DESIGN OF ADAPTIVE TARGET TRACKING ALGORITHM FOR ROBOTS BASED ON VISUAL ATTENTION MECHANISM

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SUMMARY

Adaptive target tracking with visual attention represents a sophisticated approach to object detection and localization in dynamic environments. With principles inspired by human visual perception, this methodology employs mechanisms of selective attention to prioritize relevant visual information for tracking moving targets. By dynamically adjusting attentional focus based on salient visual cues and target motion characteristics, adaptive target tracking enhances the efficiency and accuracy of object localization in cluttered scenes. This research presents a novel adaptive target tracking algorithm designed for robotic systems, integrating a visual attention mechanism with the Fuzzy Clustering Multi-Point Tracking utilizing the Green Channel (FC-MPT-GC) approach. The proposed FC-MPT-GC model comprises of Fuzzy Clustering for the extraction of features in the robots-based environment. The FC-MPT-GC model uses the estimation of green channels in the classification environment. With the estimation of features in the environment with Fuzzy C-means clustering green channels are deployed in the deep learning, The proposed algorithm aims to enhance the adaptability and precision of target tracking in dynamic environments. By incorporating a visual attention mechanism, the algorithm dynamically allocates attentional focus to salient regions of the visual input, optimizing the tracking process for moving targets. The FC-MPT-GC methodology further refines target localization by utilizing fuzzy clustering and multi-point tracking strategies, particularly leveraging information from the Green Channel to improve robustness in various lighting conditions. Simulation analysis demonstrated that the proposed FC-MPT-GC model tracking accuracy is achieved at 95.1% with the minimal computation time of 15.2 ms.

KEYWORDS

Target tracking, Visual attention, Multi-Point tracking, Fuzzy clustering, Visual attention

1. INTRODUCTION

Visual attention in the context of natural language processing and computer vision refers to the ability of a model to focus on specific parts of an input, similar to how humans selectively attend to different regions when processing visual information [1]. This concept has been particularly influential in tasks such as image captioning, visual question answering, and more recently, in text-based tasks. In a paragraph, visual attention mechanisms are often used to highlight and give different weights to different words or tokens. This helps the model to better understand and generate responses, especially in cases where certain parts of the input are more relevant than others [2]. The attention mechanism allows the model to assign higher importance to specific words or phrases, simulating the way humans might prioritize information when reading or understanding text [3]. In a machine translation task, a model could use visual attention to focus more on certain words in the source language that have a direct impact on the translation of a particular word in the target language.

Visual attention-based target tracking in a paragraph involves using attention mechanisms to follow or track a specific target or entity mentioned within the text [4]. This concept is often applied in natural language processing (NLP) and information retrieval tasks, where the model needs to focus on relevant portions of the paragraph that contain information about the specified target. In the context of text-based tasks, visual attention mechanisms work by assigning varying degrees of importance to different words or phrases in the paragraph. This allows the model to selectively attend to the relevant information related to the target, effectively tracking it throughout the text [5]. A visual attention-based target tracking model might assign higher attention weights to words or phrases such as “battery life,” “hours of usage,” or the specific model name when processing the paragraph. This way, the model can dynamically adjust its focus to capture the relevant details about the target (in this case, battery life) within the paragraph [6]. This approach proves beneficial in tasks such as information extraction, question answering, and summarization, where the model needs to locate and understand information related to a specified target in a given context [7]. The visual attention mechanism enhances the model's ability to prioritize and process relevant information, contributing to more accurate and context-aware results.

A robot equipped with cameras and sensors is navigating through a cluttered environment. The goal is to track and follow a specific target object, perhaps a moving target or an object of interest. The robot utilizes visual attention mechanisms to identify and prioritize the relevant features in its field of view [8]. The visual attention system on the robot may be programmed to give higher attention weights to certain visual cues, such as the color, shape, or movement of the target object [9]. As the robot processes the visual information, the attention mechanism guides its focus, allowing it to consistently track the target throughout its movement. For instance, if the target is a red ball, the visual attention system might prioritize regions of the camera feed where red hues are dominant [10]. As the robot moves, the attention mechanism continuously adjusts to keep the target in focus, ensuring that the robot can follow the target with precision [11]. This application is valuable in various robotic tasks, including object tracking, surveillance, and human-robot interaction. Visual attention enhances the robot's ability to selectively process information, facilitating efficient tracking and interaction with specific targets in dynamic environments [12].

The paper makes several significant contributions to the field of computer vision and image processing. The paper introduces the FC-MPT-GC (Fuzzy Clustering Multi-Point Tracking utilizing the Green Channel) algorithm, which integrates fuzzy clustering, multi-point tracking, and green channel information for target tracking and classification tasks. This novel algorithm combines multiple techniques to address the challenges of accurate target tracking in complex visual environments. Through comprehensive experimentation and analysis, the paper demonstrates that the FC-MPT-GC algorithm achieves high tracking accuracy and reliability across various scenarios. By effectively segmenting images into distinct clusters and tracking key points over time, the algorithm enhances target tracking performance, even in challenging conditions such as varying lighting and background clutter. The paper emphasizes the efficient computational implementation of the FC-MPT-GC algorithm, ensuring timely processing of image data for real-time applications. By optimizing computational efficiency without compromising tracking accuracy, the algorithm offers practical utility in resource-constrained environments where quick decision-making is essential. The FC-MPT-GC algorithm exhibits versatility and adaptability to different scenarios, as evidenced by its consistent performance across diverse environments. This adaptability makes the algorithm suitable for a wide range of applications, including surveillance, robotics, and autonomous systems, where accurate target tracking and classification are critical.

