

UNIVERSITI MALAYSIA PAHANG

**FACULTY OF ELECTRICAL & ELECTRONICS
ENGINEERING**

THESIS

**HAND GESTURE RECOGNITION SYSTEM
USING IMAGE PROCESSING**



اونيفرسيتي مليسيا قهغ السلطان عبدالله
ABANG IRFAN BIN ABANG ABDUL HALIL
AL-SULTAN ABDULLAH

**SUPERVISOR:
ROSDIYANA SAMAD**

SEMESTER 2007/2008

UNIVERSITI MALAYSIA PAHANG

JUDUL

HAND GESTURE RECOGNITION SYSTEM USING IMAGE PROCESSING

SESI PENGAJIAN: 2007/2008

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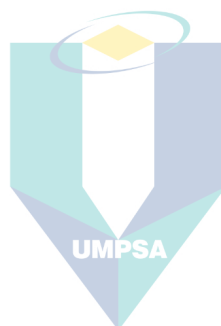
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HAND GESTURE RECOGNITION SYSTEM USING IMAGE PROCESSING

ABANG IRFAN BIN ABANG ABDUL HALIL



"This thesis is submitted as partial fulfillment of the requirements for the award of the
Bachelor of Electrical Engineering (Power Systems)"

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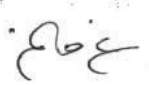
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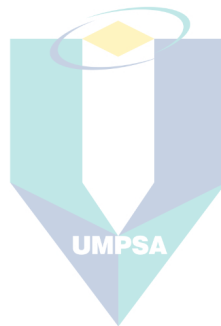
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DEDICATION



اونيور، يتي اي ياشه انا لطان عبدالله
To my beloved mother and father
Abang Abdul Halil bin Abang Naili
Zaiton binti Yusof

My fiancée for waiting me to finish this before doing hers

My supervisor who exposed me to this wonderful piece of engineering

ACKNOWLEDGEMENT

First of all I am grateful to ALLAH S.W.T for blessing me in finishing my final year project (PSM) with success in achieving my objectives to complete this project.

Secondly I want to thank my family for giving morale support and encouragement in completing my project and also throughout my study in University Malaysia Pahang (UMP) as they are my inspiration to success. I also would like to thank my supervisor Rosdiyana Samad for guiding and supervising my final year project throughout these two semesters. Shee has been very helpful to me in finishing my project and I appreciate every advice that she gave me in correcting my mistakes. I apologize my supervisor if any mistakes and things that I done wrong while doing my project. My credit also goes to Mr Professor Madya Shaikh Nasir Shaikh Abd Rahman as the dean of Electrical Engineering Faculty and Mr Addie Irawan Hashim as the coordinator of final year project with their cooperation and guide about my final year project from the beginning.

Last but not lest I want to thank all my friends that have gave me advice and encouragement in completing my project. Thank you very much to all and May ALLAH bless you.

ABSTRAK

Pemrosesan imej mempunyai potensi yang besar untuk boleh melakukan hampir apa sahaja. Tetapi dalam kehidupan sebenar ianya diburukkan lagi dengan keadaan apabila pembangunan sesuatu bidang yang diminati tidak dilakukan dengan teratur. Projek ini menampilkan sehingga terperinci pembangunan sistem pengesanan dengan menggunakan perisian pemrograman grafik NI LabVIEW. Ia kompleks dan boleh diubahsuai dalam banyak cara untuk sistem hiburan hari ini untuk kembali membawa kita kepada asas keselamatan. Ianya tidak berguna mempunyai suatu sistem yang lengkap tetapi mengabaikan keselamatan manusia. Justeru, untuk mencapai sama tinggi dengan pencapaian teknologi hari ini, projek ini akan cuba membawa teknik-teknik rumit imej pemrosesan sebagai penyelesaian kepada penyampaian arahan dalam bentuk yang lain. Perkakasan projek ini disambungkan menggunakan Kit Pembangunan Perisian, SDK daripada pembuat perkakasan tersebut, iaitu bagi projek ini Logitech Inc.. Penyaluran data yang teratur di antara perkakasan dan perisian memastikan transaksi yang licin yang meningkatkan prestasi dan kebolehannya. Kaedah pencahayaan belakang juga digunakan untuk memberikan exposure yang sesuai kepada subjek supaya pemrosesan seterusnya dan analisis blob (objek besar binary analisis) boleh dilakukan. Sistem ini juga menggunakan algoritma daripada beberapa teknik pemrosesan yang mungkin atau tidak memberikan keluaran yang sama untuk setiap satunya. Sistem ini mampu dinaik taraf dengan memasang ia secara modul-modul berasingan. Ia mungkin tidak sesuai dilakukan hari ini, tetapi dengan harga perkakasan kecil yang semakin menurun ditambah pula dengan sedikit inovasi seperti pencahayaan infra merah, 0 lux acquisition penglihatan malam, imej pemrosesan dan teknologi logic fuzzy untuk sentiasa melatih mesin, ia akan menjadi suatu kemestian harian kelak. Ini terbukti apabila menimbang penyelidikan dan pembangunan berjuta ringgit teknologi Beg Udara contohnya, satu masa dahulu kini menjadi satu keperluan.

ABSTRACT

Image processing has a very big potential to do virtually anything. But in real life, worse come to worst when the development of particular interest is not being done properly. This project comes to the extent of development details on recognition system by using state-of-the-art NI LabVIEW graphical programming software. The complexness and configurable in so many way of today's entertainment has brought us back to basic of safety. It is worthless to have a complete system that can do almost anything but compromises human life. To cope up on par to today technological achievement, this project will try to bring sophisticated ways of using image processing as a solution to deliver command in the other way. The hardware is being interfaced by using Software Development Kit (SDK) from the supplier of the hardware, in this case is Logitech Inc. Proper data channeling between hardware and software ensure smooth transaction that increase performance and capability. The method of backlighting is used to give proper exposure to the subject so that the further processing and blob (binary large object) analysis can be done on it. This system also used algorithm of several processing technique that may or may not be the same output for each type of it. The system is upgradeable to be connected by separate module. It will not be viable to implement it today, but the ever falling prices of gadget plus a little bit of innovation into infrared lighting, 0 lux night vision acquisition, refine image processing and fuzzy logic to keep the system trained, it will be everyday must. This is proven, considering costly research and development on Air Bag technology as an example, sometimes ago is now a necessity.

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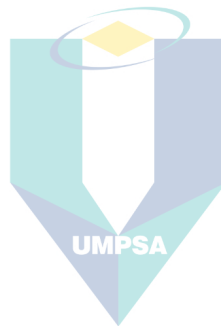
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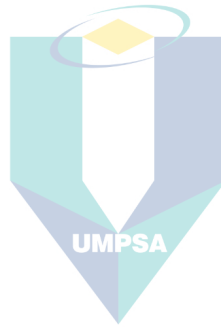
LIST OF ABBREVIATION

ABBREVIATION

CCD	–	Charge Couple Device
CMOS	–	Complementary Metal Oxide Semiconductor
DAQ	–	Data Acquisition
DLL	–	Dynamic Linked Library
DVD	–	Digital Versatile Disc
HID	–	Human Interface Device
IMAQ	–	Image Acquisition
JPEG	–	Joint Photographic Experts Group
LCD	–	Liquid Crystal Display
MAX	–	Measurement & Automation Explorer
NI	–	National Instrument
PCI	–	Peripheral Computer Interconnect
PLC	–	Programmable Logic Control
PNG	–	Portable Network Graphics
PXI	–	PCI eXtensions for Instrumentation
RGB	–	Red Green Blue
SCR	–	Script
SDK	–	Software Development Kit
USB	–	Universal Serial Bus
VI	–	Virtual Instrument
VISA	–	Virtual Instrument Software Architecture

LIST OF SYMBOLS

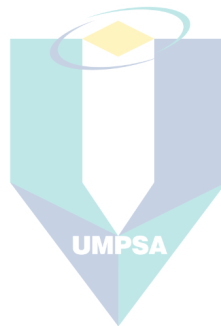
V_{dc}	-	Dc Volts
Ω	-	Ohms



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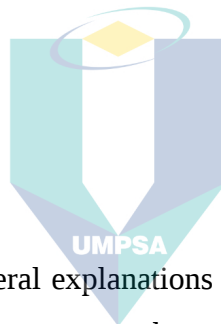


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CHAPTER 1

INTRODUCTION

1.1 Background



This chapter covers literal explanations of Hand Gesture, Image Processing and Machine Vision and how these processes brought recognition system into a whole new level of versatility. It also briefly explains National Instruments LabVIEW software and Vision Assistant of the advance G-Programming in practical application. The preceding will give an overview of image processing project specifically in recognition, the objective of the project, project scopes and thesis outline.

Machine will always be trained to replace human function in accomplishing specific task. However, recognition is not as simple as comparing it to complex mathematics operation. Computers only operate in discrete manner of 1 and 0, on and off whereas human operate in analog and abstract manner. That is why understanding analog system and abstract matters as deeply as possible will enable machine to do vision tasks almost as precise as human own capability.

Image processing is a branch of knowledge that tries to reach the same goal as human vision does. The process will not be the same but the objective is. The concept may or may not differ, depends on what sub task of the whole system is to be accomplished first. Machine look on something through segregated details to do matching based on system's hardware capability. Human on the other hand, used as much information as possible and will decide at that instance, fulfilling directly to the objective of the vision task itself. That is why trying to have the same par with human capability especially from the recognition accuracy perspective is impossible with current technology advancement available.

This project develops an alternative human interface from web camera input. Further, this system will execute a set of playback instruction on a model of car audio playback function. This project will be build by using LabVIEW Image Processing Software where block diagram programming is present. It is so far the easiest to program and troubleshoot through available step by step simulation function within.

This project is build to help drivers operate in car entertainment option. The most distracted event is when there is an incoming call from the driver's mobile phone. As reflect to that research by Volvo, the problem of drivers distracted from focusing on the road is issue to be taken care of. Distraction in certain cases can lead to collision and loss control over the vehicle.

1.2 Project objective

The objective of this project is:-

- i. To develop a hand gesture recognition system
- ii. To develop a system that can translate snapshot of hand gesture to a set of playback instruction on a model of car audio playback function.

1.3 Project scope

Below are the scopes that to be proposed for this project:

- i. To develop an image acquisition system that automatically acquire for a fixed interval of time or when the gestures are present.
- ii. To develop a set of definition of gestures and processes of filtration, effect and function available.
- iii. To develop a pre-defined gestures algorithm that command computer to do playback function of car audio model. This include Play, Stop, Pause, Fast Forward, Fast Backward, Volume Decrease, Volume Increase and ON/OFF function.
- iv. To develop image processing analysis system to be later used in feature extraction.
- v. To develop a testing system that proceeds to command if the condition is true with the processed images.
- vi. To develop a simple Graphical User Interface for input and indication purposes.
- vii. To interface acquisition hardware and software on a laptop computer until completion.

1.4 Structure of this Thesis

This thesis composed of 5 chapters each will detail out of details upon every aspect of this project. This project also being completed step-by-step chronologically order as how to easily setup any system together with National Instrument's software to do machine vision.

The beginning of this thesis will explain on what foundation the system to be built on. This includes Chapter 1 as the intro of the whole thesis. The preceding chapter 2 will touch on why this project was proposed.

Next, chapter 3 will explain how to have a complete setup for machine vision application. This chapter started with overview in sub chapter 3.1 and sub chapter 3.2 on key component of software, hardware and how both should cooperate. Then it is followed with a further look on the overall system built. These topics will detail out everything under the interest of the system itself excluding the setup explained earlier in chapter 1. Sub chapter 3.3 will explain optimum imaging environment followed by sub chapter 3.4 that will explain in detail regarding acquisition where National Instruments are very good at. Sub chapter 3.5 will touch one by one everything about processing in LabVIEW environment, whether it is a pre-processing for getting image to full processed or processing to enhanced feature extraction process. Sub chapter 3.6 will have a brief look on feature extraction. Sub chapter 3.7 will take a look on decision making. The last part of this thesis is to discuss on the overall of the finished product. This chapter 4 started of with results and discussion of the system including performance on sub chapter 4.1.1.

This thesis will properly be concluded in the last Chapter 5 followed by recommendation for the extension of this project and future prospect for the development room of improvement to grow on.

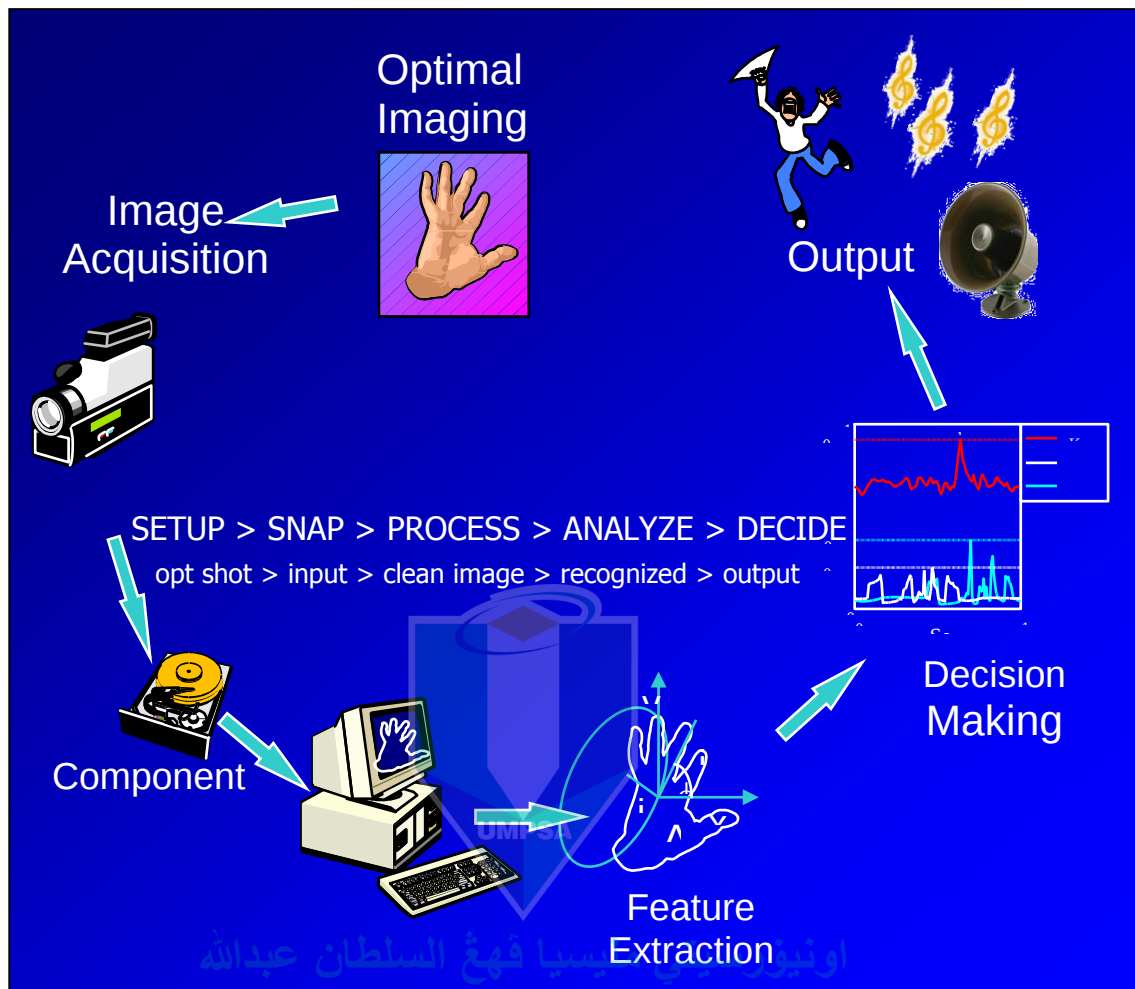


Figure 1: Graphical outline of this thesis

CHAPTER 2

LITERATURE REVIEW

2.1 Introduction



As early as in 1670, there's an expertise for human eyes named optometrist to help its patient to have a better vision on their surrounding. The first one is Benjamin Franklin that invented the first pair of bifocal glasses [1]. Benjamin's intention is to improve visibility and at that time not to aid people with sight problem like most people today. That context is referring to human capability of seeing things, contributing to a very highly valuable gift. Thanks to the fine creation of god, we do have two eyes that is one of tool to predict and act verily according to the vision tells and guides.

Just imagine how this world is if we are normal human being with healthy eyes, then we lost the vision or capability of capturing images and color. Even with one eyes, we have difficulties of estimate the distance of an object. Then, we immediately lost coordination and physical sense of everything around us. This situation best describe by having woman protect herself from strangers just by spraying chili aerosol to paralyze its attacker vision for a moment.

We cannot deny that we really dependent to our natural sensors. Lacking or not properly operational sensors can cause difficulties to our life. One of the important activities that most people do is to drive a vehicle. No blind man can drive a vehicle, it is just unacceptable. Researchers and technologist see this by first try to create self driving cars that enable to ease our life. This is considered after the growing and more entertainment option available for in car experience. If we can try to imagine a perfect working system for it, it will of course an invention of the centuries that really have a high impact on our life culture. But when thinking over these, to have this is just a long way to go. It will be available, but sure it will not available for quite sometimes as the progression on the vision technology is slowly developing.

2.2 Deadly Distraction

So, to come back to that very point, modeling and copying the vision system of human sight to work exactly like it naturally does. We imitate human sight system to have it done the same objectives, vision with a more reasonable and achievable way. That is why this project is being proposed. This project came from idea of minimizing distraction to car driver when they drive, that's it. Distraction even if it is just for a short while will endanger the driver from focusing on the road. The most distracted event is when there is an incoming call from the driver's mobile phone. As reflect to that research by Ford, it is clear that a driver who is driving while operating car audio equipment can get distracted from focusing on the road.

Early production of automotive built quality is poor. Company at that time did not want to discuss about safety. They did not remind their customer they can get hurt in these things (automobile) [2]. As time goes by, safety is considered as a taboo subject no more. By just a little bit of ongoing knowledge acquisition plus innovation here and there, it is considered as a life improvement and rewarding business. Today, company such as Volvo have stand out of crowd just because of their niche to be the safest car available on earth.

As for commercializing for this type of systems, having company making money just to improve safety for people is a very mutual profit process. There will be a team of people help to design and built safety function for the purpose of commercialization. The drivers as the end users can get benefit out of the noble deeds as well, thus improving safety level and comfortableness of life. Because of these continuing activity, automotive manufactured up to this date is much safer and refined than model available at the past.

This project has a few specific region of advancement to help not only aided driving but also to be implemented elsewhere. It is known that the implementation of this project to current automotive industries maybe is not feasible and practical. Thus there is a few usability of this project even it is not being implemented in automotive industries. To help understand better for that point, it is better for us to understand gestures literally and then the final result of this project is hoped to be.

Thus, this project will build a model of gestures operated car audio systems, a smart solution for a trouble free driving. As we look deeper, gestures have been researched by most intellectuals to strengthen the opinion of how useful gesture is. To look ahead on this, there is a need here to inform readers gestures have been researched by sociologist and biologist. And the other party is engineering student like me, to further enhance human hand capability to create and provide spectrum of command to machines.

2.3 Human Interface Device

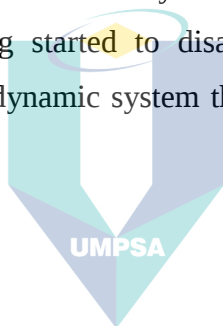
A human interface device or HID is a type of computer device that interacts directly with and most often takes input from humans and may deliver output to humans [3].

Common HIDs are:-

- Keyboard
- Mouse, Trackball, Touchpad, Laptop eraser
- Graphics tablet
- Joystick, Gamepad

The working group named as the Human Interface Device class at the suggestion of Tom Schmidt of DEC because the proposed standard supported bi-directional communication.

To have interactive input device is important to meet up problems come with it. For example using remote control is very handy. But by losing the remote control device, the purpose of easing started to disappear. Another example yet different perspective is to have a very dynamic system that can be configured programmatically instead of hardware mending.



2.4 Hand Gesture

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When we look in a wider extent, gestures came out from human body is natural. From Concise Oxford English Dictionary, *gesture* is a movement of part of the body, especially a hand or head, to express an idea or meaning [4]. As for this project, the development portion is to develop a new practical technology for alternative human interface. This gesture definition has been narrowed down to only hand and is given particular attention on details that Asian hands has.

Human do most things by using hand. The uniqueness covers from picking the smallest object to even do specialize work or even giving meaningful gestures to convey information. Take traffic police for instance, by just moving his hand and come out with different gesture each explaining go, stops or wait to the drivers.

2.5 Image Processing

Image processing is any form of information processing for which the input is an image, such as photographs or frames of video; the output is not necessarily an image, but can be for instance a set of features of the image. Most image-processing techniques involve treating the image as a two-dimensional signal and applying standard signal-processing techniques to it [5].

It is clear that image processing do have some kind of manipulation towards what it is fed to do. LabVIEW in their concept manual describe Image Processing as functions to analyze, filter and process images in NI Vision [6].

A pixel, short for *picture element*, can be thought of as a tiny dot containing information about the picture. When you snap a picture, these tiny bits of information are gathered by the camera's sensor [7]. The information is being stored in a 3 plane of information. Each plane represents three colors that are red, green and yellow plane. Each plane has the intensity from 0 up to 255 or 8-bit of information per plane. These three color combination makes up all the color we could see in an RGB images.

Simple calculation of this are 8-bit information is as follow:-

$$2^n = \text{bit}, 2^8 = 256$$

The origin of this size started when the byte was introduced back then in the origin of information capacity now have its standard. Many of the techniques of digital image processing, or digital picture processing as it was often called, were developed in the 1960s at the Jet Propulsion Laboratory, MIT, Bell Labs, University of Maryland, and a few other places, with application to satellite imagery, wire photo standards conversion, medical imaging, videophone, character recognition, and photo enhancement [8]. Digital processing is most of the time preferable because of cost issue on top of falling trend of digital devices.

