

## Object Detection Method Using Invariant Feature Based on Local Hue Histogram in Divided Area of an Object Area

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### ABSTRACT

In recent years, human support robots have been receiving attention. Then, the robots are required to perform various tasks to support humans. Especially, an object detection task is important in case that people request the robot to transport and rearrange an object. However, the detection becomes difficult owing to difference of visual aspect in case of detecting with a target object from an equipped camera on a robot. We consider that there are seven necessary properties to detect in domestic environment as follows. 1. Robustness against the rotation change. 2. Robustness against the scale change. 3. Robustness against the illumination change. 4. Robustness against the distortion by perspective projection. 5. Robustness against the occlusion. 6. Detecting an object which has few textures. 7. Detecting different objects which have the same features of the hue histogram. As conventional method, there are Scale Invariant Feature Transform (SIFT), Color Indexing and the proposed method by Tanaka et al. These conventional methods do not satisfy all seven properties needed for the robots. Therefore, to satisfy the seven properties of detection, we propose the object detection method using invariant feature based on local hue histogram in a divided area of an object area.

### KEYWORDS

Cognitive robot, hue histogram, peak and trough, divided area.

### 1 INTRODUCTION

In recent years, human support robots have been receiving attention [1-3]. Then, the robots are required to perform various tasks to support humans. Especially, an object detection task is important in case that people request the robots to transport and rearrange an object.



(a)



(b)

Figure. 1. A target object and An input image. a) A target object. b) An input image

The object detection is technology to detect a target object (Fig.1 (a)) from an input image (Fig.1 (b)).

There is a problem which the detection is difficult in case of detecting with a target object from an equipped camera on a robot, because differences of visual appearance occur such as the rotation change. Therefore, we consider that there are six necessary properties to detect in domestic environment as follows.

1. Robustness against the rotation change
2. Robustness against the scale change
3. Robustness against the illumination change
4. Robustness against the distortion by perspective projection
5. Robustness against the occlusion
6. Detecting an object which has few textures

Firstly, the robots need the robust detection for the rotation change because the rotation change is occurred in case that an object falls down such as fig.1 (b). Secondly, the robots need the robust detection for the scale change because the scale change is occurred by the position between the robots and an object. Thirdly, the robots need the robust detection for the illumination change because



Figure. 2. Example of an object which has few

Table. 1. Properties of Conventional Methods and the Proposed Method

	1. Rotation change	2. Scale change	3. Illumination change	4. Distortion by perspective projection	5. Occlusion	6. An object which has few textures	7. Different objects which have same features of histogram
SIFT	○	○	○	×	○	×	○
Color indexing	○	○	×	○	○	○	○
The conventional method	○	○	○	○	○	○	×
Our proposed method	○	○	○	○	○	○	○

the precision of detection is easy to be affected by illumination condition. Fourthly, the robots need the robust detection for the distortion by perspective projection because the distortion by perspective projection is occurred in case that the robot moves sideways, looks up or looks down. Fifthly, the robots need the robust detection for occlusion because occlusion is occurred between different objects. Finally, the robots need to detect an object which has few textures. As an example, fig.2 shows an object which has few textures.

As conventional method, there are the Scale Invariant Feature Transform (SIFT) [4] and the Color Indexing [5]. Table 1 shows properties of these methods.

To detect a target object from an input image, the SIFT compares local feature amount of a target object with local feature amount of an input image, and extracts correspondence points as shown in fig.3. Therefore, as shown item 1-3 and 5 in table 1, the SIFT has robustness against the rotation change, the scale change, the illumination change and occlusion. However, as shown item 4 in table 1, the SIFT does not have robustness against the distortion by perspective projection that local feature amount

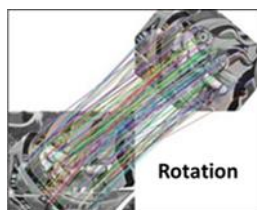


Figure. 3. Example of object detection by using SIFT

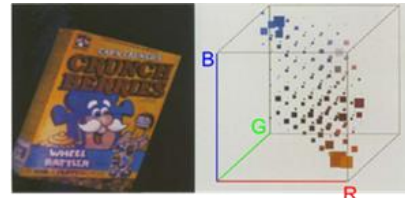


Figure. 4. Example of three dimensional color histogram

changes. In addition, as shown item 6 in table 1, the SIFT is difficult to detect an object which has few textures because the SIFT cannot detect feature amount against an object that an edge cannot be detect from such as an object which has few textures.

