

Multi-perspective Multi-modal Trajectory Descriptions for Handwritten Strokes

Mohammad Tanvir Parvez

Computer Engineering Department

Qassim University, Qassim 51477, Saudi Arabia

Email: m.parvez@qu.edu.sa

Sardar Anisul Haque

Computer Science Department

Qassim University, Qassim 51477, Saudi Arabia

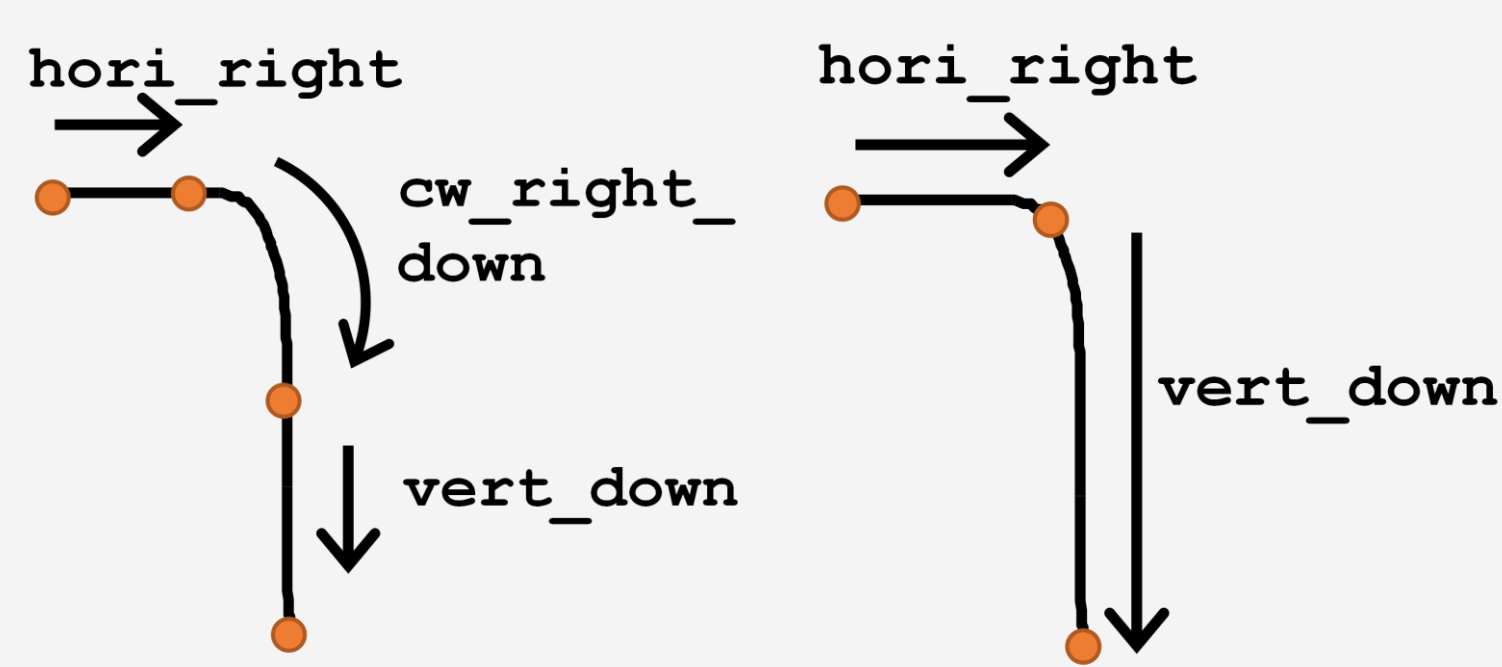
Email: s.haque@qu.edu.sa

Requirements for Stroke Descriptions

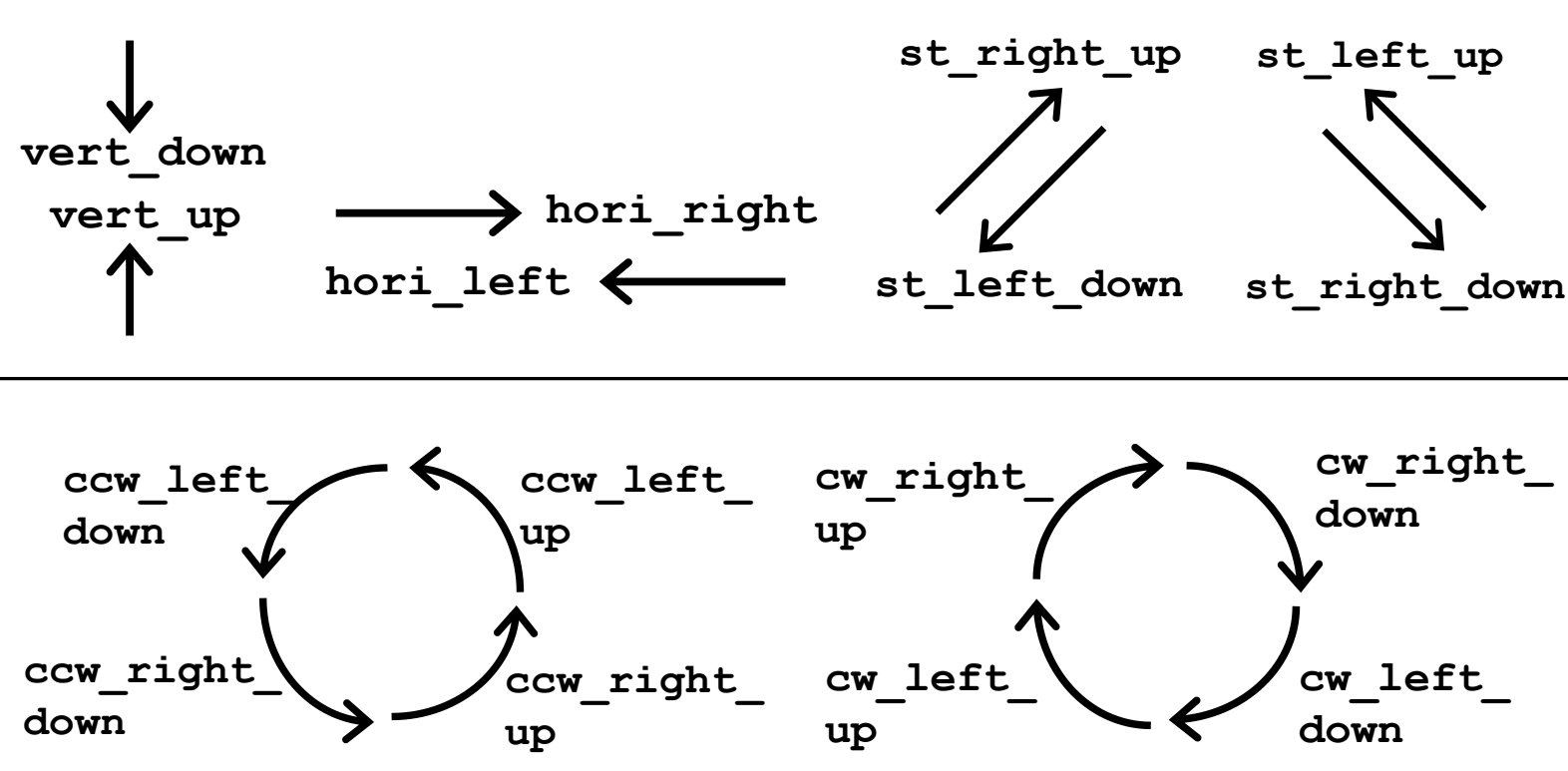
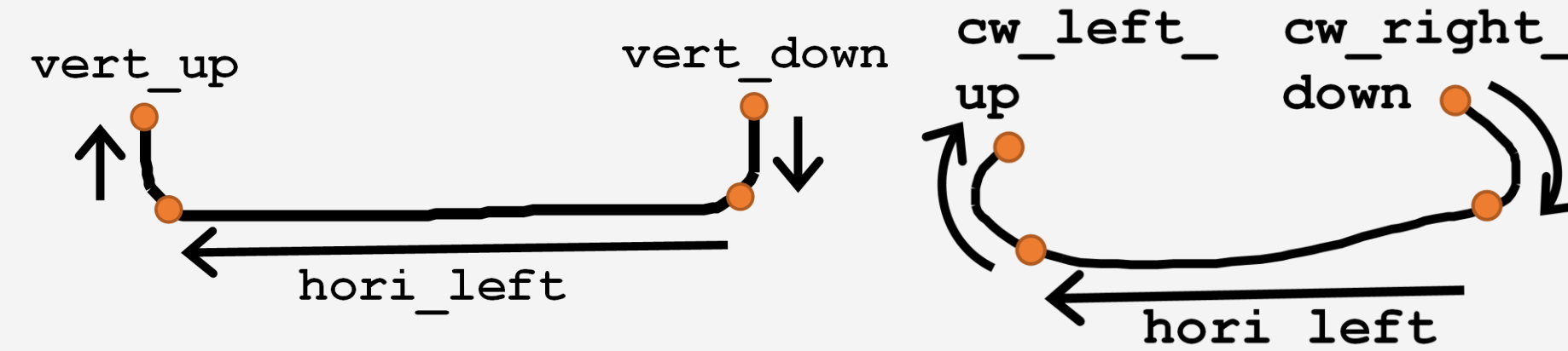