Computers are getting cheaper and more affordable to own by anyone starting in the 1970s [9]. The image processing styles emerge up to processing it in real time using appropriate image acquisition hardware. That is generally when television start to be invented and marketed to home user.

Images could then be processed in real time, for some dedicated problems such as television standards conversion. As general-purpose computers became faster, they started to take over the role of dedicated hardware for all but the most specialized and compute-intensive operations [10]. With the fast computers and signal processors available in the 2000s, digital image processing has become the most common form of image processing, and is generally used because it is not only the most versatile method, but also the cheapest.

There are many types of image processing available today. Typical image processing is grouped into Processing, Filters, Morphology, Analysis, Color Processing, Operators and Frequency Domain. While these groups are referring to only image processing available on National Instrument platform, narrowed down to some wide feature available. These image processing named only available with installation of LabVIEW 8.2 together with compatible NI Vision Development Module.



Figure 2: This image demonstrate Extract Plane image processing on an RGB image. The picture shows red, green and blue color channel over composite as image at the last

2.6 Machine Vision

Machine Vision is where machine are used to see, evaluate at the same time giving output as what human ought to give. Traditionally this is accomplished by human workers where repetitive heavy production environment and high tense situation take place. Because of human have feelings, quality are often vary most of the time.

This section describes conceptual information about high-level operations commonly used in machine vision applications such as edge detection, pattern matching, dimensional measurements, color inspection, binary particle classification, optical character recognition and instrument reading [11]. Machine vision will be explained in details in chapter 3.6, feature extraction. In addition, processing in sub chapter 3.5.2 is also indirectly mentioning processing for feature extraction purposes.

Among what machine vision can do are as follows:

- Edge Detection
- Pattern Matching
- Geometric Matching
- Dimensional Measurement
- Color Inspection
- Binary Particle Classification
- Golden Template Comparison
- Optical Character Recognition
- Instrument Readers

In test and measurement applications such as movement measurement and event recording, and result verification, you can easily integrate and correlate images with transducer-based data acquired with data acquisition hardware [12]. Manufacturing plant with a very tight production schedule to be met along with quality control will usually require a lot of attention of many. The workers are also being paid accordingly with a very large number of workers.

It is clear machine should be used and replace human in so many attention as it do not retaliate and do very forward to what being asked for. In industrial application, vision analysis routines test incoming images part quality. Overall, computer vision are more reliable and cost-effective than human workers in the high-speed, detailed, repetitive manufacturing processes required for making semiconductors, electronic, medical, pharmaceutical and computer products [13].

Machine often cost more in most automated application, requires maintenance attention and competent operator to monitor its operation. In contrast, machine vision's benefit can be fully utilized even with a very cheap setup, almost no maintenance and very little attention to as it is fully automated. This makes machine vision desirable over anything else yet still delivers cost-effectiveness. The only catch lies on the development of the system. On that solid ground, this project is being proposed.

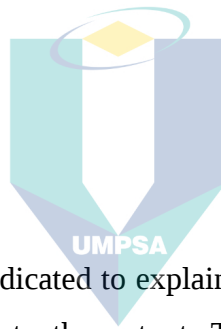


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CHAPTER 3

METHODOLOGY

3.1 Introduction



This chapter will be dedicated to explain the system in great details from setting up, to the system component to the output. The working component of this system consists of 5 different parts where most of the techniques have been simplified to ease presentation. These techniques include hardware and software setup, image acquisition, image processing, feature extraction and decision making modules.

The key working component sub chapter 3.2 will explain hardware and software requirement including available option in spite of limitation found. In sub chapter 3.3 is the method used for having optimal imaging. Very much effort in preparing the hardware will ease processing in software. Then the image acquisition in sub chapter 3.4 will briefly describe process of acquisition as it is not as simple as most people would think of especially the interfacing parts that is partially describe in sub chapter 3.2 earlier. Next are details of pre and post processing to all needed and optional processing needs explained in sub chapter 3.5. Also included the critical feature extraction and decision making module at chapter 3.6 and 3.7 respectively.

3.2 Key Working Component

This project is a development of system that consists of software and hardware section. Software and hardware details will be explained afterwards. After all programming stages completed, the last stage is to have hardware and software interfaced together. At that time, if the hardware fails to perform as it should, problem to the image acquisition stage will bring the biggest disaster.

It is undeniable the biggest part in this project is on the software side. Software is very crucial to have it work harmoniously afterwards. The software parts also includes abundant of programming and small scale detailing. The software parts also take most of the time to be slowly developed. At this stage, at the interfacing stage will be the most challenging as well. So it is a very big responsibility to make all of it, software and hardware working together to deliver desire result as a proof of application of research inside this project.

This project takes quite a long time to settle interfacing. Interfacing at the end line become more and more complicated as it's approaching to know what Logitech have in mind when they first write the web camera driver. Researching for an easier option has lead this project to the usage of Software Development Kit (SDK) provided by Logitech instead. The SDK is made available for people that already have the programming skills to use it [14].

These long searches have returned a few limitations towards writing image processing language in the fastest. CCD cameras are often expensive and their bundled software development kits (SDK) typically are proprietary, involve licensing and royalties. Beyond affordability, such SDKs often just provide ActiveX components and not the source code. As such, developing your custom application is limited to what

functions the SDK gives you [15]. Image processing is not short but it is complicated in order to function properly, or at least to do minimum machine vision tasks.

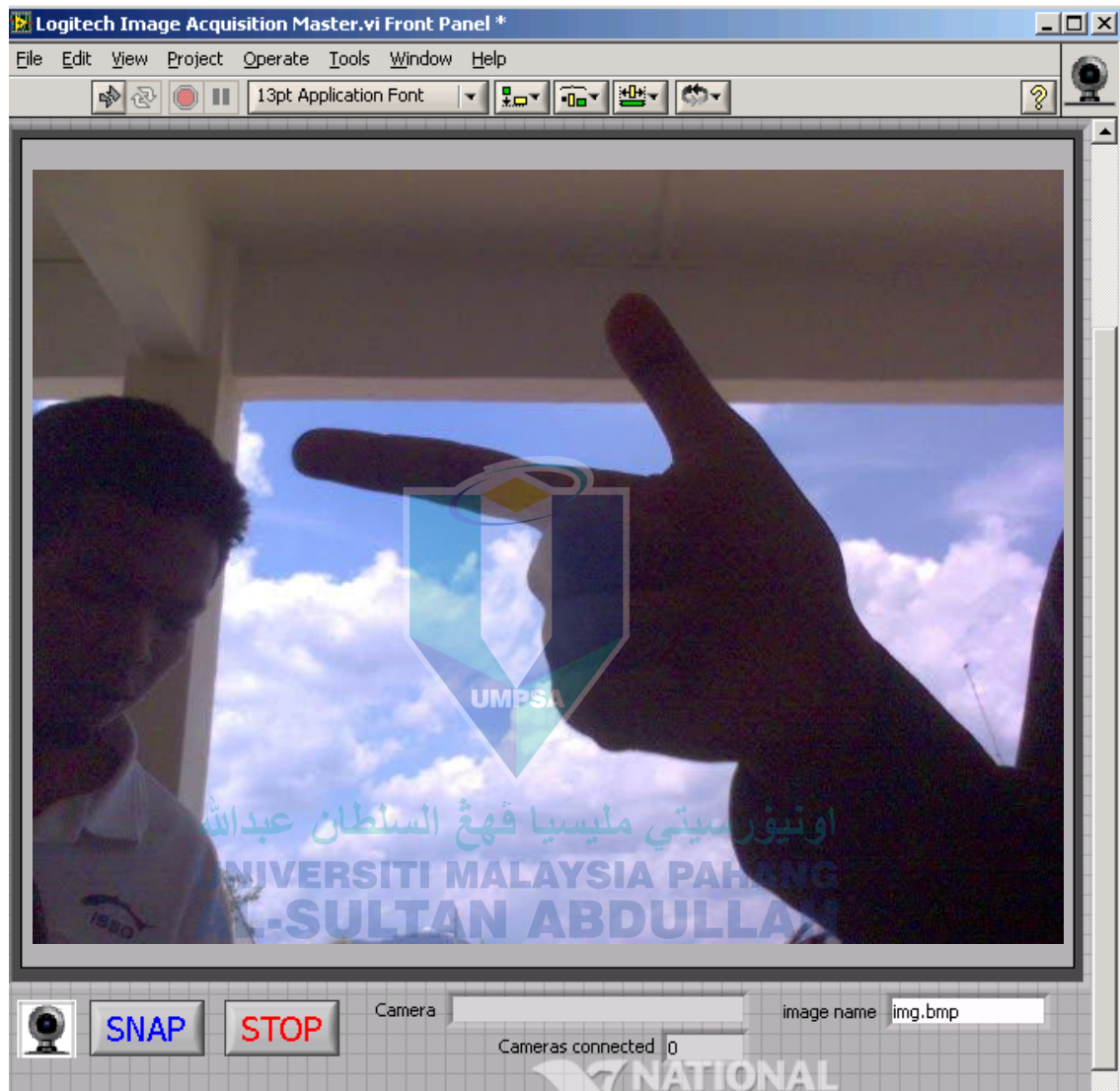


Figure 3: The SDK version acquisition system works fine in LabVIEW 6.0

The last solution is to have the LabVIEW 8.2 evaluation version along with NI Vision Development Module 8.2, NI IMAQ for USB Devices. This solution is risky and has a very limitative to what programmer can do. The evaluation version is fully functional for only 30 days. It will ask for license key after the interval has elapsed. This project utilized the evaluation software fully when it is capable of doing what a normal version can such as saving a VI files and vision assistant SCR files.

Please use recommended hardware to confirm the result for demonstration CD provided with this thesis. For Software Development Kit Demo, please find LabVIEW_Logitech_SDK_Acquisition_Demo.zip file to start of on a LabVIEW 6. Unfortunately, this thesis does not provide such software version in complementary CD but can be opened by newer LabVIEW 7 and above, however functions and wiring seem to be slightly different. Thus, most of the demo VI files are unusable.

3.2.1 Hardware

From The Free Dictionary by Farlex tells us that visual system is the sensory system for vision [16]. One of the most important thing in having a complete system that can see, as reflect to the word ‘visual’, is to have a sensory system that enable visual being processed and sent into brain to draw vision. As an introduction to the machine world, the word sensor once again is very close to web camera or the hardware used for this complete system. As human physiology, a pair of eyes functions as a color collector and being processed as an image.

This project used a web camera as an input device. To help better finishing this project without due and probable problem caused by interfacing of hardware and software, this project have been accomplished by phase. Each phase represent a portion of the system’s development. At the end of each phase, it will be directly tested on a complete system consisting of hardware and software interfaced altogether.

To have the system work, some image processing function that involves IMAQ function wouldn’t work if there is no hardware attached to it. Hardware attached to the computer will need to be first calibrated and configured to the laptop machine in order to work. In LabVIEW, the program stops running and display error message if this condition happened.

For computer to run the program and process it, this project uses Toshiba Satellite L20-C430 laptop. The demo will be using the same hardware also. The machine is equipped platform on Celeron processor and 256MB of RAM with National Instrument LabVIEW Software plus National Instrument IMAQ function installed.

3.2.1.1 Web camera

Web camera captures motion images with resolution 640 times 480 pixels and capability capturing 30 frames per seconds. Preliminary, this particular camera can go up to 25 frames per second only. Now, the capability is bigger and not impossible to increase in the near future. To enhance the capturing ability, the camera used is using CCD as a sensor. CCD stands for Charge Couple Device, which is not regarded as more superior against CMOS or Complementary Metal Oxide Semiconductor type of sensor. With three layer of CCD, each capturing each plane consisting of Red, Blue and Green respectively giving a more vibrant and sharp images. This factor also contributing to the resolution and frames per second performance on capturing images. CCD is less prone to noise.

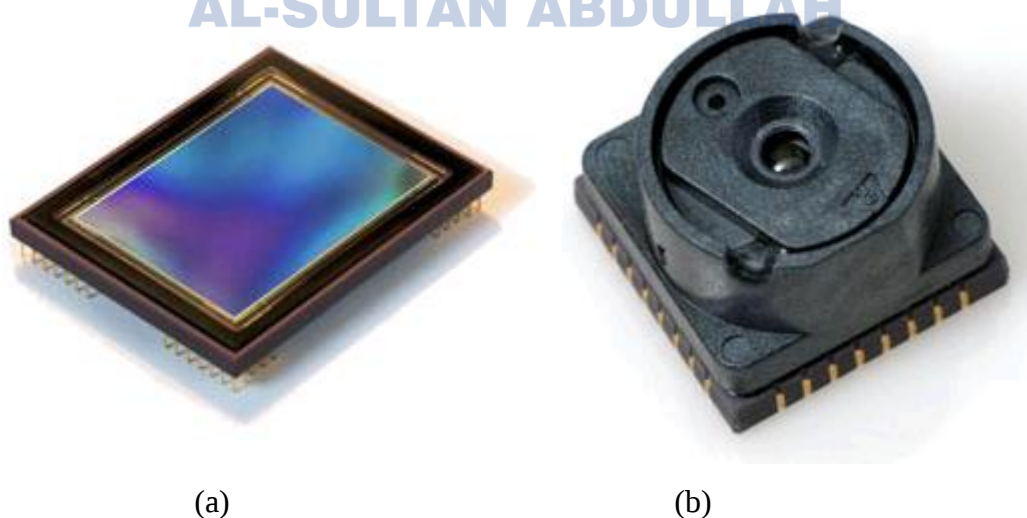


Figure 4: (a) CCD Sensor and (b) CMOS Sensor

Newer model such as QuickCam Pro 5000 that have capability of acquiring 30 frames per second and still image for about 1.2 megapixels. With the bundled, it is known it have software enhanced to help lighting condition. As for point of view, it will not be used as it will be using differently type of program and be configured to be used later by NI Explorer.



Figure 5: Logitech QuickCam PRO 5000

The hardware requirement should be enough to have it processed 25 to 30 frames per second. Even though there are a better hardware for imaging purposes such as IEEE-1394 firewire camera, line scan camera or line area camera, this hardware serve it function and its ability far exceed what software can do. The limitation is around software, thus hardware is not much a concern.

3.2.1.2 Specification

Logitech Web Camera

Name: QuickCam Express

Manufacturer: Logitech Inc.

Resolution: 352 X 244 pixel

Sensor Type: Charge Couple Display (CCD)

Interface Type: Universal Serial Bus (USB)

Please have a look on Appendix 1 for detailed hardware specification provided the manufacturer.

3.2.1.3 Protocol & Standard

To have a successful connection between LabVIEW and USB hardware, there is 4 ways of doing it as listed below:-

- Use a third party driver: These resources of hardware were provided by advance programmer professionals. This is mostly valid to open source user since the unavailability of hardware drivers is a common scenario.
- Control and acquire data from the camera by calling the camera's DLL files.
- Write your own drivers for the camera using VISA. There are several helpful resources.
- Download and install NI-IMAQ for USB Cameras: Due to the software provided is not govern by National Instrument supports, thus the availability to wide variety of manufacturers are also limited.



3.2.1.4 Usable Resources

To make it workable within LabVIEW environment, particular hardware is to be reserved from others party utilization. LabVIEW needs the particular hardware to be communicating directly to it. By having this, any manufacturer application will not be able to be utilized except by using manufacturer's DLL driver by using call library function. However the steps are not easy by using NI-VISA.

Some manufacturer will not make their source code available to public. However, by the demanding customized application, popular brand like Logitech make SDK, Software Development Kit instead. By having this particular kit, end user

especially advanced user who have the capability to do further programming can benefit all capability of said hardware to their own application.

4.2.1.5 Installation of NI-VISA Details

All hardware has their own unique ID to differentiate it with one another. All hardware must be addressed accordingly to have computer know what to find and what information to acquire out of it. Simply by understanding it is an imaging device, the information of how it require different from one another. Such as web camera, can acquire video and images from it that normally can be accessible anytime without problems. Scanner is a different story, there is a need to tell the scanner to do the scanning first before it can be acquired or else no image can came out of it.

This subchapter will details out how to use install hardware with National Instrument VISA's driver. VISA stands for Virtual Instrument Software Architecture. All driver under Windows Xp environment used INF files whether it is provided by manufacturer or other party. These simple guidelines will explain how to create an INF File using the Driver Development Wizard. This INF file will be replacing windows provided INF and this will enable hardware directly communicated with LabVIEW software during the development of the recognition system.

The best part of using VISA is to have all interfacing standards to work along with the same kind of driver. For example, a motion controls system that is being used in conjunction with hardware. The software behaves the same. It is known that different interfaces have different way to communicate with computers. By having VISA, all the hardware will have no what problem so ever if being used different interface. For example a system is being developed to communicate with hardware through serial connection. Because of having USB in portable computer instead of traditional serial interface, using VISA could make the connection works even though the new connection is USB instead of normal serial D9 connection.

To use NI-VISA, you must first tell Windows to use NI-VISA as default driver for the device. In the Windows environment, you can do this with an INF file. NI-VISA 3.0 and higher includes the VISA Driver Development Wizard (DDW) to create an INF file for your USB device.

To open the DDW, select Start»Programs»National Instruments»VISA»VISA Driver Developer Wizard. Figure 1 shows the open screen.



Figure 6: VISA DDW Hardware Bus Window

This wizard is used to create an INF file for a PXI/PCI, USB, or FireWire device. Because you are creating the driver for a USB device, click USB and Next. The VISA DDW Basic Device Information window opens as shown in Figure 2.

VISA Driver Development Wizard - USB - Basic Device Information

Welcome to the VISA Driver Development Wizard for USB. The wizard gathers the information that is necessary to allow NI-VISA to control your USB device. Please enter the basic device information below.

This wizard will generate an INF file for use with Windows XP/2000. The INF file tells the operating system to allow NI-VISA to access the USB device that you specify below.

USB Manufacturer ID (Vendor ID)	Manufacturer Name
0x3923	National Instruments
USB Model Code (Product ID)	Model Name
0x12C0	DAQPad-6020E

☐ This is a compound device which has interfaces.

NOTE: Using this wizard may not be necessary. NI-VISA may already be able to detect your USB instrument if it conforms to the USB Test & Measurement Class (USBTMC) protocol. If this is the case, DO NOT use this wizard to create an additional .INF file.

< Back Next > Cancel Help

Figure 7: VISA DDW Basic Device Information Window

For this step, the USB vendor ID and product ID for USB hardware must be known to address the right peripheral. These numbers identify the particular USB device when you install it and address your device when you want to communicate with it. According to the USB specification, both numbers are 16-bit hexadecimal numbers and should be provided by the device manufacturer. The demonstration above is directly taken from the Windows Xp Home Edition environment where Microsoft's software

automatically detects and addresses the web camera hardware. This information is being reused to configure NI-VISA to be available on MAX.

The recognition takes seconds when the hardware is plugged in. This has lead to the usage of latest VISA driver available free to download in national instrument's websites. The information appear in the Device Manager from the Control Panel and find your device on the list. Usually it is indicated as "Other Devices". The Logitech driver apparently was readily available under Xp environment. Double click the device to open the properties. Select the Details tab and ensure that "Device Instance Id" shows in the attribute dropdown box. A string of characters will be displayed similar to Figure 10. The four characters to the right of "VID_" and "PID_" indicating vendor ID and product ID, respectively.

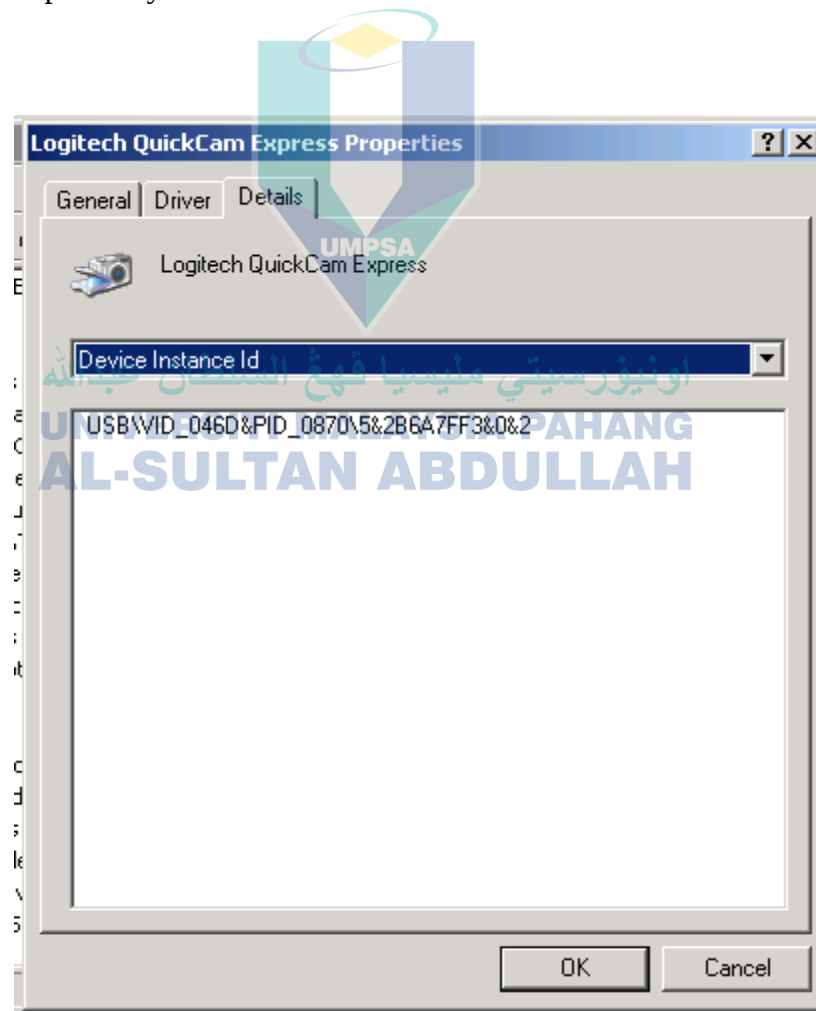


Figure 8: Vendor ID and Product ID appear in Windows Xp Device Manager

The Logitech QuickCam Express came with Vendor ID of 046D and Product ID of 0870. These prefix is shown in hexadecimal format. Enter the vendor ID, product ID, manufacturer name, and model name for your device into their respective field. Click Next. The Output Files Properties window is displayed as shown in Figure 11.

