

Hand detection using Internal Haar-like features and contextual information in human-robot interaction systems.

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Abstract: This topic focuses on hand detection using Internal Haar-like features and scene information in human-robot interaction systems. In the context of practical applications of automated robots, the research aims to solve the problem of accurately and quickly determining the position and state of the hand. Through a combined theoretical and experimental approach, the topic builds a system capable of efficiently processing image data. The expected result is to provide a foundation for enhancing reliability in human-robot interaction, while also contributing to the research field of image recognition and multi-sensor signal processing.

Keywords: Hand detection, Internal Haar-like, Scene information, Human-robot interaction, Image processing