



SightLine

APPLICATIONS

EAN-Detection Modes

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**Contact:**

Web: sightlineapplications.com

Sales: sales@sightlineapplications.com

Support: support@sightlineapplications.com

Phone: +1 (541) 716-5137

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 **CAUTION:** Alerts to a potential hazard that may result in personal injury, or an unsafe practice that causes damage to the equipment if not avoided.

 **IMPORTANT:** Identifies crucial information that is important to setup and configuration procedures.

 *Used to emphasize points or reminds the user of something. Supplementary information that aids in the use or understanding of the equipment or subject that is not critical to system use.*



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1 Overview

This document provides information and guidelines on the parameters that primarily affect the detection modes. This document will focus on the settings that will have the most impact on detection performance, and those that will need some adjustment beyond their default settings.

To understand how these parameter settings impact performance, use this document during evaluating and testing.

1.1 Associated Documents

[EAN-Target Tracking](#) - Provide guidelines regarding the different parameters to set for optimal target tracking and scene tracking performance, as well as a list of commands used for tracking.

[Interface Command and Control Document \(IDD\)](#): Describes the native communications protocol used by the SightLine Applications product line.

Panel Plus User Guide: (Located in the Panel Plus application in the *Help* menu) Provides descriptions of all the settings in the Panel Plus application.

1.2 SightLine Software Requirements

ⓘ IMPORTANT: The Panel Plus software version should match the firmware version running on the board.

1.3 Application Bit Requirements

The functions described in this EAN require Application Bits (app bits) purchased from SightLine. App bits reside on the hardware unit and are enabled with a license file provided by SightLine at initial unit purchase or during a license upgrade process. License files use a hardware ID that is applicable to a specific hardware serial number. For questions and upgrade support contact [SightLine Sales](#).

Table 1: Application Bits Requirement Table

Detection Modes	Minimum Software Version	Required Application Bit(s)
Anomaly	ALL	Detection - Base. 0x0008
Blob	2.24.xx	Detection - Base. 0x0008
Gas	2.25.xx	Detection - Base. 0x0008
Radiometric	2.23.xx	Detection - Base. 0x0008
Staring	ALL	Detection - Base. 0x0008
Vehicle	ALL	Detection - Base. 0x0008
Aerial	ALL	Detection - Base + Advanced. 0x0028
Drone	2.24.xx	Detection - Base + Advanced. 0x0028
Drone w/ Classifier	2.25.xx	Detection - Base + Advanced. 0x0028
Maritime	2.23.xx	Detection - Base + Advanced. 0x0028



2 Detection Modes

The following six detection modes are currently supported.

Vehicle Moving Target Indication:

- Works best finding moving vehicles in a moving scene.
- Works well from a moving platform for finding objects that are typically 10 to 100 pixels long in the scene.
- Not suitable for finding very small, very large, slow, or erratically moving objects.
- Commonly used to assist in track designation. Detects up to 5 objects.



Drone Detection:

- Best for finding drones in a moving or stationary scene.
- Works well from moving or stationary platform for finding drones that are typically 10 to 100 pixels long in the scene.
- Best for tracking slow and erratically moving objects.
- Commonly used to assist in track designation. Detects up to 5 objects.
- Classification helps reduce operator workload by utilizing state of the art deep learning algorithms to reduce false positives



Staring Moving Target Indication:

- Works best from a ground camera that is either stationary or moves and then stares for an extended time at a scene.
- Detects objects that are small and move slow or fast, move at varying rates, or that temporarily stop.
- Detects up to 100 objects.



**Aerial Moving Target Indication:**

- Works best from a moving platform and can find small, slow moving objects.
- The only moving target mode capable of handling frame-to-frame perspective changes which makes it ideally suited for airborne applications.
- Takes the most computational resources and is likely to impact frame rate especially on the SLA-1500.
- Detects up to 100 objects.

**Anomaly Detection:**

- Works from a moving or stationary platform and finds objects that are unique in the scene based on color and intensity.
- Does not require objects to be moving to be detected.
- Detects up to 100 objects.