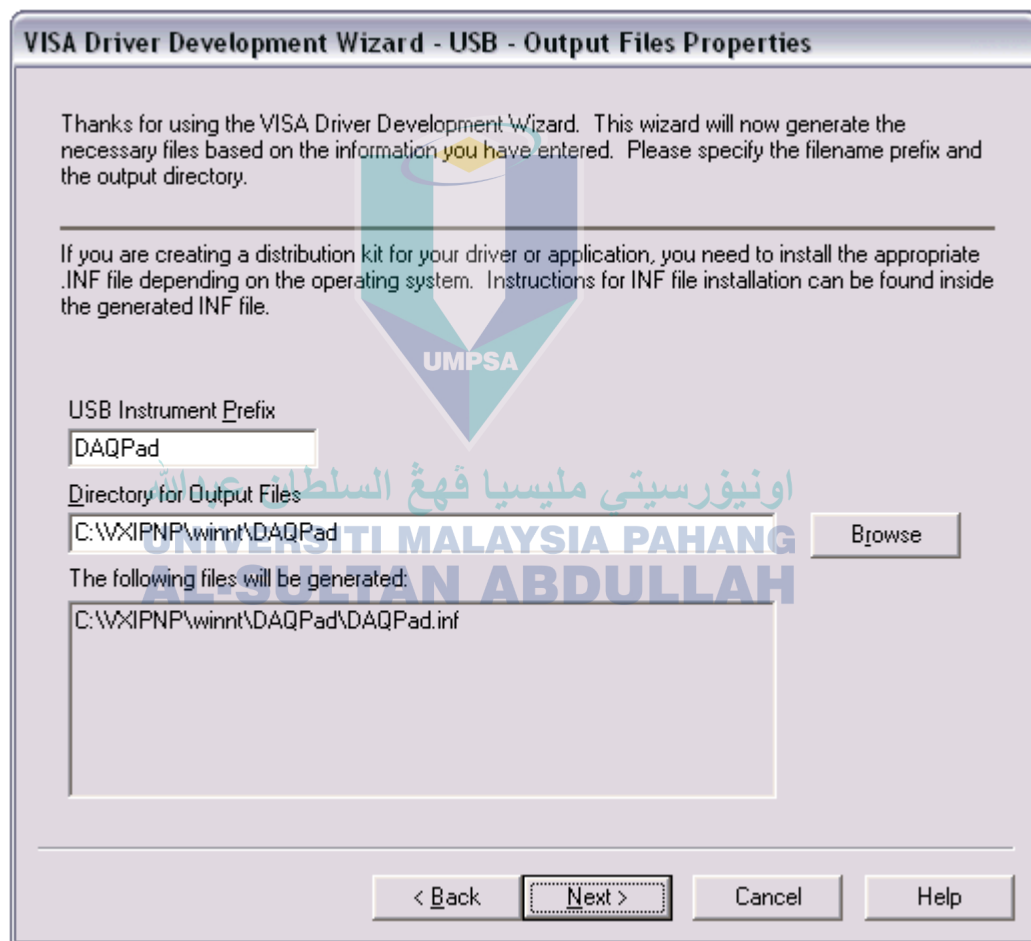


Figure 9: VISA DDW Output Files Properties Window

The USB instrument prefix is simply a descriptor you use to identify the files used for this device. Enter a USB instrument prefix, select the desired directory in which to place these files, and click next. The next window will provide you installation options. The default selection is to install the setup information for the operating system and is usually the best option. Once you select an option, click Finish to exit the wizard. The INF file is created in the directory you specified in the output file directory field in the previous window. Install the INF files and the respective USB device.

3.2.1.6 Advantech Data Acquisition Card

These are among the feature available for a DAQ card. DAQ card is very to get along with as it has input and output specifically for advance electrical application to computer interface. This package comes with a PCI Card, data connector and a Multifunction Card. The usage is rather easy, by just installation and go type of software. However to get it right, it must be installed in a sequential as follows:-

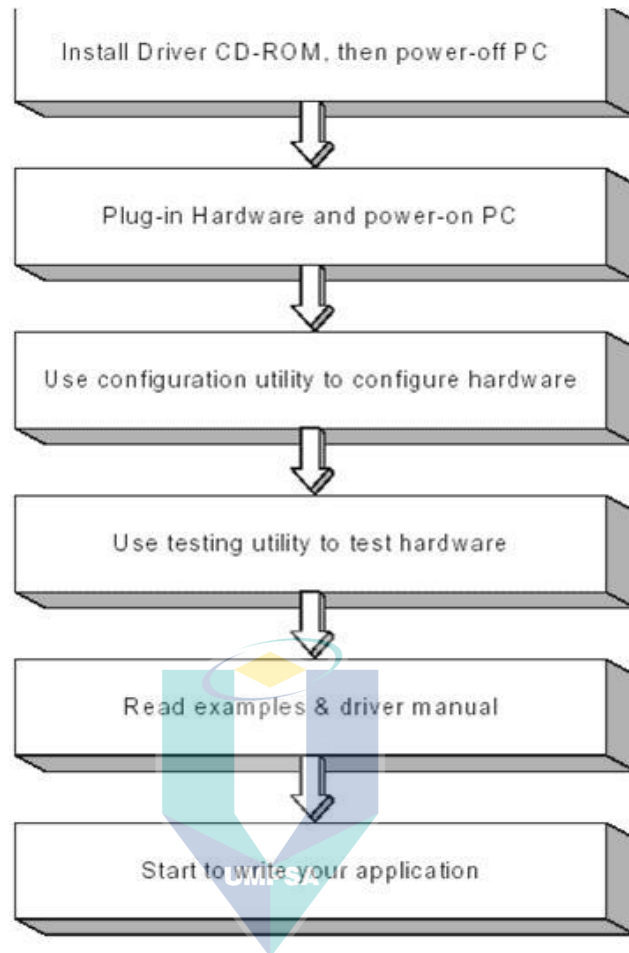


Figure 10: Step for installing hardware and software all together

By having these done, the hardware can be used directly. There are some function that is supplied with programming example include DAQ Open and DAQ Close that give the facility to automatically acquire port number and hardware location. If it is supplied into the source code, it is ready to be used. This part of programming has been used in decision making process. Additionally, it is a need to install driver for LabVIEW support provided by Advantech. Below are the features of this hardware.

100 KS/s, 12-bit, 16-ch Multifunction Card w/o Analog Output

- 16 single-ended, 8 differential or a combination of analog inputs
- 12-bit A/D converter, with up to 100 kHz sampling rate

- Programmable gain for each input channel
- Free combination of single-ended and differential inputs
- On-board 4 K samples FIFO buffer
- Two 12-bit analog output channels
- 16 digital inputs and 16 digital outputs
- Programmable pacer/counter
- Board ID™ Switch
- Short circuit protection



Figure 11: Data Acquisition Card with Terminal Board with Din-Rail

Industrial Wiring Terminal Board with CJC Circuit

- Low-cost screw-terminal boards
- On-board CJC (Cold Junction Compensation) circuits for direct thermocouple measurement.
- Reserved space for signal-conditioning circuits such as low-pass filter, voltage attenuator
- Industrial-grade screw-clamp terminal blocks for heavy-duty and reliable connections.
- Supports PCI-1710/1710L/1710HG/1710HGL/1711/1711L/1716/1716L cards
- DIN-rail mounting case for easy mounting
- Dimensions (W x L x H): 169 x 112 x 51 mm (6.7" x 4.4" x 2.0")

3.2.1.7 Protocol & Standard

Advantech have a complimentary compact disc that comes with almost everything. It provide driver for the hardware and some vi for labview software implementation. The connection is directly from DAQ card to a PCI interfaces.

3.2.1.8 Autotronic's Triggered MP4 Player

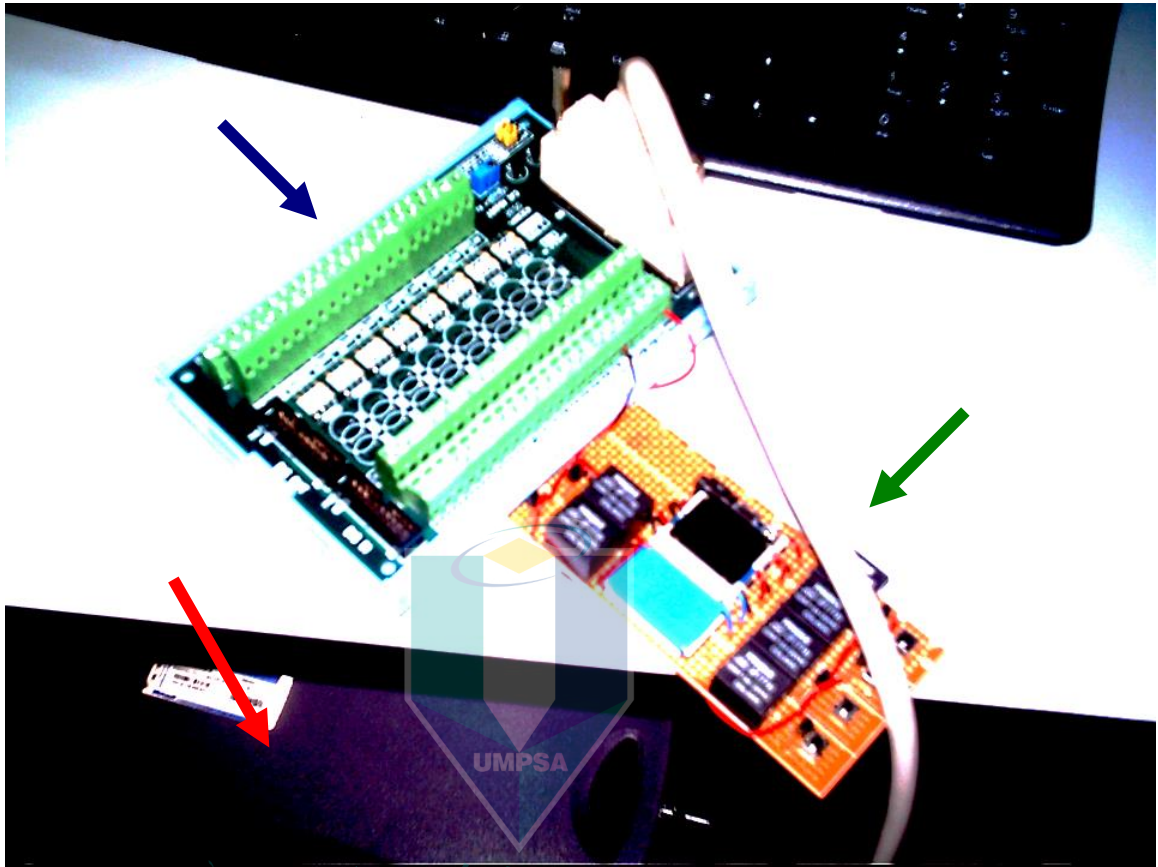


Figure 12: Overall Hardware (Red) Dell Desktop Computer (Blue) Advantech Data Acquisition Card (Green) MP4 Player and Autotronics Control

This project used simple autotronics to short any of its 7 buttons of control on the mp4 player. The circuit is shown below:

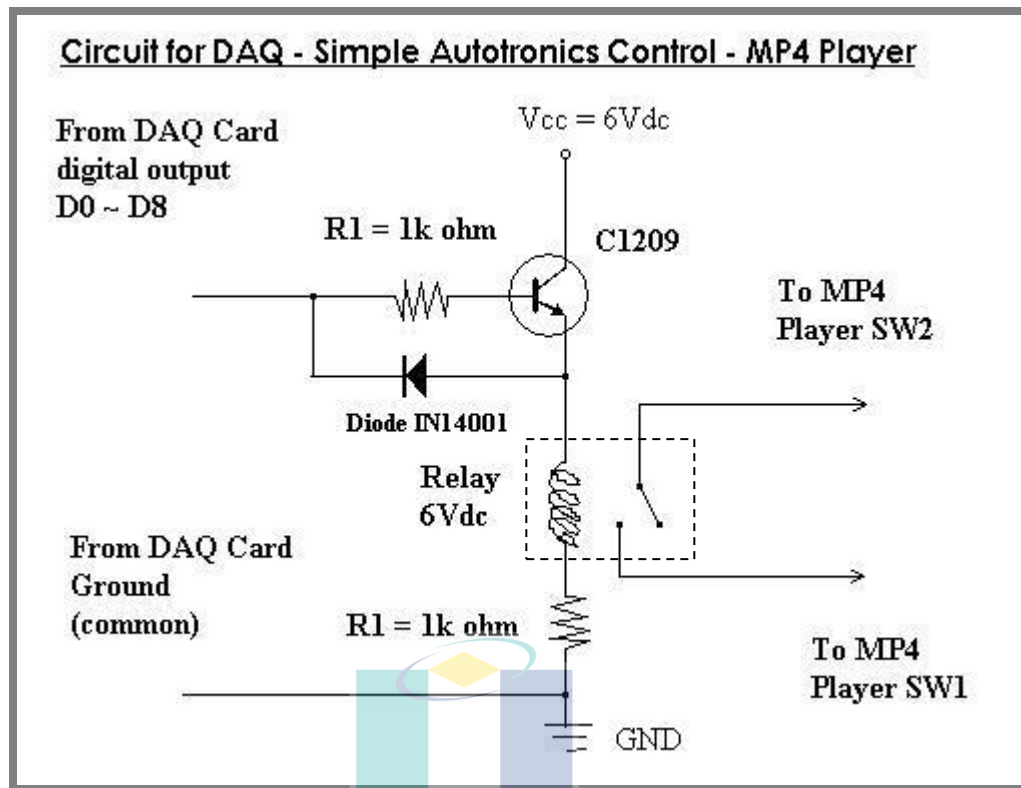


Figure 13: Darlington pair, impedance output and relays

Transistor were used because of different voltage of each circuit whereas relay were use to negotiate with a straightforward and simple circuitry.

Digital outputs were used, for driving 6 relay of rated 6Vdc. Instead having normal C9013 transistor, it was then replaced with a Darlington transistor C1209. Both were NPN transistors but different in arrangement especially Darlington transistors have the ability to share ground connection from the 5Vdc DAQ card with the autotronics 6Vdc circuit's supply. It is specialized to handle data output interface such as Advantech PCI-8710 had on it. IN14001 diodes were used to ensure compatibility and no back flowing of current from either system one another.

3.2.2 Software

Block diagram programming using LabVIEW is also known as programming in *G*. As reflect to nowadays culture of seeing things, programming in *C* to date is the most popular one. *C* refers to computer programming while *G* refers to graphical programming.

G programming popularity was increasing as most other software besides LabVIEW is going to follow the same trends. Ladder diagram programming in Programmable Logic Controls started to be the one of them, to have an easy yet customizable programming. Today, PLC's programming also use block diagram programming instead of ladder diagram. It is the interest of who is the end user that benefit from it.

This is due to professional such as engineers do not have a solid background in programming specifically. Engineers do need however, to program as what they application needs. NI introduces LabVIEW for this purpose. They do not need to know into depth what machine language say, but they need to use it to get their jobs done. This is actually derived from programmers view, where viewing into binary data transfer and receive is also not a need. Let it be programming software to look into it. Up to the demand that National Instrument take initiative to create graphical programming environment where it was made to be intuitive and user friendly.

Next, to gain knowledge to program in *G*, there's a need here to literate coding in *G*, distinguish data type as it will become the right parameter feed, creating sub-VIs and lastly to solve simple data acquisition tasks with LabVIEW with interfaced hardware later on.

LabVIEW is a high level language that giving it's user a choice of functions instead of typing it or referring to syntax programming guide. It is a norm for a

programmer to have the syntax programming book beside him when coding the program. So the choice of having internally built functions is something similar with the norm. With this kind of programming environment, many more advance feature played by the functions can be fully utilized.

Some company is not that much concern on the details of the programming; they intended programming tasks to be settled in order to fill their needs within a short period of time. As for popularity, this specific type of programming is also entering the next stage to become as popular as normal syntax typing programming language. Most of our advance application in the near future will no longer need tedious job of typing, but implementing instead block diagram to ask computer to help out for the tedious parts.

3.2.2.1 National Instrument LabVIEW version 8.2

The LabVIEW block diagram programming starts from left to right. Some of the function consist its own already built program. It can later be customized base on the needs of our program. For such needs, it is a very straightforward process. Putting require process that refer to the program needs all inside the block, then interconnecting it from left to right as well. The particular function must be connected to the similar function type by the same group of wire. This includes session, image, error and data lines. All else is connected when necessary and as an input or output to trigger something else.

National Instrument has a very high reputation on developing this software mostly used in instrumentation and measurement. Internationally, this type of programming software is very highly recommended and the positive comment came from its user and employee who put a requirement LabVIEW as compulsory on new recruitment. Some company hires people just because they literate with LabVIEW platform.

3.2.2.2 Measurement & Automation Explorer (MAX)

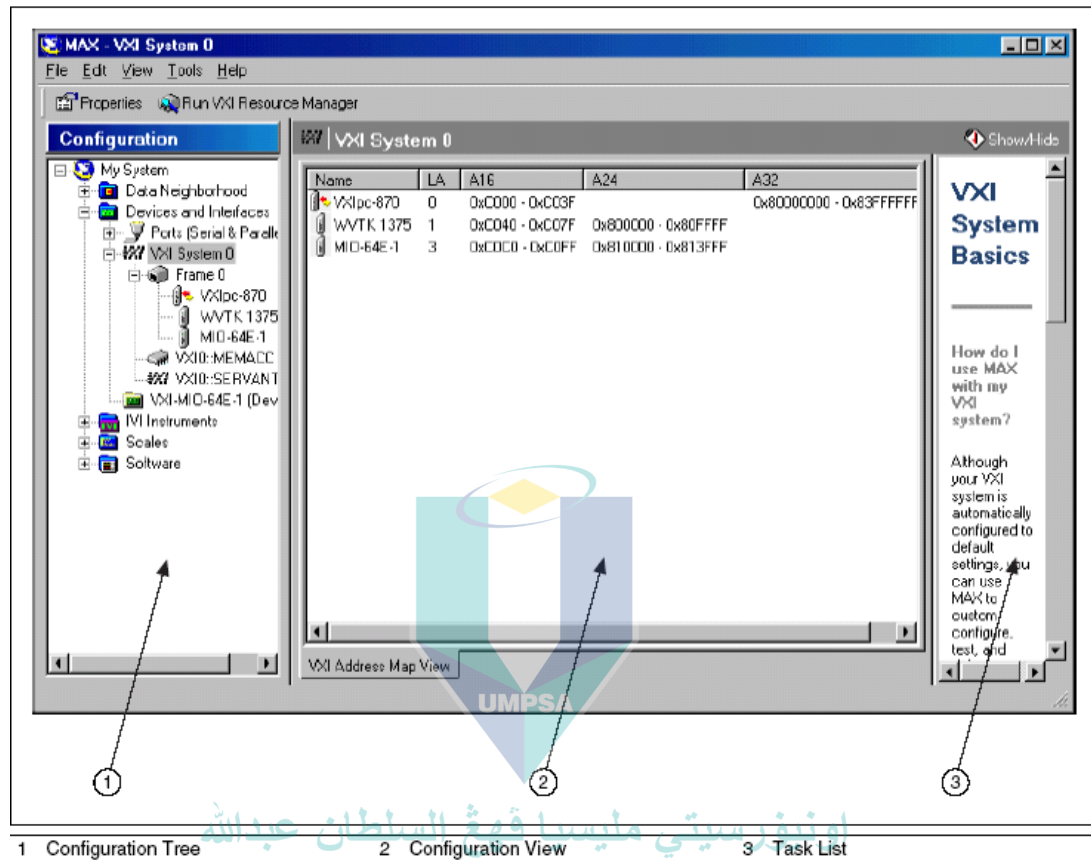


Figure 14: Measurement & Automation Explorer main graphical interface

Measurement & Automation Explorer (MAX) provides access to all your National Instruments DAQ, GPIB, IMAQ, IVI, Motion, VISA, and VXI devices. With MAX, you can configure your National Instruments hardware and software, add new channels, interfaces, and virtual instruments, execute system diagnostics, and view the devices and instruments connected to your system. MAX installs automatically with NI-VISA version 2.5 or higher or NI-VXI version 3.0 or higher. MAX is available only for Win32-based operating systems.

