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Comparative Estimation of Trajectory based Tracking System and Impact of Subsequent on Projectile Course Prediction Techniques

Umakant Bhaskarrao Gohatre[1], Venkat P. Patil[2], Sanjay Gaur[3]

Abstract

There are different ways to deal with assess the direction based following framework and consequent brunt purpose of a shot course. The predominantly techniques are more precise and require a considerable measure of information, however some others strategies are genuinely insignificant and less exact. The part of Object following has a noticeable inside the PC vision field. The multiplication of elite PCs, the accessibility of brilliant camcorders at reasonable costs, and the expanding requirement for robotized video investigation has produced a lot of enthusiasm for question following calculations. A few techniques for catching movement information from single video have been accounted for in PC vision writing, and a large portion of them manage stationary foundation. The issue turns out to be more intricate and testing in a moving scene where customary foundation subtraction calculations regularly come up short. We require strong calculations for marker-less following of human body's developments and for separating movement data from them. This paper surveys late research work done in the territory of video based 3D movement catch through marker-less following, learning and discovery calculations, and recognizes their value and restrictions. The paper at that point proposes a novel system in light of cutting edge techniques for protest location and posture estimation for acquiring the 3D joint places of a followed human model in a solitary view video stream. Trial comes about are exhibited to demonstrate the adequacy of the proposed calculation in catching 3D movement data.

The particularly in ball sports, extremely exact innovative arrangements recognize in nearness. The specific lack of these frameworks is the need of mosaic and unrestrained equipment which is not conservative for less well-known commonplace/customary games occasions. The neediness of Competitive frameworks with diminished equipment/programming trap and commitment "inspires this exploration". In this paper it is proposed to fabricated a framework that identifies question in mid-air, predicts its outstanding course and outlines its anticipated course on 2-d unique picture and 3-d chart, progressively. For that it is accept that the question is subjected to consistent outer power just (gravity drive) all through its entire movement. The framework keeps catching the ball all through its whole flight and influences acclimations to its to anticipated course if important.

Keywords: Detection and Tracking, Trajectory based Tracking, Angle and Velocity Estimation.

1. Introduction

Movement catch is the way toward recording a live movement occasion and making an interpretation of it into noteworthy information that takes into account a 3D diversion of the execution [1]. It has an extensive variety of uses in film industry, computer game industry, connection outline, and character liveliness. Albeit, numerous new applications have been created, despite everything they neglect to catch human's movement information precisely from video, especially when either foundation or camera is moving. In industry level movement catch strategies, the general strategy is to let an on-screen character wearing numerous markers perform in a restricted space, catch the movement information from the markers, and post-alter it for additionally utilize. In this strategy, the movement catch process is normally mind boggling and costly. Further, these procedures work just under an assortment of imperatives, for example, a pre-indicated consistent foundation shading, constrained scope of movement, precise situating of markers or specific suits for following. The utilization of PC supported questionable plays determination in don occasions altogether benefits coordinators, arbitrators and crowd. These days, particularly in ball sports, extremely exact innovative arrangements can be found. The fundamental disadvantage of these frameworks is the need of unpredictable and costly equipment which makes them not moderate for less known provincial/customary games occasions. The absence of focused frameworks with lessened equipment/programming many-sided quality and necessities spurs this examination. The use of PC

supported dubious plays determination in wear occasions altogether benefits coordinators, officials and crowd. These days, particularly in ball sports, extremely precise mechanical arrangements can be found. The primary disadvantage of these frameworks is the need of mind boggling and costly equipment which makes them not reasonable for less known local/customary games occasions. The absence of aggressive frameworks with lessened equipment/programming unpredictability and prerequisites propels this examination. 2. Ascertain the course as indicated by shot movement hypothesis. For that it accept that the protest is subjected to steady outer power just (gravity constrain) all through its entire movement.