On the other hand, Swain et al. proposed the Color Indexing. To detect a target object from an input image, the Color Indexing compares three dimensional color histogram of a target object with three dimensional color histogram of a candidate object. As an example, fig.4 shows three dimensional color histogram. As shown in fig.4, a size of the square in three dimensional color histogram expresses the frequency of each color. The frequency of each color does not change in case that the rotation change, the scale change, the distortion by perspective projection and occlusion are occurred. In addition, the Color Indexing can detect an object which has few textures by using the color information. Therefore, as shown item 1, 2 and 4-6 in table 1, the Color Indexing has robustness against the rotation change, the scale change, distortion by perspective projection, occlusion and an object which has few textures. However, as shown item 3 in table 1, the Color Indexing is difficult to detect in case that illumination is changed, because the Color Indexing uses RGB color system which is easy to be affected by the illumination change.

In our laboratory, Tanaka et al. [6] focused on hue. Hue has three merits. Firstly, hue is hardly affected by illumination and shadow. Secondly, hue is invariable against the distortion by perspective projection. Finally, the detection using hue can detect an object which has few textures. In addition, as shown in fig.5, the positions of peak and trough of the hue histogram is invariable against the rotation change, the scale change, the illumination change, the distortion by perspective projection and occlusion. In fig.5, we define the longitudinal axis as the frequency, and the lateral axis as the hue value. In addition, the circle indicates the position of peak

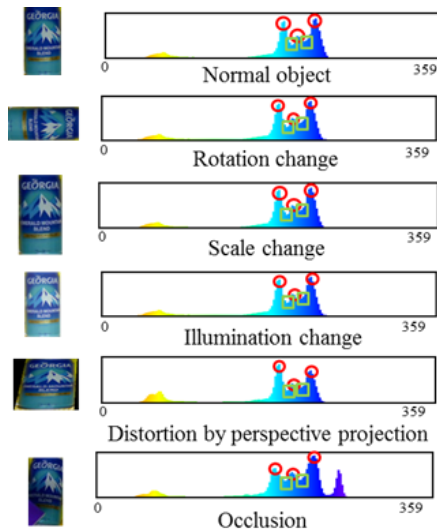


Figure. 5. Example of the positions of peak and trough

and the square indicates the position of trough. Accordingly, Tanaka et al. proposed the object detection method using invariant feature based on the hue histogram. Here, we define the proposed method by Tanaka et al. as the conventional method. To detect a target object from an input image, the conventional method extracts the positions of peak and trough of the hue histogram as invariant feature. In addition, the conventional method compares invariant feature of a target object with invariant feature of a candidate object. As mentioned above, the positions of peak and trough of the hue histogram do not change in case that the rotation change, the scale change, the illumination change, the distortion by perspective projection and occlusion are occurred. In addition, the conventional method can detect an object which has few textures by using hue information. Therefore, as shown item 1-6 in table1, the conventional method has robustness against the rotation change, the scale change, the illumination change, the distortion by perspective projection, occlusion and an object which has few textures. However, the conventional method does not satisfy a property as follows.

#### 7. Distinguishing different objects which have the same features of the hue histogram

The conventional method cannot distinguish objects which have the different textures but have the same positions of peak and trough of the hue histogram. As an example, fig.6 (a), (b) shows different objects which have the same features of the hue histogram. Fig.6 (c), (d) shows the hue histogram of fig.6 (a),

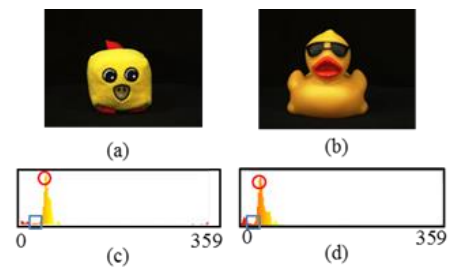


Figure. 6. Example of different objects which have same invariant feature. a) The object which has same invariant feature with (b). b) The object which has same invariant feature with (a). c) Hue histogram of (a). d) Hue histogram of (b)

(b). As shown item 7 in table 1, the conventional method cannot distinguish objects (Fig.6 (a), (b)) as different object because the positions of peak and trough of fig.6 (a) equal the positions of peak and trough of fig.6 (b) as shown in fig.6 (c), (d). As mentioned above, as shown in table 1, the SIFT, the Color Indexing and the conventional method do not satisfy all seven properties.