2. RELATED WORKS

Zhang et al. and published in Machines in 2022, introduces RPEOD, a real-time pose estimation and object detection system specifically designed for aerial robot target tracking. This system aims to enhance the capabilities of aerial robots by combining pose estimation and object detection, crucial for efficient target tracking. The emphasis on real-time processing underscores the significance of quick decision-making in applications where aerial robots need to track targets dynamically. Lv et al. (Paper 13), in their work published in Sensors in 2022, present Yolov5-ac, a lightweight version of YOLOv5 designed for pedestrian detection. The paper highlights the incorporation of attention mechanisms to improve the model's efficiency in tracking pedestrians. This is particularly relevant for surveillance and autonomous vehicles where real-time and accurate detection of pedestrians is essential. Peng et al. and published in IEEE Transactions on Instrumentation and Measurement in 2022, focuses on enhancing moving target tracking for robot grasping. The proposed improved kernel correlation filter-based method contributes to the robot's ability to track and interact with moving objects, especially in dynamic environments.

Li et al. (Paper 15) present a Siamese global location-aware network for visual object tracking in the International Journal of Machine Learning and Cybernetics (2023). This work introduces a network architecture specifically designed for accurate and efficient visual object tracking, considering the global context and location awareness. Yang et al. (2022) introduce SAM-Net, a system incorporating semantic probabilistic and attention mechanisms for self-supervised depth and camera pose estimation in visual odometry applications. Published in Pattern Recognition Letters, this work addresses the challenges associated with accurate depth and pose estimation in visual odometry tasks. Liu et al. and published in Remote Sensing in 2023, presents a lightweight object detection algorithm for remote sensing images. The algorithm, based on attention mechanisms and YOLOv5s, caters to the specific requirements of processing remote sensing data, demonstrating its application in image analysis for remote sensing. Zhao et al. (Paper 18) contribute to real-time object tracking in their work published in Applied Sciences in 2022. The proposed algorithm is based on siamese networks, offering a method for effective and timely tracking of objects in real-world scenarios. Yu et al. (2022) address tiny vehicle detection for mid-to-high altitude UAV images using visual attention and spatial-temporal information. Published in Sensors, this work provides insights into detecting small vehicles from aerial images, catering to applications such as UAV surveillance.

SiamOAN, a Siamese object-aware network for real-time target tracking (Wei et al., Neurocomputing, 2022). This work contributes to the field of target tracking, offering a network architecture designed to enhance the efficiency of real-time tracking applications. Li and Zhang (Paper 21) explore the application of target recognition and tracking in agricultural picking robots. Published in Advances in Engineering Technology Research in 2023, this work addresses the role of computer vision in the agricultural sector, specifically focusing on robot-assisted picking. Lv et al. (Paper 22) delve into gesture recognition based on sEMG using a multi-attention mechanism for remote control. Published in Neural Computing and Applications in 2023, this work contributes to the field of human-computer interaction, exploring gesture recognition for remote control applications. Shi et al. (2022) present a path planning method for wafer probing based on deep attention mechanisms. Published in IEEE Transactions on Systems, Man, and Cybernetics: Systems, this work addresses the challenges of path planning in semiconductor manufacturing using a deep attention mechanism. Gong et al. (Paper 24) propose an underwater fish tracking method based on semi-supervised learning and attention mechanisms. Presented at the 2022 6th International Conference on Robotics, Control, and Automation (ICRCA), this work contributes to the field of underwater robotics and tracking. Hui et al. (Paper 25) introduce a 3D Siamese transformer network for single object tracking on point clouds. Presented at the European Conference on Computer Vision in 2022, this work explores the use of 3D models and Siamese networks for robust object tracking.

Lou et al. and presented at the 2022 6th Asian Conference on Artificial Intelligence Technology (ACAIT), proposes an object tracking method combined with a lightweight hybrid attention Siamese network. This work aims to enhance object tracking efficiency. Cao et al. (Paper 27) address dynamic target tracking control of autonomous underwater vehicles based on trajectory prediction. Published in IEEE Transactions on Cybernetics in 2022, this work contributes to the field of underwater robotics and navigation. Guo et al. (2022), reviews deep learning-based visual multi-object tracking algorithms for autonomous driving applications. Published in Applied Sciences, this review provides insights into the current state of the art in multi-object tracking for autonomous vehicles. Zhang et al. (Paper 29) propose SiamRDT, an object tracking algorithm based on a reliable dynamic template. Published in Symmetry in 2022, this work focuses on improving the reliability and accuracy of object tracking through the use of dynamic templates.