3.2.2.3 NI Vision Development Module

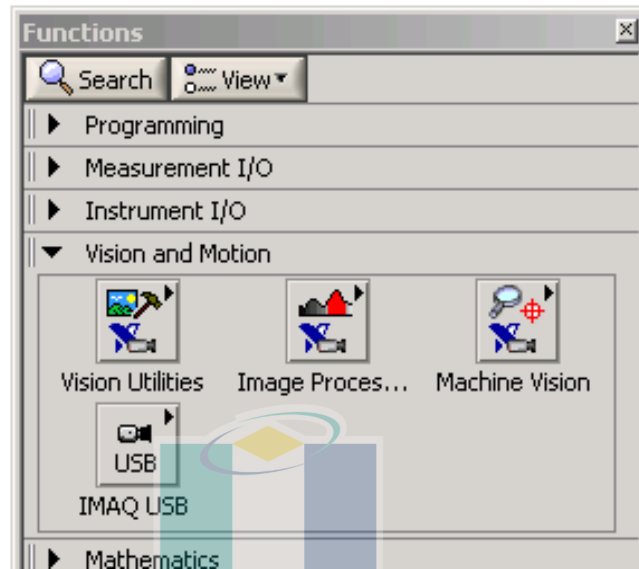


Figure 15: With NI Vision Development Module installed

It appears inside Vision and Motion sub Main Functions, where it has Vision Utilities, Image Processing and Machine Vision. NI IMAQ for USB was taken from NI IMAQ for USB device driver. NI IMAQ for USB will be explained later.

3.2.2.4 NI Vision Assistant

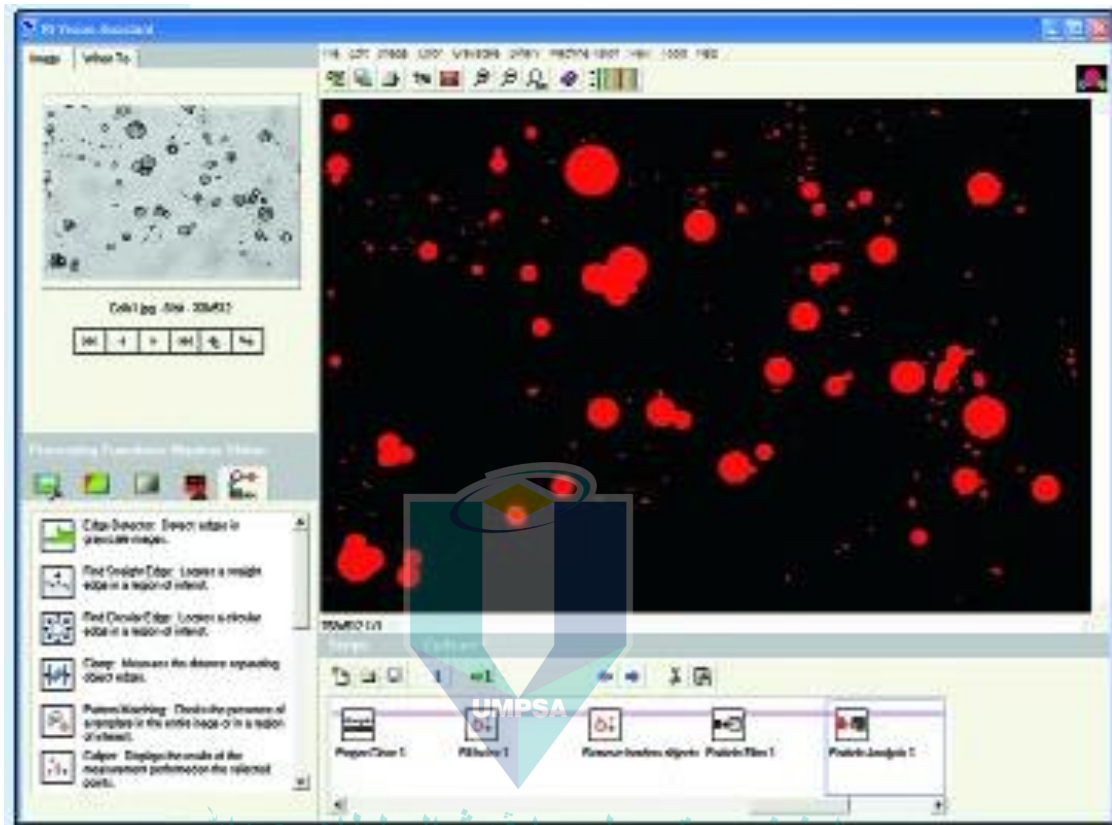


Figure 16: NI Vision Assistant

NI Vision Assistant gives a configurable image processing at user disposal, by graphically see the changes each processing and compare it to original one. It is a newer Vision Builder (explained later), processing in step-by-step and simple layout of pass and fail step status screen. The parameters in this environment are then converted into usable parameter to be fed in LabVIEW environment later on. This software is a trial version, thus cannot be exported directly to LabVIEW. Redo all the function and some findings through functions and library is necessary.

3.2.2.5 Vision Builder version 2.5

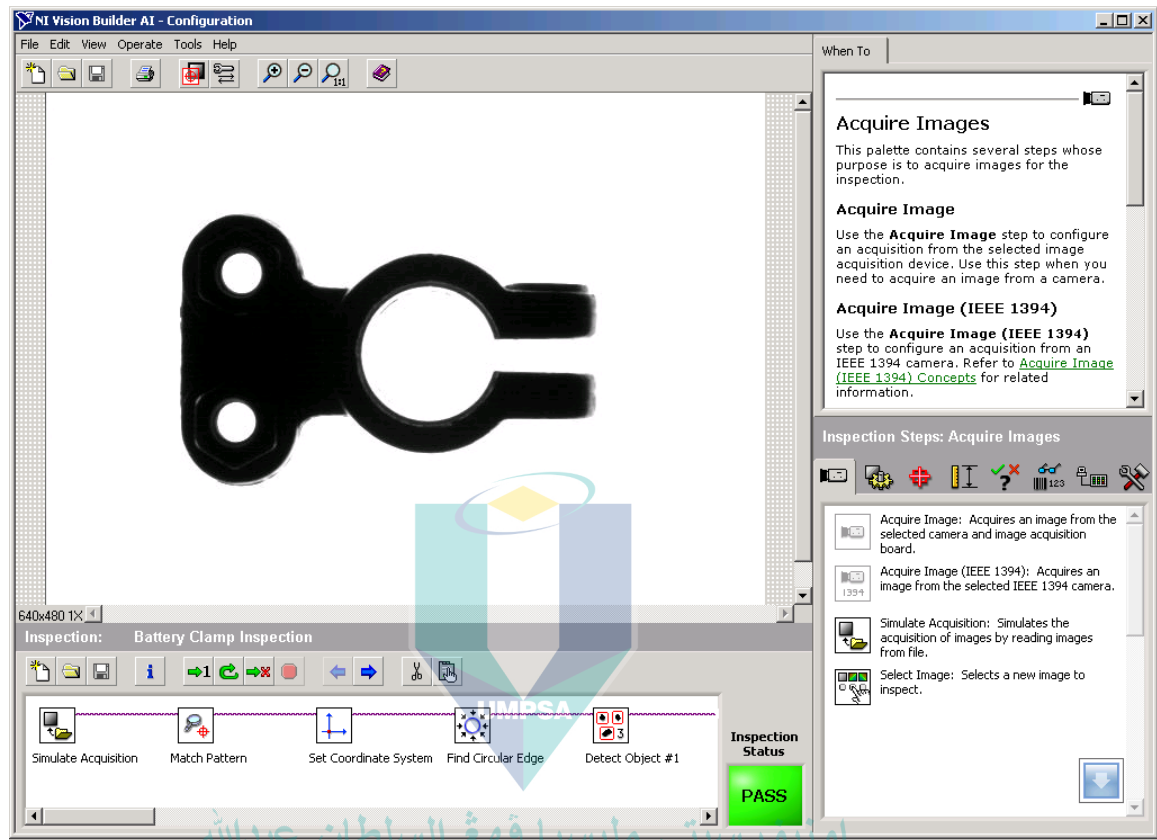


Figure 17: Shown Vision Builder Automated Inspection Version 2.5

There are two modes available within Vision Builder that is Configure Inspection and Inspect Product. Configure Inspection were used to apply any functions and processing to images setup for the particular project. On the other hand, Inspect Product will use finished Vision Tasks to have evaluated the performance of any given system.

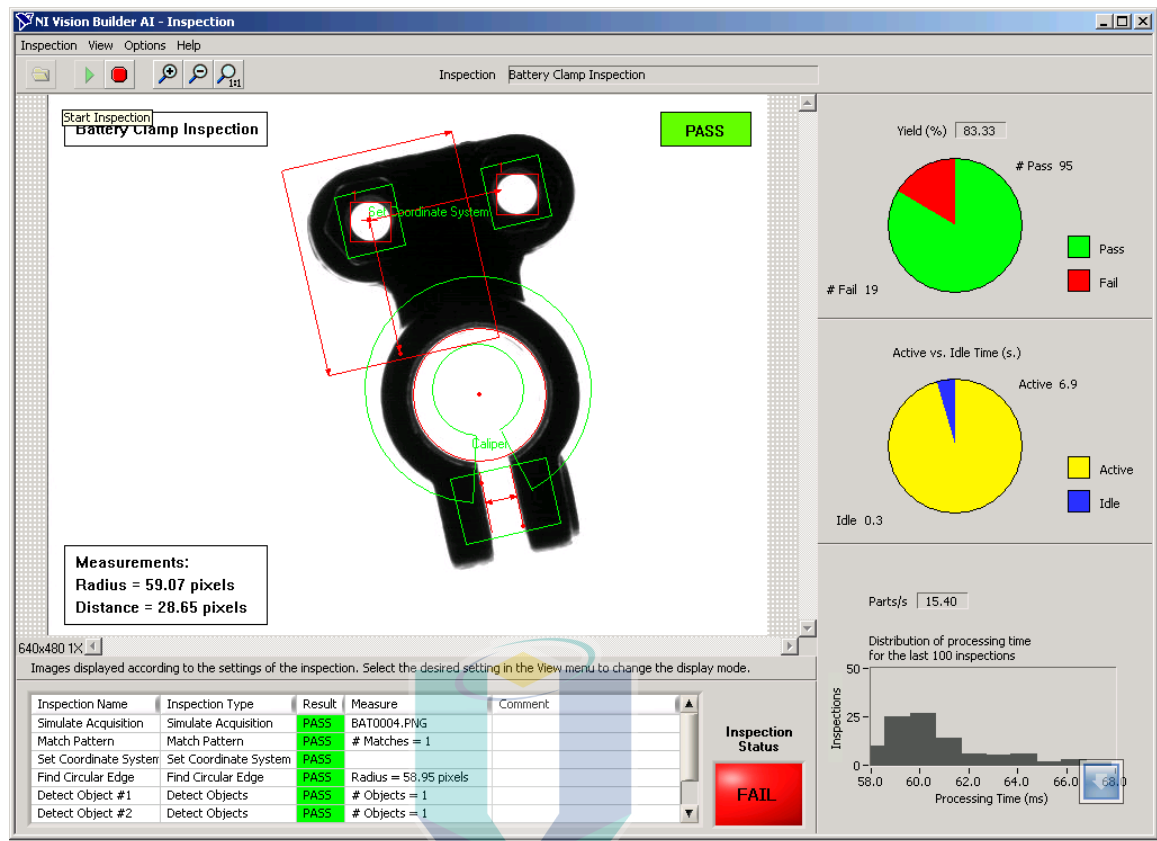


Figure 18: Inspection Mode to evaluate vision task or system performance

Vision builder is somewhat the same as NI Vision Assistant. It is an older version of Vision Assistant and before it comes with a plug-in of vision assistant. For today's Vision Assistant are actually same as Vision Builder with some Vision Assistant in complement with each other. Shown in figure 18 are the Battery Clamp Inspection Demo were used to be inspected, where yield (%), Active vs. Idle Time data, parts per second and Processing Time (ms).

3.2.2.6 NI IMAQ for USB Camera

The NI-IMAQ for USB Camera driver supports any camera with a Direct Show filter. This typically includes any USB camera, microscope, scanner, etc, most IEEE-1394 cameras, and even USB video adapters (takes analog video and converts it to USB).

This driver is not meant for high-end vision applications because the cameras that have Direct Show filters are typically consumer grade low resolution cameras. The industrial IEEE-1394 cameras with Direct Show filters typically don't provide as many resolutions and frame rates with the Direct Show filter as the IEEE-1394 interface provides. This driver is geared towards academic applications and users who want to acquire images but don't require high quality images. The camera's Direct Show filter typically compresses images and adds compression artifacts to the image that make image processing difficult.

The NI-IMAQ for USB Camera driver does not support grabbing from more than one camera simultaneously. It is also recommended to use the driver with single processor non hyper threaded machines. If you do have a dual processor or hyper threaded machine, you can disable these features to allow for better USB acquisition performance with this driver.

3.3 Preparation of Optimal Imaging

Images could be taken properly for vision application and further processing with the consideration of imaging environment. This will greatly enhanced unneeded processing in later stage.

3.3.1 Backlighting

The effect of backlighting discovered from the unsolicited condition of heavy light from the background. The parameter of RGB used for color threshold were the resultant of research onto how backlighting can assist computer not to get easily confused.

This project used a very simple tool available free at the public domain. The tool named color picker that can pick any color on screen and then translated into the intensity of every component with the margin of 0 to 255.

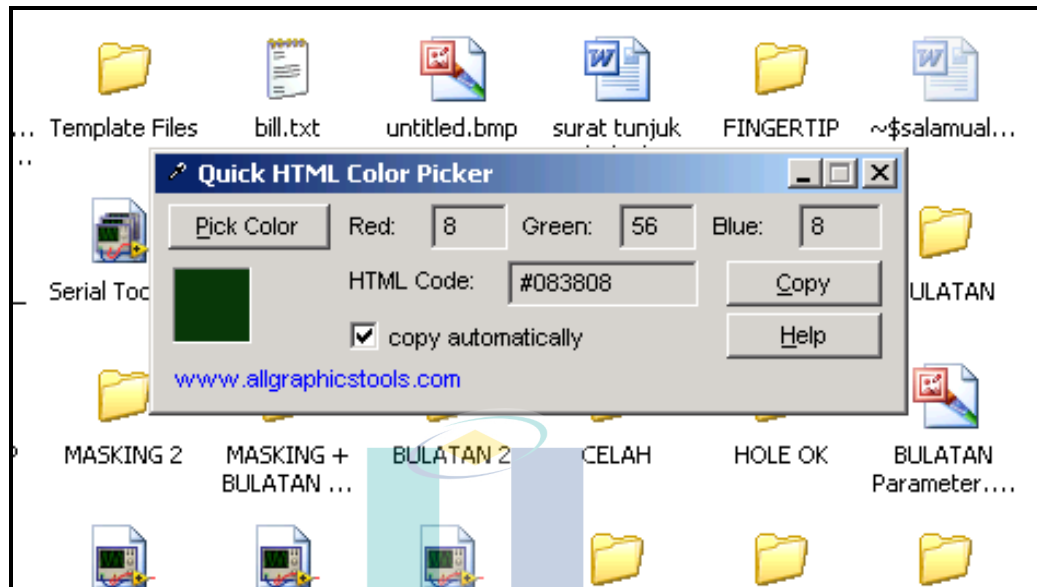


Figure 19: Color Picker showing green composites made up of 8 red, 56 green and 8 blue color channels



Figure 20: Back lighting imaging setup



Figure 21: Shown color image under backlighting effect

No.	Red	Green	Blue
1	41	24	0
2	24	12	0
3	24	20	0
4	33	20	16
5	66	44	16
6	36	33	33
7	57	28	8
8	44	21	8

Table 1: Example of hand's color composition samples

It is concluded that human skin contains dominant color of red, moderate number of green and a small or no number of blue channels. The intensity of the color was reduced to a smaller range. The table below is some of the values used for parameter settings. This is important for having thresholding value from color thresholding function. The best of this technique, the 32-bit RGB image will be changed to 2-bit binary image at once processing only. This is the type of image that can be used to take information out of it right away.

3.4 Process of Acquisition

Image Acquisition is actually referring to acquired by hardware available. Image processing system uses any hardware capable of doing image snapshots and grab continuous capturing ability. Acquisition in this context is the part responsible to acquire in input to be processed later. This input then be manipulated, processed and changed into useful information.

IMAQ is actually the abbreviation of Image Acquisition. Function that have IMAQ is actually refers to certain parts that responsible for doing image information capturing. The data stream of acquired images can be taken by discrete steps or continuously. This can be illustrated by VI below:-

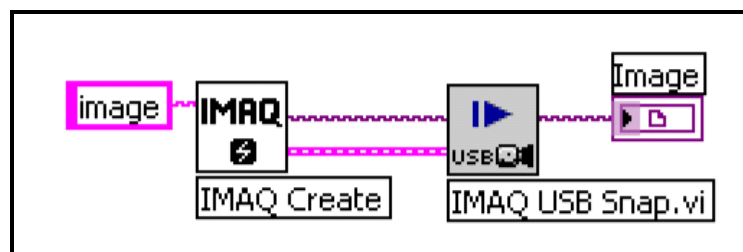


Figure 22: Acquisition using IMAQ USB Snap function

Snap function have the advantages over acquire to give sharper image and require less time for a given input to be processed. This project incorporates this VI instead of grab function. However, both can be used together for its own function.

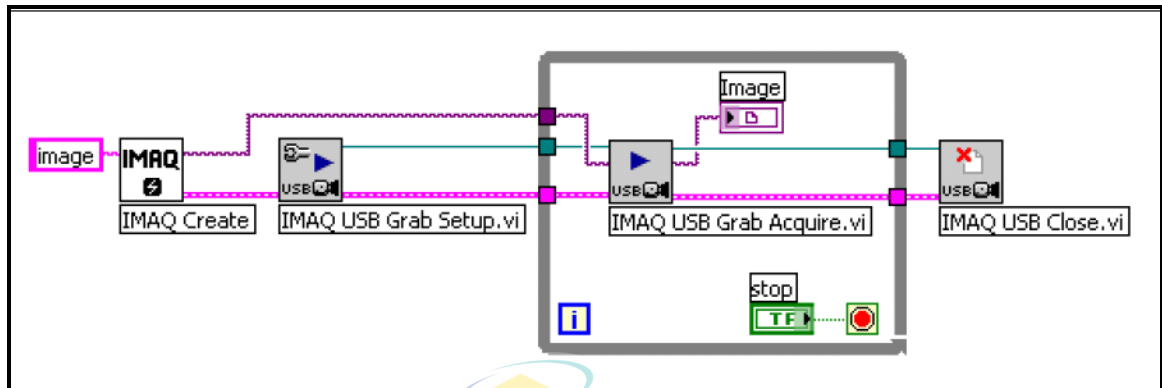


Figure 23: Acquisition using IMAQ USB Grab Acquire function

A grab is a continuous, high-speed acquisition of data to a single buffer in host memory. This function performs an acquisition that loops continually on one buffer [15]. Grab gives smoother images for displaying purposes.

The human's hands movement is suitable for grab whereas snapshot taken to be fed into system is suitable for snap. This is true as somewhat like our world such as audio signal appears to be analog signal, but to be taken into system it must be spoon-feed digitally.

Explained below are basic acquisitions in process whenever information from web camera is taken into software part. Because LabVIEW access hardware without anything and particular hardware resources needed to be freed, it is partly programming to engaging it as well. Manufacturer fancy and easy software are non usable except what the camera hardware side can do, that is snap and grab.

3.4.1 Initialize – engaging input hardware

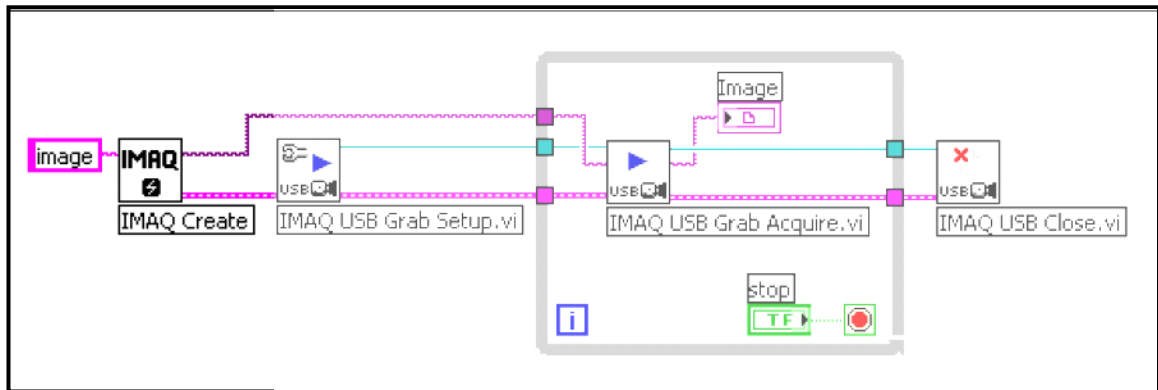


Figure 24: IMAQ create

IMAQ create responsible for having an image container and create the specific data to have a place in memory, name shown there as 'image'. This name is important as the memory is momentarily kept as a file.

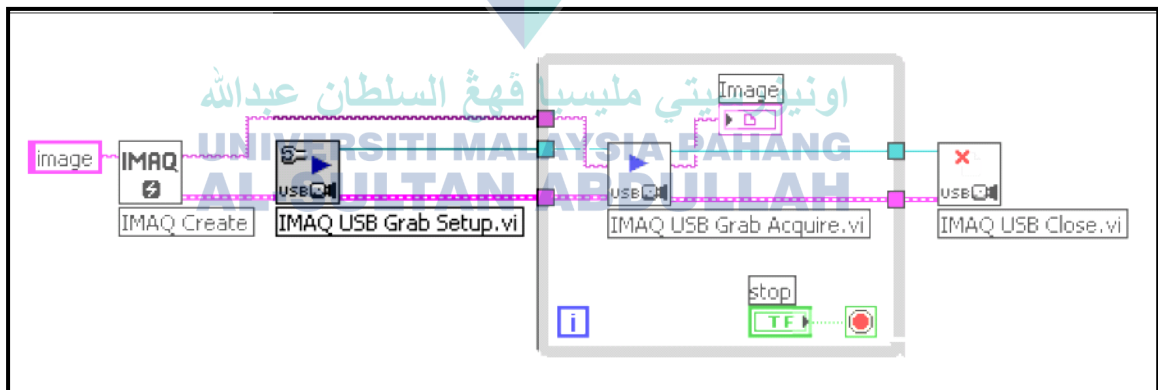


Figure 25: IMAQ USB Grab Setup

Setup is required to have automatically connected USB web camera with all the suitable settings. This is for doing the connection setup, thus if there are more features available from the hardware can be used if the programmer knows really well the data flow from the camera. The addressing has been explained earlier. Setup also determines how data flows from the sensor to LabVIEW programs created.