Therefore, to satisfy the seven properties of detection, we propose the object detection method using invariant feature based on the local hue histogram in a divided area of an object area instead of invariant feature based on the hue histogram in the whole object area. As our approaches, firstly, the proposed method divides an object area into plural areas. As an example, fig.7 (a), (b) shows divided objects. Secondly, the proposed method extracts hue from each divided area and generates local hue

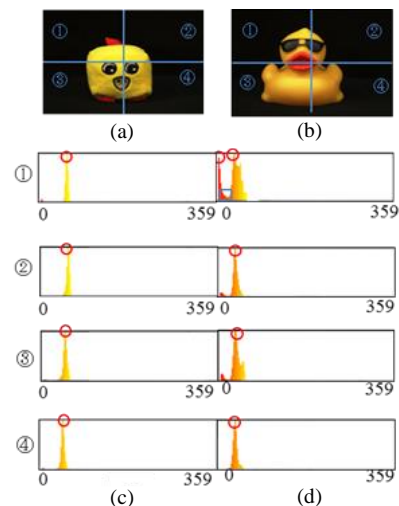


Figure. 7. Example of local hue histograms in divided area of an object. a) Divided area of fig.6 (a). b) Divided area of an fig.6 (b). c) Local hue histograms in each divided area of fig.7 (a). d) Local hue histograms in each divided area of fig.7 (b).

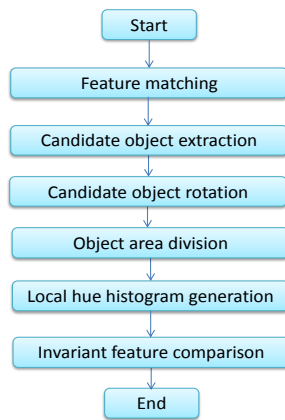


Figure. 8. Flow of the proposed method.

histograms. As an example, fig.7 (c), (d) shows the local hue histogram of fig.7 (a), (b). Thirdly, the proposed method extracts the positions of peak and trough from each local hue histograms as invariant feature. As shown in fig.7 (c), (d), the positions of peak and trough of the local hue histogram changes for each divided area by dividing an object area. Finally, the proposed method compares invariant feature of the target object with invariant feature of the candidate object every each local hue histograms. Thereby, the proposed method can distinguish different objects which have the same feature of hue histogram. Furthermore, the proposed method has robustness against the rotation change, the scale change, the illumination change, the distortion by perspective projection, occlusion and an object which has few textures as shown in table 1.

## 2 PROPOSED METHOD

### 2.1 Flow of Proposed Method

We show the flow of the proposed method in fig.8. We represent each processing in the next sections.

### 2.2 Feature Matching

Firstly, the proposed method extracts feature points from the registered image (Fig.9 (a)) and the input image (Fig.9 (b)) based on the feature of the

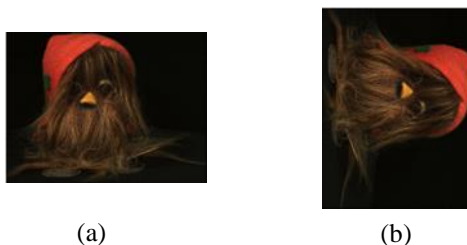


Figure. 9. Registered image and input image. a) Registered image. b) Input image.

BRISK [7]. As an example, we set the registered image which rotated 90 degrees to the input image in this time. Finally, the proposed method performs matching based on the BRISK descriptor between the registered image and the input image.

### 2.3 Candidate Object Extraction

Firstly, the proposed method calculates a vector  $A$  from the most matched feature point to the most far away endpoint of the object area in the registered image, and defines a norm of vector  $A$  as the maximum distance  $dm$ . Secondly, the proposed method calculates vectors from the most matched feature point to the second most matched feature point in the registered image and the input image, and calculates the ratio of the size of the registered image and the input image using the calculated vectors. Thirdly, the proposed method describes a circle with center is the most matched feature point and radius is vector  $A$  in the registered image. In addition, the proposed method describes a circle with center is the most matched feature point and radius is vector  $B$  in the input image. Vector  $B$  is calculated by using

$$B = A \div r \quad (1)$$

Where  $B$  is vector  $B$ ,  $A$  is vector  $A$ ,  $r$  is the calculated ratio. Fourthly, the proposed method extracts the contour of the a circle in the registered image and the input image. Finally, the proposed method trims the registered image and the input image based on the extracted contours. Thereby, it is possible to accurately extract the candidate area even when scale is different or occlusion occurs as shown in fig.10.