**Radiometric Detection:**

- Works from a moving or stationary platform and finds objects within a specified temperature range.
- Does not require objects to be moving to be detected.
- Detects up to 100 objects.



**Maritime Detection:**

- Works from a moving or stationary platform and finds objects in a maritime environment such as ships or life jackets.
- Does not require objects to be moving to be detected.
- Detects up to 100 objects.

**Blob Detection:**

- Works from a moving or stationary platform and finds objects that are light or dark compared to their surroundings.
- Does not require objects to be moving to be detected.
- Detects up to 100 objects.

**Gas Detection:**

- Works from a moving or stationary platform.
- Reduces operator workload.
- Enhances and colorizes gasses that are visible with specialized cameras sensitive in the methane absorption band.





3 Best Practices

The best place to start is to use the *Detect* default parameters in Panel Plus » *Tracking* tab » *Detect* tab (Figure 1). Adjust the sensitivity and notice how that changes the number of detections (both true and false detects).

Advanced detection settings can be found by clicking the Advanced button in the Detect tab.

The following sections will not describe every parameter in depth but will attempt to explain parameters that may need adjusted depending on the hardware setup and use case.

Processing at a constant frame rate is also important for detection performance. The display processing load can be reduced by setting a display frame step, turning off enhancement, choosing a faster encoder (MPEG4 for 1500), and using a smaller output frame size.

The Performance graphs in Panel Plus shows the time used by the processing steps. From the main menu go to View » Show Performance Graphs.

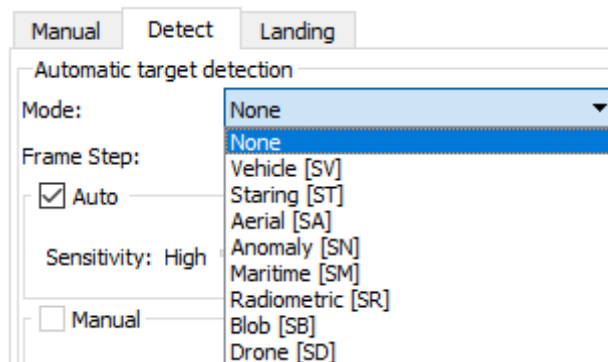


Figure 1: Automatic Target Detection Modes

3.1 Vehicle and Drone MTI

The primary parameter setting for Vehicle and Drone Detection MTI is *Sensitivity*. Use the default value as a starting point for easy adjustments. Other key settings are *Regions of Interest* and *Downsample* covered in the [Performance and Speed](#) section.

3.1.1 Acquisition Assist

In the **Set Tracking Parameters (0x0C)** message, the *Acquisition Assist* (Figure 2) setting has an impact on Vehicle and Drone MTI. It uses an algorithm, with hints of detection data, to make an optimal axis aligned bounding box for the target. If it is not enabled, only the detection data is used. It also works well if the scene is not cluttered. If the scene becomes too cluttered, it should be disabled.



3.1.2 Intelligent Assist

Enabling Intelligent Assist is useful in Drone Mode. Intelligent assist allows the track box to be resized as needed.

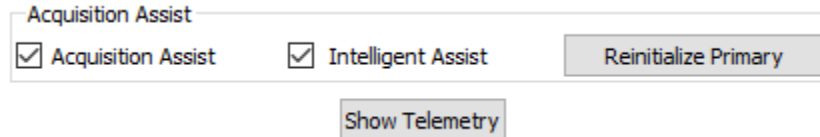


Figure 2: Acquisition and Intelligent Assist

3.1.3 Classification

The *Use Classifier* setting is only available on the 3000-OEM using drone detection mode. This enables a deep learning algorithm that continuously runs on the detections to reduce the number of false positives. When an object is detected in the scene the classifier will evaluate that object. If the object is labeled a drone a track is started, otherwise the detection is ignored. The classifier is also intermittently run on all tracks. If a track no longer classifies as a drone the track is dropped. The label and confidence the classifier assigned to a detection can be included in telemetry using the **Track Positions Extended (0xA0)** message.