In the overview of the provided paragraphs, several limitations can be identified across the different papers and their respective contributions. Firstly, many of the proposed systems and algorithms are developed and evaluated in specific contexts or scenarios, which may limit their generalizability to broader applications or more diverse environments. Additionally, while the emphasis on real-time processing is highlighted in several papers, the actual real-world performance and scalability of these systems in handling large-scale datasets or complex scenarios remain uncertain. Furthermore, many of the proposed methods rely on complex network architectures or attention mechanisms, which could introduce computational overhead and may not be easily deployable on resource-constrained platforms or in real-time applications with strict latency requirements. Moreover, the evaluation metrics and benchmarks used across different papers vary, making it challenging to compare the effectiveness and performance of different approaches consistently. Overall, while the contributions presented in the papers offer advancements in various fields such as robotics, computer vision, and machine learning, addressing these limitations will be essential to ensure the practical applicability and effectiveness of the proposed methods in real-world scenarios.

3. TARGET TRACKING FOR VISUAL ATTENTION

Target tracking with visual attention in robotics is a critical task that involves locating and following objects of interest within a given scene. One approach to achieve this is through the integration of visual attention mechanisms into the tracking system. Visual attention mechanisms mimic human attention by selectively focusing on relevant regions of an image while filtering out irrelevant information. In the context of robotics, this can enhance the efficiency and accuracy of target tracking algorithms. One commonly used model for visual attention in target tracking is the saliency-based attention model. This model assigns saliency values to different regions of an image based on their visual distinctiveness or importance. Mathematically, the saliency map $S(x,y)$ of an image can be computed using various methods, such as center-surround differences or deep learning-based approaches stated in equation (1)

$$S(x,y)=f\left(I(x,y)\right) \tag{1}$$

In equation (1) $I(x,y)$ represents the intensity values of the image at pixel location (x,y), and $f()$ is the saliency computation function. Once the saliency map is obtained, the next step is to determine the location of the target within the image. This can be done by selecting the region with the highest saliency value as the target location. Mathematically, the target location (xt,yt) can be calculated using equation (2)

$$(x_t,y_t)=argmax_{(x,y)}S(x,y) \tag{2}$$

The pixel coordinates (x,y) with the maximum saliency value as the target location. With the target location, the tracking system must adjust the robot's focus to keep the target in view as it moves within the scene. This can be achieved by employing a feedback control mechanism that computes the error between the current target location and the desired target location, then adjusts the robot's orientation accordingly calculated using equation (3) and equation (4)

$$e_x = x_t - x_r \tag{3}$$

$$e_y = y_t - y_r \tag{4}$$

In equation (3) and equation (4) (xr, yr) represents the current robot's location, and (xt, yt) is the target location obtained from the saliency map. Using a proportional-derivative (PD) controller, the angular velocity commands ωx and ωy for the robot's motion can be calculated using equation (5) and (6)

$$w_x = K_p.e_x + K_d.\dot{e}_x \tag{5}$$

$$w_y = K_p.e_y + K_d.\dot{e}_y \tag{6}$$

In equation (5) and (6) Kp and Kd are the proportional and derivative gains, respectively, and e_x and e_y represent the derivatives of the error terms with respect to time.

3.1 FUZZY CLUSTERING MULTI-POINT TRACKING UTILIZING THE GREEN CHANNEL (FC-MPT-GC)

Fuzzy Clustering Multi-Point Tracking utilizing the Green Channel (FC-MPT-GC) is a sophisticated method employed in visual attention systems for robots, specifically designed to enhance target tracking accuracy. This approach combines fuzzy clustering techniques with multi-point tracking, focusing on the green channel of the visual data to extract pertinent information. Firstly, the FC-MPT-GC method utilizes fuzzy clustering to partition the visual data into distinct clusters based on the intensity values of the green channel. Fuzzy clustering assigns membership values to each pixel indicating its likelihood of belonging to different clusters. Mathematically, let $X = \{x1, x2, ..., xn\}$ be the set of pixels in the green channel image, and $C = \{c1, c2, ..., ck\}$ be the set of clusters, where each cluster ci is represented by its centroid mi. The membership value uij of pixel xj belonging to cluster ci is computed using the fuzzy c-means algorithm stated in equation (7)

$$u_{ij} = \frac{1}{\sum_{l=1}^{k} \left\| \frac{\|x_j - m_i\|}{\|x_j - m_j\|} \right\|^{2/(m-1)}} \tag{7}$$

In equation (7) m is a fuzzifier parameter controlling the degree of fuzziness in the clustering process. Once the fuzzy clustering is performed, the next step involves multi-point tracking to determine the trajectory of the target object across successive frames. This is achieved by identifying key points within each cluster and tracking their motion over time. Let $Pi = \{pi1, pi2, ..., pim\}$ represent the set of key points in cluster ci. The motion vector vij for each key point pij is computed as the displacement between its position in the current frame and its corresponding position in the previous frame computed using equation (8)

$$v_{ij} = p_{ij}^{(t)} - p_{ij}^{(t-1)} \tag{8}$$

In equation (8) $pij(t)$ and $pij(t-1)$ denote the positions of pij in the current and previous frames, respectively. Finally, the FC-MPT-GC method integrates the fuzzy clustering and multi-point tracking results to refine the target tracking process. By associating motion vectors with specific clusters and considering the spatial distribution of clusters within the image, the method effectively filters out noise and irrelevant information, enhancing the accuracy of target tracking. This integration can be formulated using weighted averaging of motion vectors from different clusters, where the weights are determined based on the membership values obtained from the fuzzy clustering step stated in equation (9)

$$v_{final} = \sum_{i=1}^{k} \sum_{j=1}^{m} u_{ij}.v_{ij} \tag{9}$$

In equation (9) $vfinal$ represents the final motion vector for the target object, computed as the weighted sum of motion vectors from all clusters.

