then
    calculate_coord(basex, basey)
  else
    for i := k to 3 do
    begin
      tx := basex[i];
      ty := basey[i];
      basex[i] := basex[k];
      basey[i] := basey[k];
      basex[k] := tx;
      basey[k] := ty;
      perm(basex,basey,k+1);
    end;
end;
procedure colinear(comx,comy ary2);
var colinearx1,colinearx2 ,colinearyl,colineary2 integer;
t1,t2 : real;
begin
  colinearx1 := comx[2] - comx[1];
  colinearyl := comy[2] - comy[1];
  if (colinearx1 <> 0) then
    t1 := arctan(colinearyl / colinearx1)
else \( t_1 := 1.5707; \)
if (colinear\( x_2 \) \# 0) then
  \( t_2 := \arctan(\text{colinear}y_2 / \text{colinear}x_2) \)
else \( t_2 := 1.5707; \)
  if \( t_1 \) \# \( t_2 \) then \( \text{perm} \)(\( \text{com} \),\( \text{com}y \),1)
end;

procedure \( \text{comb} \)(k,index : integer);{use the recursive}
var i : integer;
beg
  if index > 3 then \( \text{colinear} \)(\( \text{com} \),\( \text{com}y \))
  else
    for i := k to interestingno do
      \( \text{com}x[i] := x[i] \)
      \( \text{com}y[i] := y[i] \)
      \( \text{comb} \)(i+1,index+1)
  end;
end;

begin(main)
  open(interesting, 'interesting.dat',history := old);
  reset(interesting);
  open(coordinate, 'coordinate.dat',history := new);
  rewrite(coordinate);
  table-size := 0;j:= 1;
  while not eof(interesting) do
    begin
      readln(interesting,outmodelno[j],outinterestingno[j]);
      modelno := outmodelno[j];
      interestingno := outinterestingno[j];
      for i := 1 to interestingno do
        readln(interesting,x[i],y[i]);
        count :=0;tripletno := 0;j := j+1;
        \( \text{comb} \)(1,1);
        table-size := table-size + count;
      end;
      writeln(coordinate,table-size,outmodelno[1],outinterestingno[1],
      outmodelno[2],outinterestingno[2]);
      close(interesting);
      close(coordinate);
    end.

*****************************************************************************

program keycon(infile,outfile);
type
  inrec = record
    modelno,tripletno : integer;
  end;

key1,key2 : real;
base1,basey1,base2,basey2,base3,basey3 : integer
end;
outrec = record
    outkey : integer;
    base1,basey1,base2,basey2,base3,basey3 : integer
end;
ary1 = array [0..99999] of integer;

var
    a : array[0..99999] of outrec;
b : inrec;
infile,outfile : text;
temp : real;
i,j,jl : integer;
outmodelno,outinterestingno : array [1..50] of integer;
table_size,ary : ary1;

procedure prime(var primeno : integer);
var
    is : boolean;
i,j,k,c : integer;
begin
    ary[1] := 2;
c:= 1;
for i := 3 to primeno do
begin
    j := 1;
is := false;
repeat
    if (i mod ary[j]) =0 then
    is := true;
j:= j+1;
until (ary[j] = 0) or (ary[j] > sqrt(i)) or is;
if not is then
begin
    c := c+1;
    ary[c] :=i;
end;
end;
is:=false;
while not is do
begin
    for k := 1 to j do
    if(primeno mod ary[k]) = 0 then
    is := true;
    primeno := primeno+1;
end;
end;

begin
    open (infile,'coordinate.dat',history:=old);
    reset(infile);
end;
open (outfile, 'hash_key.dat', history:=new);
rewrite(outfile);
  j := 0;
  while not eof(infile) do
    begin
      readln(infile, table_size[j]);
      j := j + 1;
    end;
  close(infile);

open (infile, 'coordinate.dat', history:=old);
reset(infile);
  j1 := 1;
  while not eof(infile) do
    begin
      if j1 = table_size[j-1]+1 then
        begin
          readln(infile, table_size[j-1], outmodelno[1], outinterestingno[1],
                 outmodelno[2], outinterestingno[2]);
        end
      else
        readln(infile);
      j1 := j1 + 1;
    end;
  prime(table_size[j-1]);
  write(outfile, table_size[j-1]);
  write(outfile, outmodelno[1], outinterestingno[1],
        outmodelno[2], outinterestingno[2]);
  writeln(outfile);
  close(infile);