3.4.2 Acquire

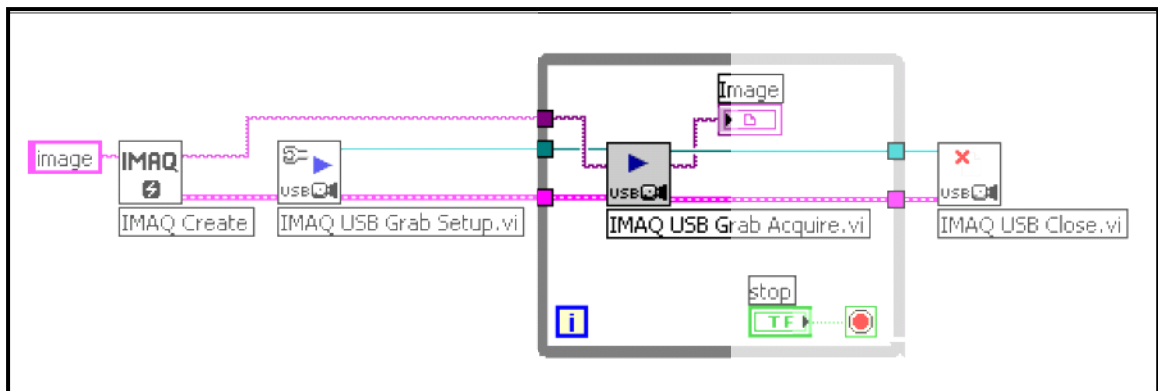


Figure 26: IMAQ USB Grab Setup

USB Grab Acquire will continuously acquire images in a very high rate at approximately 25 ~ 26 frame per seconds. This project acquires 352x244 pixels of RGB format images from Logitech QuickCam Express. Better response will not improve in anyway the system performance. This project is very much software dependent.

3.4.3 Use data

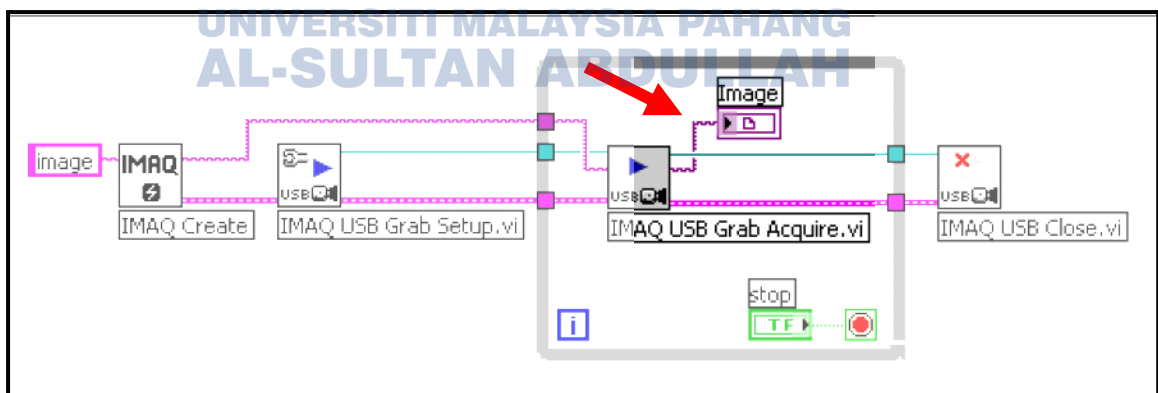


Figure 27: Shown are images being used as an indicator and being shown in front panel area

The information will be used for processing in background or being shown in front panel. There are control for inputting programming variables and indicator for displaying or give output to be seen in front panel.

3.4.4 Dump

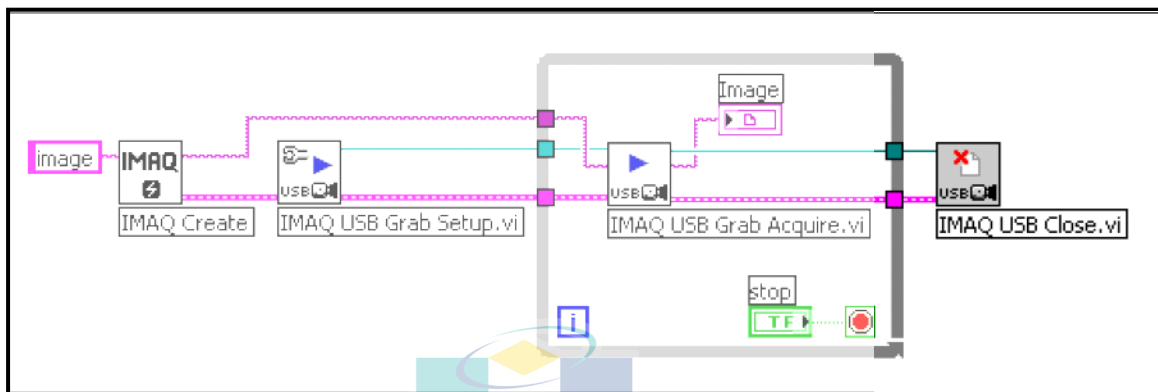


Figure 28: To free the cache to be used for the next image to fill or done before terminating application

After that, resources & cache used will be needed to be freed from the memory. This will enable it being used again for any other purposes or for properly terminating the whole program.

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3.5 Preprocessing & Processing

This step was done to generate a clear image that is only the interest to be processed out. This project was characterized into two main steps that is preprocessing and processing. This project was to apply temporal, where all acquired images will be processed. Thus there were neither minimizing the burden of preprocessing steps nor mechanism skip processing steps of an issue.

To have a clear advantage of normal recognition, all acquired images will be recognized, whether the user is performing a gesture or not. As a hypothesis, when

gestures are present and same as predefined, the scores of recognition is very good as high as 800 over 1000. In contrast, when there is no gesture, the processed gesture will leave no action state at all time. This is very tricky when it comes to a very bad environment as computer mistakenly identified none of the predefined.

The performance, will not be elaborated here will be most likely almost the same as the program will be going the same path over and over again. For more information on performance, please refer to chapter 4.

LabVIEW keeps a library or group of function in block diagram area as *Functions*. These functions can be used drag-and-drop to block diagram area. Image processing functions is kept under Image Processing sub library.

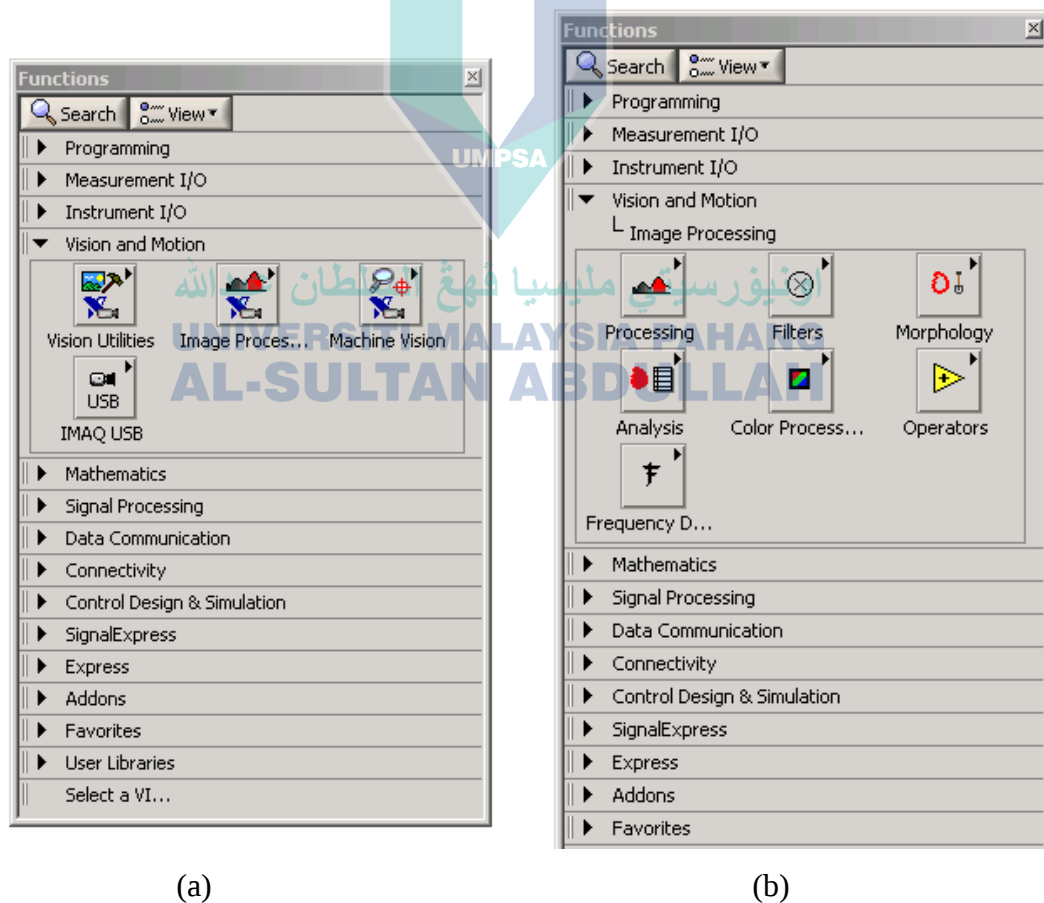


Figure 29: (a) Vision and Motion sub Library and (b) Image Processing sub library

The available have eight basic groups of functions. These processes are able to automatically recognized inspection. The groups are as follows: -

- i. Acquire Images
- ii. Enhance Images
- iii. Locate Features
- iv. Measure Features
- v. Check for Presence
- vi. Identify Parts
- vii. Communicate
- viii. Additional Tools

The steps are a basic process for all image processing. By using image processing, the capability is quite wide. Many other projects are being developed just to copy what human vision can do. If most the development is a success, all the things that human can do is no longer impossible to the robots and machine.

To have better understanding of the whole, this sub chapter 3.5 will be dedicated to explain in great details of each of each processing function use within this project's scope.



3.5.1 Preprocessing

Preprocessing is the amendment process to filter out what is the region of interest or area necessary to be take feature out of it. This step has nothing to do to improve machine vision's readability on specified system. It does however, to pin point the location of hand, the object of interest of this project.

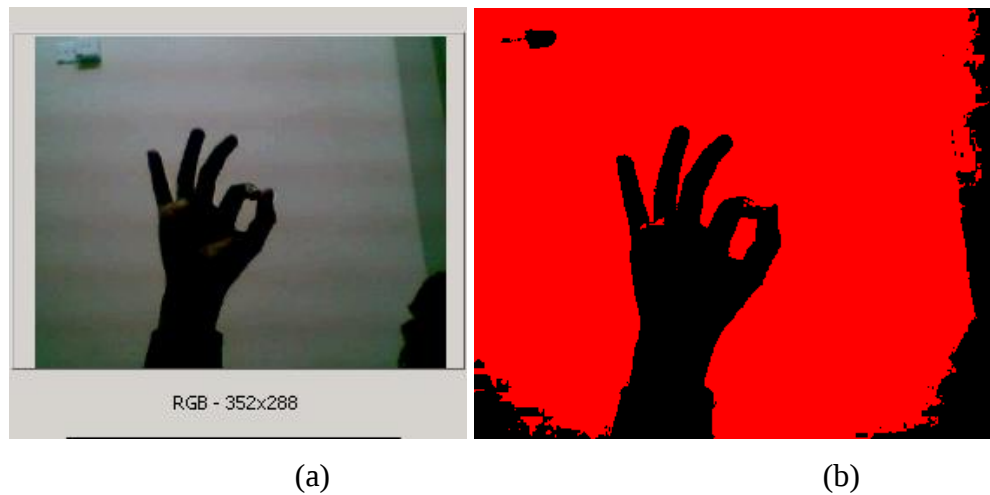


Figure 30: Image Processing Steps (a) Image Acquisition, shown RGB type with resolution of 352 x 244 pixels (b) Threshold

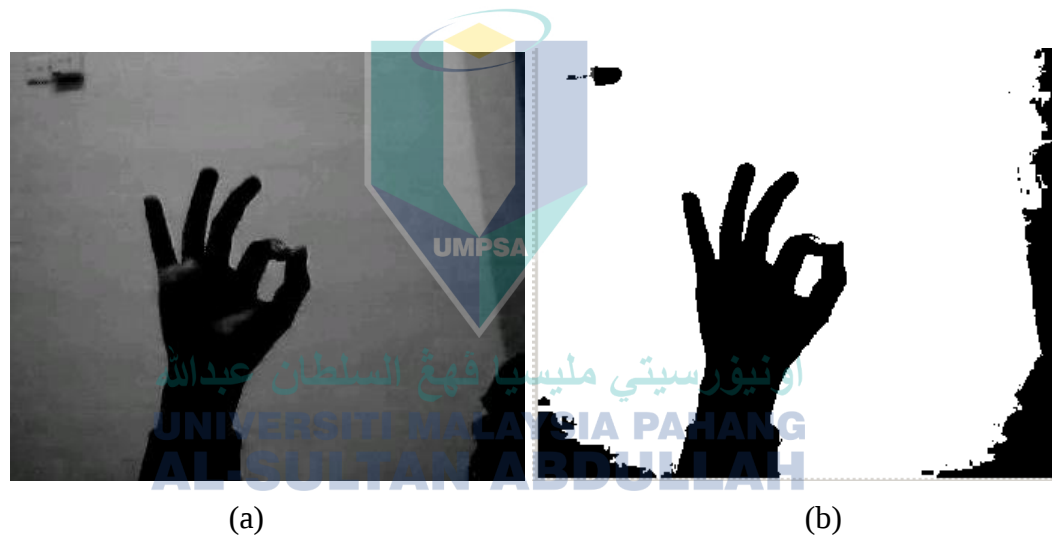


Figure 31: Image Processing Steps (a) Remove small object (b) Lookup table

Image Processing Step Applied

1. Extract RGB – Red Plane 1
2. Threshold 1 – Auto threshold: Inter Variance
3. Remove Small Object – Iteration: 3, Square, Connectivity: 4/8
4. Lookup Table – Equalize

This is crucial to have an image usable for the next step. Next to have



Figure 32: Image Processing Steps (a) Inverse Binary Image (b) Particle Filter

Image processing step applied

5. Inverse Binary Image
6. Particle Filter - % Area/Image Area, Keep: 10-100%, Conectivity: 4/8

By using particle filter, the image is very much ready to be processed. Resultant image were very clear of anything besides biggest binary large object between 10 ~ 100% of the whole area. The end result of this step determined how high the accuracy should be as it goes to the next steps that is feature extraction processing.

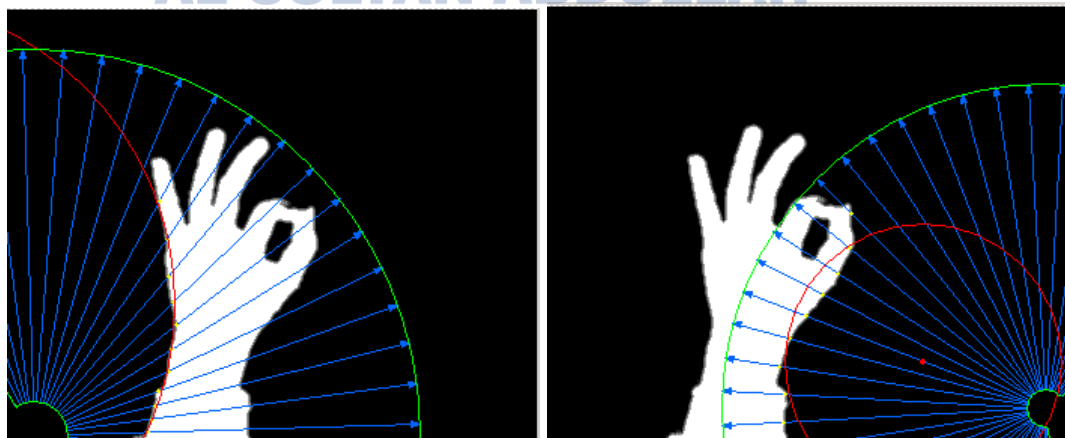


Figure 33: Image Processing Steps: Find circle

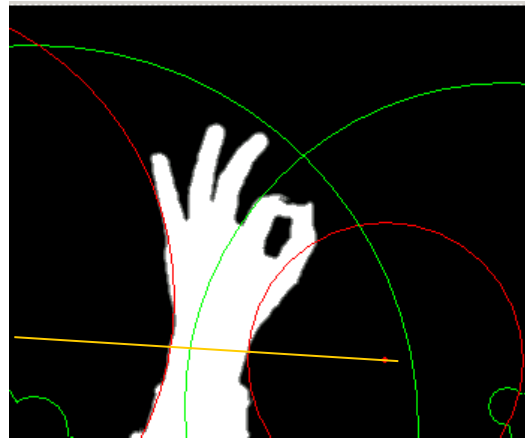


Figure 34: The processing finds circular edge perfectly crops at yellow line marking.

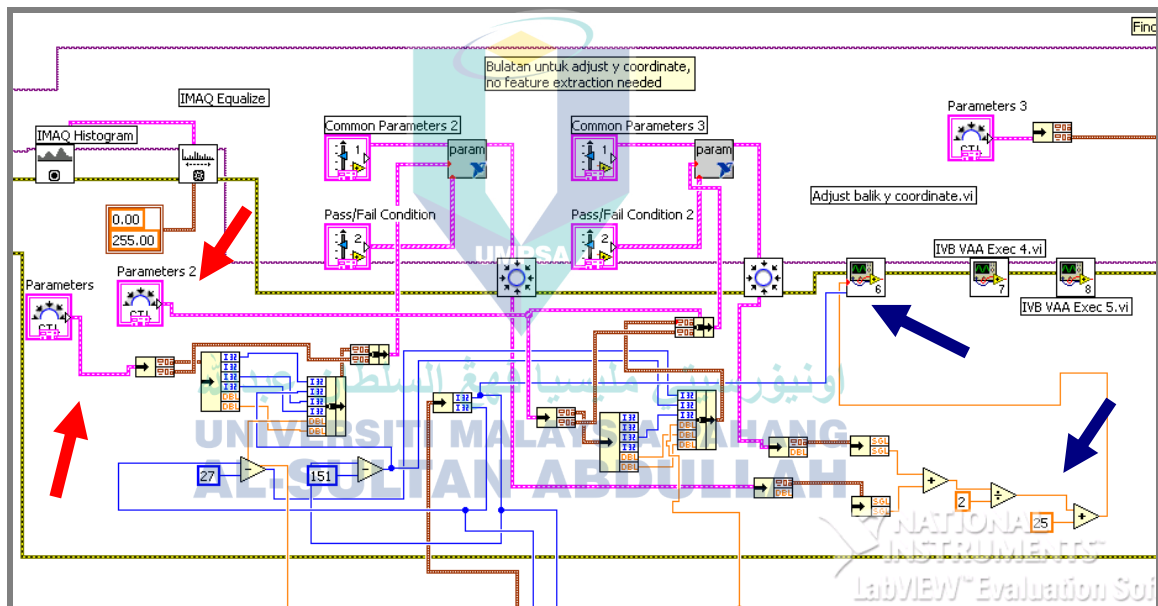


Figure 35: The automated masking and bottom y-coordinate for detaching arm with surrounding particles (red) variables input (blue) new y-coordinate

The mid-point between two were taken by additional pixel to have it not to cut too much. Thus, leaving some part of arm that is too small to sway output information.

Finding circular edge are for having average height of the centre of the hole to cut a little bit at bottom of y position in order to discriminate arm area with the

surrounding that may have connection to arm. This step brings better accuracy of hand's area without most of the arm area. This step used to give a better approximation if the center body mask used in find circle, feature extraction. Below are the same step processed on a bigger sample of 640x480 pixels RGB image file. When bigger image were used, the area is absolutely bigger, where the percentage will have very much the same amount. This process successfully cropped y axis only its algorithm also shown in figure 36.

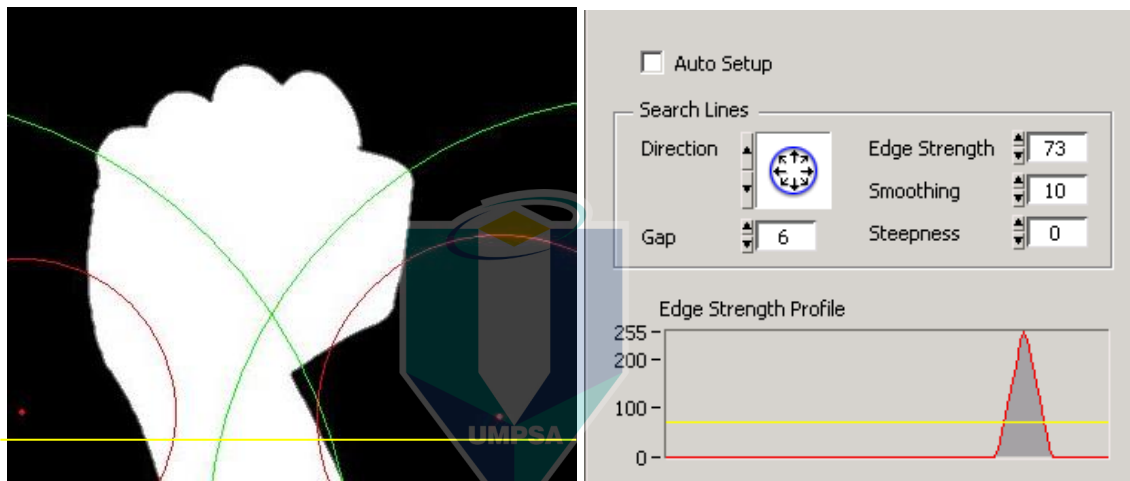


Figure 36: This test image of 640x480 pixels is also compatible with the processing

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3.5.2 Processing

Processing is to override the current image to an enhanced version. These steps were done to optimize the system performance when feature extractions were made upon. This involved process apply contrast or to filter out noise. Processing was also made at processing level. Pre-processing and processing can happen between each other and does not bounded with sequential operation. Both are used to complement each other and at the same time both serve different function.