- Handling how a handwritten stroke can be 'viewed'

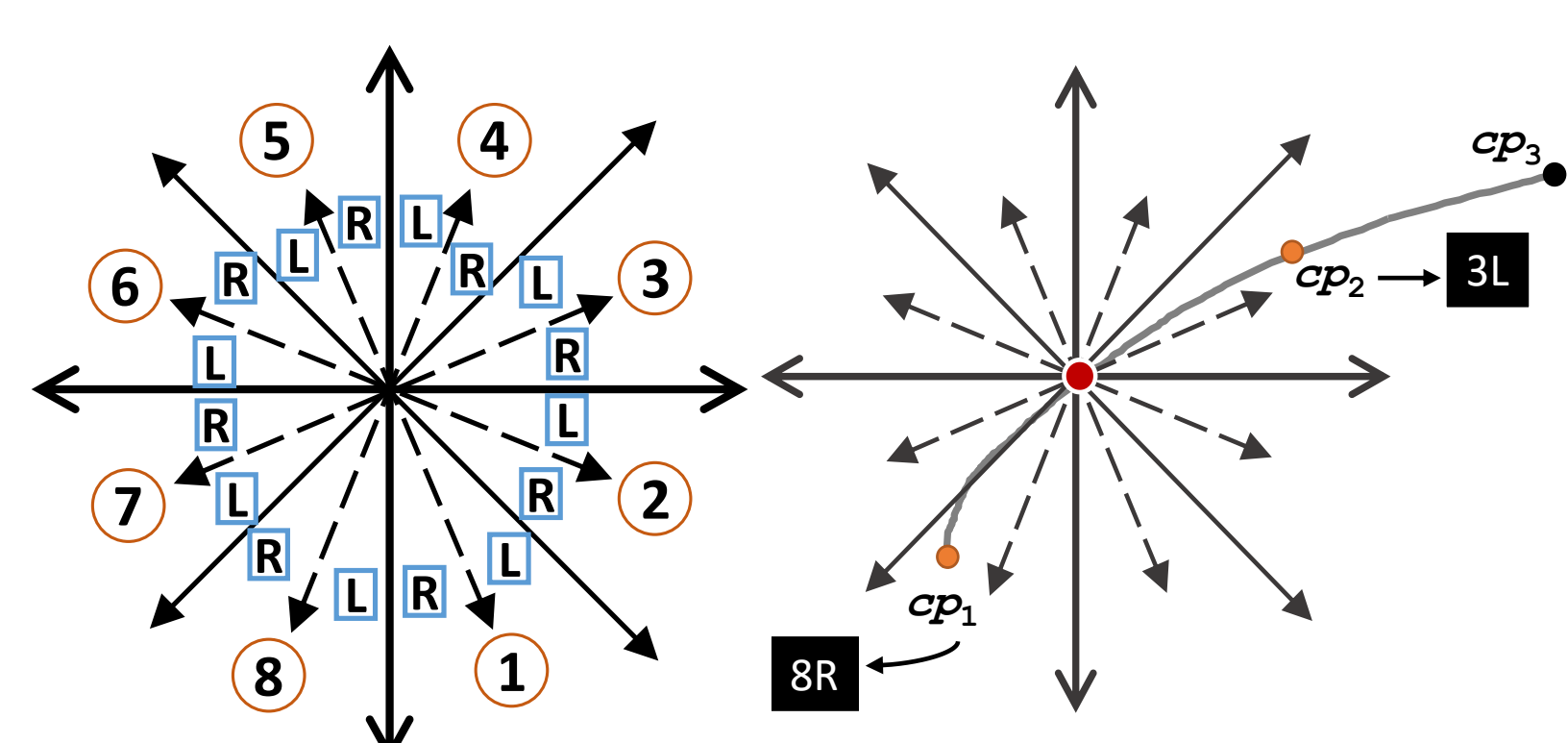
Issue of Perspective



Issue of Modality



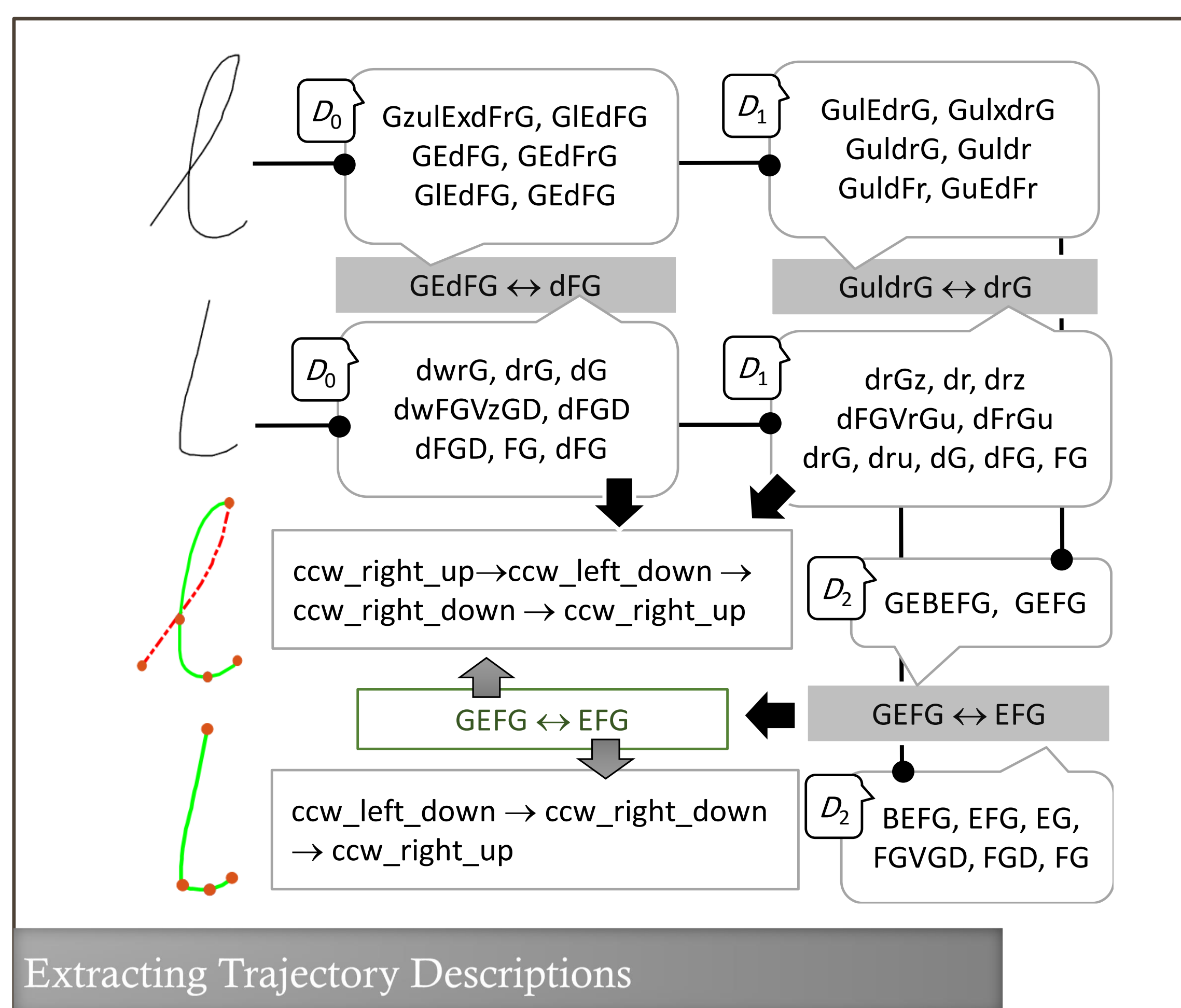
Shape Descriptors



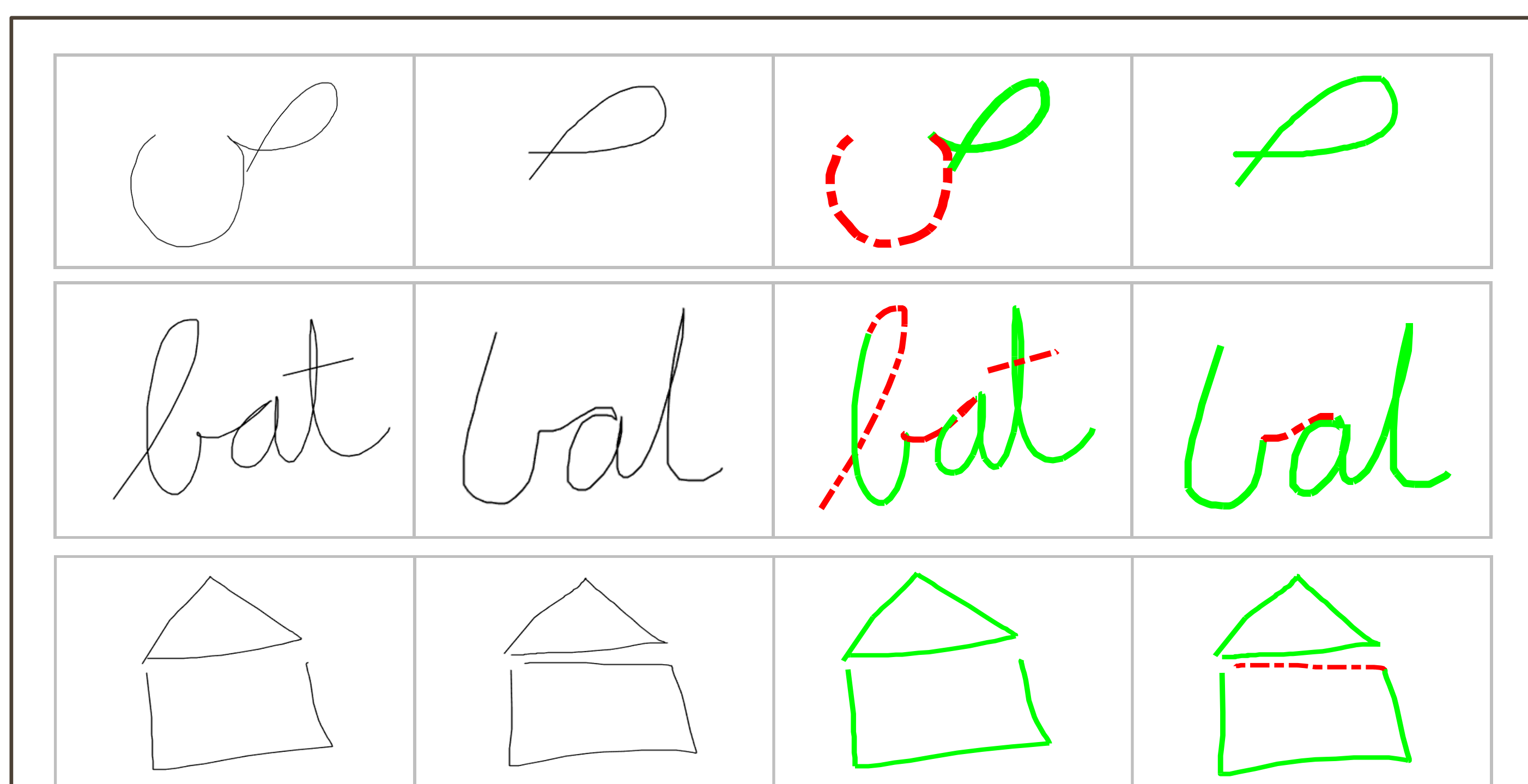
Segment to Descriptor Mapping

Descriptors and Mapping

Applications – Handwriting Learning



Extracting Trajectory Descriptions



Handwritten Shapes with Feedback

Shape Descriptor Fitting Criteria

Descriptor	Rigidity Level	Fitting Criteria
↓	Strict	$(\text{pos}(cp_1) = 4L \vee 5R) \wedge (\text{pos}(cp_2) = 1R \vee 8L)$
	Relaxed	$(\text{pos}(cp_1) = 4 \vee 5) \wedge (\text{pos}(cp_2) = 1 \vee 8)$
↑	Strict	$(\text{pos}(cp_1) = 1R \vee 8L) \wedge (\text{pos}(cp_2) = 4L \vee 5R)$
	Relaxed	$(\text{pos}(cp_1) = 1 \vee 8) \wedge (\text{pos}(cp_2) = 4 \vee 5)$
→	Strict	$(\text{pos}(cp_1) = 6L \vee 7R) \wedge (\text{pos}(cp_2) = 2L \vee 3R)$