3.2 Staring MTI

Parameters for this feature can be found by clicking the Advanced button in the Detect tab. The parameter settings for *Staring* and *Aerial MTI* are nearly identical. In most cases, the default values are sufficient. *Staring MTI* uses two additional parameters.

- **Average Time Constant:** The approximate amount of time to fully replace the background model.

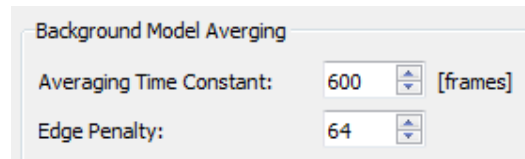


Figure 3: Staring Settings

- **Edge Penalty:** Applied to edges in the background model, minimizing small differences to reduce the number of false detects. The higher the value, the larger the penalty. Lowering the value allows smaller slower moving objects to be detected but may have more false detections.

Staring MTI requires the *Stationary Camera Low Drift* setting. This corresponds to setting the *Update Rate* in the Registration Parameters (0x9E) message to 10.

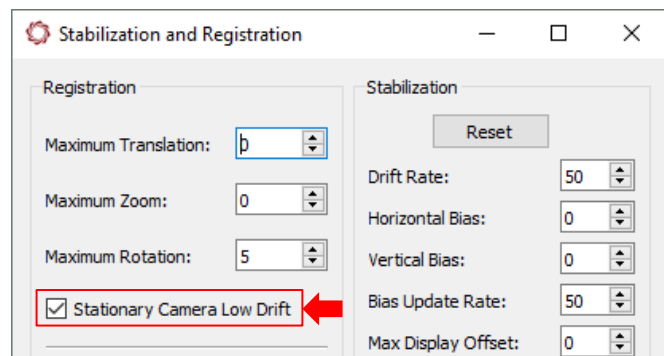


Figure 4: Stationary Camera Low Drift Setting



3.3 Aerial MTI

Parameters for this feature can be found by clicking the Advanced button in the Detect tab.

The *NframesBack* setting determines how far back in time to search.

Reductions in frame rates will need to be changed under certain circumstances. For example, if every other input frame is being skipped, the number may need to be lowered. The number should also be lowered for fast moving objects (between 6 and 15).

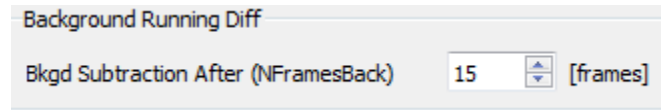


Figure 5: Aerial Settings

3.4 Anomaly, Radiometric, Blob, Maritime Detection

Parameters for this feature can be found by clicking the Advanced button in the Detect tab.

Use Registration: Anomaly, Radiometric, Blob, and Maritime detection modes use this parameter. It is used to control whether detections are tracked from frame to frame.

When looking for detections on each frame independent of other frames, i.e., when scanning a large area, disable this setting.

When slowly scanning or staring, use the registration results along with a higher number of watch frames to reduce the number of false detects.

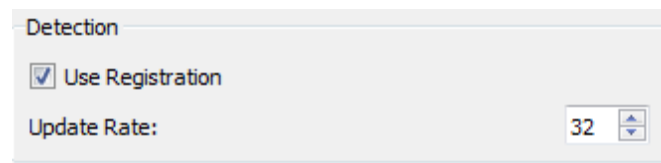


Figure 6: Anomaly, Radiometric, Maritime, Blob, Detection Settings

Update Rate: Anomaly and Maritime use this parameter. It controls how fast the detection model is updated. Larger values put more emphasis on the current frame. Typical values are in the 8 to 64 range. For example, when running Maritime detection mode in high seas, lowering this number helps reduce the number of false detects. When running in calm seas where registration may be less accurate, increasing this value can be beneficial.

3.5 Radiometric Detection

Radiometric Detection looks for pixels that fall within a user specified range of gray values. This algorithm can operate on 8-bit or 14-bit data.