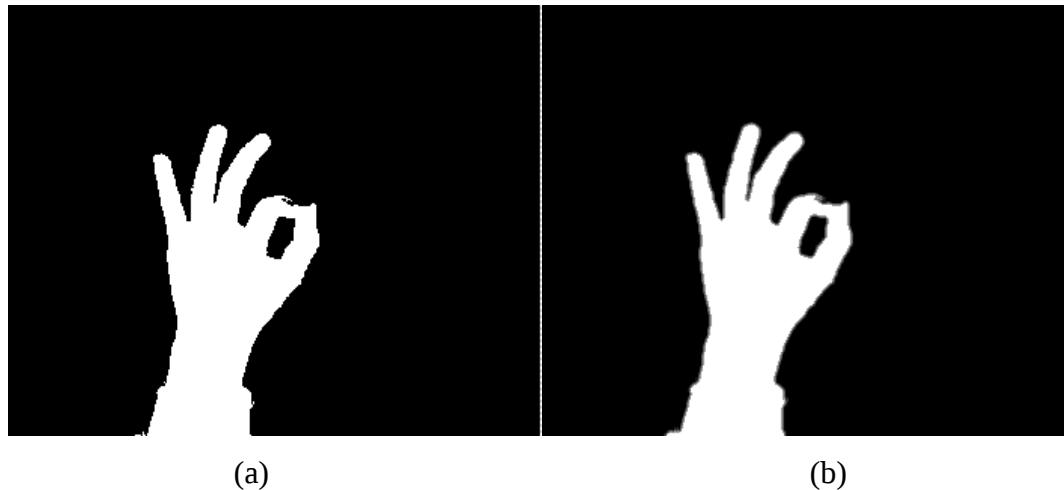


Figure 37: Image Processing Steps (a) Threshold (b) Smoothing

Image processing step applied

7. Lookup Table – Equalize
8. Smoothing – Low Pass 1, Filter Size: 3x3

Smoothing will have an enhanced number of pixel deviations. Where the number will most likely be lower and increase the chance of the step for feature extraction such as *Find Circular Edge* to have pass state.

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3.6 Feature Extraction

Programming has never been easier with graphical programming. Even with a very easy way of coding, programming must be followed by a good practice to ensure readability and neat program. Programming tends to contain error that needed to be carefully corrected in order for it to work.

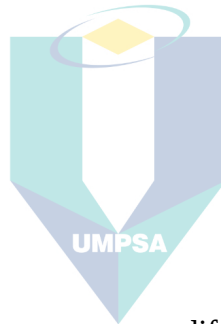
Pattern matching for fingertip have an output of position, angle, scale, score and bounding box. All of this parameter has been under careful consideration and to have score within acceptable margin. Trial and error first, then modification to perfected the template and tweaking the parameter to give optimum score whether to fail or pass

inspected feature. Too easy on detection parameter will have many data to consider and increase error on output state.

Most of the considerations were made under automated inspection within Vision Assistant environment. Unfortunately, there were slight differences when comparing data with the actual system completely under LabVIEW full programming. This might occur because of differences in versions and refined function.

The parameter determined to be most unique are as follows:-

- a. Circle
- b. Wedge
- c. Fingertip
- d. Hole



3.6.1 Conversion Process

LabVIEW function gives output way different from *Boolean* logic format. The data can be in cluster such as positions have the x-coordinate and y-coordinate each. Each position is an array of positions of every object available.

3.6.2 Find Circular Edge

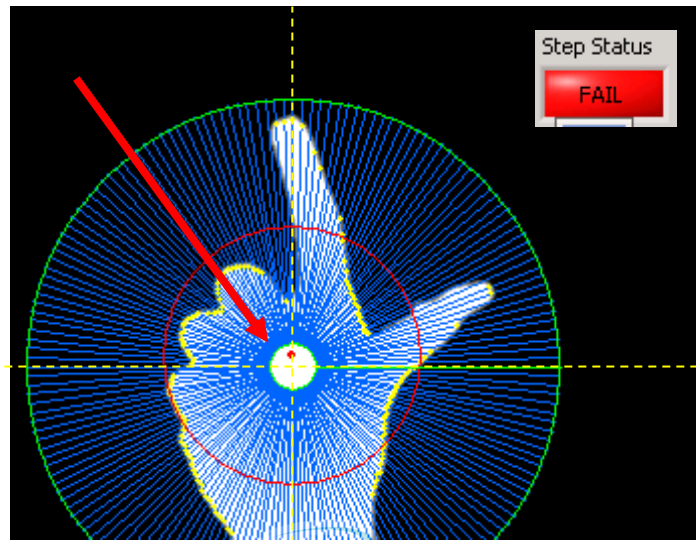


Figure 38: Outside deviation (arrow) Note the position of centre

The pixel deviates away too much because the finger was present.

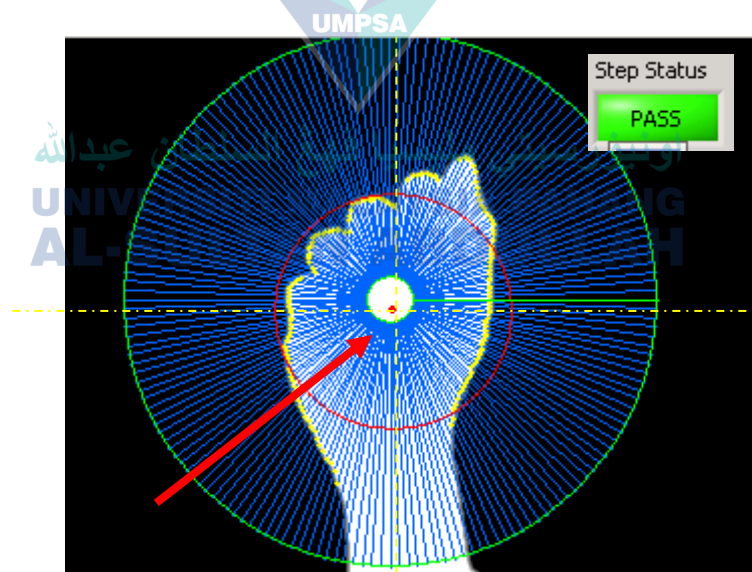


Figure 39: Within deviation (arrow) Note the position of centre

The system is designed to have a dynamic variables so the system is more automated than in the whole inspection vary depend on center body mass taken from

Particle Analysis data. This automated processed have been tested with different picture, and different size apparently of 640x480 pixels.

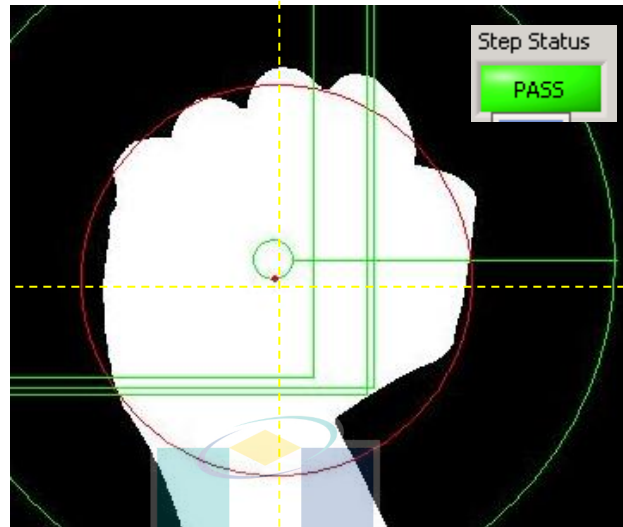


Figure 40: Within deviation (arrow) note the position of centre

Find circular edges appear to be finding clear edges. By having gap decrease, the roundness of object to evaluate also increases.

3.6.3 Pattern Matching – Fingertip Detection

All pattern matching regardless of what to match with, uses the same method in order to carry out detection of feature. To have a match, feature to be found must being compared to a template as. This thesis uses the word pre-defined as indication of average look of what to find. This template must be selected from the most prominent image to show important details of thumb or fingertip taken from the same hardware in this system. For fine tuning, the picture selected was being trial and error method.

To understand how NI Vision Assistant do their observation. To have equally good scores for most given acquisition, it must have normally with score greater than 800. The template can be selected randomly from any picture inside vision assistant. All

templates are stored in PNG files of height and width very small to increase speed in calculation and to produce 8-bit or binary image containers.

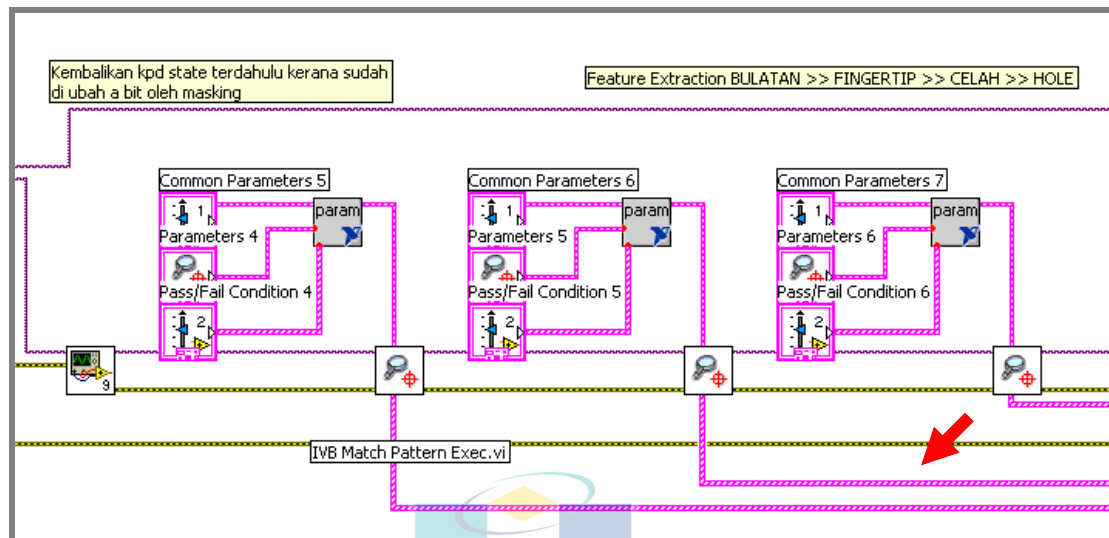


Figure 41: Fingerprint Detection Row 1 (arrow) Feature Extraction Data Out

Most of hand gesture recognition systems since the year 1992, the first attempts were made to recognize hand gestures from color video signals in real time [17] was fingertip detection. It is proven to be the only feature that did not appear twice (in the meaning of occurrences) in human hands. This project also uses fingertip as the main feature to be detected thus can freely be regarded as fingertip detection. This matter is carefully being raised as the needs to detect fingertip remain the decision factor and can affect the decision making process. Whereas other feature such as wedge, hole and circle will affect only certain predefined gesture and if it does appear in any other gesture, the decision of having it present be neglected if not necessary.

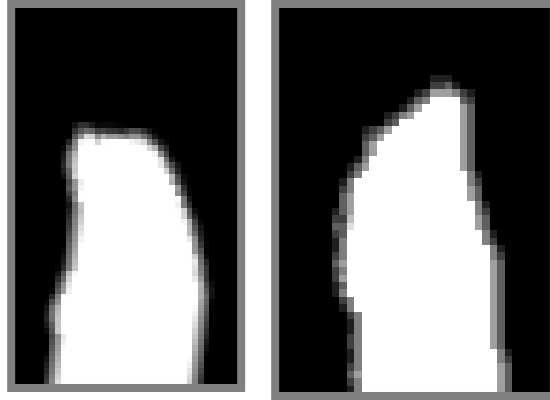


Figure 42: Thumb recognized as fingertip

Early development of this system, fingertip and thumb are separated as for human bare eye, it has distinct differences. As compared to the picture below:-



Figure 43: Fingertip used as master template

The feature must appear to be unique. No connection should appear (referring to black area in figure 42 and figure 43) to surrounding. The black area is actually holds 0 value of pixel location.

3.6.4 Pattern Matching - Others



Figure 44: Three fingertips were detected

Three fingertips were detected for having score over 800. As shown are 975 points matched, 984 points match and lastly 982 points. These template matched is said to be almost as identical as predefined template.

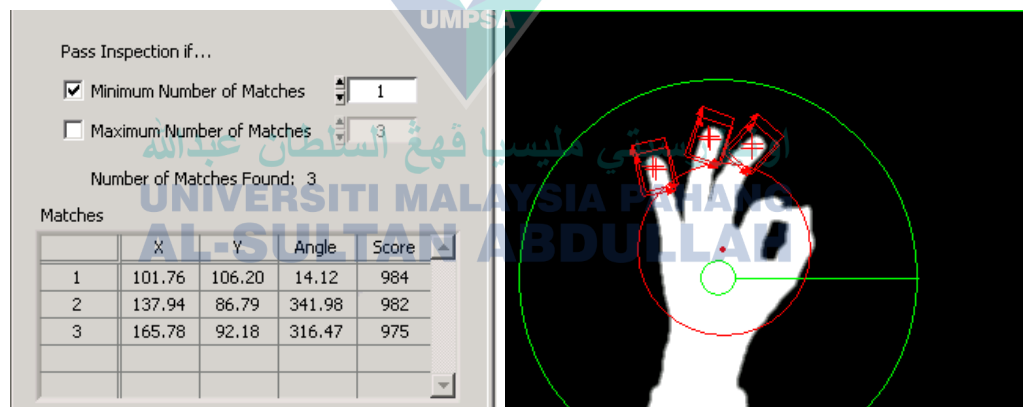


Figure 45: Three fingertips and a circle were detected with score, angle and location

As shown feature output with all the information taken out from a specific template detected. Among the criteria to be met so that the output would be true is the orientation. Shown in figure 46 the origin of NI LabVIEW system is not as usually used in daily life. Need to be pinpoint here this is machine translation. It is the default (0, 0) origin coordinates for any image files. That is actually not a problem as machine states

the top and left as the origin and the other two as bottom and right as the maximum width and height. This refers to maximum resolution of acquired signal.

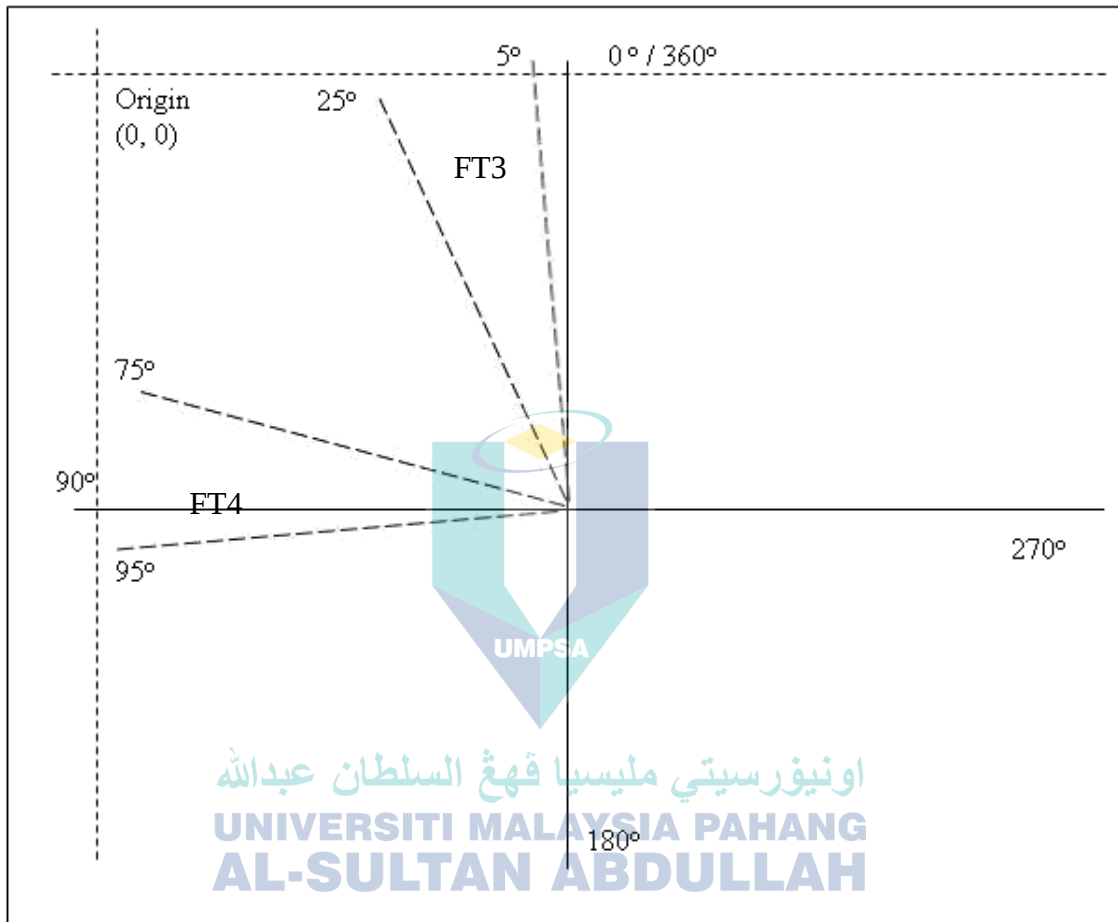


Figure 46: Shown coordinate system and FT3 and FT4 criteria

FT3 will show hold true logic if the template is within deviation between the angle of 5° to 25° and FT4 will hold true logic for any template detected within the angle of 75° to 95° . Data was taken from and being evaluated under decision making section. This is why there is a close relation of feature extraction section with decision making module.

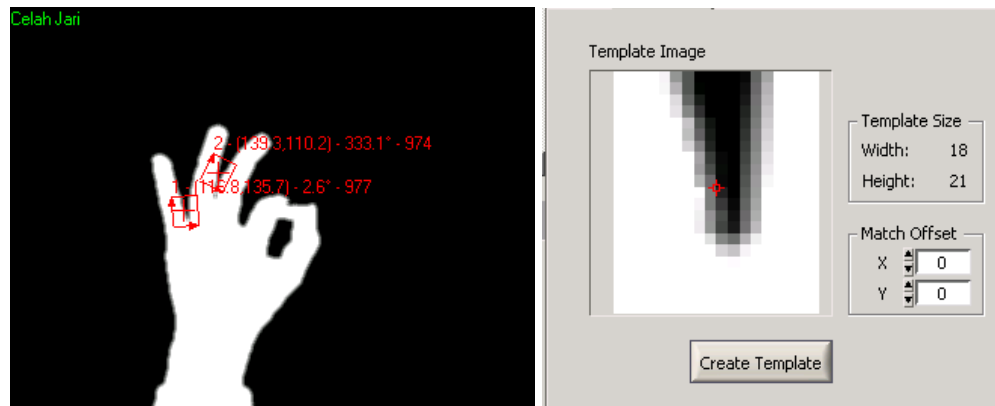


Figure 47: Two wedges detected with template shown

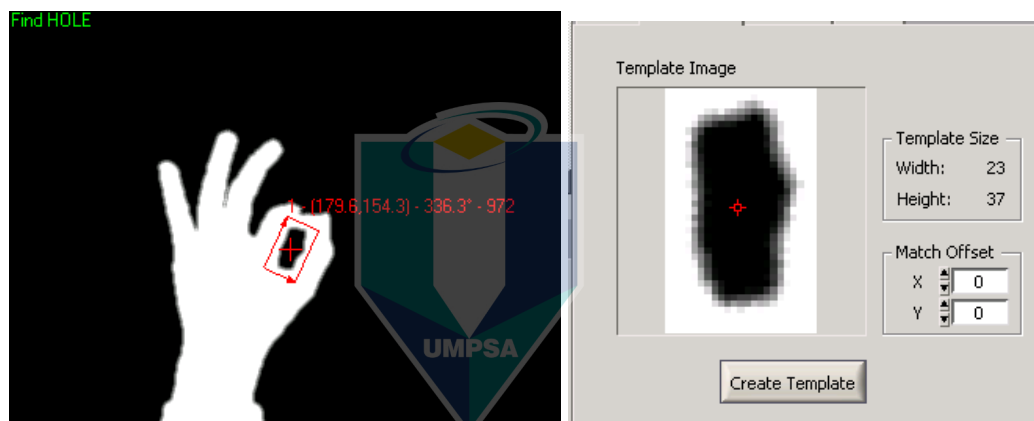


Figure 48: A hole detected with template shown

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3.7 Decision Making

This project implements fuzzy logic in decision making module, where all data analyze will be fuzzy logically output certain decision.

