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The Development of a Low-Cost Robotic Visual Tracking System

***A thesis presented in partial fulfilment of the requirements for
the degree of***

Master of Engineering

Mechatronics

at Massey University, Albany, New Zealand.

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2009

ACKNOWLEDGMENT

I wish to express my gratitude to my supervisor, Dr. Johan Potgieter, who was abundantly helpful and offered invaluable assistance, support and guidance throughout the duration of the project.

Special thanks also to all my graduate friends, especially Biqing Chen and Baden Rielly for sharing the literature and invaluable assistance. Not forgetting to my best friend Jennifer who always been there.

I wish to express my gratitude to my beloved families, for their understanding and encouragement through my studies, in particular I would like to thank my parents for their love and patience, my brother Vince and my cousin Kevin, without their assistance this project would not have been made possible.

By The Author
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ABSTRACT

This thesis describes a system which is able to track and imitate human motion. The system is divided into two major parts: computer vision system and robot arm motion control system. Through the use of two real-time video cameras, computer vision system identifies the moving object depending on the colour features, as the object colour is matched within the colour range in the current image frame, a method that employs two vectors is used to calculate the coordinates of the object. After the object is detected and tracked coordinates are saved to a pre-establish database in the purpose of further data processing, a mathematical algorithm is performed to the data in order to give a better robotic motion control. Robot arm manipulator responds with a move within its workspace which corresponds to a consequential human-type motion. Experimental outcomes have shown that the system is reliable and can successfully imitate a human hand motion in most cases.

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