

ABSTRACT

Learning on TLD is one process that differentiates TLD with other object tracking method. Learning process occurs when the object observed in a video out-of-view or occlusion, when the object will reappear, it will be detected again as the object being observed because learning tasked is estimating error detection and there are training examples to avoid mistakes. To represent the observed objects geometric shapes are used, such as bounding boxes.

TLD system is given input in the form of image sequences and given the value of scale parameters and shift parameters that have been determined. Next, initialized to an object that is represented in the bounding box of the first frame. After TLD system has been completed, then the output obtained in the form of image sequences that already exist bounding box and the point bounding box value.

The result of this final project is represented in the form of one-pass evaluation graph (OPE) which shows the result of performance parameter, that is success plot and precision plot. Each performance parameter also displays a graph based on eleven challenge problems. Overall, the values of success plot and precision plot are obtained at the value of the 0.5 scale parameter and the parameter value of shift 10 which means, the smaller the value of the scale parameter and the shift parameter value the better the performance.

Keywords: Bounding box, groundtruth, Scale, Tracking-learning-detection (TLD), Frame, shift, attribute, one-pass evaluation graph (OPE).