The decision is simple, that are:

1. no action
2. on / off
3. play
4. pause

5. fast forward
6. fast backward
7. volume up
8. volume down

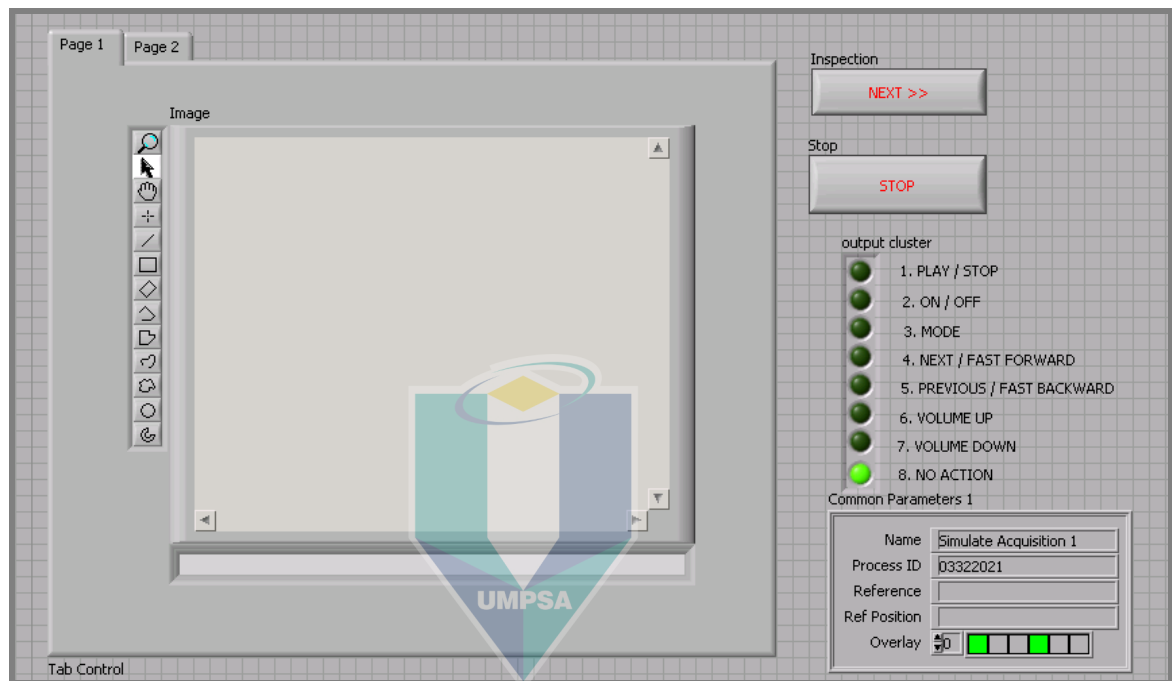


Figure 49: Front Panel of the system including decided action

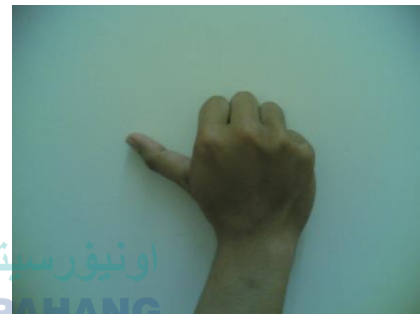
The decision have eight considerations, to put in binary system is 3 bit consideration. Since this project is all about developing a recognition system, it will be classified into four main group to fraction it down for easier fuzzy logic coding. This is in respect to three group of two, which have identical gestures.

The first two bit will classify what group of two it will be. These four groups are as follows:

1. *Boolean* of 00x for no action / stop gestures



2. *Boolean* of 01x for pause or resume / fast backward gesture



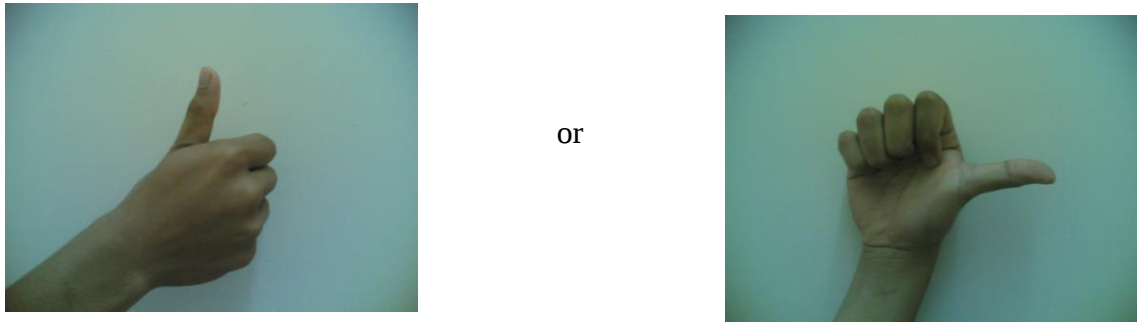
3. *Boolean* of 10x for volume up / volume down gesture



or



4. Boolean of 11x for play / fast forward gestures



All four groups will don't-care the third bit values. When these four classifications succeeded, this system will have 12.5 % accuracy. This action is also known as Data Clustering.

Fine tuning recognition only needed for these two gestures.

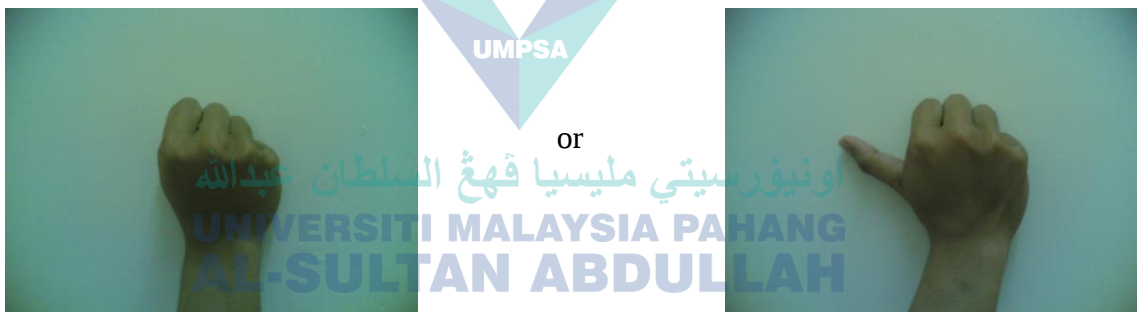


Figure 50: 01x for pause or resume / fast backward gesture

There is not much different except the absent of thumb. Both have slightly referring to the same gesture, but there is differences needed for the system to detect. This includes what object, other information that can be incorporated with such as position and bounding box. These features will help to decide is it appearing to be one on the other. In another example below:

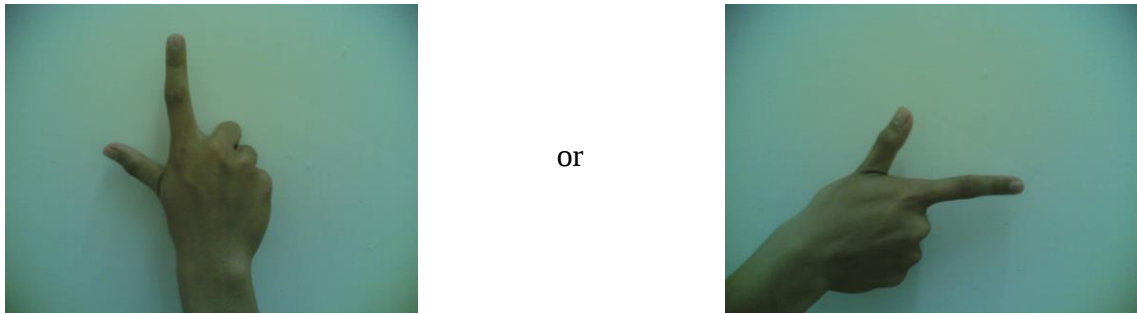


Figure 51: 10x for volume up / volume down gesture

The different is also not much except the orientation the object. Deep into recognition matters, the most machine vision task can be fulfilled is by presetting reference image and pattern matching.

From all, generally no arm is being taken into consideration. It is also wise to build a system that determined by web camera at a base of a table and user input gestures by laying his/her hands on the sensor's equipped table. This is possible with assist of external lighting and wide lenses. It is not used considering the hands location can be anywhere inside a car. Fixed position will not make gesture input as an easier choice. The purpose for easing will not be reached.

This simple making of the definition will easier guide programmer to go deeper with advance fuzzy logic programming. To go briefly into fuzzy logic, the rule if x and then y then z is used as a general rule. Only one criterion to be met, all definition is represented in numerical values.

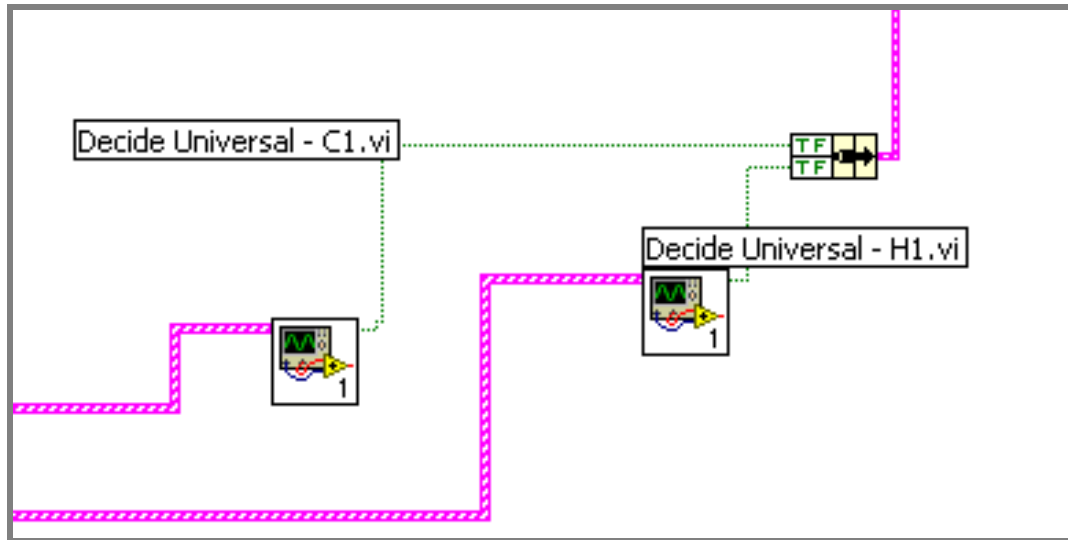


Figure 52: C1 and H1 logic from Decision Making for Circle and Hole respectively

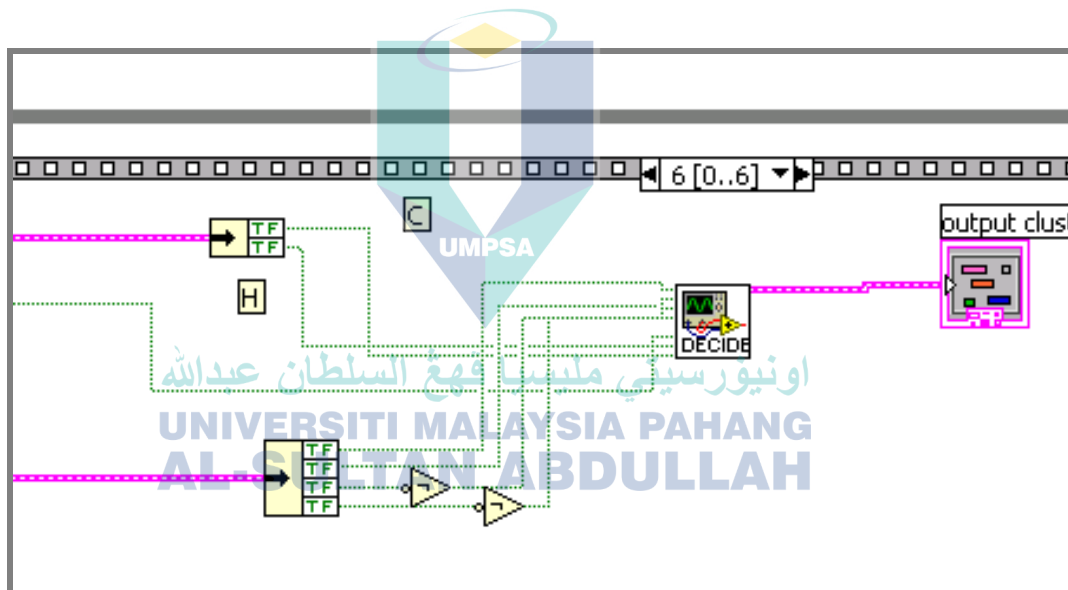


Figure 53: Overall Decision Making to the output cluster of LCD

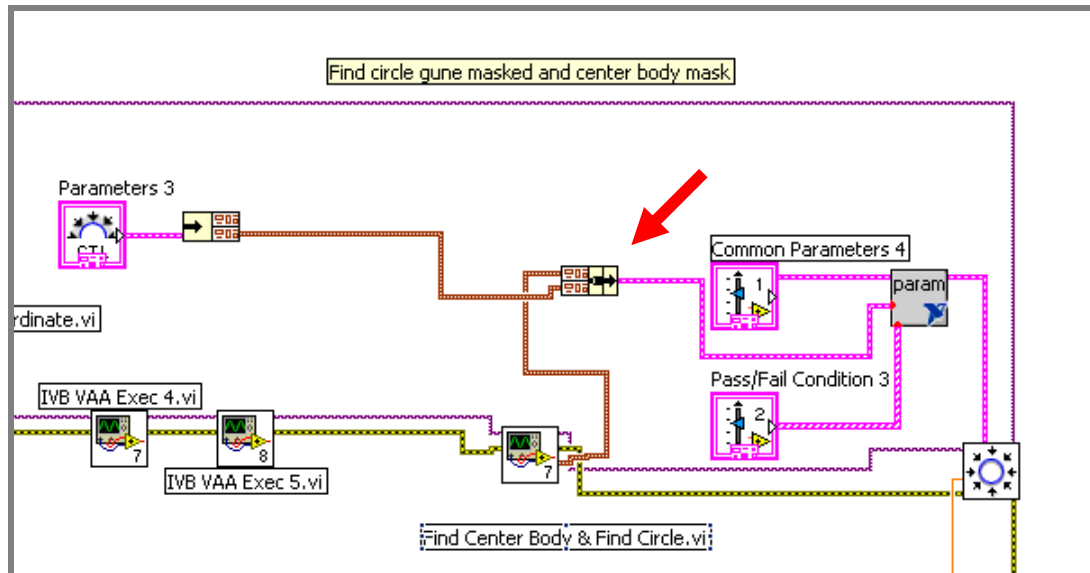


Figure 54: Modified parameter of x and y coordinate for find circular edge

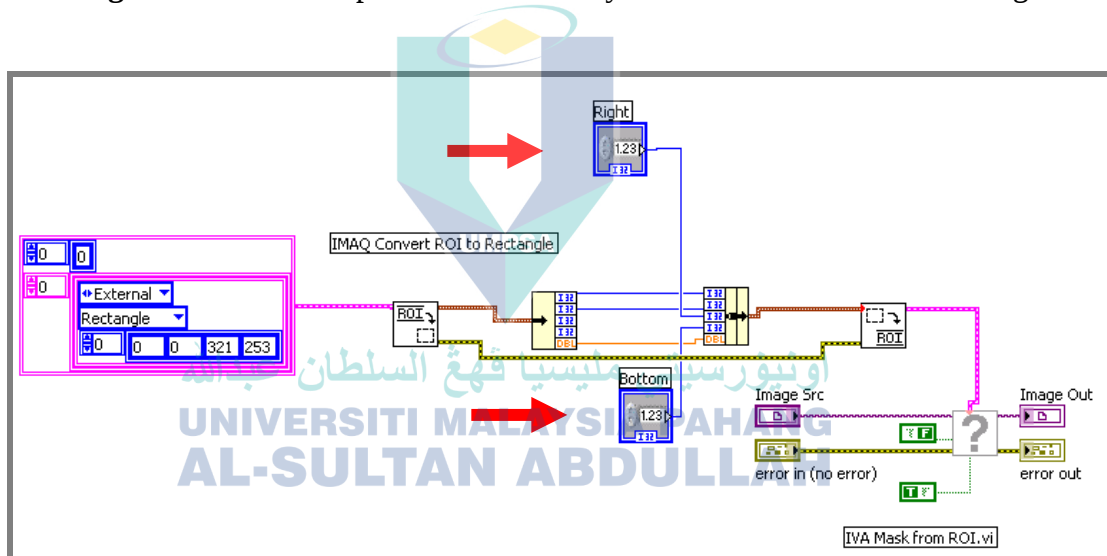


Figure 55: Re-injecting new x and y position for find circle

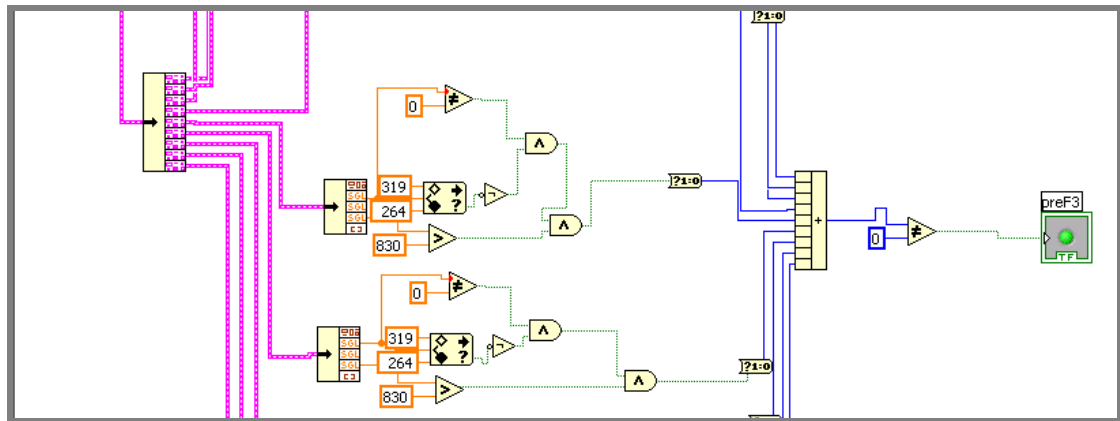


Figure 56: Position, score, bounding box, angle and scale

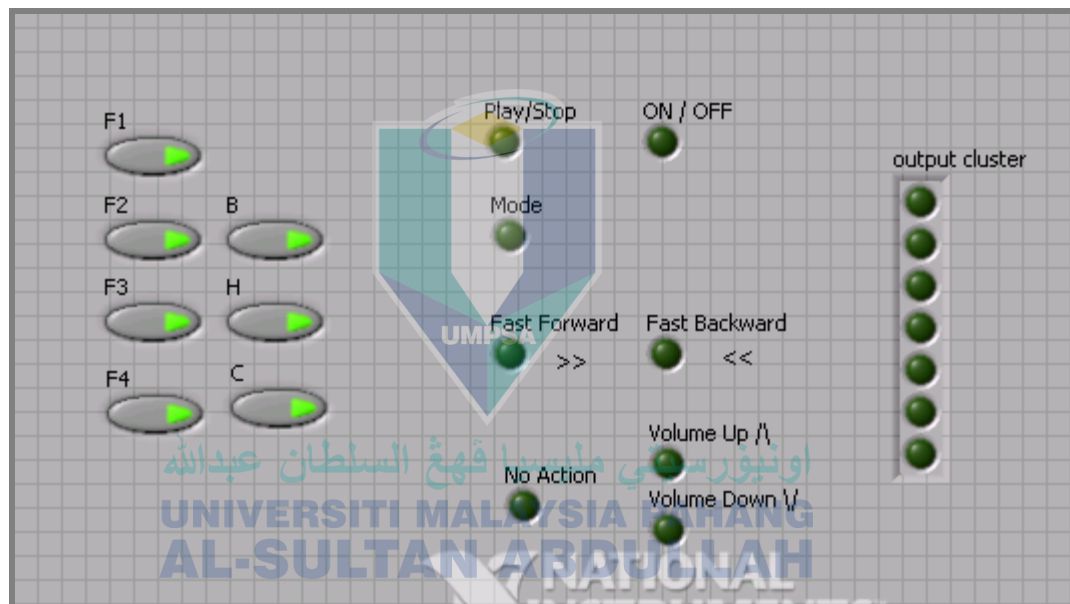
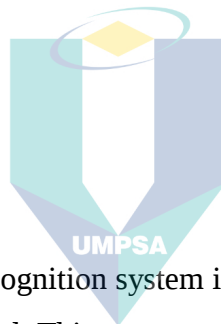


Figure 57: Improved Decision Making front panel

CHAPTER 4

RESULTS & DISCUSSION

4.1 Introduction



Performance of any recognition system is by the degree of precision of any given signal fed into it and recognized. This system emphasis more on fingertip recognition as the main feature to be evaluated thus requires a comparison to available system using the very same method as well. This also include how fast the system can compute to churn out last bit parameter completely to Boolean logic then to decide what to do.

Precision for this system is very subjective. This system is made very loose in evaluating correct parameter output. To detect many blobs, it is held on algorithm to filter out only the highest probability of gesture and the quality of acquisition is it can or not take it up into decision process. Fingertip system available outside can have the very good result up to 90 over percent.

4.1.1 System Performance

This system was evaluated by having the calculation to a very big sample size of any picture, regardless of output it made. The system capable of doing 450 ~ 500 ms or approximately 2 frame per second. The speed calculation was also being made under Vision Assistant Environment. The actual calculation time vary between images acquainted. Some processing takes more time than the other, and this also apply to images information type and size. This project feeds on JPG files, a compressed version of BMP files and RGB color set.