### 2.4 Candidate Object Rotation

As shown in fig.11, in case that the input image rotates, the feature amount of the hue histogram changes. Therefore, it is necessary to rotate the input

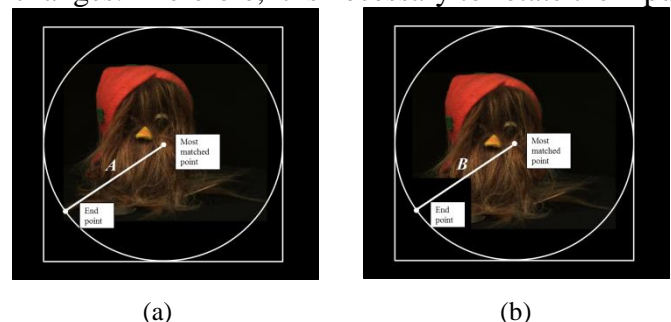


Figure. 10. Candidate area extraction. a) Registered image. b) Input image.



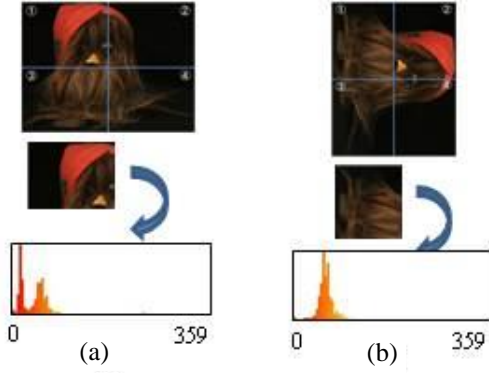


Figure. 11. In case that input image rotates. a) Feature amount of the hue histogram of registered image. b) Feature amount of the hue histogram of input image

image. Firstly, the proposed method extracts feature points from the trimmed registered image and the trimmed input image, and performs matching based on the BRISK descriptor between the trimmed registered image and the trimmed input image. Finally, the proposed method rotates the trimmed input image by using extracted correspondence points by expression (2). We represent expression (2) as follows.

$$\begin{pmatrix} sx_2 \\ sy_2 \\ s \end{pmatrix} = H \begin{pmatrix} x_1 \\ y_1 \\ 1 \end{pmatrix} = \begin{pmatrix} h_{11} & h_{12} & h_{13} \\ h_{21} & h_{22} & h_{23} \\ h_{31} & h_{32} & h_{33} \end{pmatrix} \begin{pmatrix} x_1 \\ y_1 \\ 1 \end{pmatrix}, \quad (2)$$

where  $H$  is the homography matrix,  $(x_1, y_1)$  are the coordinates before the rotation,  $(x_2, y_2)$  are the coordinates after the rotation,  $s$  is coefficient.

## 2.5 Object Area Division

To generate the local hue histogram, the proposed method divides the trimmed registered image and the rotated input image into plural areas. Here, we define the number of division as four as an example.

## 2.6 Local Hue Histogram Generation

Firstly, the proposed method extracts hue from each divided area and generates local hue histograms. The hue value of the generated

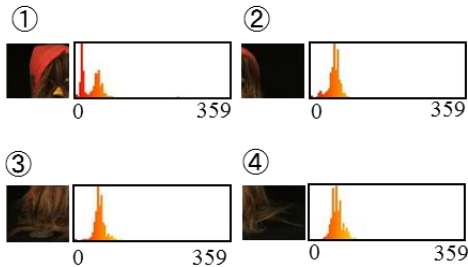


Figure. 12. Divided area and local hue histograms.

histogram is represented from 0 to 359. Fig.12 shows the divided areas and local hue histograms. We define the vertical axis as the frequency, and the horizontal axis as the hue value. Here, we pay attention to item ① of fig.12. Fig.13 (a) shows an expanded hue histogram of item ① of fig.12. In fig.13 (a), because there are small irregularities at 7 and 9 of hue value, the feature amount becomes unstable by detecting the positions of peak and trough of the hue histogram in this state. Secondly, to eliminate those small irregularities, the proposed method smooths the hue histogram by using Gaussian filter. Fig.13 (b) shows a smoothed hue histogram of fig.13 (a). In fig.13 (b), we can see that small irregularities of the hue histogram are omitted and the characteristic positions of peak and trough of the hue histogram are remained. Finally, the proposed method extracts the positions of peak of the smoothed hue histogram from each divided areas of the registered image and the input image by using

$$(H_{x-1} < H_x) \wedge (H_x > H_{x+1}), \quad (3)$$

and the positions of trough of the smoothed hue histogram from each divided areas of the registered image and the input image by using

