

REFERENCES

1. Mdm Hema C. R (2006.) *Intelligence Vision System Lecture Note (1-8) for semester 7*
2. Qin Zhang and John F. Reid (2002) *Agricultural Vehicle Navigation Using Multiple Guidance Sensors* Department of Agricultural Engineering University of Illinois at Urbana-Champaign Urbana, IL 61801, USA; Noboru Noguchi Department of Agricultural Engineering Hokkaido University Sapporo 060, JAPAN.
3. Qin Zhang and John F. Reid (2003) *Machine Vision-based Guidance System for Agricultural Grain Harvesters using Cut-edge Detection* E.R. Benson Bioresources Engineering Department, University of Delaware, USA
4. Cuozzoa, C. D'Eliaa, C. De Stefanoa, F. Fontanellab, C. Marroccoa, M. Molinaraa, A. Scotto di Frecaa, F. Tortorellaa (2001) *Comparison of Object-based Classification Techniques on Multispectral Images* G. DAEIMI. University of Cassino, Italy
5. Magneti Marelli *Car Vision Electronics technology for day and night safe driving Partners: Armines, CEA-List, CEA-Leti, CR Fiat, FICOSA, Intempora, ITC-IRST, Neuricam, STMicroelectronics, Ulis*
6. Louka Dlagnekov, Serge Belongie *Recognizing Cars* Department of Computer Science and Engineering University of California, San Diego, USA
7. Louka Dlagnekov (2003) UNIVERSITY OF CALIFORNIA, SAN DIEGO *Video-based Car Surveillance: License Plate, Make, and Model Recognition..*
8. Massimo Bertozzi and Alberto Broggi *Vision-Based Vehicle Guidance,PARMA*
9. I Henry Schneiderman and Takeo Kanade (2002) *Object Detection Using the Statistics of Parts I* International Journal of Computer Vision,. Robotics Institute Carnegie Mellon University Pittsburgh,UK
10. Prof. Sergiu Nedevschi, Radu Danescu, Dan Frentiu, Tiberiu Marita, Florin Oniga, Ciprian Pocol (1999) *High Accuracy Stereo Vision System for Far Distance*

Obstacle Detection Technical University of Cluj-Napoca Department of Computer Science, DENMARK

11. Anurag Mittal.and Larry Davis (2002) *Unified Multi-camera Detection and Tracking Using Region Matching* University of Maryland College Park, USA
12. DEWAN NEGARA (1997) Order Paper <http://www.parlimen.gov.my>,30 May 2007
13. Charles E. Thorpe Martial, Hébert Takeo Kanade, Robert Bolles (1997) *A High-Performance Vision System for Obstacle Detection* Ph.D. Thesis Proposal, Todd Andrew Williamson Thesis Committee, USA
14. Todd M. Jochem (2004) *Using Virtual Active Vision Tools to Improve Autonomous Driving Tasks* <http://www.cs.cmu.edu/~tjochem/thesis/proposal>, 14 Sept 2006

APPENDICES

Appendix A : MATLAB Source Code

```
%For Camera Captured
%
cardum=vcapg2;
x=vcapg2;
imwrite(x,'cam1.jpg');
subplot(4,2,1);
imshow(x);
title('cam1');

% Read Image
x = imread('cam1.jpg');
imshow(x);
subplot(4,2,2);
imwrite(x,'cam1.jpg');
title('Original Image');

%Resizing and displaying the resized files
a=imresize(x,[800,600]);
subplot(4,2,3);
imshow(a);
title('Resized Image')

%Convert RGB to Grayscale image
a1 = rgb2gray(a);
subplot(4,2,4);
imshow(a1);
title('Grayscale Image')

%Filtering & Convert Grayscale to Binary image
L=medfilt2(a1,[5 5]);
BL = im2bw(L,0.3);
subplot(4,2,5);
imshow(BL);
title('Binary Image')

%Filtering Binary image
L1=medfilt2(BL,[2 2]);
L2=medfilt2(L1,[4 4]);
subplot(4,2,6);
```

```

imshow(L2);
title('Filtered Image')

%Edge image was extracted to optimise the feature data
S=medfilt2(L2,[3 3]);
S1=medfilt2(S);

%Edge detection using Canny Edge
E=edge(S1,'canny');
subplot(4,2,7);
imshow(E);
title('edge image')

%Feature extraction through singular value decomposition
F=svd(double(E))
fout=fopen('input.dat','a');

    for j= 1:1:40
        fprintf(fout, '%f\t',F(j));
    end
    fprintf(fout, '\n');
fclose(fout);
fprintf('Execution Over');

%-----

% Read Image
x = imread('C:\MATLAB7\work\henry\s4.jpg');
imshow(x);
subplot(4,2,1);
imwrite (x,'s4.jpg');
title('Original Image');

%Resizing and displaying the resized files
a=imresize(x,[80,60]);
subplot;
imshow(a);
title('Resized Image')

%Convert RGB to Grayscale image
a1 = rgb2gray(a);
subplot(4,2,3);
imshow(a1);
title('Grayscale Image')

%Filtering & Convert Grayscale to Binary image