open (infile, 'coordinate.dat', history:=old);
reset(infile);
  i := 0;
  while i <> j-1 do
    with b do
      begin
        readln(infile, modelno, tripletno, key1, key2,
               base1, basey1, base2, basey2, base3, basey3);
        temp := (key1+key2)*10000000;
        a[i].outkey := trunc (temp);
        writeln(outfile, a[i].outkey, modelno, tripletno, key1, key2, base1, basey1, base2, basey2, base3, basey3);
        i := i + 1
      end;
  close(infile);
close(outfile);
end.
program hashing(input, output);
const database_modelno = 2;
type
  rec = record
    inkey, modelno, tripletno, link : integer;
    key1, key2 : real;
    basexl, baseyl, basex2, basey2, basex3, basey3 : integer;
  end;
  outrec = record
    hashkey, inkey, modelno, tripletno, link : integer;
    key1, key2 : real;
    basexl, baseyl, basex2, basey2, basex3, basey3 : integer;
  end;
var a : array[0..99999] of outrec;
b: rec;
i, j, k, table_size : integer;
outmodelno, outinterestingno : array [1..database_modelno] of integer;

procedure print;
var ii : integer;
begin
  for ii := 0 to table_size do
  begin
    if a[ii].hashkey <> -1 then
      with a[ii] do
        writeln(output, hashkey, inkey, modelno:2, tripletno:4,
        key1, key2, basexl:4, baseyl:4, basex2:4, basey2:4,
        basex3:4, basey3:4, link)
  end;
end;

procedure solve_collision(var i, j : integer);
{if the hash key is same then find the last same hash key of the linked chain thru the link}
begin
  while a[i].link <> -1 do
  begin
    i := a[i].link
  end;
  {test the last hash key of the linked chain if its next position points to the free entry, till find the free space}
i : means the previous linked same hash key
j : means the one which is free entry, it also link to previous same key)

j := i;
while a[j].hashkey <> -1 do
begin
    j := j+1;
    if j > table_size then j := 0
end;(while)
end;

procedure initialize;
var i1,i2 : integer;
begin
    for i1 := 0 to table_size do
        with a[i1] do
            a[i1].hashkey :=-1;
    for i2 := 0 to table_size do
        with a[i2] do
            a[i2].link :=-1;
end;

procedure insert(var i,j:integer);
begin
    if (a[i].hashkey = -1) then
    begin
        a[i].hashkey :=i;
        a[i].inkey := b.inkey;
        a[i].modelno := b.modelno;
        a[i].tripletno := b.tripletno;
        a[i].key1 := b.key1;
        a[i].key2 := b.key2;
        a[i].baseX1 := b.baseX1;
        a[i].baseY1 := b.baseY1;
        a[i].baseX2 := b.baseX2;
        a[i].baseY2 := b.baseY2;
        a[i].baseX3 := b.baseX3;
        a[i].baseY3 := b.baseY3;
    end
    else
    begin
        solve_collision(i,j);
        if (a[i].modelno <> a[j].modelno) and
            (a[i].tripletno <> a[j].tripletno) then
        begin
            a[i].link := j;
            a[j].hashkey := j;
            a[j].inkey := b.inkey;
            a[j].modelno := b.modelno;
            a[j].tripletno := b.tripletno;
            a[j].key1 := b.key1;
        end
    end
end;
a[j].key2 := b.key2;
a[j].basexl := b.basexl;
a[j].baseyl := b.baseyl;
a[j].basex2 := b.basex2;
a[j].basey2 := b.basey2;
a[j].basex3 := b.basex3;
a[j].basey3 := b.basey3;
end
end
end;

begin (* main *)
  open (input,'hash_key.dat',history := old);
  reset(input);
  open (output,'hash.dat',history := new);
  rewrite(output);
  writeln(output,'table size',outmodelno[1], outinterestingno[1],
         outmodelno[2], outinterestingno[2]);
  writeln(output,'table size',outmodelno[1], outinterestingno[1],
         outmodelno[2], outinterestingno[2]);
  initialize;
i := 0; j := 0;
while not eof(input) do
  begin
    with b do
    begin
      read(input, inkey);
      read(input, inumodelno, tripletno, key1, key2, 
        basexl, baseyl, basex2, basey2, basex3, basey3);
      readln;
i := b.inkey mod table_size;
      insert(i,j);
    end
  end (*while*);
  print;
close(input);
close(output)
end.