$$(H_{x-1} > H_x) \wedge (H_x < H_{x+1}), \quad (4)$$

and registers them as invariant feature. Where  $H_x$  is the hue value which is focused on,  $H_{x-1}$  is the hue value before one of  $H_x$ .  $H_{x+1}$  is the hue value after one of  $H_x$ . And then, the extracted positions of peak and trough of the registered image are expressed by using

$$\{p_1^{(\alpha)}, p_2^{(\alpha)}, \dots\} \in P^{(\alpha)}, \quad (5)$$

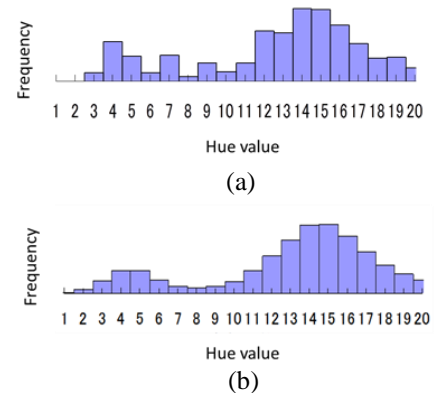


Figure. 13. Smoothing processing. a) A part of hue histogram. b) A part of smooth hue histogram

$$\{t_1^{(\alpha)}, t_2^{(\alpha)}, \dots\} \in T^{(\alpha)} \quad (6)$$

where  $P^{(\alpha)}$  is a set of peak position of a smoothed hue histogram in a divided area  $\alpha$ .  $p_1^{(\alpha)}, p_2^{(\alpha)}, \dots$  which are each peak positions of a smoothed hue histogram,  $T^{(\alpha)}$  is a set of trough position of a smoothed hue histogram in a divided area  $\alpha$ .  $t_1^{(\alpha)}, t_2^{(\alpha)}, \dots$  which are each trough positions of a smoothed hue histogram. In addition, the extracted positions of peak and trough of the input image are expressed by using

$$\{hp_1^{(\beta)}, hp_2^{(\beta)}, \dots\} \in hP^{(\beta)}, \quad (7)$$

$$\{ht_1^{(\beta)}, ht_2^{(\beta)}, \dots\} \in hT^{(\beta)}, \quad (8)$$

where  $hP^{(\beta)}$  is a set of peak position of a smoothed hue histogram in a divided area  $\beta$ ,  $hp_1^{(\beta)}, hp_2^{(\beta)}, \dots$  which are each peak positions of a smoothed hue histogram,  $hT^{(\beta)}$  is a set of trough position of a smoothed hue histogram in a divided area  $\beta$ ,  $ht_1^{(\beta)}, ht_2^{(\beta)}, \dots$  which are each trough positions of a smoothed hue histogram.

## 2.7 Invariant feature comparison

Firstly, the proposed method calculates difference values between invariant feature of the registered image and invariant feature of the input image by using

$$Dp_1 = \min_{1 \leq y \leq n} |p_1^{(\alpha)} - hp_y^{(\beta)}|, \quad (9)$$

$$Dp_2 = \min_{1 \leq y \leq n} |p_2^{(\alpha)} - hp_y^{(\beta)}|, \quad (10)$$

⋮

$$Dt_1 = \min_{1 \leq z \leq l} |t_1^{(\alpha)} - ht_z^{(\beta)}|, \quad (11)$$

$$Dt_2 = \min_{1 \leq z \leq l} |t_2^{(\alpha)} - ht_z^{(\beta)}|, \quad (12)$$

⋮

$$DP = \sum_{\alpha=1}^m Dp_{\alpha}, \quad (13)$$

$$DT = \sum_{b=1}^k Dt_b, \quad (14)$$

$$D = DP + DT, \quad (15)$$

where  $n$  is the number of peak of a smoothed hue histogram in a divided area  $\beta$ ,  $l$  is the number of valley of a smoothed hue histogram in a divided area  $\beta$ ,  $Dp_1, Dp_2, \dots$  which are the smallest difference values between  $hP^{(\beta)}$  to  $p_1^{(\alpha)}, p_2^{(\alpha)}, \dots$ ,  $p_1^{(\alpha)}, p_2^{(\alpha)}, \dots$  which are each peak positions of a smoothed hue histogram in a divided area  $\alpha$ ,

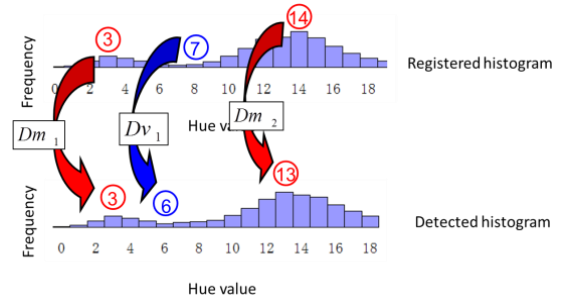


Figure. 14. Comparing invariant feature of registered image with invariant feature of input image.