```

```

L=medfilt2(a1,[5 5]);
BL = im2bw(L,0.3);
subplot(4,2,4);
imshow(BL);
title('Binary Image')

%Filtering Binary image
L1=medfilt2(BL,[2 2]);
L2=medfilt2(L1,[4 4]);
subplot(4,2,5);
imshow(L2);
title('Filtered Image')

%Edge image was extracted to optimise the feature data
S=medfilt2(L2,[3 3]);
S1=medfilt2(S);

%Edge detection using Canny Edge
E=edge(S1,'canny');
subplot(4,2,6);
imshow(E);
title('edge image')

%Feature extraction through singular value decomposition
F=svd(double(E))
fout=fopen('input.dat','a');

    for j= 1:1:40
        fprintf(fout, '%f\t',F(j));
    end
    fprintf(fout, '\n');
fclose(fout);
fprintf('Execution Over');

%-----

% random_file
%
clear all
clc;
a = xlsread('norinput.xls');
b = xlsread('noroutput.xls');
[c d] = random_matrix(a,b);
xlswrite('rannorinput.xls',c);
xlswrite('rannoroutput.xls',d);

```

```

%-----

% random_matrix
%
function [c d] = random_matrix(a,b)
[m1 n1] = size(a);
[m2 n2] = size(b);
c = zeros(m1,n1);
d = zeros(m2,n2);
if (m1 == m2)
    for i = 1:m1
        index = randint(1,1,[1,m1]);
        for j = 1:n1
            c(i,j) = a(index,j);
        end;
        for j = 1:n2
            d(i,j) = b(index,j);
        end;
    end;
end

%-----

%function xnor = bin_nor_xls('input.xls')
% Data from an Excel file is normalized along column wise
% and result written into an Excel file
% Activate the function by bin_nor_xls('infile.xls','outfile.xls')
x_un_nor = xlsread('input.xls');

[m,n] = size(x_un_nor);
xmax = max(x_un_nor);
xmin = min(x_un_nor);

d = xmax - xmin;
for i= 1:m
    for j = 1:n
        xnor(i,j) = (0.8/d(j))*(x_un_nor(i,j) - xmin(j)) + 0.1;
        % xnor1(i,j) = (0.8/d(j))*(x_un_nor1(i,j) - xmin(j)) + 0.1;
    end
end
end
xlswrite('norinput.xls',xnor);

```

```

x_un_nor1 = xlsread('output.xls');
[m,n] = size(x_un_nor1);
xmax = max(x_un_nor1);
xmin = min(x_un_nor1);
d = xmax - xmin;
for i= 1:m
    for j = 1:n
        %xnor(i,j) = (0.8/d(j))*(x_un_nor(i,j) - xmin(j)) + 0.1;
        xnor1(i,j) = (0.8/d(j))*(x_un_nor1(i,j) - xmin(j)) + 0.1;
    end
end
xlswrite('noroutput.xls',xnor1);

%-----

% neural

clear all;
clc;
p1 = xlsread('input.xls');
t1 = xlsread('output.xls');
tic
p = p1';
t = t1';
net=newff(minmax(p),[30,2],{'logsig','logsig'},'trainlm');
net.trainParam.show = 10;
net.trainParam.lr = 0.005;
net.trainParam.epochs = 200;
net.trainParam.goal = 1e-5;
% Maximum validation failures
net.trainParam.max_fail = 5;
% Factor to use for memory/speed trade off.
net.trainParam.mem_reduc = 1;
% Minimum performance gradient
net.trainParam.min_grad = 1e-10;
% Initial Mu
net.trainParam.mu = 0.001;
% Mu decrease factor
net.trainParam.mu_dec = 0.1;
% Mu increase factor
net.trainParam.mu_inc = 10;
% Maximum Mu
net.trainParam.mu_max = 200;

```



```

[net,tr]=train(net,p,t);
toc
save net1 net;
a = sim(net,p)
at = a';
tt = t';
res = [];
for i = 1:26
    res = [res;at(i,1) tt(i,1) at(i,2) tt(i,2)];
end
res
e = a-t;
et = e';
[m n] = size(et);
count = 0;
for i = 1:m
    flag = 0;
    for j =1:n
        if(et(i,j) > 0.12)
            flag = 1;
        end
    end
    if flag == 0
        count = count + 1;
    end;
end;
perc_class = count/m

%-----

```

Appendix B : Comparison Between Filtered, Resized, Binary And Edge Image

