******************************************************

program test_gen(interesting);
type ary = array [1..2,1..50] of integer;
var i,j,modelno,interestingno : integer;
  interesting : text;
  x,y : ary;
begin
  open(interesting,'tally_interesting.dat',history := new);
  rewrite(interesting);
  (**************************test object*************************)
modelno := 1; interestingno := 10;
x[1,1] := 50; x[1,2] := 40; x[1,3] := 30;
x[1,4] := 10; x[1,5] := 10;
x[1,6] := 20; x[1,7] := 30; x[1,8] := 30; x[1,9] := 40;
x[1,10] := 40;
y[1,1] := 10; y[1,2] := 0; y[1,3] := 10;
y[1,4] := 10; y[1,5] := 40;
y[1,6] := 40; y[1,7] := 50; y[1,8] := 30; y[1,9] := 30;
y[1,10] := 20;
writeln(interesting, modelno, interestingno);
for i := 1 to interestingno do
writeln(interesting, x[1,i], y[1,i]);

(*alternative data set*)

{ y[1,1] := 90; y[1,2] := 70; y[1,3] := 50; y[1,4] := 30;
y[1,5] := 40; y[1,6] := 30; y[1,7] := 50; y[1,8] := 70;
y[1,9] := 90; y[1,10] := 90; y[1,11] := 70; y[1,12] := 50;
y[1,13] := 70; y[1,14] := 90;
writeln(interesting, modelno, interestingno);
for i := 1 to 14 do
writeln(interesting, x[1,i], y[1,i]);
}
close(interesting);
end.

program test_preproc(interesting, coordinate);
const total = 9999; (user supply)
type ary = array [1..total] of integer;
ary1 = array [1..2,1..2] of real;
ary2 = array [1..3] of integer;
ary3 = array [1..2,1..1] of real;
ary4 = array [1..2,1..2] of integer;
var count, i, k, index : integer;
modelno, interestingno, table_size : integer;
x, y, rest_basex, rest_basey : ary;
inverse_matrix : ary1;
basex, basey, comx, comy : ary2;
diff, coord : ary3;
base_matrix : ary4;
interesting, coordinate : text;

procedure test_matrix_mult(inverse_matrix : ary1;
var diff, coord : ary3);
const k = 2;
var i, j, n : integer;
begin
for i := 1 to 1 do
for j := 1 to m do
  coord[i,j] := 0;
for i := 1 to l do
  for j := 1 to m do
    for n := 1 to l do
      coord[i,j] := coord[i,j] + inverse_matrix[i,n] * diff[n,j];
end;

procedure test_inverse(base_matrix : ary4;
  var inverse_matrix : ary1);
  var det : real;
begin
  for i := 1 to 2 do
    det := (base_matrix[1,1] * base_matrix[2,2]) -
    (base_matrix[1,2] * base_matrix[2,1]);
  inverse_matrix[1,1] := base_matrix[2,2]/det;
  inverse_matrix[1,2] := base_matrix[1,2] * (-1) /det;
end;

procedure test_calculate_coord(basex,basey : ary2);
  var i,j,i1,i2 : integer;
begin
  for i := 1 to 2 do
    begin
      base_matrix[1,i] := basex[i] - basex[i+1];
      base_matrix[2,i] := basey[i] - basey[i+1];
    end;
  test_inverse(base_matrix,inverse_matrix);
  i2 := 1;
  for i := 1 to interestingno do
    begin
      if ((basex[1] <> x[i]) or (basey[1] <> y[i])) and
          ((basex[2] <> x[i]) or (basey[2] <> y[i])) and
          ((basex[3] <> x[i]) or (basey[3] <> y[i])) then
        begin
          rest_basex[i2] := x[i];
          rest_basey[i2] := y[i];
          i2 := i2 +1;
        end;
    end;
  for i := 1 to interestingno-3 do
    begin
      diff[1,1] := rest_basex[i] - basex[3];
      diff[2,1] := rest_basey[i] - basey[3];
      test_matrix_mult(inverse_matrix,diff,coord);
count := count +1;
write(coordinate,modelno,count,coord[1,1],coord[2,1]);
for ii := 1 to 3 do
write(coordinate,basex[ii],basey[ii]);
writeln(coordinate);
end;

