

Biomimic Spider Double Stereo Vision by the Walking Tree Method

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Abstract

The spider is an amazing creature, and some of which have developed two pairs of front eyes, for the short and long range distance measures. Here, inspired by the spider's double pairs of stereo vision, we describe how we scaled up our previous work in the basic stereo vision into the double stereo vision, to dramatically increase the vision sensing range.

1 Introduction

When we look at a forest, it resolves itself into a set of trees, some nearer and some further away. This seems so natural that it's only when we try to consider the mechanism that we realize how difficult a problem this is. Specifically, we start with light coming into our eyes, going through a lens into some light sensitive cells in the retina and then through some neural processing, and look and behold we see the trees. The specific problem is that the external (we assume 3D) world is mapped through a 2D retina and yet we "see" in 3 dimensions. We all know part of the trick, that is, binocular vision. Instead of one picture, we start with two 2D pictures and somehow "fuse" these two 2D representations into a 3D representation. How does a biological organism do this fusing? How could we instruct (or build) a robot to "see" in three dimensions? One way to think about the difference between two pictures of the same scene is to think in terms of objects. An object that is far away will be in roughly the same place in both pictures. But an object close to the viewer will be in very different places. Our idea is to align objects and use the distance between aligned pairs to estimate distance (depth) in the third dimension.

We convert 2D images into 3D images by adding an extra piece of information to every pixel of a 2D image: the distance from the observer to the pixel. 3D vision usually requires the comparison of two or more pictures. Sequences of pixels have to be aligned between pictures in order to use the distance "shift" of the same pixels to determine distances, e.g., the closer the object, the bigger its shift.

This image alignment problem is similar to the string alignment problem in genetics. For string alignment, dynamic programming algorithms can rapidly find an alignment, if one uses the edit-distance model [Gusfield, 1997; Setubal, et al, 1996] which assumes that changes between strings occur locally. But there is evidence showing that large scale non-local changes are possible [Devos, 1993], e.g., meiotic cell DNA replication is usually followed by homologous chromosome DNA recombination in which large pieces of DNA can be moved from one location to another (translocations), or replaced by their reversed complements (inversions). To handle such non-local changes, as well as the local changes, we created the Walking Tree method and demonstrated its use in phylogeny, gene discovery, and gene verification [Cavener et al, 2004, Cull et al, 1992, 1994, 1998, 1999a, 1999b, 2001, 2003a, 2003b, 2004]. This paper will show that the walking tree is also a reasonable tool for aligning 2D images to compute 3D images, and the stereo vision can be easily extended to double stereo vision.

Spiders have several pairs of eyes, e.g., the jumping spider has two pairs of front eyes. The inner pair has a small view angle, but magnifying objects in details. This simple idea allows us to scale up our basic stereo vision to the double stereo vision without using expensive high-resolution cameras.

2 Walking Tree Methods

2.1 Why are Walking Tree Methods Needed?

Dynamic programming [Scharstein, 2002] can be utilized to implement stereo vision by comparing two pictures. If two pictures of a scene are taken by a pair of cameras, dynamic programming cannot align segments which are not in the same sequential order in both pictures (Figure 1). But, the Walking Tree Method can align segments even when the two segments' locations are swapped in the two pictures, and it can also handle insertions, deletions, and substitutions. Further, the Walking Tree heuristic tends to highlight features of objects, e.g. genes (Figure 2). Since

inversions do not occur in pictures, this feature of the walking tree method can be turned off and the picture alignment can be computed more quickly than a genetic alignment.

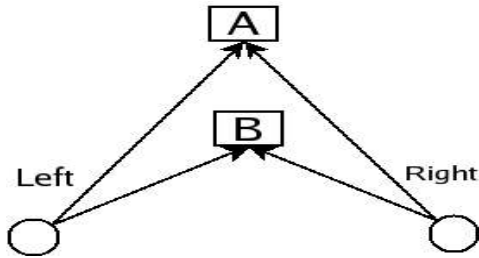


Figure 1: The segments ordering observed by the left camera is "AB", while "BA" is observed by the right camera. A standard dynamic programming method can't detect such a translocation, but the Walking Tree Method can.