	Relaxed	$(\text{pos}(cp_1) = 6 \vee 7) \wedge (\text{pos}(cp_2) = 2 \vee 3)$
←	Strict	$(\text{pos}(cp_1) = 2L \vee 3R) \wedge (\text{pos}(cp_2) = 6L \vee 7R)$
	Relaxed	$(\text{pos}(cp_1) = 2 \vee 3) \wedge (\text{pos}(cp_2) = 6 \vee 7)$
↘	Strict	$a_{1,2} < a_{low}$
	Relaxed	$a_{1,2} < a_{high}$
↙	Strict	$(\neg H \wedge \neg V) \wedge (cp_{1x} < cp_{2x} \wedge cp_{1y} > cp_{2y})$ override $\neg \wedge \text{loc}(mid_{1,2}) = \text{'right'}$
	Relaxed	$\neg \wedge \text{loc}(mid_{1,2}) = \text{'left'}$ override $\neg \wedge \text{loc}(mid_{1,2}) = \text{'left'}$
↗	Strict	$a_{1,2} < a_{low}$
	Relaxed	$a_{1,2} < a_{high}$
↖	Strict	$(\neg H \wedge \neg V) \wedge (cp_{1x} > cp_{2x} \wedge cp_{1y} > cp_{2y})$ override $\neg \wedge \text{loc}(mid_{1,2}) = \text{'right'}$
	Relaxed	$\neg \wedge \text{loc}(mid_{1,2}) = \text{'left'}$ override $\neg \wedge \text{loc}(mid_{1,2}) = \text{'left'}$