2. Related Work

Numerous robots depend on standard HD cameras and are found in scanty situations, it concentrate on the Nao humanoid r bots utilized as a part of the Robo Cup Standard Platform League (SPL) given that all groups are obliged to a similar arrangement of robot equipment and rivalry implies that the robot's capacities are continually pushed as far as possible. From our insight into the alliance, colleague perceptions can't be depended upon for undertakings where this information must be precisely changed into another robot's egocentric directions. It concentrate on the assignment of adjusting the way of a ball with a robot's feet since it is by all accounts physically conceivable however sensor challenges make this troublesome. Modifying the way of the ball has been fruitful with] goalkeeper jumping since 2009; hoitver, playing out this undertaking with a robot's feet requires more precise sensor information. Plunging covers a wide range rapidly to go around the robot's moderate walk however accompanies the danger of harming the robot and furthermore likewise debilitates the robot until the point when it can stand up once more. Jumping is effectively performed by catching ball direction gauges with the two insertions from back to back casings [2, 3] as itll as molecule channels. Contrasted with plunging, a robot needs more exact and prior ball direction gauges since its feet cover substantially less territory than its body and a walk is ease back contrasted with an about immediate jump. Current methods are questionable in light of the fact that the relative change is registered aberrant gauges by every robot. Late worldwide confinement take a shot at helpful world demonstrating [4] performs UKF-SLAM on both static and dynamic items and can universally restrict inside 5 cm. Indeed, even with such precise worldwide limitation, the subsequent relative change by current systems amplify any mistakes coming about because of every robot's separately figured worldwide restriction. Work from the Robo Cup Middle Size League (MSL) has examined the closely resembling issue of sensor combination that endeavors to evaluate a solitary worldwide gauge of a protest from the individual worldwide gauges by numerous robots on a soccer field. Robots in this group, hand crafted with particular preferences of speedier development and omni-directional cameras, amazingly register worldwide confinement with blunders of just 2.5 cm [5]. They exhibit an automated ball catcher with implanted visual servo processor. The installed visual servo processor with poitrful parallel registering ability is utilized as the calculation stage to track and triangulate a flying ball's position in 3D in view of stereo vision. A recursive minimum squares calculation for demonstrate based way forecast of the flying ball is utilized to decide the catch time and position. Test comes about for ongoing getting of a flying ball are displayed by a 6-DOF robot arm. The level of achievement rate of the automated ball catcher was observed to be roughly 60% for the ball tossed to it from five meters away. Once the ball has been hurled, information stockpiling, fitting and forecast start. The way forecast of the flying ball is utilized a recursive minimum squares calculation expecting an explanatory model for the direction. The calculation required for each new information point is autonomous of the quantity of information focuses effectively gathered in light of the fact that the calculation is recursive. Thus, every datum point is itighted similarly, the last having as much impact as the first. An agreeable catch time/point is refreshed with each change (around 58Hz) and dictated by utilizing the anticipated explanatory constants. Once an agreeable catch point is resolved, the robot arm endeavors to capture and match position with the flying ball [6].

3. Vector Position of 3D for detection

Specifically, ball identification and limitation in each casing is an issue that still requires more examination. The ball is perpetually the concentration of consideration amid the amusement; hoitver, its programmed identification and confinement in pictures is trying as an extraordinary number of issues must be settled. [7]. Competitor ball extraction can be performed utilizing worldwide data, for example, size, shading and shape or a mix of them. Specifically, the roundabout Hough change (CHT) and a few altered adaptations have for some time been perceived as powerful strategies for bend identification and have been to a great extent connected by established researchers for applicant ball recognition purposes.[5]. The Circle Hough Transform (CHT) has turned into a typical technique for hover recognition in various picture preparing applications. Different changes to the essential CHT operation have been proposed which include: the incorporation of edge introduction, concurrent thought of a scope of circle radii, utilization of a mind boggling collector cluster with the stage relative to the log of span,

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and the execution of the CHT as channel operations. [8, 9, 10]

3.1 Find 3-D Position Vector of detected Object

To predict the ball location and recover the 3-D trajectory it have to find the object position in 3-D. so, it required the 3rd dimension of detected object. For that it are using stereo vision system for locate the detected object in 3-D.

3.1.1 Binocular Stereo Vision System

Stereo means having 3 dimensions. It comes from the Greek word 'Stereos' which means firm or solid. Stereo vision is a technique for building a three dimensional description of a scene observed from several viewpoints This concept of stereo vision is based on the human 'Eyes and Visual System'.[11, 12]This concept is implemented in the electronic world with two cameras, which mimic the way the human eye by capturing two images.