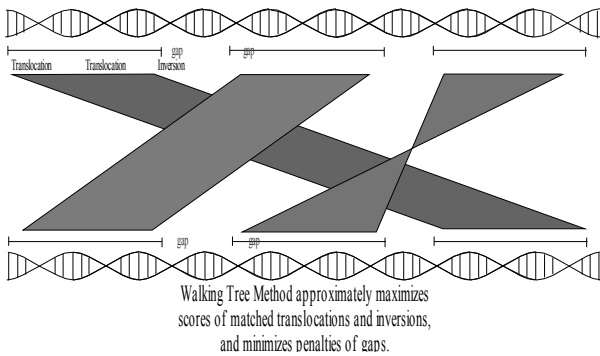


Figure 2: This picture illustrates translocation, inversion, and gaps which can be located by the Walking Tree Method. DNA strings can be replaced by strings of pixels for image comparison.

2.2 The Basic Method

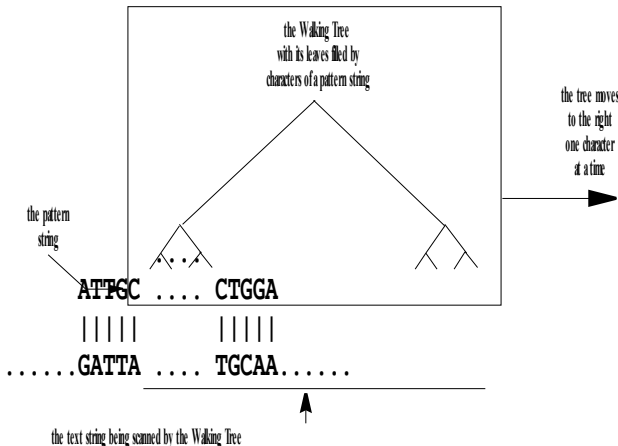


Figure 3: This picture shows the walking tree's structure, a binary tree. Leaves of the tree contain the characters of the pattern string P. After comparing each leaf with a corresponding character of the text string, the walking tree updates its nodes with new scores, then moves to the next position by moving each of its leaves one character to the right. Then it repeats the leaf comparison, and updates its node scores until it reaches the end of the text string.

The problem is to find an approximate alignment between two strings of pixels, one called pattern P, and the other called text T. Our metaphor is to consider the data structure as a walking tree [Python, 1989] with |P| leaves, one for each

pixel in the pattern. When the walking tree is considering position $l + 1$, the internal nodes remember some of the information for the best alignment within the first l pixels for the text (see Figure 3). On the basis of this remembered information and the comparisons of the leaves with the text pixels under them, the leaves update their information and pass this information to their parents. The data will percolate up to the root where a new best score is calculated. The tree can then walk to the next position by moving each of its leaves one pixel to the right. The whole text has been processed when the leftmost leaf of the walking tree has processed the rightmost pixel of the text.

We use a function that gives a positive contribution based on the similarity between aligned pixels, and a negative contribution that is related to the number and length of gaps, translocations, and inversions. A gap in an alignment occurs when adjacent pixels in the pattern are aligned with non-adjacent pixels in the text. The length of the gap is the number of pixels between the non-adjacent characters in the text.

The computation at each leaf node makes use of two functions, MATCH and GAP. MATCH looks at the current text pixel and compares it with the pattern pixel represented by the leaf. In the simplest case we use

$$\begin{aligned} \text{MATCH}(P_i, T_j) &= c & \text{if } P_i = T_j \\ \text{MATCH}(P_i, T_j) &= 0 & \text{if } P_i \neq T_j \end{aligned}$$

For many of our examples we use $c = 2$. If we were matching similar pixels then MATCH could return a value depending on how similar the two compared pixels are.

If we only used the MATCH function, the leaves would simply remember if they had ever seen a matching pixel in the text. We use the GAP function to penalize the match for being far from the current position of the tree. So the leaf needs to remember both if it found a match and the position of the walking tree when it found a match. For example, a simple GAP function could be:

$$\text{GAP}(\text{currentpos}, \text{pos}) = \log |\text{currentpos} - \text{pos}|,$$

where currentpos is the current position of the walking tree, and pos is the position at which the walking tree found a match. Then the leaf could compute

$$\text{SCORE} = \max[\text{MATCH}(P_i, T_j), \text{SCORE} - \text{GAP}(\text{currentpos}, \text{pos})]$$

and update pos to currentpos if MATCH is maximal. This means that a leaf will forget an actual match if it occurred far from the current position.