$Dt_1, Dt_2, \dots$  are the smallest difference values between  $hT^{(\beta)}$  to  $t_1^{(\alpha)}, t_2^{(\alpha)}, \dots$ ,  $t_1^{(\alpha)}, t_2^{(\alpha)}, \dots$  which are each trough positions of a smoothed hue histogram in a divided area  $\alpha$ ,  $m$  is the number of peak of a smoothed hue histogram in a divided area  $\alpha$ ,  $k$  is number of trough of a smoothed hue histogram in a divided area  $\alpha$ ,  $DP$  is the total value of difference value of peak position,  $DT$  is the total value of difference value of trough position,  $D$  is the total difference value. As an example, fig.14 shows that the comparison of the hue histogram of a registered image and the hue histogram of an input image. As shown in fig.14, the proposed method compares the positions of peak and trough of a smoothed hue histogram of a registered image with the positions of peak and trough of a smoothed hue histogram of an input image, and calculates difference values. In addition, the proposed method registers a peak and a trough having the smallest difference value as the nearest peak and trough. Finally, the proposed method detects the object which has smallest  $D$ .

## 3 EXPERIMENT

### 3.1 Experiment Relating to The Number of Division of an Image

1) *Experiment Overview:* In this experiment, to determine the optimum number of division, changing the number of division from 1 piece to 25 pieces, the proposed method detected a registered object from an input image. Furthermore, we calculated the correct answer ratio by using

$$A = \frac{C}{Z} \times 100 [\%], \quad (15)$$

and defined the number having the highest correct answer ratio as the number of division. Where  $A$  is the correct answer ratio,  $C$  is the number which the proposed method could correctly detect objects,  $Z$  is

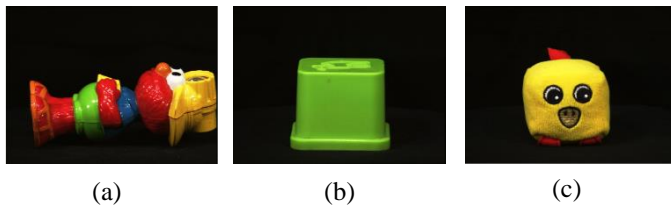


Figure. 15. Feature of the object. a) Normal object. b) object which has few textures. c) object which has same hue value

the number of the registered objects. We selected 5 pieces in normal object (Fig.15 (a)), 5 pieces in object which has few textures (Fig.15 (b)), and 5 pieces in object which has same hue value (Fig.15 (c)), totaling 15 pieces of objects from Amsterdam Library of Object Images [8] as the test image. In object which has same hue value, we selected object which has hue values of yellow and red.

2) *Experimental Results:* Fig.16 shows the result of this experiment. As a result, a correct answer ratio increased as number of division increased. In addition, the correct answer ratio became highest in case that the number of division is four and continued maintaining afterwards. However, we carried out the experiment on occluded objects, because we could not determine the most suitable number of division in this result. Fig.17 shows the result of the experiment of the occluded objects. As a result, the correct answer ratio became highest in

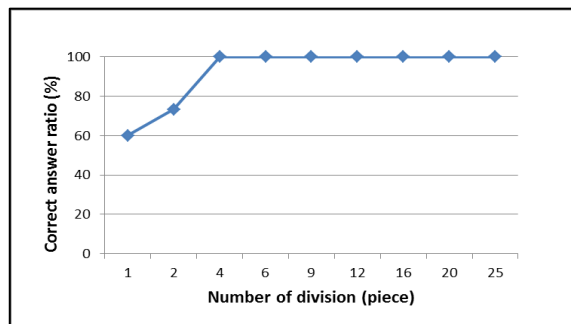


Figure. 16. The correct answer ratio for the number of division.