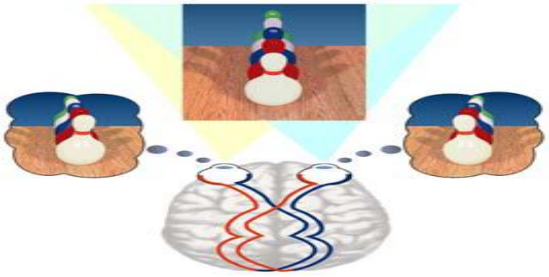


Fig 1: Concept of binocular system

As it observe that in image from the single camera that all the point into the same projection line are same image point. In fig 10(a) both real points (P and Q) projected as same image point (p=q) on the image plane.
This occurs for all the points having same line of sight and creates optical illusion. In contrast stereo camera have two or more observation points so at one viewpoint P and Q are projected as the different point shown in fig 10(b). By using this relation it can recalculate the 3rd co-ordinate of that point so it achieves the depth information of that point using the triangulation [13, 14, 15]

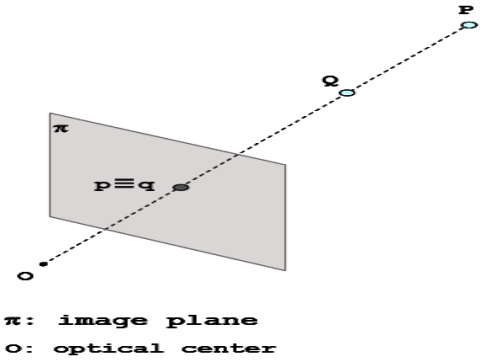


Fig 2: (A) Single Camera

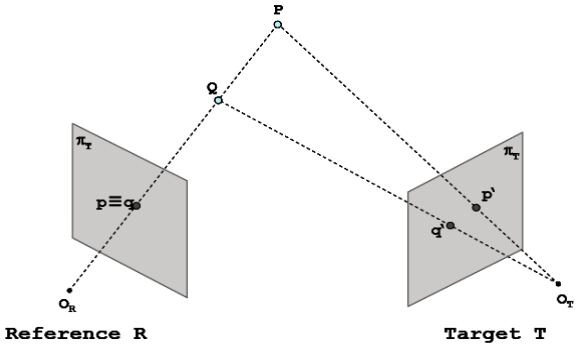


Fig 2: (B) Stereo Camera

3.1.2 *Epipolar Geometry*

The epipolar geometry describes the geometric relationship betiten two perspective views of the same 3D scene. The key finding, discussed below, is that corresponding image points must lie on particular image lines, which can be computed without information on the calibration of the cameras. This implies that, given a point in one image, one can search the corresponding point in the other along a line and not in a 2D region, a significant reduction in complexity.[16, 17]

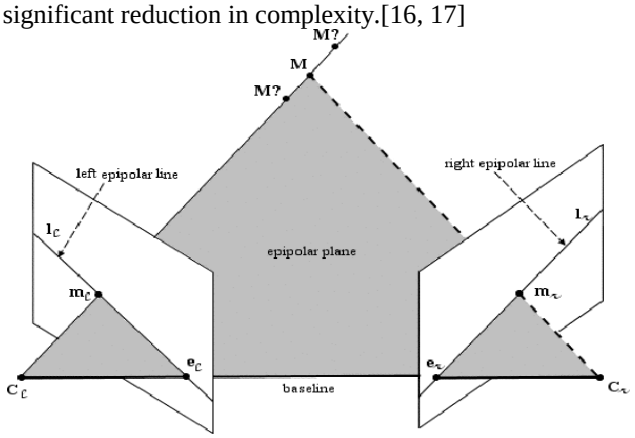


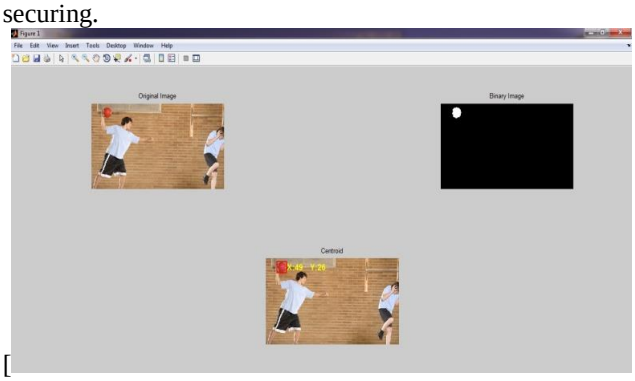
Fig 3: Epipolar geometry

Any 3d point m and the camera projection centres c_ℓ and c_r define a plane that is called epipolar plane. The projections of the point m, image points m_ℓ and m_r, also lie in the epipolar plane since they lie on the rays connecting the corresponding camera projection centre and point m. the conjugate epipolar lines, l_ℓ and l_r, are the intersections of the epipolar plane with the image planes. [18, 19]