An internal node will only look at what it is remembering and at what its children have computed. Like a leaf node, the internal node computes

$$\text{SCORE} - \text{GAP}(\text{currentpos}, \text{pos})$$

which depends on what the node is remembering. From its two children, the node computes

$$\text{SCORE.left} + \text{SCORE.right} - \text{GAP}(\text{pos.left}, \text{pos.right})$$

This will penalize the sum of the children's scores because the position for the two scores may be different. But, the internal node also has to penalize this score because the left or

right position may be far from the current position, so it also subtracts

$$\min[\text{GAP}(\text{currentpos}, \text{pos.left}), \text{GAP}(\text{currentpos}, \text{pos.right})].$$

The internal node will keep the better of the score from its remembered data and the score computed from its children.

The walking tree will be computing a score for the current position of the tree. It is possible that it could forget a better score that was far from the present position. To avoid this problem, we add a special root node which simply keeps track of the best score seen so far.

In short, the walking tree finds an alignment f so that

$$f: [1, \dots, |P|] \rightarrow [1, \dots, |T|]$$

The alignment found approximately maximizes

$$\sum_{i=1}^{|P|} \text{MATCH}(P_i, T_{f(i)}) - \sum \text{GAP}(f(i), f(i+1)).$$

The actual functional being maximized is best described by the method itself and has no simple formula. Among other reasons, the above formula is only an approximation because the method tries to break strings into substrings whose lengths are powers of 2, even when using other lengths would increase the value of this formula.

2.2 Adjusting Gaps

The basic method places gaps close to their proper positions. If we use the method to align the string "ABCDEF" in the string "ABCXXDEF" the gap may be placed between 'B' and 'C', rather than between 'C' and 'D'. This is a result of the halving behavior of the basic method. By searching in the vicinity of the position that the basic method places a gap we can find any increase in score that can be obtained by sliding the gap to the left and right. The cost of finding better placements of the gaps is a factor of $\log|P|$ increase in runtime since at each node we have to search a region of the text of length proportional to the size of the substring represented by the node.

3 The Basic Stereo Vision

Two experiments were performed for our basic stereo vision: one for the virtual world, and one for the real world. This allows us to explore the real world test using the knowledge based on the virtual world, using a digital camera that costs less than \$10 USD. No special treatment was used to preprocess the taken pictures.

3.1 Virtual World Test



Figure 4: Analogous to Figure 1, the bigger block is A, and the smaller block is B. The left picture is what the left camera sees,

and the right picture is what the right camera sees. Do you know which object is closer? The big block is closer to the cameras, while the small block is further. The big block is closer not because of its size. Why? You may try to look at them using only one eye per picture. Namely, use a piece of paper to separate the pictures and eyes so that the left eye can see only the left picture, and the right eye can see only the right picture. When both eyes focus on the big block, your eyes are twisted inward, meaning the big block is closer. When the small block is focused, both eyes relaxed, meaning it's further.

We simulated two pictures (see Figure 4) in which two objects are placed in a way similar to Figure 1. Since both cameras' lines of sight are parallel, the objects taken by the left camera position a little to the right, while the objects taken by the right camera position a little to the left. Then, the Walking Tree Method processes the pixels of the two pictures, line by line, horizontally, to determine the depth of each pixel. The more "shift" a pixel does, the closer it is to the observer.

Why do we want to highlight this special simulated condition in which the two objects' locations are swapped in the two cameras? Because such a condition is the most difficult one for classic dynamic programming methods to solve.