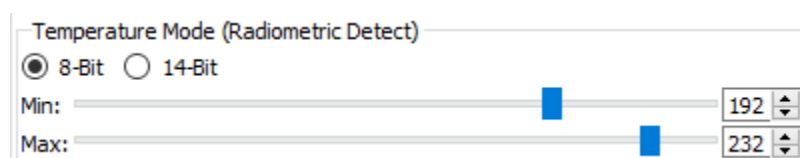


Figure 7: Radiometric Detect - Temperature Mode



3.6 Gas Detection

Parameters for this feature can be found by clicking the Advanced button in the Detect tab.

NframesBack: Dictates how far back in time to search. Use 5 for a moving camera (recommended). Increase this amount for a fixed camera or for more sensitivity.

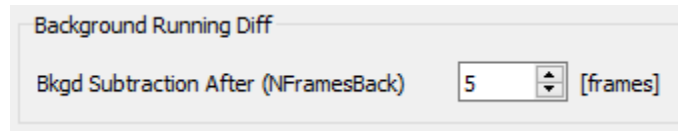


Figure 8: Gas Detection Settings

From the Panel Plus main menu » *Configure* » *System Value*. Use this dialog to change the overlay gas color.

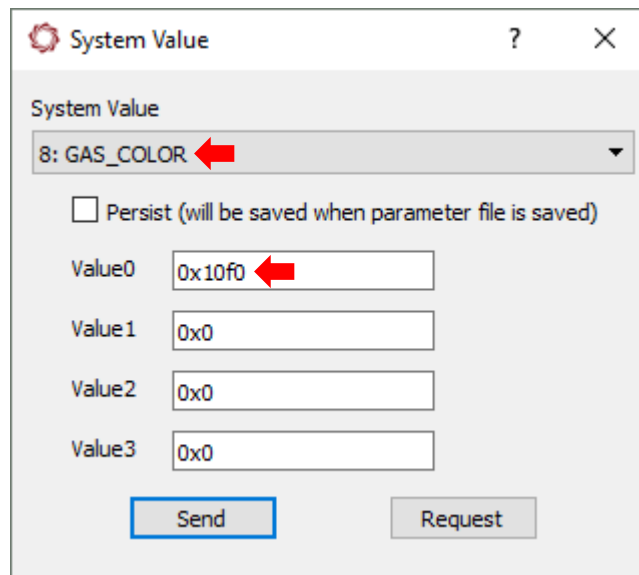


Figure 9: Change Overlay Gas Color



3.7 Auto and Manual Sensitivity

For Aerial, Starring, Anomaly, Maritime, Blob, Gas, and Radiometric Detection modes, the sensitivity can be controlled in one of two ways using the **SetDetectionParameters (0x2D)** message.

Auto sensitivity: Easiest to use. The sensitivity directly controls other parameters. A higher sensitivity will result in a greater likelihood of detecting a target but has a greater likelihood of false detections.

Manual sensitivity: Allows the user to directly control the background threshold, watch frames, and suspicious score. The sensitivity setting does not apply.

Automatic target detection

Mode: **Aerial [SA]** Use Classifier Show Debug

Frame Step: **1**

Auto

Sensitivity: High Low

Manual

Bkgd Threshold: **12** Susp Score: **2**

Watch Frames: **5**

Figure 10: Auto and Manual Sensitivity

The background threshold defines how different an object needs to be from the background model to be detected. In the example shown below, a low background threshold number will generate more detections.

Watch Frames: Defines how long a target should be watched before reporting it to the user. A lower number of watch frames will result in shorter detection times and can result in more false positives.

Suspicious Score: Defines a level at which the algorithm will consider a track to be unstable based on a history of the track detections. For example, a leaf that blows in the wind moves erratically and would require a high suspicious score to show up as a detection. A car driving in a straight line would require a much lower suspicious score to show up as a detection.

The suspicious score does not apply to the Anomaly, Radiometric, Blob, Gas, or Maritime detection modes. The background threshold parameter does not apply to the Radiometric Detection mode.



4 Performance and Speed

This section reviews the tradeoffs between performance (how well the algorithm does at detecting objects) and speed (how long the algorithm takes to run). Settings are in Panel Plus » *Tracking tab* » *Detect tab* » *Advanced*.