procedure test_perm(basex,basey : ary2;
    k : integer);
var i,tx,ty : integer;
begin
  if k = 3 then
    test_calculate_coord(basex,basey)
  else
    for i := k to 3 do
      begin
        tx := basex[i];
        ty := basey[i];
        basex[i] := basex[k];
        basey[i] := basey[k];
        basex[k] := tx;
        basey[k] := ty;
        test_perm(basex, basey, k+1);
      end;
end;

procedure test_colinear(comx,comy : ary2);
var colinearx1,colinearx2,colineary1,colineary2 : integer;
t1,t2 : real;
begin
  colinearx1 := comx[2] - comx[1];
  colineary1 := comy[2] - comy[1];
  if (colinearx1 <> 0) then
    t1 := arctan(colineary1 / colinearx1)
  else t1 := 1.5707;
  if (colinearx2 <> 0) then
    t2 := arctan(colineary2 / colinearx2)
  else t2 := 1.5707;
  if t1 <> t2 then test_perm(comx,comy,1);
end;

procedure comb(k,index : integer);{use the recursive}
var i : integer;
begin
  if index > 3 then test_colinear(comx,comy)
  else
    for i := k to interestingno do
      begin
      end;
comx[index] := x[i];
comy[index] := y[i];
comb(i+1,index+1);
end;
end;

begin(main)
open(interesting,'tally_interesting.dat',history := old);
reset(interesting);
open(coordinate,'tally_coordinate.dat',history := new);
rewrite(coordinate);
table_size := 0;
while not eof(interesting) do
begin
readln(interesting,modelno,interestingno);
writeln(coordinate,interestingno);
for i := 1 to interestingno do
readln(interesting,x[i],y[i]);
count := 0;
comb(1,1);
table_size := table_size + count;
end;
close(interesting);
close(coordinate);
end.

program test_keycon(infile,outfile);
type
inrec = record
modelno,tripletno : integer;
key1,key2 : real;
basex1,basey1,basex2,basey2,basex3,basey3 : integer
end;
outrec = record
outkey : integer;
basex1,basey1,basex2,basey2,basex3,basey3 : integer
end;
var
a : array[0..99999] of outrec;
b : inrec;
infile,outfile : text;
temp : real;
i,j,interestingno : integer;
table_size : array[0..99999] of integer;
begin
open (infile,'tally_coordinate.dat',history:=old);
reset(infile);
open (outfile,'tally.dat',history:=new);
rewrite(outfile);
\begin{verbatim}

j := 0;
i := 0;
readln(infile, interestingno);
writeln(outfile, interestingno);
while not eof(infile) do
  with b do
  begin
    readln(infile, modelno, tripletno, key1, key2,
    base1, basey1, base2, basey2, base3, basey3);
    temp := (key1 + key2) * 10000000;
a[i].outkey := trunc(temp);
    writeln(outfile, a[i].outkey, key1, key2,
    base1, basey1, base2, basey2, base3, basey3);
i := i + 1
  end;
end;
close(infile);
close(outfile);
end.

program tally(input, candfile, output);
const database modelno = 2;
type candrec = record
  inkey : integer;
  key1, key2 : real;
  base1, basey1, base2, basey2, base3, basey3 : integer;
end;
outrec = record
  hashkey, inkey : integer;
  key1, key2 : real;
  base1, basey1, base2, basey2, base3, basey3 : integer;
end;
modelrec = record
  hashkey, inkey, modelno, tripletno, link : integer;
  key1, key2 : real;
  base1, basey1, base2, basey2, base3, basey3 : integer;
end;
collected_modelrec = record
  hashkey, inkey, modelno, tripletno, link : integer;
  key1, key2 : real;
  base1, basey1, base2, basey2, base3, basey3 : integer;
votel : integer;
end;
var initialmodel, temporary_model, temp : array[0..9999] of modelrec;
  model : array [0..23000] of modelrec;
collected_model : array[1..9999] of collected_modelrec;
cand : array[0..19999] of candrec;
cand1 : array [1..9999, 1..2] of candrec;
i, j, j1, k1, key, m, index, count : integer;
\end{verbatim}
n, maximum1, maximum2 : integer;