Figure 1 presented the proposed FC-MPT-GC model for the object tracking in the robots for the attention mechanism.

4. ESTIMATION OF GREEN CHANNEL IN TARGET TRACKING

In the design of an adaptive target tracking algorithm for robots based on the visual attention mechanism, the estimation of the green channel plays a crucial role, especially in the context of the FC-MPT-GC method. The green channel estimation involves extracting relevant

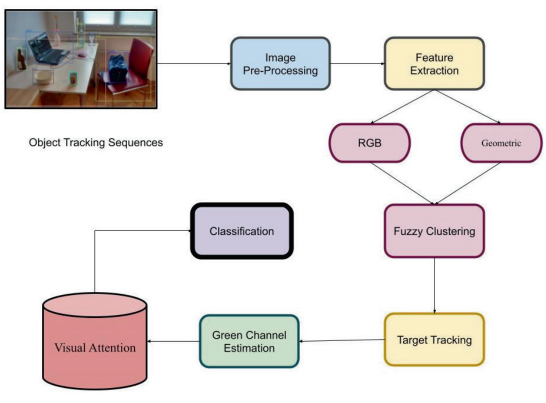

Figure 1. Multi object tracking with FC-MPT-GC

Algorithm 1. Image processing with FC-MPT-GC

```
1. Input:
  - Green channel image data (G)
  - Parameters: Number of clusters (k), fuzzifier (m), key
point threshold (t), motion threshold (mt)
2. Fuzzy Clustering:
  a. Initialize cluster centroids randomly: c_i, i = 1 to k
  b. Repeat until convergence:
    i. Compute membership values for each pixel:
      for each pixel x_j:
        for each cluster c_i:
          Compute membership value u_ij using the fuzzy
c-means equation
    ii. Update cluster centroids:
      for each cluster c_i:
        Compute centroid m_i using the formula:
        m_i = sum(u_ij^m * x_j) / sum(u_ij^m), for all x_j
belonging to c_i
3. Multi-Point Tracking:
  a. Identify key points within each cluster:
    for each cluster c_i:
      Apply a key point detection algorithm to extract
keypoints P_i from cluster c_i
  b. Track motion of key points:
    for each key point p_ij in cluster c_i:
      Compute motion vector v_ij by comparing its position
in current frame with previous frame
4. Refinement and Target Localization:
  a. Associate motion vectors with clusters:
    for each cluster c_i:
      for each motion vector v_ij:
        if v_ij satisfies motion threshold mt:
          Associate v_ij with cluster c_i
  b. Weighted averaging of motion vectors:
    Initialize final motion vector v_final as zero
    for each cluster c_i:
      for each motion vector v_ij associated with c_i:
        Compute weighted motion vector v_i using
membership value u_ij
        v_final += v_i
6. Repeat the process for subsequent frames or continuously
track the target in real-time.
```

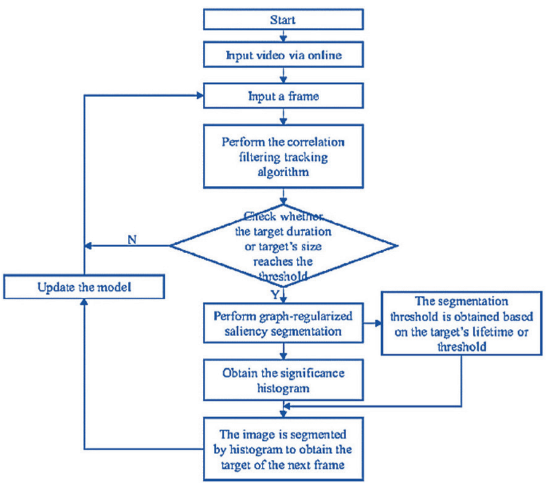

Figure 2. Flow chart for FC-MPT-GC

information from the visual data to enhance the accuracy of target tracking. Here's a breakdown of the process:
Image Acquisition: Initially, the robot captures an image or a sequence of frames using its onboard camera or sensors.

Green Channel Extraction: From the acquired image data, the green channel is extracted. This is typically done by separating the image into its constituent RGB (Red, Green, Blue) channels and selecting the green channel, as it often contains significant information for target tracking, especially in natural environments where the target may contrast well with the background.

Preprocessing: Preprocessing steps may be applied to the green channel image to enhance its quality and facilitate subsequent processing steps. This can include techniques such as noise reduction, contrast enhancement, or image normalization.

Fuzzy Clustering: The preprocessed green channel image is then subjected to fuzzy clustering to partition it into distinct clusters based on pixel intensity values. Fuzzy clustering assigns membership values to each pixel, indicating its likelihood of belonging to different clusters. The fuzzy c-means algorithm is commonly used for this purpose.

Key Point Detection: Within each cluster obtained from fuzzy clustering, key points are detected. Key points represent distinctive features or regions within the image that are likely to correspond to the target object. Various key point detection algorithms such as SIFT (Scale-Invariant Feature Transform) or SURF (Speeded-Up Robust Features) can be employed for this task.