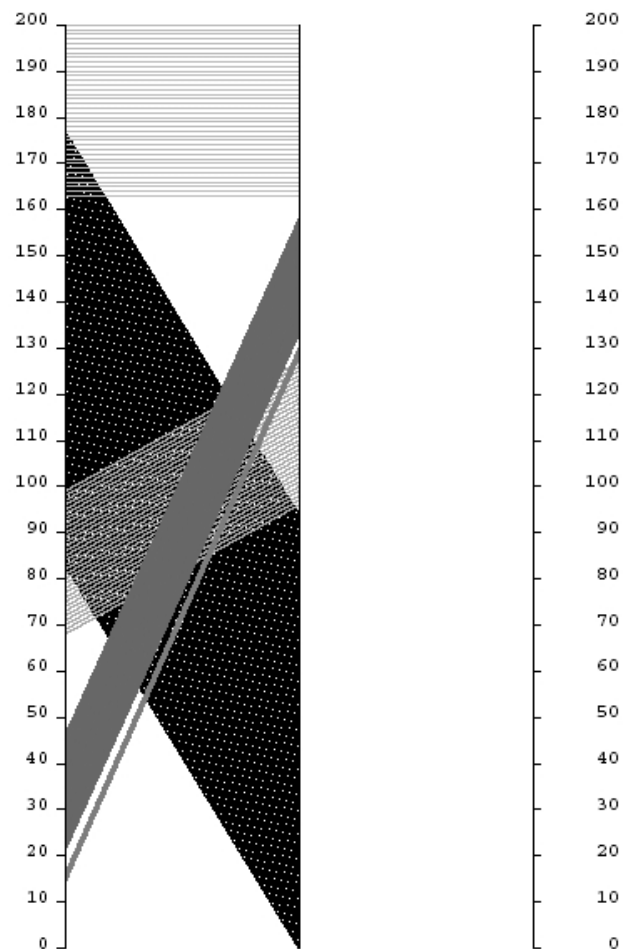


Figure 5: This is the alignment computed by the Walking Tree Method using the vertical lines passing through both objects in pictures of Figure 4. The middle axis represents the pixel string of Figure 4's left picture, and the left axis represents the pixel string of Figure 4's right picture. Because it's impossible to have a positive "shift" from the left picture to the right picture, this

figure's two widest bands will be ignored, while only the bands of negative shift will be considered. And, the bigger shift of the red segment does tell us that it's closer to us, while the blue segment is further from us.

Figure 5 shows the alignment computed by the Walking Tree Method to demonstrate its ability to see swapped objects. We define a "positive" shift to be an object shifting its position, from the left location of a picture, to the right location of another picture. And, all other cases to be the "negative" shift. Because it's impossible to have a "positive" or "non-negative" shift from the left picture to the right picture, figure 5's two widest bands will be ignored, while only the bands of negative shift will be considered. So, the alignment tells us that the Walking Tree Method does see the two segments, even when their locations are swapped. And, the bigger shift of the big block does tell us that it's closer to us, while the small block's smaller shift tells us that it's further from us. The only problem left is that the area between both segments seems to be part of one of the two segments. This problem can be easily corrected by measuring the vertical shift using another pair of cameras.

3.2 Real World Test



Figure 6: Two pictures are taken for the real world test. The left is taken by the left camera, and the right is taken by the right camera. For humans, it's easy to determine the relative distances of the three objects: the table lamp in the middle, and the black container on the left, and the shiny column on the right. We will let the Walking Tree Method to determine their relative distances by their "shifts" in the two pictures.

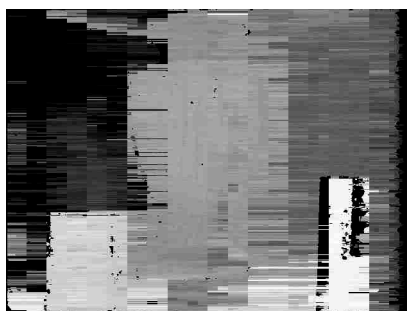


Figure 7: The distances of objects are represented by the brightness of a pixel. If the pixel is closer, it's brighter. This picture shows that the brightest part is at the lower right, i.e., the shiny column is the closest. The 2nd brightest object is at the lower left, i.e., the black container of the Figure 6. The 3rd brightest is the table lamp. And, the darkest is the wall. So, we know the relative distance from the closest to the furthest are the shiny column, the black container, the table lamp, and the wall.

We used an inexpensive digital camera to take two pictures as shown in Figure 6. In Figure 6, the left picture is taken when

the camera is positioned at the left, and the right picture is taken when the camera is moved to the right. We ran the Walking Tree Method on two sequences of pixels, where one sequence is from the left picture, and one from the right picture. We constructed the 3D information of pixels based on the amount of their shifts (Figure 7). There are noises in the 3D picture, but we believe its quality can be improved by using more cameras taking pictures simultaneously (to avoid lighting changes) and using cameras that use X3 technologies [Merrill & Billings, 1999] (to avoid the mosaic effect of cameras that use single color photo sensors).