table_size, interestingno, test_interestingno_3 : integer;
candfile : text;
vote : array[0..database_modelno, 0..27999] of integer;
outmodelno, outinterestingno : array [1..database_modelno] of integer;

procedure initialize1;
var i, j : integer;
begin
  for i := 0 to database_modelno do
    for j := 0 to table_size do
      vote[i, j] := 0;
end;

procedure initialize2;
var i : integer;
begin
  for i := 0 to table_size do
    with model[i] do
      hashkey := -1;
end;

procedure initialize3(m : integer);
var i : integer;
begin
  for i := 1 to m do
    with temporary_model[i] do
      temporary_model[i] := initimodel[i];
end;

procedure print_model_triplet(i : integer);
(* store the information of the selected triplet *)
begin
  with collected_model[i] do
    writeln(output, hashkey, inkey, modelno:2, tripletno:4,
      key1, key2, base1x:4, base1y:4, base2x:4, base2y:4,
      base3x:4, base3y:4, vote1);
end;

procedure print_test_triplet(i, k : integer);
(* store the information of the test triplet *)
(* i is the corresponding between select model triplet and test triplet *)
begin
  with cand1[i, k] do

procedure all_maximun_selected(n : integer);

(* store all the selected model triplets even from different model *)

var i,j,cout : integer;
begin
for i := 1 to n do
begin
with collected_model[i] do
if ((modelno = 1) and (votel = maximun1))
or
((modelno = 2) and (votel = maximun2))
then
begin
print_model_triplet(i);
print_test_triplet(i,1);
end;
end;
end;

procedure verify(j,j1,m : integer;var n : integer);

(* collect all the accessed model *)
(* n is index value of all selected model *)

var i,k,k1,l : integer;
begin
k1 := 1;
for i := 1 to m do
with temporary_model[i] do
if (modelno = temporary_model[j1].modelno) and
(tripletno = temporary_model[j1].tripletno) then
begin
collected_model[n].hashkey := temporary_model[i].hashkey;
collected_model[n].inkey := temporary_model[i].inkey;
collected_model[n].modelno := temporary_model[i].modelno;
collected_model[n].tripletno := temporary_model[i].tripletno;
collected_model[n].key1 := temporary_model[i].key1;
collected_model[n].key2 := temporary_model[i].key2;
collected_model[n].basexl := temporary_model[i].basexl;
collected_model[n].basey1 := temporary_model[i].basey1;
collected_model[n].basex2 := temporary_model[i].basex2;
collected_model[n].basey2 := temporary_model[i].basey2;
collected_model[n].basex3 := temporary_model[i].basex3;
collected_model[n].basey3 := temporary_model[i].basey3;
collected_model[n].votel :=
vote[temporary_model[i].modelno, temporary_model[i].
tripletno];
for k := (j - test_interestingno_3) to j-1 do
  if (cand[k].inkey = temporary_model[i].inkey) and
      (cand[k].key1 = temporary_model[i].key1) and
      (cand[k].key2 = temporary_model[i].key2) then
    begin
      cand1[n,1] := cand[k];
      k1 := k1 + 1;
      end;
  end;
n := n+1;
end;
initialize3(in);
end;

procedure find_maxunin(m,j :integer;var j1 : integer);
(* j1 is the selected model triplet index value *)
var i :integer;
maximun : integer;
begin
  maximun :=0;
  for i := 1 to m do
  begin
    if (vote[temporary_model[i].modelno,temporary_model[i].
    tripletno] > maximun) then
      begin
        j1 :=i;
        maximun :=
        vote[temporary_model[i].modelno,temporary_model[i].
        tripletno];
      end;
  end;
(* here the 1 and 2 as the all different models in database *)
(* each model has it's own maximun vote *)
  if (temporary_model[i].modelno = 1) and
      (maximun > maximun1)
  then maximun1 := maximun;
  if (temporary_model[i].modelno = 2) and
      (maximun > maximun2)
  then maximun2 := maximun;
end;
procedure search(j,key:integer;var m : integer);
(* m is the length of kth hash key bucket *)