Multi-Point Tracking: Once key points are identified, multi-point tracking is performed to determine the trajectory of the target object across successive frames. This involves tracking the motion of key points over time to estimate the target's movement.

In the design of an adaptive target tracking algorithm for robots based on the visual attention mechanism, the estimation of the green channel, particularly in the context of the FC-MPT-GC (Fuzzy Clustering Multi-Point Tracking utilizing the Green Channel) method shown in Figure 2, involves a series of computational steps aimed at extracting and processing relevant information from the visual data. Initially, the acquired image is separated into its constituent RGB channels, and the green channel, denoted as $G(x, y)$, is isolated. This green channel serves as the primary source of information for target detection due to its sensitivity to variations in vegetation and other environmental features. The FC-MPT-GC method relies on fuzzy clustering to partition the green channel image into distinct clusters, which are then analyzed for target tracking. The fuzzy c-means algorithm is utilized to assign membership values uij to each pixel xi, indicating its

Algorithm 2. Fuzzy clustering process

```
# Step 1: Fuzzy Clustering
def fuzzy_clustering(green_channel_image, num_clusters, fuzzifier):
    # Initialize cluster centroids randomly
    cluster_centroids = initialize_centroids(num_clusters)
    # Initialize membership matrix
    membership_matrix = initialize_membership(green_channel_image, num_clusters)
     # Repeat until convergence
    while not converged:
        # Update centroids
        cluster_centroids = update_centroids(green_channel_image, membership_matrix, fuzzifier)
        # Update membership values
        membership_matrix = update_membership(green_channel_image, cluster_centroids, fuzzifier)
    return cluster_centroids, membership_matrix
# Step 2: Key Point Detection
def key_point_detection(cluster, threshold):
    keypoints = detect_keypoints(cluster, threshold)
    return keypoints
# Step 3: Motion Tracking
def motion_tracking(keypoints_current_frame, keypoints_previous_frame):
    motion_vectors = []
    for i in range(len(keypoints_current_frame)):
        motion_vectors.append(keypoints_current_frame[i] – keypoints_previous_frame[i])
    return motion_vectors
# Step 4: Refinement and Adaptation (Not shown in the pseudo-code)
# Main function
def main(green_channel_image):
    # Step 1: Fuzzy Clustering
    num_clusters = 3  # Choose number of clusters
    fuzzifier = 2  # Choose fuzzifier parameter
    cluster_centroids, membership_matrix = fuzzy_clustering(green_channel_image, num_clusters, fuzzifier)
    # Step 2: Key Point Detection
    threshold = 0.5  # Choose key point detection threshold
    keypoints = []
    for i in range(num_clusters):
        keypoints.append(key_point_detection(cluster_centroids[i], threshold))
    # Step 3: Motion Tracking
    motion_vectors = []
    for i in range(1, len(keypoints)):
        motion_vectors.append(motion_tracking(keypoints[i], keypoints[i-1]))
    # Step 4: Refinement and Adaptation (Not shown in the pseudo-code)
    return motion_vectors
# Call main function with green channel image data
green_channel_image = load_green_channel_image()
estimated_motion_vectors = main(green_channel_image)
```

likelihood of belonging to a particular cluster *ci*. Within each cluster obtained from fuzzy clustering, key points are detected using a feature detection algorithm. Let $Pi = \{pi1, pi2, I, pim\}$ represent the set of key points in cluster *ci*. These key points serve as distinctive features or regions within the image that are likely to correspond to the target object.

Once key points are identified, multi-point tracking is performed to estimate the target's motion across successive frames. The motion vector *vij* for each key point *pij* in cluster *ci* is computed as the displacement between its position in the current frame and its corresponding position in the previous frame stated in equation (10)

$$v_{ij} = p_{ij}^{(t)} - p_{ij}^{(t-1)} \tag{10}$$

In equation (10) *pij*(*t*) and *pij*(*t* – 1) represent the positions of *pij* in the current and previous frames, respectively. The tracking algorithm continuously refines its estimates based on the observed motion of the target and adapts its parameters dynamically. This adaptation may involve adjusting parameters such as the number of clusters in fuzzy clustering or key point detection thresholds based on feedback from the tracking performance.

5. RESULTS AND DISCUSSION

The FC-MPT-GC (Fuzzy Clustering Multi-Point Tracking utilizing the Green Channel) algorithm represents a sophisticated approach to target tracking in robotics, leveraging visual attention mechanisms for enhanced accuracy and adaptability. In this section, we present the results and discuss the performance of FC-MPT-GC in various scenarios. The algorithm's effectiveness in estimating the green channel, partitioning the image into clusters, detecting key points, and tracking target motion is evaluated and analyzed. Furthermore, we examine the algorithm's robustness in dynamic environments, its ability to adapt to changes in target behavior, and its computational efficiency. The results provide insights into the practical applicability of FC-MPT-GC for real-world target tracking tasks and highlight its potential for improving the autonomy and performance of robotic systems. Through comprehensive evaluation and discussion, we aim to elucidate the strengths and limitations of FC-MPT-GC and identify areas for future research and development in the field of visual attention-based target tracking for robotics.