4.1 Downsampling

Parameters for this feature can be found by clicking the Advanced button in the Detect tab.

In *Auto* mode, the downsampling rate is automatically set and is based on the image size and algorithm. Increasing the downsampling time allows bigger and faster targets to be detected (faster processing time). Lowering the downsampling time allows for slower and smaller moving targets to be (slower processing time).

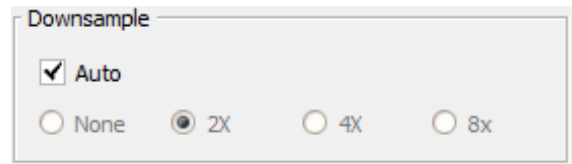


Figure 11: Downsampling Options

Downsampling can also be adjusted to detect slower and smaller targets with HD inputs. This may reduce the output frame rate or require the user to make changes to other parameters such as the Region of Interest to maintain full frame rate. Downsample does not apply to anomaly detection.

4.2 Regions of Interest

Regions of Interest can be used to control the speed and performance of the various detection algorithms. In the example below the search area is define in blue based on the settings shown. This region directly impacts the speed of the algorithm since this the region that will be processed. The detection area is defined in red and based on the settings shown. Detection will be reported in this area. To detect objects as soon as they enter the detect region, make the search region slightly larger. When using the *Set Mouse* option from Panel Plus the detection and search areas are set to the same size.

Both areas can be the same size, but the detection area cannot be larger than the search area.

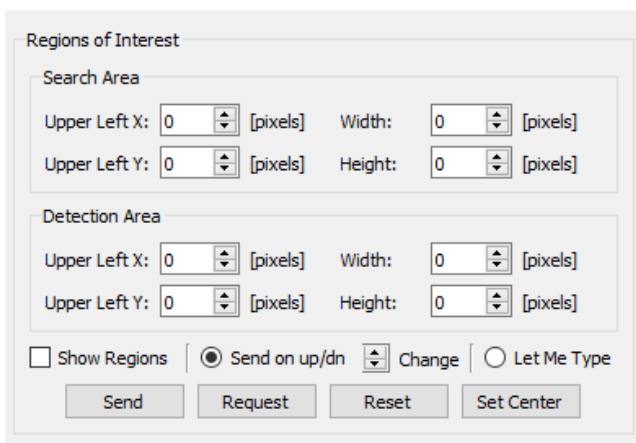


Figure 12: Regions of Interest Example



4.3 Frame Step

Frame Step is under the *Automatic target detection* section in the *Detect* tab. It can be used to reduce the processing load by only running the algorithm every other or every third frame. It can also be used to increase the amount of motion between frames, allowing detection of slower moving objects.

Keep a consistent frame rate through the system. Frame stepping an individual algorithm should only be used as a last resort.

Frame Step does not apply to Vehicle or Drone MTI.

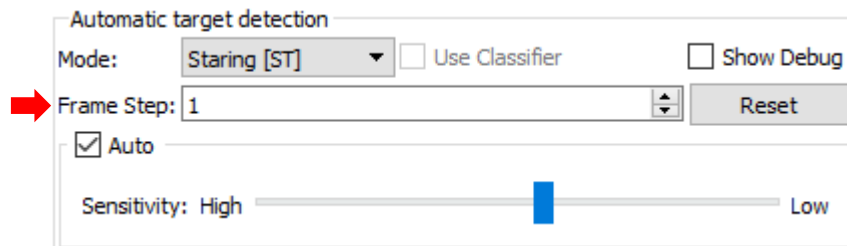


Figure 13: Frame Step

5 Filtering Detections

Use these settings to help setup filtering parameters. Settings are in Panel Plus » *Tracking tab* » *Detect tab* » *Advanced*.

Detections can be filtered based on many different parameters including size, velocity, and in some cases acceleration.

Setting these parameters correctly can be difficult, but when done correctly it can help filter out false detections.

Filtering does not apply to gas detection.