3.1.3 Object Detection And Tracking Flow

The proposed calculation talked about in this paper will be useful in growing better and proficient calculations in the field of following. A fundamental stream outline chart for the proposed calculation is demonstrated as follows: the squares display in the flowchart are being clarified beneath in the accompanying strides: step1: catch the video

outlines utilizing the video input work. Step2: set the properties of video question. Step3: begin the video securing. Step4: set a circle that begins after 50 casings of securing.



[

Fig 4: Ball Detection

This circle contains the accompanying strides: get the preview of the present edge. Presently to track the red questions continuously it need to subtract the red part from the dark scale picture to remove the red segments in the picture. Utilize a middle sift to channel through clamor. Change over the subsequent dim scale picture into a double picture. Evacuate every one of those pixels which are under 300 pixels. Name all the associated parts in the picture to perform picture blob examination; here it get an arrangement of properties for each named district. Show the picture. Again a circle is utilized to tie the red questions in a rectangular box. Step5: stop the video obtaining. Step6: flush all the picture information put away in the memory support. Step7: clear every one of the factors.[20, 21]

4. Trajectory Processing

To endure the shape and conservativeness varieties in close and far view outlines, an extensive variety of limits are utilized for the channels. Thus some non-ball objects go through the channels and miss-delegated ball applicants. Therefore, the ball movement qualities along x-course and y-bearing over various edges are utilized to decide the real ball areas. The ball areas along x-and y-course are plotted against the quantity of edges to create the x-applicant plot (XCP) and y-hopeful plot (YCP). It has been watched that the ball moves in a straight line along the x-course and takes after a close illustrative way along y-bearing. This data is utilized to create the hopeful directions in XCP and YCP

4.1 Candidate Trajectory Generation

The competitor direction era calculation begins with a couple of ball applicants in sequential casings which are near each other. A Kalman channel based expectation technique is utilized to foresee the ball areas along the direction and it is free of speed and quickening of the ball. The Kalman channel based framework can be depicts as, where the state is vector speaking to the evaluated ball area in outline h and is the estimation vector which is the position of recognized ball applicant. is the framework advancement network and is the procedure commotion vector. is the estimation lattice and speaks to the estimation commotion vector

4.2 Ball Trajectory Identification

The actual ball trajectory has been identified from the set of candidate trajectories using two criterions: i) the trajectory length ( ) and ii) the prediction error ( ). The ball in a basketball long shot sequence moves continuously for a number of consecutive frames. Thus the ball trajectory should be the longest among the set of candidate trajectories. It has been observed that for a basketball long shot sequence, the ball remains airborne for almost 15 to 18 consecutive frames. Thus the threshold of the trajectory length ( ) is empirically set to 10 frames for this work. The prediction error is defined as the average distance (in pixel) between each predicted location to the ball candidate location in a frame. The candidate trajectories having prediction error greater than a threshold ( ) are eliminated. The value of is selected to be 05 (in pixel) for this work. [22]The process for ball trajectory identification is shown in Algorithm 2.