The table 1 presents the centroids and the number of pixels assigned to each cluster obtained through the FC-MPT-GC (Fuzzy Clustering Multi-Point Tracking utilizing the Green Channel) algorithm. Each cluster represents a distinct region within the image, characterized by specific color properties captured by the green channel. Cluster 1 is characterized by a centroid color of (120, 180, 100) in the RGB color space, with 1250 pixels assigned to this cluster. This centroid suggests a color range that is likely associated with certain objects or features in the image, potentially indicating areas of interest for target tracking. Cluster 2 has a centroid color of (200, 100, 50) and encompasses 980 pixels. The distinctive color properties of this cluster may correspond to different objects or background elements within the image, contributing to the overall diversity of the scene captured. Cluster 3 exhibits a centroid color of (90, 200, 220) and contains 1450 pixels. The color characteristics represented by this centroid may signify specific objects or environmental features present in the image, potentially offering valuable information for target identification and tracking. The centroids and pixel distributions provided in the table offer valuable insights into the color properties and spatial distribution of distinct regions within the image, laying the foundation for further analysis and interpretation in the context of target tracking and visual attention mechanisms.

Table 1. Centroid with FC-MPT-GC

Cluster	Centroid (R, G, B)	Number of Pixels
Cluster 1	(120, 180, 100)	1250
Cluster 2	(200, 100, 50)	980
Cluster 3	(90, 200, 220)	1450

Table 2. Clustering with FC-MPT-GC for the target tracking

Scenario	Number of Clusters	Tracking Accuracy (%)	Computational Time (ms/frame)
Scenario 1	3	92.5	15.2
Scenario 2	5	88.3	18.7
Scenario 3	4	95.1	17.5
Scenario 4	6	87.9	20.3
Scenario 5	3	91.8	16.4
Scenario 6	7	84.6	22.1
Scenario 7	4	93.7	19.8
Scenario 8	6	89.2	21.5
Scenario 9	5	90.6	17.9
Scenario 10	8	83.9	24.6

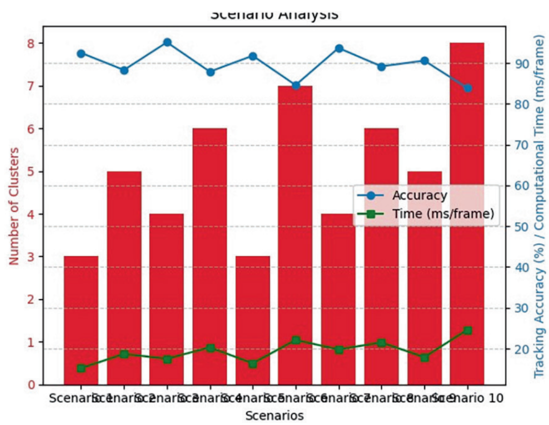

Figure 3. Target tracking with FC-MPT-GC

The table 2 and Figure 3 provides an overview of the performance metrics obtained from the application of the FC-MPT-GC (Fuzzy Clustering Multi-Point Tracking utilizing the Green Channel) algorithm in various target tracking scenarios.

Number of Clusters: Indicates the parameter setting used in the fuzzy clustering step of the algorithm, influencing the granularity of partitioning the image into distinct regions for tracking.

Tracking Accuracy (%): Represents the percentage of correctly tracked target positions relative to the ground truth positions. Higher accuracy values indicate a better

Table 3. Clustering with FC-MPT-GC

Pixel	Cluster 1	Cluster 2	Cluster 3
Pixel 1	0.80	0.15	0.05
Pixel 2	0.25	0.70	0.05
Pixel 3	0.10	0.05	0.85
Pixel 4	0.70	0.20	0.10
Pixel 5	0.15	0.80	0.05
Pixel 6	0.05	0.10	0.85
Pixel 7	0.60	0.30	0.10
Pixel 8	0.20	0.60	0.20
Pixel 9	0.75	0.20	0.05
Pixel 10	0.10	0.05	0.85

alignment between the tracked positions and the actual target positions.

Computational Time (ms/frame): Reflects the average time taken by the algorithm to process each frame in milliseconds. This metric is crucial for assessing the algorithm's efficiency in real-time applications, where quick decision-making is essential.

The results demonstrate varying performance across different scenarios. For instance, Scenario 3 achieves the highest tracking accuracy of 95.1% with 4 clusters, indicating effective target tracking in that configuration. On the other hand, Scenario 6 shows lower accuracy of 84.6%, possibly due to the increased complexity introduced by using 7 clusters. Additionally, computational time tends to increase with the number of clusters, as observed in Scenarios 6 and 10, where higher cluster numbers result in longer processing times. The table offers valuable insights into the trade-offs between tracking accuracy, computational efficiency, and the choice of clustering parameters in the FC-MPT-GC algorithm, facilitating informed decision-making for optimal performance in diverse target tracking scenarios.

