robotic process model of active visual search and scene grammar in naturalistic environments

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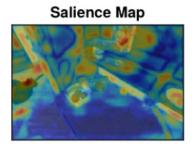
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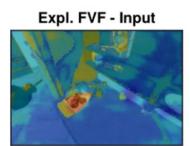
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Human-inspired active vision and scene grammar for cognitive robotics











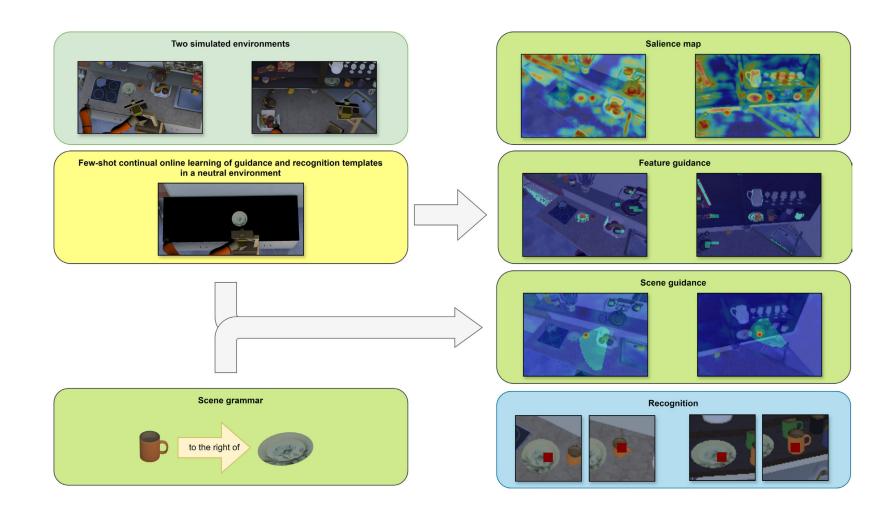


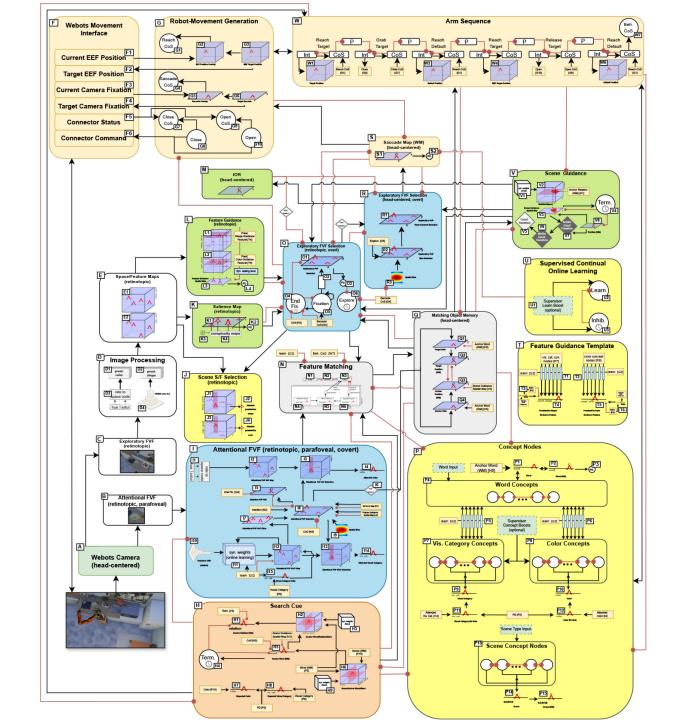


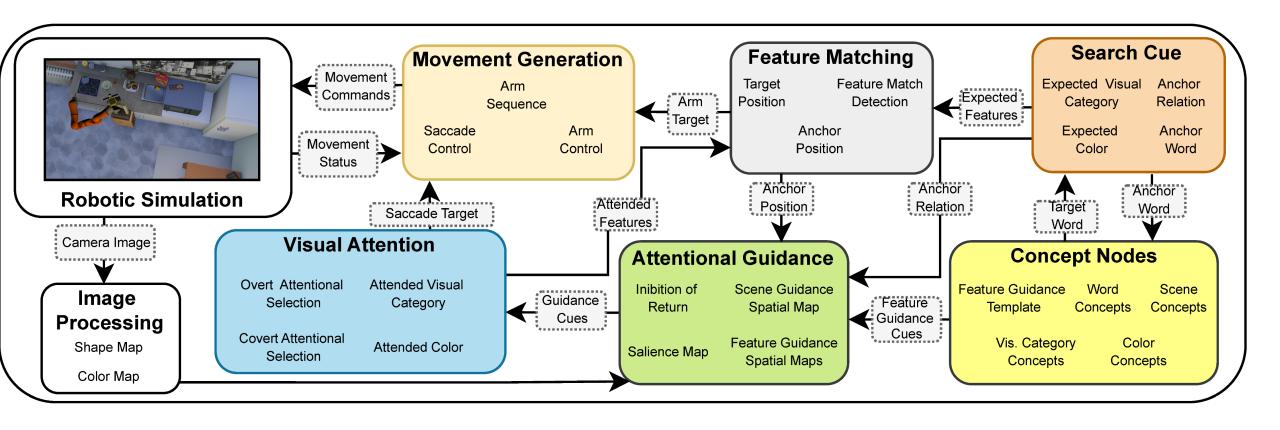
Challenges

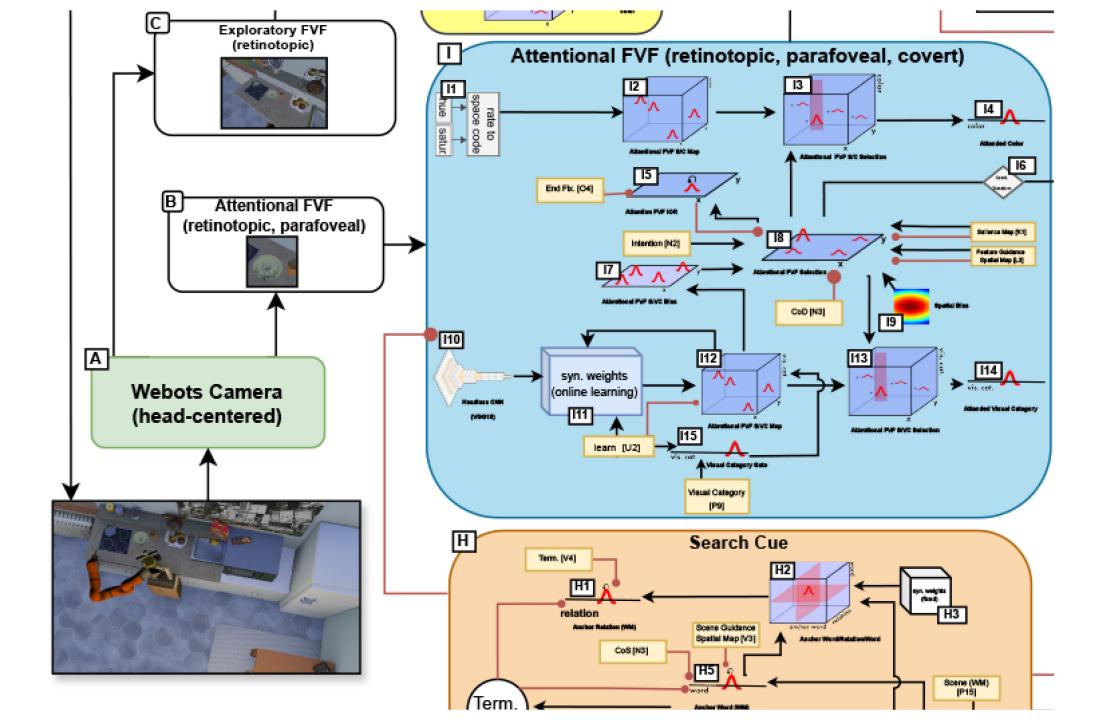
- Combine covert and overt attention:
 - Four coordinate systems: world, head, camera and image
 - Integrate space- and object-based inhibition of return
 - Find objects outside of the camera frame
- Integrate space- and object-based analysis
- Learn new objects with minimal human supervision
- Autonomous switching between exploration and visual search
- Learning while working (continual online learning)

Human-inspired active vision and scene grammar for cognitive robotics







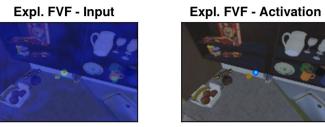








Salience Map Feature Guidance



Att. FVF - Sig. Activation

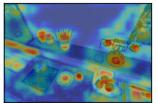


····Input: Cup ····Input: Banana - - Plate - - Cup - - Phone - - Banana - Saccade CoS - CoS









Expl. FVF - Input



Feature Guidance



Expl. FVF - Activation



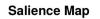
Att. FVF - Sig. Activation

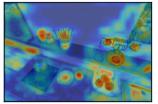


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Expl. FVF - Input



Feature Guidance



Expl. FVF - Activation



Att. FVF - Sig. Activation