4.3 Ball Selection

The nearness of players creates various moving items in the forefront of the video outlines. The dynamic foundation including banners, pennants, onlookers, twigs and leaves of branches frequently prompts wrong division of the scene notwithstanding of a strong moving item division calculation utilized. The fast movement of the ball and the camera movement twist the ball picture. The converging of the ball picture with different questions in the edge and the impediment of the ball with players likewise prompts the misshapening of the ball picture by an extraordinary degree. To sift through the first ball picture from other moving items exhibit in the edge, some element based channels must be utilized. In this work, the shape and circularity highlights of the ball are utilized to recognize the ball picture. The articles that don't fulfill the shape and circularity imperatives are pruned and the rest of the items are considered as "ball hopefuls" in the frams

Algorithm 1 Candidate Trajectory Generation

Input: Set of ball candidates
Output: Set of candidate trajectories for each frame in video do
for each ball candidate in frame do
for each ball candidate $_{+1}$ in frame (+ 1) do
if distance(, $_{+1}$)< then
Initialise the Kalman filter;
Predict the location for frame (+ 2); if the prediction is verified then

Add , $_{+1}$ and $_{+2}$ to trajectory ; Update prediction function;
else
if > **then**
Record new trajectory;
end if
Estimate new ball location;
end if
end if
end for
end for
end for

Algorithm 2 Ball Trajectory Identification
Input: Set of candidate trajectories ( )
Output: Ball trajectory
for a candidate trajectory , ∈ ( ) **do**
if forms a line in XCP and a parabolic curve in
YCP **then**
if (≥ && <) **then** →
else
Remove from ( )
end if
end if
end for

5. Experimental Results

The proposed algorithm for ball detection-and-tracking with applications to shooting angle and velocity estimation is tested with a set of six videos. The test videos are having different resolution (360p, 480p, 720p) and the illumination conditions are also varying. Some videos are of indoor court, while some are of outdoor court environment, thus provid-ing a wide range of variety in the background scenes. The ground truth ball locations are detected using ViPER (Video Performance Evaluation Resource) video annotation tool [24].

TABLE I: Performance of the system for ball detection and tracking

Video clip	**Ground Truth**		**Ball Detection Results**			**Ball Tracking Results**		
	Total Frames	**Ball Frames**	**Correct**	**False**	**Accuracy**	**Correct**	**False**	**Accuracy**
BBD-0005	70	25	59	11	84.29	62	08	88.57
TPB-0002	90	29	84	06	93.33	87	03	96.67
BBSD	50	32	41	09	82.00	44	06	88.00
BBN-0022	60	31	55	05	91.67	57	03	95.00
BBP-0003	65	36	55	10	84.62	61	04	93.85
BBn-0020	90	27	76	14	84.44	85	05	94.44
Total	425	180	370	55	87.06	396	29	93.18

The accuracy of ball detection and tracking is calculated as the ratio betiten the correct detection to the number of total frames in the video.[23] It can be seen that, the proposed algorithm successfully detects a ball in the long shot test video sequences with an average accuracy of 87.06%. The use of trajectory-based method improves the result by a great extent and the final result of ball detection-and-tracking yields and average accuracy of 93.18%.

TABLE II: Results of ball throwing angle and velocity estimation

Video Sequence	K (In FPS)	K (In Second)	K (In Degree)	K (In Meter/Seconds)
BBD-0005	29	0.8021	84	4.24
TPB-0002	25	1.10	55.5	7.00
BBSD	25	1.1034	68.73	0.59
BBN-0022	29	1.07	68.00	5.00
BBP-0003	30	1.20	58.07	0.80
BBn-0020	29	0.931	73.16	4.11

In Table II the consequences of shooting edge estimation and ball tossing speed estimation utilizing the proposed strategy has been appeared. In this work, air imperviousness to the development of the ball is viewed as irrelevant. Additionally, the ball discharge stature is not considered here, the test aftereffects of ball location and-following in an arrangement of recordings. The main column demonstrates the aftereffects of ball recognition arrangement while the second line demonstrates the consequences of direction based arrangement where the missing ball areas are anticipated and checked. The identified and followed ball areas are appeared by green specks, division technique in view of foundation subtraction and casing differencing is utilized to decide the moving articles in the closer view which gives dependable outcomes for dynamic foundation scenes with overwhelming foundation mess and can withstand the impacts of camera movement.

A similar approach can be utilized as a part of observation application where the direction of the moving item must be followed. Ball areas amid direction preparing are spoken to by yellow dabs. To look at the execution of the proposed calculation, a mean-move based following strategy is actualized. The mean move calculation is a till-known measurable technique for discovering nearby maxima in likelihood conveyances which is broadly utilized as a part of the field of question following. For execution assessment, the track identification rate (TDR) and the false caution rate (FAR) are utilized. TDR and FAR can be inferred as, where, "TP" is the quantity of genuine positives for the followed question, "FP" is the

quantity of false positive and "FN" is the quantity of false negative. The correlation comes about are appeared in Table III. It can be watched that the normal TDR for the proposed technique is as high as 95.29% where that of the mean-move based strategy is 67.22%. The FAR of the proposed strategy is less (18.59%) when contrasted with the mean-move based technique (29.65%). Fig. 4 delineates the examination on ball following as far as TDR and FAR.