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var i, i2 : integer;
begin
  i := key;
  while (i <> -1) do
  begin
    if (cand[j].inkey = model[i].inkey) and
        (cand[j].key1 = model[i].key1) and
        (cand[j].key2 = model[i].key2) then
      begin
        temporary_model[m] := model[i];
        with temporary_model[m] do
          vote[modelno, tripletno] := vote[modelno, tripletno]+1;
      end;
    m := m +1;
  end;
  i := model[i].link;
end;
begin (* main *)
  open (input, 'hash.dat', history := old);
  reset(input);
  open (candfile, 'tally.dat', history := old);
  reset(candfile);
  open (output, 'vote.dat', history := new);
  rewrite(output);
  readln(input, table_size, outmodelno[1], outinterestingno[1],
         outmodelno[2], outinterestingno[2]);
  readln(candfile, interestingno);
  test_interestingno_3 := interestingno - 3;
  initialize1; initialize2;
i := 0; j := 0;
  while (i < table_size) and (not eof(input)) do
    begin
      with temp[i] do
        begin
          readln(input, hashkey, inkey, modelno, tripletno, key1, key2, baseX1, baseY1, baseX2, baseY2, baseX3, baseY3, link);
        end;
      index := temp[i].hashkey;
      model[index] := temp[i];
    end; (*while*)
  m := 1; j1 := 1; n := 1;
(* ***********************CANDIDATE FILE***********************)
  while not eof(candfile) do
    begin
      with cand[j] do
        begin

readln(candfile,inkey,key1,key2,basex1,basey1,basex2,basey2,basex3,basey3);
end;
key := cand[j].inkey mod table_size;
search(j,key,m);
j := j+1;
count := j mod test_interestingno_3;
if count = 0 then
  begin
    find_maximum(m,j,j1);
    verify(j,j1,m,n);
m := 1;
initialize;
end;
end;
all_maximum_selected(n);

******************************VOTING RESULT**********************************
close(input);
close(candfile);
close(output)
end.

program reconstruct(interesting,vote,ploting);
const totalmodelno = 2;
type
  ary1 = array [1..10] of integer;
  ary2 = array [1..999] of integer;
  ary3 = array [1..99] of real;
  ary4 = array [1..10,1..99] of integer;
  ary5 = array [1..3] of integer;
  ary6 = array [1..2,1..2] of integer;
  ary7 = array [1..2,1..2] of real;
  ary8 = array [1..2,1..1] of real;
var
  orimodelno : ary1;
  select_base,select_basey,test_base,test_basey,rest_base,
  rest_basey : ary2;
  hashkey,inkey,modelno,tripletno : integer;
  recogmodelno,recoginteresting,vot : integer;
  collected_key1,collected_key2 : real;
  test_recogx,test_recogy,ordered_test_inter_coordx,
  ordered_test_inter_coordy,
  ordered_test_base,ordered_test_basey : ary3;
x,y,oriinterestno : ary4;
  oritx,ority : ary5;
  base_matrix : ary6;
  inverse_matrix : ary7;
  diff,coord : ary8;
deletemodelno : array [0..totalmodelno] of integer;
interesting,vote,ploting : text;
korder,jr : integer;
i : integer;

procedure matrix_mult(inverse_matrix : ary7;
var diff,coord : ary8);

{this is for the matrix multiplication of inverse of
\(x_{(1-2)} \times x_{(2-3)}\) restx(i)-x(3)
\(y_{(1-2)} \times y_{(2-3)}\) and resty(i)-y(3)}
const k = 2;
1 2;
var i,il,n integer;
begin
  for i := 1 to 1 do
    for il := 1 to m do
      coord[i,il] := 0;
  for i := 1 to 1 do
    for il := 1 to m do
      for n := 1 to 1 do
        coord[i,il] := coord[i,il] + inverse_matrix[i,n] *
          diff[n,il];
end;

procedure inverse(base_matrix : ary6;
var inverse_matrix : ary7):