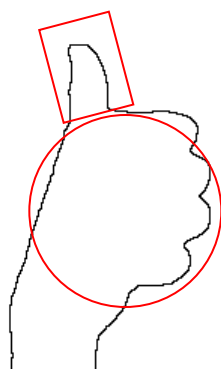
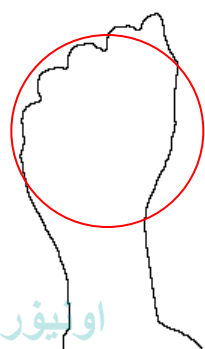
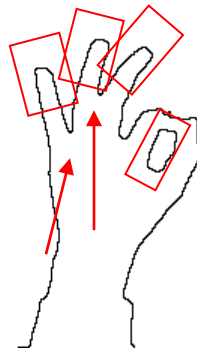
This project is considered successfully if only both of decision making can decide out from the acquisition, processing and anything else are working together wonderfully. Beside that, the key performance indicator for this project lay on the percentage of successfulness to translate gesture given into command with minimal acceptable error margin. The gestures include no matter what size, background, noise or lighting condition, the system still work together. To have this done is the most challenging part of all.

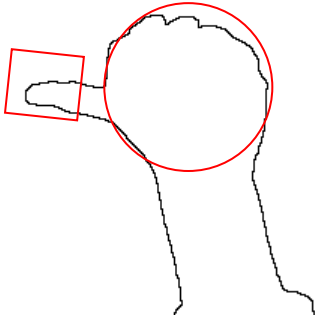
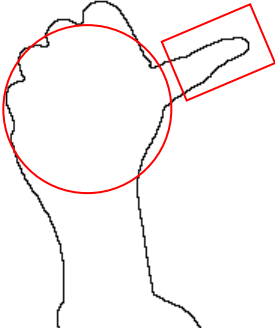
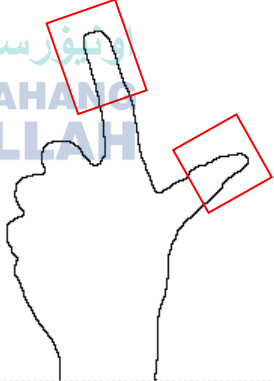
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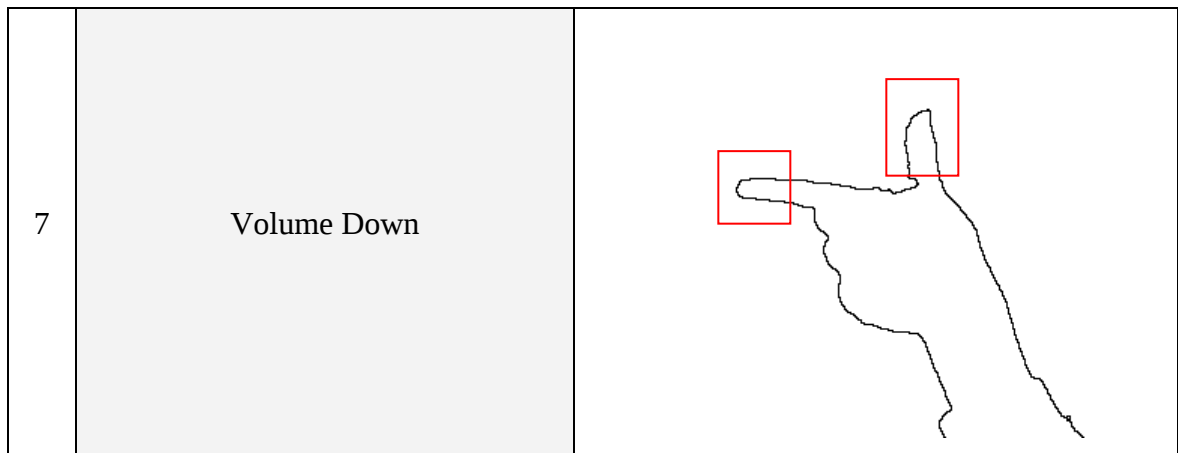
4.2 Discussion

This project must have an output no matter what. The last improved decision making VI was tested by running continuously and proven to be giving only one input at any given time. At the gesture not detected, the algorithm found none and the scores are low, no action will active. Other than that, only one will active above 7 possibilities.

Table 2: Feature Extraction Summary

No	Description	Gesture
1	Play / Pause	
2	ON / OFF	
3	Mode	

4	Fast Backward	
5	Fast Forward	
6	Volume Up	



Shown is the finalized decision making *Boolean* rule to follow. Notes there are too many don't care everywhere. This give the system flexibility upon evaluating any hand gesture fed into it.

Table 3: Decision making truth table

Boolean \ Gesture	1	2	3	4	5	6	7
FT1	T	F	T	T	T	T	T
FT 2	F	X	T	F	F	F	F
FT 3	F	X	F	T	T	X	F
FT4	F	X	F	T	F	F	X
C1	T	T	X	T	T	F	F
H1	X	X	T	X	X	X	X
W1	X	X	T	X	X	X	X

Remarks

FT: Fingertip

C: Circle

H: Hole

W: Wedge

Any result other than on the truth table will return to no action. As seen in the above table, result is very much depends on how much feature detected within the system. This project at evaluation phase has a cumulative of 246 samples each represent varieties of gesture. There are only 7 gestures whereas the eighth is going to be the only decision when the detection didn't return any results. Among the 246 samples, for astounding 175 were rejected as having to heavy background, giving for only 71 samples to be used. All samples are included in the DVD attached at the back.

4.2.1 System Limitation

Table 4: Result for feature recognition

No	Feature	Results	Comment
1	FT1	65/71	Problems at gesture number three, attaching particle regarded as detached features especially at low score as predefined settings.
2	FT2	65/71	
3	FT3	65/71	
4	FT4	64/71	
5	C1	59/71	Return very tricky, need some advance detection
6	H1	63/71	
7	W1	57/71	Worse when unwanted background available.

As refer to earlier discussion, this feature will be evaluated functional and effective (denoted as how many per the sample size) if it turns true when feature available and turn to false when feature unavailable.

Wedge turn to be the worse as almost anything can give illustrate wedge shape in particular. The predefined matching is very lenient as the location can be almost anywhere. There are gesture than cannot filter out all the background noise and left out only the gestures, that is where wedge detected too much as the background became them.

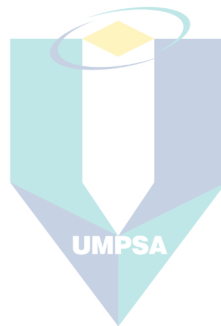
Most of the acquisition for bigger sensor sized image return zero. These parts still needed to be refined in the future. Fingertip is very effective. It turns to be if the FT1 is okay, the FT2, FT3 and FT4 will be okay as well. The only different is at the orientation and how many were detected. The only problems occur when attaching particles are declared as fingertip as well.

Table 5: Result for gesture recognition (Please refer table 2 for gesture number)

No	Gesture	Results	Comment
1	1	34/71	
2	2	37/71	
3	3	24/71	
4	4	27/71	
5	5	34/71	
6	6	0/71	Decision making problems
7	7	0/71	Decision making problems

This result is much easier as it can be observed by the front panel. This project comes with a live acquisition version, however is it not comfortable to take measurement when it is in live mode as this system return output very much faster than taking measurement. The outcome is very positive despite limitation under certain lighting condition and for having almost blank as background. This part of evaluation

will evaluate functional and effectiveness (denoted as how many per the sample size) if it turns true when gesture match what have been given and turn to false when gesture unavailable. The numbers a quite low, but by looking at the earlier table of feature extraction, detecting more feature and improved decision making programming rules is a good idea.

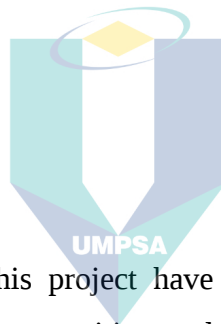


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CHAPTER 5

CONCLUSION

5.1 Conclusion



It is concluded that this project have successfully achieved its objective by having a complete system of recognition and be able to deliver output to respective device. However, there are plenty of rooms of improvement especially in processing and training for this purpose. The system can be developed to do additional processing where needed or to bypass unnecessary processing. This can be accomplished by using artificial intelligent programming. The numbers of sample should be improved in the future. This problems lies at sample collection that turns out saving picture on the same file over and over again. At last, the only solution is to acquire input images manually. Interfacing between software and hardware should address the usability of widely accepted standards such as serial and parallel communication or even a USB port.

5.2 Future Recommendation

It is hopefully this project could reach end with a success of a minimum error working system. This project is hopefully being used for the following:

- i. To be used as a basis of motion processing. These include conveying information with not only capture function but also grab function, available in LabVIEW.
- ii. To be later assist the advancement and courses on advance usage of LabVIEW programming environment especially attached with Instrumentation & Measurement subject. The subject is available in electrical, mechanical, civil and chemical engineering
- iii. To be used coupled with technology such as holographic technology.
- iv. To be used as a video editing software that use motion input to control the editing process and fixed to timeline functions.

It's a very good start for having advance usage of image and motion processing and analysis in the future.

5.2.1 Cost & Commercialization

The cost impact for a recognition system can start for as low as RM 130 to a few thousand ringgit. As reflected for this project the cost is very low. This includes assumption of the interested party have a personal computer and LabVIEW software installed and running at their disposal.

For a web camera will only cost not more than RM75 per unit. For the autotronics parts, the pricing for simple circuitry hardly exceed RM50. The cost of overall system will be much if higher performance devices were used such as IEEE-1394 cameras or Line Scan conveyor belt camera. These cameras were design to cut processing time by having some optimum imaging function built from the hardware

section. In some design, high performance camera is more cost effective, as the general rules are all varied.

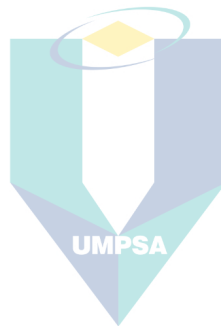
In industrial application, very fast camera not just the only option when encountering abundant pending vision tasks. Using multiple camera arrangement can also achieve the same results to complement with the software part. IEEE-1394 for example has the capability to be used in multiple acquisition arrangement. The performance of the camera is also good. The cost for a firewire cameras vary from RM300 to RM500 based on its functionality. By having setting up multiple cameras with firewire devices, a multiplexer will be added to complete the system.

Table 6: Cost impact

No	Item	Per Unit (in MYR)	Qty	Sub total (in MYR)
1	LabVIEW Base System for Windows with 1 Yr Service (English)	4 748	1	4 748
2	NI Vision Development Module Ver 8.5, Includes 1 Year SSP	13 064	1	13 064
3	NI Vision Run-Time License	1 184	1	1 184
4	Autotronics control circuit	67	1	67
5	Web camera	75	1	75
6	Advantech DAQ Card	3 000	1	3 000
			TOTAL	22 138

As for looking of limitless capability, it is a viable investment to be made. If there is enough time, more time can be used to enhance the capability of the whole

system. The purpose of this sub chapter is to support informed decision before selecting to spend on any particular software for development purposes.

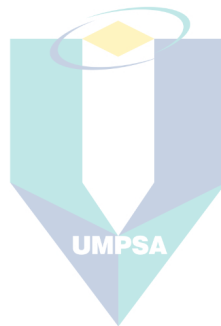


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PCI-1710 PCI-1710HG

**100 kS/s, 12-bit, PCI-bus
Multifunction Card**

**100 kS/s, 12-bit, PCI-bus,
High Gain, Multifunction Card**



Features

- 16 single ended, 8 differential or a combination of analog inputs
- 12 bit A/D converter, with up to 100 kHz sampling rate
- Programmable gain for each input channel
- Free combination of single ended and differential inputs
- On-board 4096 samples FIFO buffer
- Two 12 bit analog output channels
- 16 digital inputs and 16 digital outputs
- Programmable pacer/counter
- BoardID™ Switch
- Short circuit protection

Introduction

The PCI-1710 Series are multifunction cards for the PCI bus. Their advanced circuit design provides higher quality and more functions, including the five most desired measurement and control functions: 12-bit A/D conversion, D/A conversion, digital input, digital output, and counter/timer.

Specifications

Analog Input

- Channels 16 single-ended/ 8 differential (SW programmable)
- Resolution 12 bits
- Max. Sampling Rate* 100 kS/s
- FIFO Size 4096 samples
- Overvoltage Protection $\pm 30V_p$
- Input Impedance 1 G Ω
- Sampling Modes Software, onboard programmable pacer, or external
- Input Range (V, software programmable)

PCI-1710/1710L					
Bipolar	± 10	± 5	± 2.5	± 1.25	± 0.625
Unipolar	-	0-10	0-5	0-2.5	0-1.25
Accuracy (% of FSR $\pm 1LSB$)	0.01	0.01	0.02	0.02	0.04

PCI-1710HG/1710HGL								
Bipolar	± 10	± 5	± 1	± 0.5	± 0.1	± 0.05	± 0.01	± 0.005
Unipolar	-	0-10	-	0-1	-	0-0.1	-	0-0.01
Accuracy (% of FSR $\pm 1LSB$)	0.01	0.01	0.02	0.02	0.02	0.02	0.04	0.04

*Note:

The sampling rate and throughput depends on the computer hardware architecture and software environment. The rates may vary due to programming language, code efficiency, CPU utilization and so on.

Analog Output (PCI-1710/1710HG only)

- Channels 2
- Resolution 12 bits
- Output Rate Static update
- Output Range (V, software programmable)

Internal Reference	Unipolar	0 - +5 V @ -5 V
		0 - +10 V @ -10 V
External Reference		0 - +x V @ -x V (-10 < x < 10)

- Slew Rate 10 V/ms
- Driving Capability 3 mA
- Operation Mode Software polling
- Accuracy INLE: $\pm 1/2$ LSB, CNLE: $\pm 1/2$ LSB

Digital Input

- Channels 16
- Compatibility 5 V/TTL
- Input Voltage Logic 0: 0.8 V max.
Logic 1: 2.0 V min.

Digital Output

- Channels 16
- Compatibility 5 V/TTL
- Output Voltage Logic 0: 0.4 V max.
Logic 1: 2.4 V min.
- Output Capability Sink: 8.0 mA @ 0.8 V
Source: -0.4 mA @ 2.0 V

Pacer/Counter

- Channels 1
- Resolution 13 bits
- Compatibility 5 V/TTL
- Max. Input Frequency 1 MHz

Specifications Continued

General

- **Bus Type** PCI2.2
- **I/O Connector** 1 x SCSI 68-F
- **Dimensions (L x H)** 175 x 100 mm (6.9" x 3.9")
- **Power Consumption** Typical: 5 V @ 650 mA
Max: 5 V @ 1.0 A
- **Operating Temperature** 0 ~ 60° C (32 ~ 140° F) (refer to IEC 68-2-1, 2)
- **Storing Temperature** -20 ~ 70° C (-4 ~ 156° F)
- **Storing Humidity** 5 ~ 95% RH non-condensing (refer to IEC 68-2-3)

Ordering Information

- **PCI-1710** 100 kS/s, 12-bit Multifunction Card, user's manual and driver CD-ROM. (cable not included)
- **PCI-1710L** 100 kS/s, 12-bit Multifunction Card w/o AO, user's manual and driver CD-ROM. (cable not included)
- **PCI-1710HG** 100 kS/s, 12-bit High-Gain Multifunction Card, user's manual and driver CD-ROM. (cable not included)
- **PCI-1710HGL** 100 kS/s, 12-bit High-Gain Multifunction Card w/o AO, user's manual and driver CD-ROM. (cable not included)
- **PCLD-8710** Industrial Wiring Terminal Board with CJC circuit for DIN-rail mounting (cable not included)
- **PCLD-8710BNC** Industrial Wiring Terminal Board with CJC circuit and BNC connectors for DIN-rail mounting (cable not included)
- **PCL-10168** 68-pin SCSI-II cable with male connectors on both ends and special shielding for noise reduction, 1 m.
- **PCL-10168-2** 68-pin SCSI-II cable with male connectors on both ends and special shielding for noise reduction, 2 m.
- **ADAM-3968** 68-pin SCSI-II Wiring Terminal Board for DIN-rail Mounting-Feature Details

Feature Details

PCI-1710 series provide specific functions for different user requirements:

PCI-1710	100 kS/s, 12-bit Multifunction Card
PCI-1710L	100 kS/s, 12-bit Multifunction Card w/o AO
PCI-1710HG	100 kS/s, 12-bit High-Gain Multifunction Card
PCI-1710HGL	100 kS/s, 12-bit High-Gain Multifunction Card w/o AO

Mixed Single-ended or Differential Analog Inputs

PCI-1710 and PCI-1710HG feature an automatic channel/gain scanning circuit. The circuit, rather than your software, controls multiplexer switching during sampling. The on-board SRAM stores different gain values and configurations for each channel. This design lets you perform multi-channel high-speed sampling (up to 100 KHz) with different gains for each channel and a low free combination of single-ended and differential inputs.

On-board FIFO (First In First Out) Memory

PCI-1710, PCI-1710L, PCI-1710HG and PCI-1710HGL have an on-board FIFO buffer that can store up to 4 K A/D samples. PCI-1710 and PCI-1710HG generate an interrupt when the FIFO is half full. This feature provides continuous high-speed data transfer and more predictable performance on Windows systems.

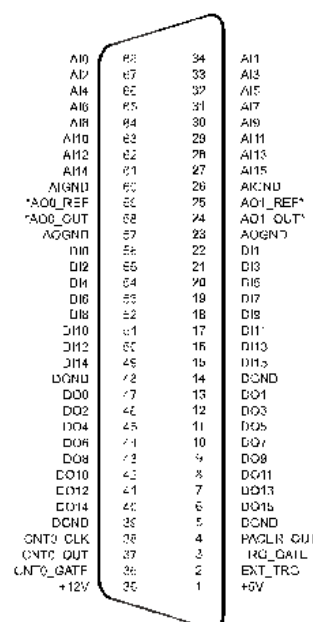
On-board Programmable Counter

The PCI-1710/1710HG/1710HGL provides a programmable counter to generate a timer trigger for the A/D conversion. The counter chip is an 82C54 or equivalent, which includes three 16-bit counters on a 10 MHz clock. One counter is used as an event counter for counting events coming from the input channels. The other two are cascaded together to make a 32-bit timer for a timer trigger.

Special Shielded Cable for Noise Reduction

The PCL-10168 shielded cable is specially designed for the PCI-1710/1710HG to reduce noise in the analog signal lines. Its wires are all twisted pairs, and the analog lines and digital lines are separately shielded, providing minimal cross talk between signals and great protection against EMI/EMC problems.

Pin Assignments



* Pin 23-25 and pins 57-59 are not defined for PCI-1710/1710HG

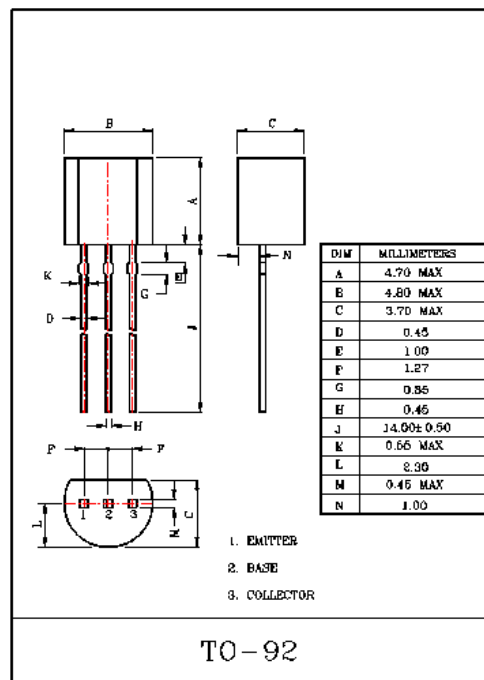
GENERAL PURPOSE APPLICATION.
SWITCHING APPLICATION.

FEATURES

- Excellent h_{FE} Linearity.
- Complementary to KTC9012

MAXIMUM RATINGS ($T_a=25^\circ\text{C}$)

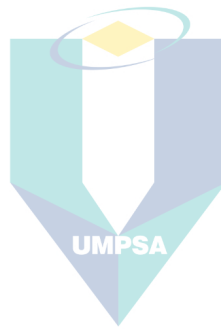
CHARACTERISTIC	SYMBOL	RATING	UNIT
Collector-Base Voltage	V_{CBO}	40	V
Collector-Emitter Voltage	V_{CEO}	30	V
Emitter-Base Voltage	V_{EBO}	5	V
Collector Current	I_C	500	mA
Emitter Current	I_E	-500	mA
Collector Power Dissipation	P_C	625	mW
Junction Temperature	T_j	150	$^\circ\text{C}$
Storage Temperature Range	T_{stg}	-55~150	$^\circ\text{C}$



ELECTRICAL CHARACTERISTICS ($T_a=25^\circ\text{C}$)

CHARACTERISTIC	SYMBOL	TEST CONDITION	MIN.	TYP.	MAX.	UNIT
Collector Cut-off Current	I_{CBO}	$V_{CB}=35\text{V}, I_E=0$	-	-	0.1	μA
Emitter Cut-off Current	I_{EBO}	$V_{EB}=5\text{V}, I_C=0$	-	-	0.1	μA
DC Current Gain	$h_{FE}(\text{Note})$	$V_{CE}=1\text{V}, I_C=50\text{mA}$	64	-	246	
Collector-Emitter Saturation Voltage	$V_{CE(\text{sat})}$	$I_C=100\text{mA}, I_B=10\text{mA}$	-	0.1	0.25	V
Base-Emitter Voltage	V_{BE}	$I_C=100\text{mA}, V_{CE}=1\text{V}$	-	0.8	1.0	V
Transition Frequency	f_T	$V_{CE}=6\text{V}, I_C=20\text{mA}, f=100\text{MHz}$	140	-	-	MHz
Collector Output Capacitance	C_{ob}	$V_{CB}=6\text{V}, I_E=0, f=1\text{MHz}$	-	7.0	-	pF

Note : h_{FE} Classification D:64~91, E:78~112, F:96~135,
 G:118~166, H:144~202, I:176~246



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