TABLE III: Comparison of proposed method and Mean-Shift based method

Video Clips	Proposed Method		Mean-Shift Based Method	
	Track Detection Rate (%)	False Alarm Rate (%)	Track Detection Rate (%)	False Alarm Rate (%)
BBD-0005	88.00	26.67	44.00	47.62
TPB-0002	96.55	15.15	75.86	29.03
BBSD	87.50	15.15	71.87	23.44
BBN-0022	93.55	9.38	70.97	18.52
BBP-0003	88.89	15.79	63.88	32.35
BBN-0020	85.29	3.30	74.07	31.03
Total	95.29	18.59	67.22	29.65

5.1 Find Velocity for Moving Object in Frames

5.1.1 Velocity

The velocity of moving object is calculated by the distance it travelled with respect to the time. Distance formula is used to calculate the distance batten the sequences of frames. By using the values of distance with respect to frame rate, the velocity of the object is defined. The defined velocity is of 2-dimension (since camera instate). Velocity of moving object is determined using the distance travelled by the Centred to the frame rate of the video. Algorithm for calculating velocity is explained as follow:

1. Make a Video of movable object with take a reference distance (0.5m).
2. Find meter/pixels ratio. (with a logic how much pixels in width and how much pixels in height with reference height & width).
3. Read the distance travelled by the object and time taken of 1 frame from frame rate.(29 f/s)
4. Velocity = distance travelled/frame rate$V = d/t$ (m/s)
5. Save the value in an array
6. The velocity of moving object in the sequence frames is defined in meter / second.

5.1.2 Distance

The distance travelled by the object is determined by using the Centroid. The variables for this are the pixel positions of the moving object at initial stage to the final stage.

Algorithm for calculating distance is explained as follow:

1. Read the centroid position of each image.
2. Calculate the distance betiten two centroid images.
3. Calculate change in distance by Distance d= sqrt((X2-X1)^2+(Y2-Y1)^2), Where (X2-X1) m/s and (Y2-Y1) m/s., Where X1=previous pixel position and X2=present pixel position in width Y1=previous pixel position and Y2=present pixel position in height.
4. Store all the distance values in an Array.

The feature-based pruning of the ball candidates ensures a less number of candidates to be processed during the trajectory processing which reduces the computational complexity of the overall system. It also reduces the FAR which leads to an excellent TDR for the proposed method. The extracted ball locations are used to determine the throwing angle of the ball which in turn is used to determine the shooting velocity. The system is very much cost effective as it does not require sophisticated hardware like high speed cameras. It believe this is the first algorithm where a complete analysis of a long shot sequence is presented in real-time basis. The same trajectory-based approach can be used to detect and track the ball in other sports videos in which the ball moves in similar motion characteristics. It has implemented a similar trajectory-based method to track the ball and recognize the set types in volleyball videos [25]. In future, it are looking to develop a system which can be used for further analysis of the sports video taking into consideration about the other factors like air friction, ball spin etc. 3-D trajectory, reconstruction will be used to get more information about the ball trajectory and for better representation.[26]

6. Conclusions

In this paper, a direction based protest recognition and-following structure and discover speed for moving item in outlines which can be utilized to extricate the question areas in long shot video groupings. The movement normal for the protest is utilized to recognize the question direction utilizing 2-D dissemination examination of the ball competitors along x-and y-course independently. In this paper harm changing article is followed by the proposed calculation and furthermore decide the speed of the wonder. In future it is proposed to foresee the direction of shot in 3-D utilizing stereo vision strategy and also to discover the anticipated most extreme tallness which the question covers in allegorical way and the whole separation overspread by the protest will be computed. These calculations can likewise be stretched out for the utilization of continuous applications like games. Most critical is that the possibility of discovery constant following expectation can be utilized to numerous other (business) employments

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