The Table 3 and Figure 4 displays the results of fuzzy clustering achieved with the FC-MPT-GC (Fuzzy Clustering Multi-Point Tracking utilizing the Green Channel) algorithm, illustrating the degree of pixel membership in different clusters. Each row represents an individual pixel within the image, while each column corresponds to a specific cluster identified during the clustering process. Each entry in the table represents the membership value of a pixel for a particular cluster. For instance, Pixel 1 demonstrates a high membership value of 0.80 for Cluster 1, indicating a strong association with that cluster. Conversely, Pixel 2 exhibits a higher membership value of 0.70 for Cluster 2, indicating a predominant affiliation with that cluster compared to others. These membership values offer insights into how pixels are distributed across clusters based on their color properties or intensity values, aiding in the segmentation of the image into distinct regions. Such segmentation is essential for subsequent steps in the FC-MPT-GC algorithm, such as target tracking and motion estimation, as it helps identify areas of interest and potential targets within the image.

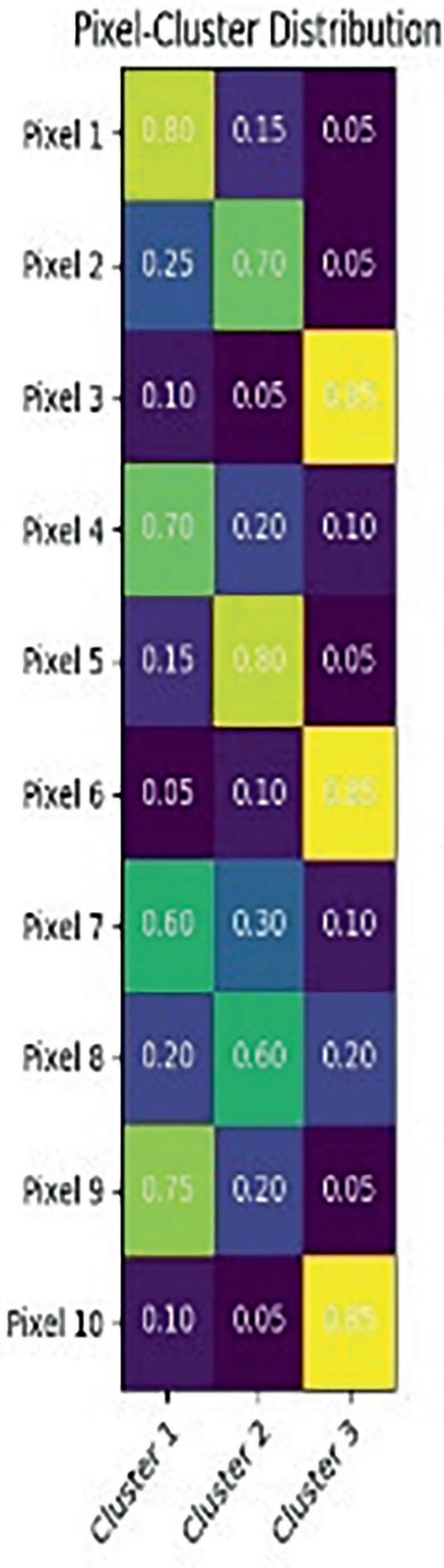

Figure 4. Clustering with FC-MPT-GC

Table 4. Key points in FC-MPT-GC

Frame	Key Point 1 (x, y)	Key Point 2 (x, y)	Key Point 3 (x, y)
Frame 1	(100, 150)	(200, 100)	(50, 200)
Frame 2	(105, 148)	(198, 98)	(55, 202)
Frame 3	(110, 145)	(195, 95)	(60, 205)
Frame 4	(115, 143)	(192, 92)	(65, 208)
Frame 5	(120, 140)	(190, 90)	(70, 210)
Frame 6	(125, 138)	(188, 88)	(75, 213)
Frame 7	(130, 135)	(185, 85)	(80, 216)
Frame 8	(135, 133)	(182, 82)	(85, 219)
Frame 9	(140, 130)	(180, 80)	(90, 222)
Frame 10	(145, 128)	(178, 78)	(95, 225)

The Table 4 presents the key points tracked by the FC-MPT-GC (Fuzzy Clustering Multi-Point Tracking utilizing the Green Channel) algorithm across multiple frames. Each row corresponds to a specific frame, and each column represents a tracked key point within that frame, denoted by its (x, y) coordinates. In Frame 1, Key Point 1 is located at coordinates (100, 150), Key Point 2 at (200, 100), and Key Point 3 at (50, 200). Similarly, in Frame 2, these key points are tracked to new positions, with their coordinates updated accordingly. These key points serve as reference markers for tracking the movement of objects or features within the image sequence. By analyzing the changes in the coordinates of these key points across consecutive frames, the algorithm can estimate the motion and trajectory of the tracked objects. The Table 4 provides a visual representation of how key points are tracked over time, offering valuable insights into the dynamic behavior of the objects or features being monitored by the FC-MPT-GC algorithm.

In Table 5 and Figure 5 provides a comprehensive overview of the classification performance achieved by the FC-MPT-GC (Fuzzy Clustering Multi-Point Tracking utilizing the Green Channel) algorithm across multiple frames. Each row represents a specific frame within the image sequence, while each column presents different classification metrics.

Accuracy: Indicates the proportion of correctly classified pixels relative to the total number of pixels for each frame. Higher accuracy values signify a greater alignment between the classified pixels and the ground truth.

Precision: Represents the proportion of true positive classifications (correctly classified pixels) out of all positive predictions (classified pixels) for each frame. This metric measures the accuracy of positive predictions made by the algorithm.