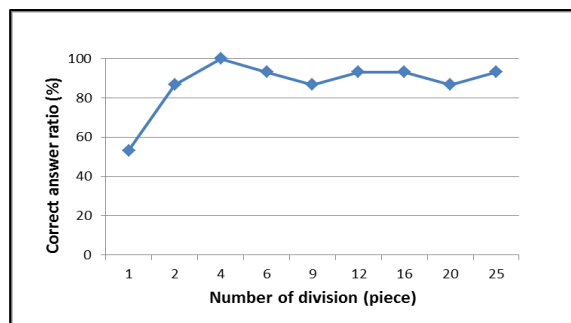


Figure. 17. The correct answer ratio for the number of division on the occluded objects.

case that the number of division is four. However, the correct answer ratio repeated increase and decrease between 80% and 100%. From these results, we defined the number of division as four pieces in this paper.

3) *Discussions:* We understood that the optimal number of division was difference according to objects from these experimental results. Therefore, we saw that it is necessary to statistically calculate the optimal parameter to increase the correct answer ratio.

### 3.2 Experiment of Robustness Against All Difference of Visual Appearance

1) *Experiment Overview:* In this experiment, to show the robustness against seven properties mentioned above of the proposed method, we carried out the experiment while giving objects changes, and compared the correct answer ratio of the proposed method with the correct answer ratio of conventional methods. We used objects same as experiment of the number of division as the inspection object. In addition, we calculated the correct answer ratio by using equation (15). Here, we show setting of each method. In the proposed method, we defined the number of division as four pieces, the threshold of the peak as 40, the threshold of the trough as 5 and  $\sigma$  of Gaussian filter as 1.0. In the conventional method, we defined  $\sigma$  of Gaussian filter as 1.0. In the SIFT, we defined the threshold of correspondence points as 70.0. In addition, we defined the object which has correspondence points more than ten points and most correspondence points as a detection result. In the Color Indexing, we defined 255 gradation which was divided into four as each axis of the histogram.

2) *Experiment Results:* We only indicate the result of the proposed method without comparing the proposed method with the conventional methods, because both the proposed method and the conventional methods have robustness against the rotation change and the scale change.

a) *The scale change:* We carried out the experiment while increasing the scale level from 0.8 times to 1.2 times every 0.2. As a result of this experiment, the correct answer ratio was 100% in each scale level.

b) *The rotation change:* We carried out experiment while increasing the rotation degree from 0 degrees to 180 degrees every 90 degrees. As a result of this experiment, the correct answer ratio was 100% in each rotation degree.

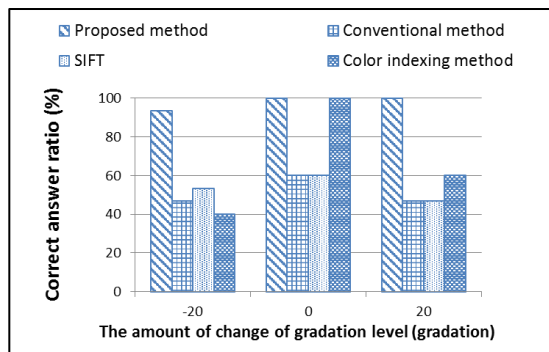


Figure. 18. The result of the experiment about the illumination change

We indicate the result of the experiment about robustness against the illumination change, the distortion by perspective projection and occlusion.

c) *The illumination change:* We carried out the experiment while increasing the gradation levels from -20 gradations to +20 gradations every 20 gradations. Fig.18 shows the result of the experiment about the illumination change. As shown in fig.18, the correct answer ratio of the proposed method was high, whereas the correct answer ratio of the Color Indexing was low as we expected.

d) *The distortion by perspective projection:* We carried out the experiment for the rotation in 30 degrees and 45 degrees. Fig.19 shows the result of the experiment about the distortion by perspective projection. As shown in fig.19, the correct answer ratio of the proposed method was high, whereas the correct answer ratio of the SIFT was low as we expected.

e) *The occlusion:* We carried out the experiment while increasing occlusion ratio from 10 percent to 40 percent every 10 percent. As an example, we show an occluded object in fig.20. Fig.21 shows the

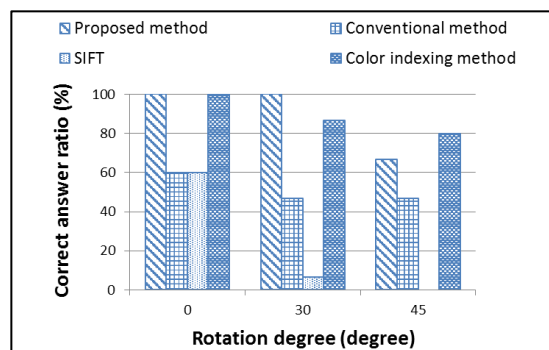


Figure. 19. The result of the experiment about the distortion by perspective projection



Figure. 20. The occluded object.