↘	Strict	$a_{1,2} < a_{low}$
	Relaxed	$a_{1,2} < a_{high}$
↙	Strict	$(\neg H \wedge \neg V) \wedge (cp_{1x} < cp_{2x} \wedge cp_{1y} < cp_{2y})$ override $\neg \wedge \text{loc}(mid_{1,2}) = \text{'left'}$
	Relaxed	$\neg \wedge \text{loc}(mid_{1,2}) = \text{'right'}$ override $\neg \wedge \text{loc}(mid_{1,2}) = \text{'right'}$
↗	Strict	$a_{1,2} < a_{low}$
	Relaxed	$a_{1,2} < a_{high}$
↖	Strict	$(\neg H \wedge \neg V) \wedge (cp_{1x} > cp_{2x} \wedge cp_{1y} < cp_{2y})$ override $\neg \wedge \text{loc}(mid_{1,2}) = \text{'right'}$
	Relaxed	$\neg \wedge \text{loc}(mid_{1,2}) = \text{'left'}$ override $\neg \wedge \text{loc}(mid_{1,2}) = \text{'left'}$

W	Trajectory Representation (from top-left)	Parameter Settings
	vert_down ccw_right_up vert_up vert_down ccw_right_down vert_up	$\tau = 2, \alpha_{low} = 10$ maxSegLen = 0.4 $D_0 = \downarrow s, \uparrow s, \rightarrow s, \leftarrow s, \searrow s, \swarrow s, \nearrow s, \nwarrow s, \nearrow s, \nwarrow s, \searrow s, \swarrow s$
	vert_down ccw_right_up ccw_right_down vert_up	$\tau = 3, \alpha_{low} = 10$ maxSegLen = 0.4 $D_0 = \downarrow s, \uparrow s, \rightarrow s, \leftarrow s, \searrow s, \swarrow s, \nearrow s, \nwarrow s, \nearrow s, \nwarrow s, \searrow s, \swarrow s$
	vert_down vert_up vert_down vert_up	$\tau = 3, \alpha_{high} = 20$ maxSegLen = 0.6 $D_1 = \downarrow r, \uparrow r, \rightarrow r, \leftarrow r, \searrow r, \swarrow r, \nearrow r, \nwarrow r, \nearrow r, \nwarrow r, \searrow r, \swarrow r$
	ccw_right_down ccw_right_up ccw_right_down ccw_right_up	$\tau = 3, \text{maxSegLen} = 0.8$ $D_2 = \searrow r, \swarrow r, \nearrow r, \nwarrow r, \nearrow r, \nwarrow r, \searrow r, \swarrow r$

An Example