4 The Double Stereo Vision

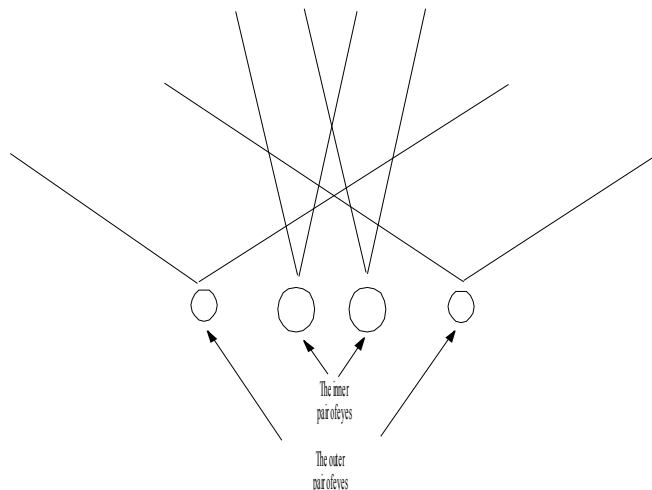


Figure 8: This picture shows the linear parallel arrangement of the inner pair and the outer pair of eyes, similar to the four front eyes of a spider. The outer pair is for seeing near objects, as well as the remote objects. However, because of the finite resolution of an eye (or camera), remote objects' distance can't be determined by their indistinguishable shifts. The inner pair is like a pair of telescopes, able to see remote objects. Because of its long range vision property, each eye of the inner pair has a narrow view angle versus the wide view angle of the outer pair. In our experiment, the outer pair is done by zooming the camera's lens.

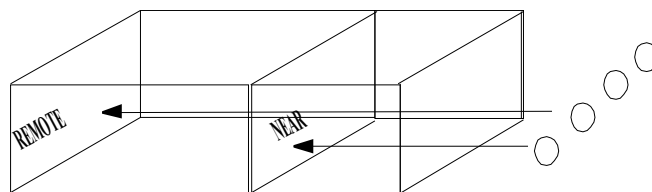


Figure 9: This picture shows the zooming effect of combining two pairs of stereo vision eyes. The inner pair can determine the distance of remote objects. This simple idea allows us to implement our long range sensor without using high resolution cameras. Furthermore, this idea also implies that implementations of triple, quadruple, or N-tuple stereo vision are do-able. And, pairs of stereo vision don't have to be crowded in a line; they can be arranged in any way, as long as each pair parallel to each other.

We now extend our basic stereo vision to make it do what a spider does. **Figure 8** shows the concept of our spider-mimic double stereo vision. A spider has developed two pairs of stereo vision. The outer pair is for long range, while the inner pair is for short range. By combining two pairs of fixed-focal-length eyes, a spider can determine distance of near and

remote objects without using expensive variable-focal-length eyes. **Figure 9** shows the zooming concept of two pairs of spider-mimic eyes. There are several advantages of double stereo vision: 1) both near and remote objects' distances can be determined, 2) high-resolution cameras are no longer needed to determine shifts, and 3) less image processing delay because no mechanical parts are needed to do what a variable focal length lens does. Certainly, its obvious disadvantage that is the furthest zooming image probably represents only a small block of what the outer pair sees.

5 Algorithmic Complexity

The Walking Tree Method is both time and space efficient. It can align two strings of length n in time proportional to n squared. The space used for computing this alignment is proportional to $n \log n$. Further, as shown in [Cull *et al.*, 2003a] a parallel version of the method will run in time proportional to n . In our experiments, a sequential version of the algorithm was run on a fairly slow PC and the alignments were still constructed in under a second. While our goal is to use this method for robotic vision, we believe that the Walking Tree is not unreasonable for a biological system. To verify this contention, we should show how to embody this algorithm as a neural network. Since the interconnection pattern is so simple, we believe that this will be an easy task. The double stereo vision only doubles the runtime complexity.

5 Conclusion

From the result, we found that Walking Tree Method is also a powerful tool for stereo vision. The technique works by finding a "best" alignment between two strings of pixels. In addition to what can be done by a standard dynamic programming approach, the Walking Tree Method can find segments of swaps (translocations), which are required to accurately identify objects at various distances. Furthermore, since the Walking Tree Method computes the 3D information by comparing sequences of pixels, instead of objects, its capability is not limited to the amount of objects in a picture. What we did in the experiments is just a small step toward a much bigger goal of ours: to handle extremely complicated pictures for robots' 3D vision. With the double stereo vision, our robot can see its 3D environment better.

6. References

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