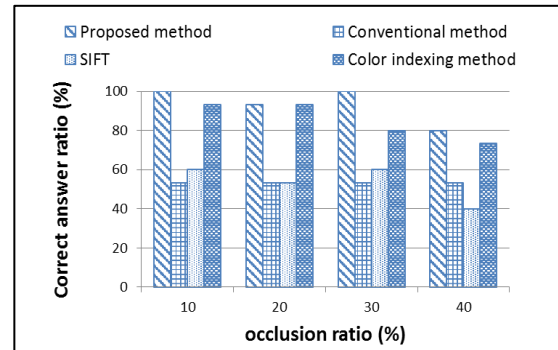


Figure. 21. The result of the experiment about occlusion.

result of the experiment about occlusion. As shown in fig.21, the correct answer ratio of the proposed method was higher than the correct answer ratio of conventional methods as we expected.

In addition, we focus on the feature of the each object. Fig.22 shows the correct answer ratio of the each object. As shown in fig.22, the proposed method and the Color Indexing got a high correct answer ratio in all features, whereas the SIFT got a low correct answer ratio in the object which has few texture. In addition, the conventional method got a low correct answer ratio in the object having the same hue value and the normal object.

### 3) Discussions:

a) *The proposed method:* The correct answer ratio was higher or nearly equal than the conventional methods. However, the correct answer

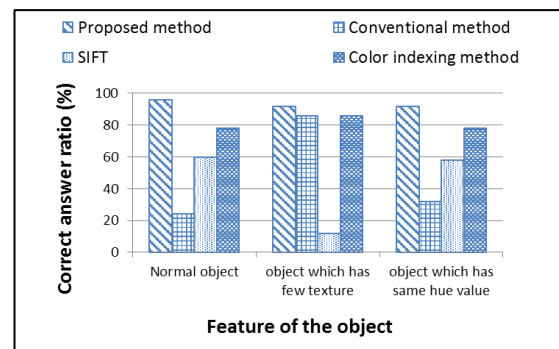


Figure. 22. The correct answer ratio on features of objects.



ratio decreased a little in case of 45 degrees of the distortion by perspective projection, because the proposed method uses local feature amounts on candidate object extraction and rotation processing.

*b) The conventional method:* The correct answer ratio was less than 60% in all changes. However, we see that there are few differences by comparing the correct answer ratio in the object which a change is given and the correct answer ratio in the object which a change is not given. Therefore, we focus on the feature of the each object. As shown in fig.22, the correct answer ratio was low in the object having the same hue value and the normal object. The reason for this, when the candidate objects have plural pieces of color information, they have the same hue value with high probability, therefore it is thought that erroneous recognition occurred and the correct answer ratio decreased.

*c) The SIFT:* The correct answer ratio was less than 60% in all changes. Especially, the correct answer ratio decreased on the distortion by perspective projection. The reason for this, the local feature amount changes by the distortion by perspective projection, therefore it is thought that the SIFT descriptor changes and the correct answer ratio decreased. In addition, we focus on the feature of the each object. As shown in fig.22, the correct answer ratio was low in the object which has few textures. The reason for this, the SIFT descriptor uses the gradient information of the object, therefore it is thought that the SIFT could not detect the feature amount on the object which has few edges such as the object which has few textures, and the correct answer ratio decreased.

*d) The Color Indexing:* The correct answer ratio decreased on the illumination change. The reason for this, the RGB color system which is used for the Color Indexing is easy to be affected by the illumination change, therefore it is thought that the value of the three dimensional color histogram changed and the correct answer ratio decreased.

## 4 CONCLUSION

In this study, we proposed the object detection method using invariant feature based on the local hue histogram in a divided area of an object area for

the human support robot. To show that the proposed method satisfies all seven properties as follows,

1. Robustness against the rotation change
2. Robustness against the scale change
3. Robustness against the illumination change
4. Robustness against the distortion by perspective projection
5. Robustness against the occlusion
6. Detecting an object which has few textures
7. Detecting different objects which have the same features of the hue histogram

We carried out experiments. As a result, we could show that the proposed method satisfies all seven properties. However, the detection accuracy is limited, because the proposed method uses only two dimensional information. Therefore, in the future, we aim to improve the ability for detection by using three dimensional information such as the shape information.

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