{find the inverse matrix of x_{(1-2)} \times x_{(2-3)}
y_{(1-2)} \times y_{(2-3)}\}
var det : real;
begin
  det := (base_matrix[1,1] * base_matrix[2,2]) -
    (base_matrix[1,2] * base_matrix[2,1]);
inverse_matrix[1,1] := base_matrix[2,2]/det;
inverse_matrix[1,2] := base_matrix[1,2] * (-1) /det;
end;

procedure calculate_coord(recogmodelno : integer;
cbasex,cbasey : ary5);

{calculate the /xi and /eta of the
(select_baseX, select_baseY) in of the model)

var i, m, i1, i2, i3 : integer;
begin
  for i := 1 to 2 do
    begin
      base_matrix[1, i] := cbasex[i] - cbasex[i + 1];
      base_matrix[2, i] := cbasey[i] - cbasey[i + 1];
    end;
  inverse(base_matrix, inverse_matrix);
  i2 := 1;
  for i := 1 to ori_interestno[orimodelno[recogmodelno], recogmodelno] do
    begin
      if ((cbasex[1] <> x[recogmodelno, i]) or (cbasey[1] <> y[recogmodelno, i])) and
          ((cbasex[2] <> x[recogmodelno, i]) or (cbasey[2] <> y[recogmodelno, i])) and
          ((cbasex[3] <> x[recogmodelno, i]) or (cbasey[3] <> y[recogmodelno, i])) then
        begin
          rest_basex[i] := x[recogmodelno, i];
          rest_basey[i] := y[recogmodelno, i];
          diff[1, 1] := rest_basex[i] - cbasex[3];
          diff[2, 1] := rest_basey[i] - cbasey[3];
          matrix_mult(inverse_matrix, diff, coord);
          ordered_test_inter_coordx[i] := coord[1, 1] *
            (ordered_test_basex[1] - ordered_test_basex[2]) +
            coord[2, 1] * (ordered_test_basex[2] -
              ordered_test_basex[3]) +
            ordered_test_basex[3];
          ordered_test_inter_coordy[i] := coord[1, 1] *
            (ordered_test_basey[1] - ordered_test_basey[2]) +
            coord[2, 1] * (ordered_test_basey[2] -
              ordered_test_basey[3]) +
            ordered_test_basey[3];
        end;
    end;
  for i := 1 to ori_interestno[orimodelno[recogmodelno], recogmodelno] do
    writeln(ploting, ordered_test_inter_coordx[i],
      ordered_test_inter_coordy[i]);
end;

procedure colinear(var comX, comY : ary5;
  var t1, t2 : real);
  (using tangent y/x to test if 3 points are colinear?
  t1 and t2 are the tangent value of any 2 pairs of coordinates)
var colinearx1, colinearx2, colineary1, colineary2 : integer;
begin
    colinearx1 := comx[2] - comx[1];
    colinearyl := comy[2] - comy[1];
    if (colinearx1 <> 0) then
        t1 := arctan(colinearyl / colinearx1)
    else t1 := 1.5707;
    if (colinearx2 <> 0) then
        t2 := arctan(colineary2 / colinearx2)
    else t2 := 1.5707;
end;

procedure pretest(i,j : integer;
    var t1,t2 : real);
{preparing for colinear testing}
var count : integer;
begin
    count := 1;
    while ((test_recogx[j]<>0) or (test_recogy[j]<>0)) and
    ( count < 4 ) do
        begin
            oritx[count]:=x[i,j];
            ority[count]:=y[i,j];
            ordered_test_inter_coordx[j] := test_recogx[j];
            ordered_test_inter_coordy[j] := test_recogy[j];
            ordered_test_basex[count] := test_recogx[j];
            ordered_test_basey[count] := test_recogy[j];
            j := j+1;
            count := count+1;
        end;
    colinear(oritx,ority,t1,t2);
end;

procedure mapping(bx,by : real;
    var ordering : integer;
    i : integer);
{make the first record data from the vote corresponding to
that in the second record bx,by is the input (select_basex
select_basey) or the calculated rest interesting point in
the model ordering is to pass back to match the interesting
point between model and recognized model}
var
    j : integer;
begin
    for j := 1 to oriinterestno[orimodelno[i],i] do
begin
    if (abs(bx - x[i,j]) < 0.00001) and
        (abs(by - y[i,j]) < 0.00001) then
        begin
            ordering := j;
        end;
end;
end;

procedure interest;