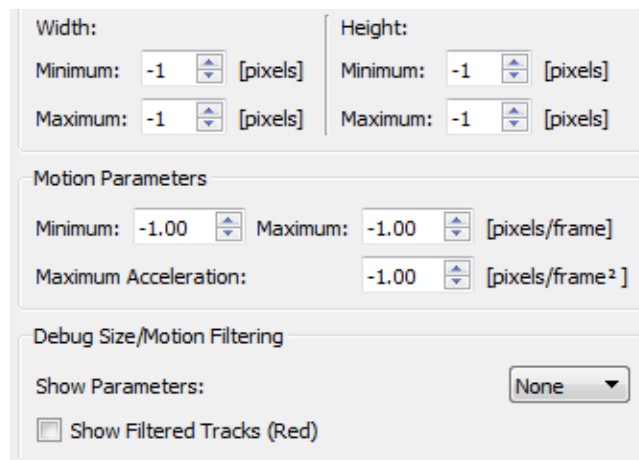


Figure 14: Filtering Settings



6 Command and Control

The following packets are used to set up and control the detection algorithms. Details on these can be found in the [Interface Command and Control \(IDD\)](#).

6.1 Reporting Results

Tracking Position (0x43)

Tracking Positions (0x51)

Tracking Positions Extended (0xA0)

Set Coordinate Reporting Mode (0x0B)

Set Telemetry Destination (0x64)

6.2 Display Related Commands

Set Overlay Mode (0x06)

6.3 Set Display Parameters (0x16) Detection Related Commands

Set Detection Parameters (0x2D)

Set Advanced Detection Parameters (0x76)

Set Detection Region of Interest (0x7C)

Set Tracking Parameters (0x0C)

7 Troubleshooting

Expected detections are not shown: Enable the debug window. This shows what the algorithm is actually seeing.

Additional troubleshooting: Turn off all detection modes, overlays, and stabilization. Record 1 to 2 minutes of video and send it to SightLine. SightLine will post process it and provide an analysis of performance and make parameter recommendations.

7.1 Questions and Additional Support

For questions and additional support, please contact [Technical Support](#). Additional support documentation and Engineering Application Notes (EANs) can be found on the Support pages of the SightLine Applications [website](#).

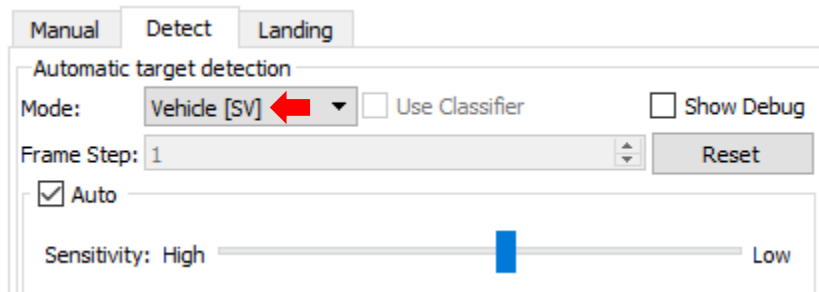


Appendix - Testing MTI

1. From the main menu in Panel Plus, go to *Configure » Acquisition Settings*.
2. Under the Camera Type drop down menu, select *TestPattern Car* or *TestPattern Multi Car*.
3. The *Apply* button will turn red indicating input field changes have been detected. Click *Apply*.



4. From the main menu, go to *Parameters » Save to board*. Cycle the system power or go to *Reset » Board*.
5. After the board resets, the test pattern video should be displayed in Panel Plus. Go to *Tracking tab » Detect* tab. In the *Mode* dropdown menu select *Vehicle [SV]*.



6. The system should detect the car and place a detection box around it.

The mouse can be used to designate other targets.



7. To exit the test pattern, from the main menu in Panel Plus, go to *Configure » Acquisition Settings*.
8. Under the Camera Type drop down menu, select a previous camera setting or select *None*.
9. Click *Apply*.
10. From the main menu, go to *Parameters » Save to board*. Cycle the system power or go to *Reset » Board*.