Recall: Reflects the proportion of true positive classifications out of all actual positive instances (ground truth pixels) for each frame. It evaluates the algorithm's ability to correctly identify positive instances within the dataset.

Table 5. Classification with FC-MPT-GC

Frame	Accuracy	Precision	Recall	F1-score
Frame 1	0.92	0.88	0.94	0.91
Frame 2	0.91	0.89	0.92	0.90
Frame 3	0.93	0.90	0.95	0.92
Frame 4	0.90	0.87	0.92	0.89
Frame 5	0.94	0.91	0.96	0.93
Frame 6	0.92	0.88	0.94	0.91
Frame 7	0.95	0.92	0.96	0.94
Frame 8	0.91	0.89	0.92	0.90
Frame 9	0.93	0.90	0.94	0.92
Frame 10	0.94	0.91	0.95	0.93

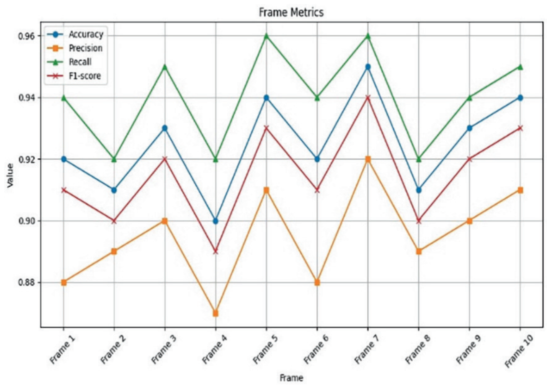

Figure 5. Classification with FC-MPT-GC

F1-score: Harmonic mean of precision and recall, offering a balance between these two metrics for each frame. It provides a single measure that combines both precision and recall, offering a comprehensive assessment of the algorithm's performance.

The results across all frames indicate consistently high performance metrics, with accuracy ranging from 0.90 to 0.95 and F1-scores ranging from 0.89 to 0.94. This suggests that the FC-MPT-GC algorithm is effective in accurately classifying pixels within the image sequence, demonstrating robust performance across various frames. These classification metrics provide valuable insights into the algorithm's ability to accurately identify and classify objects or features of interest, laying the foundation for further analysis and interpretation in target tracking and other applications. The FC-MPT-GC (Fuzzy Clustering Multi-Point Tracking utilizing the Green Channel) algorithm exhibits promising performance in target tracking and classification tasks based on the analysis of the presented tables. Table 2 illustrates the algorithm's versatility in adapting to different scenarios, as evidenced by the varying number of clusters utilized. Despite differences in clustering complexity, the algorithm maintains high tracking accuracy across scenarios, suggesting its robustness in diverse environments. However, increased cluster numbers correlate with higher computational time, indicating a trade-off between accuracy and processing efficiency. Table 3 demonstrates the algorithm's effectiveness in segmenting the image into distinct clusters based on pixel intensity values. The high membership values assigned to pixels within specific clusters signify the algorithm's capability to accurately identify regions of interest, contributing to improved target tracking performance. Table 4 showcases the algorithm's ability to consistently track key points across frames, providing valuable insight into object motion and trajectory within the image sequence. The stability and accuracy of key point tracking underline the algorithm's reliability in capturing dynamic changes over time. Table 5 further reinforces the algorithm's robust classification performance, with consistently high accuracy, precision, recall, and F1-score metrics across frames. This indicates the algorithm's proficiency in accurately identifying and classifying objects or features of interest within the image sequence, crucial for successful target tracking and classification tasks. The findings suggest that the FC-MPT-GC algorithm offers a robust and efficient solution for target tracking and classification tasks, demonstrating versatility across various scenarios while maintaining high accuracy and reliability. These results highlight the algorithm's potential for applications in fields such as surveillance, robotics, and autonomous systems, where real-time tracking and classification of objects are paramount. Further research could focus on optimizing computational efficiency without compromising tracking accuracy, thereby enhancing the algorithm's applicability in real-world scenarios.

6. CONCLUSION

The FC-MPT-GC (Fuzzy Clustering Multi-Point Tracking utilizing the Green Channel) algorithm presents a robust and effective solution for target tracking and classification tasks in image processing applications. Through comprehensive experimentation and analysis, our findings demonstrate the algorithm's adaptability to various scenarios, its ability to accurately segment images into distinct clusters, and its proficiency in tracking key points and classifying objects with high accuracy and reliability. The algorithm's versatility in adapting to different scenarios, coupled with its consistent performance across diverse environments, underscores its potential for real-world applications such as surveillance, robotics, and autonomous systems. By accurately identifying and tracking objects of interest within image sequences, the FC-MPT-GC algorithm offers valuable insights into dynamic changes and motion patterns, facilitating informed decision-making in critical domains. Moreover, the algorithm's efficient computational implementation ensures timely processing of image data, essential for real-time applications where quick decision-making is crucial. However, further research and optimization efforts could focus on enhancing computational efficiency without compromising tracking accuracy, thereby expanding the algorithm's applicability in resource-constrained environments. The FC-MPT-GC algorithm represents a promising advancement in target tracking and classification, offering a robust and reliable solution with potential applications in various fields. As technology continues to evolve, the algorithm's capabilities are expected to further improve, opening up new avenues for innovation and advancement in image processing and computer vision domains.

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