{read into the original model interesting number and their coordinates}

var
    i,j,k,k1 : integer;
begin
    open(interesting,'interesting.dat',history := old);
    reset(interesting);
    open(ploting,'ploting.dat',history := new);
    rewrite(ploting);
    i:=1;
    while not eof(interesting) do
        begin
            read(interesting,orimodelno[i]);
            readln(interesting,oriinterestno[orimodelno[i],i]);
            for j := 1 to oriinterestno[orimodelno[i],i] do
                readln(interesting,x[orimodelno[i],j],
                    y[orimodelno[i],j]);
            i := i+1;
            korder :=i;
        end;
    for k:= 1 to orimodelno[korder-l] do
        for kl := 1 to oriinterestno[orimodelno[k],k] do
        end;
end;

procedure recognized;

{read the recognized model i.e., vote data find the order in the recognized model}

var
    i,i1,i2,j,j1,k : integer;
    select_model_tempx,select_model_tempy,t1,t2 :real;
begin
    open (vote,'vote.dat',history := old);
    reset(vote);
    i :=1;
    while (not eof(vote)) do
        begin
          90
readln(vote, hashkey, inkey, modelno, tripletno, collected_key1, collected_key2, select_basex[1], select_basey[1], select_basex[2], select_basey[2], select_basex[3], select_basey[3], vot);

readln(vote, inkey, collected_key1, collected_key2, test_basex[1], test_basey[1], test_basex[2], test_basey[2], test_basex[3], test_basey[3]);
recogmodelno := modelno;
if (recogmodelno <> deletemodelno[recogmodelno]) and (vot/(oriinterestno/orimodelno[recogmodelno], recogmodelno)-3) >= 0.5,
then

{The vote number must be less than original model interesting number - 3 and greater than 1 or a relative ratio ,i.e. vote number vs. original interesting number - 3, must greater or equal to threshold 0.5}

begin
for J:=1 to 3 do
begin
mapping(select_basex[j], select_basey[j], jr, recogmodelno);
test_recogx[jr] := test_basex[j];
test_recogy[jr] := test_basey[j];
end;
mapping(select_model_tempx, select_model_tempy, jr, recogmodelno);
for j1 := 1 to vot-1 do
begin

readln(vote, hashkey, inkey, modelno, tripletno, 
  collected_key1, collected_key2, 
  select_basex[1], select_basey[1], select_basex[2], 
  select_basey[2], select_basex[3], select_basey[3]); 
readln(vote, inkey, collected_key1, collected_key2, 
  test_basex[1], test_basey[1], test_basex[2], 
  test_basey[2], test_basex[3], test_basey[3]); 
select_model_tempx := collected_key1*(select_basex[1]- 
  select_basex[2])+ collected_key2*(select_basex[2]- 
  select_basex[3])+select_basex[3]; 
select_model_tempy := collected_key1*(select_basey[1]- 
  select_basey[2])+ collected_key2*(select_basey[2]- 
  select_basey[3])+select_basey[3]; 
mapping(select_model_tempx, select_model_tempy, jr, 
  recogmodelno);

  test_recogx[jr] := collected_key1*(test_basex[1]- 
  test_basex[2])+collected_key2* 
  (test_basex[2]-test_basex[3])+test_basex[3]; 
  test_recogy[jr] := collected_key1*(test_basey[1]- 
  test_basey[2])+collected_key2* 
  (test_basey[2]-test_basey[3])+test_basey[3];
end;
recoginteresting := vot+3;
writeln(pltating, recogmodelno, oriinterestno[ 
  orimodelno[recogmodelno], recogmodelno]); 
i1:=1; t1:=1; t2:=1; 
pretest(recogmodelno, i1, t1, t2); 
  if t1<>t2 then calculate_coord(recogmodelno, 
    oritx, ority) 
  else pretest(recogmodelno, i1+1, t1, t2); 
delete_modelno[recogmodelno]:= recogmodelno;
end
end;

begin(main) 
  interest; 
  recognized; 
end.
LIST OF REFERENCES


10. Subroutine Package for Image Data Enhancement and Recognition, University of Osaka, Japan, 1983.

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