

# Mobile Lenses

A Hybrid Approach to Direct Interaction  
with Maps and Kiosks

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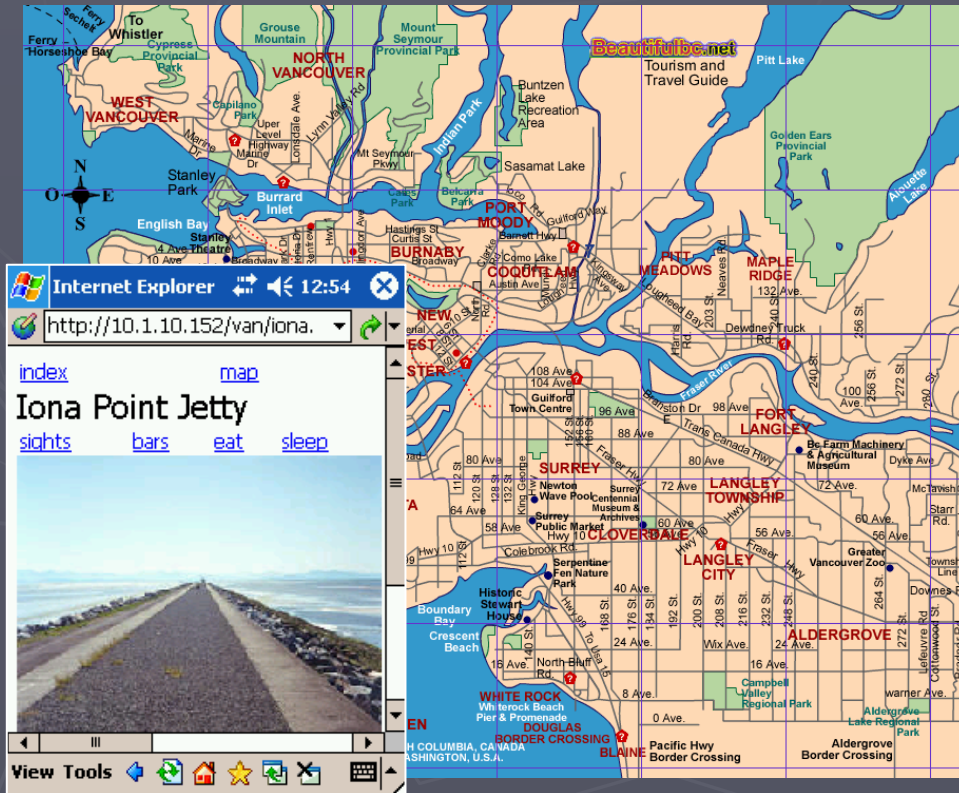
# Marked-up Maps



- ▶ Continue to use paper maps when mobile, for survey knowledge
- ▶ Link to electronic information through direct interaction

# Previous Work

## ► Point-and-click hyperlinking



5/16/2006

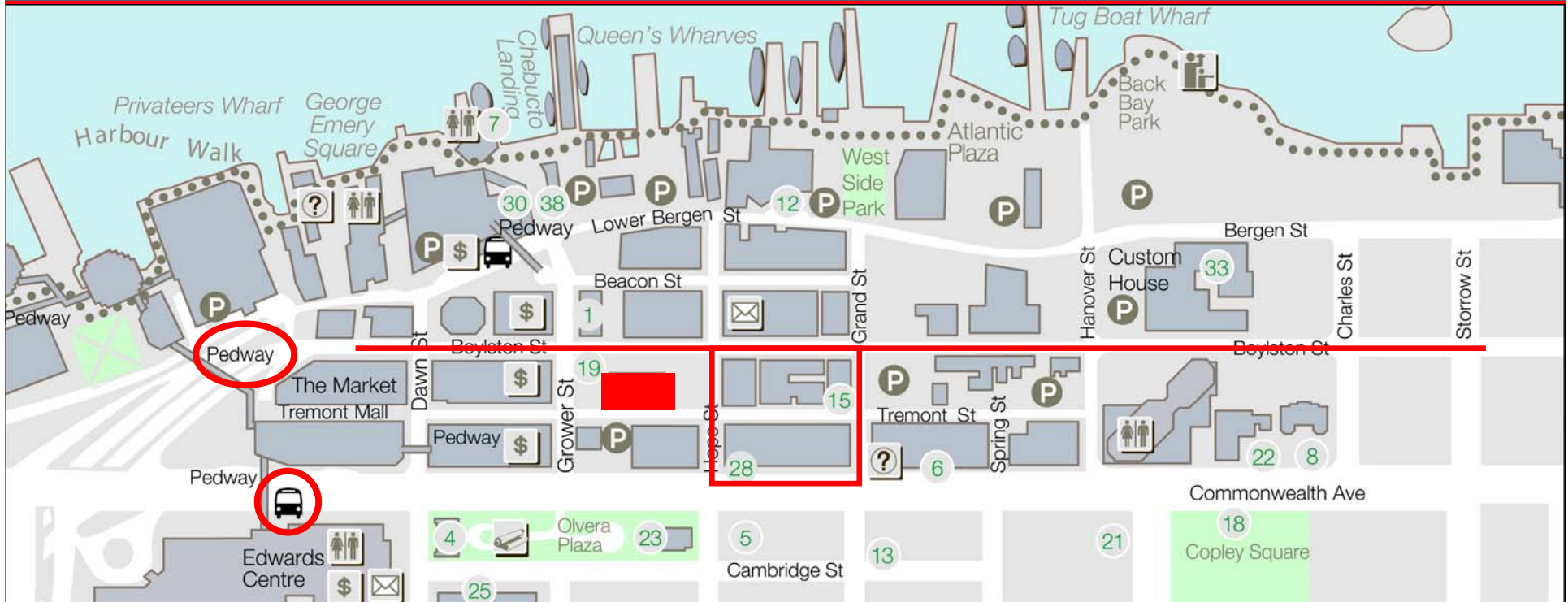
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# "Make-believe" study

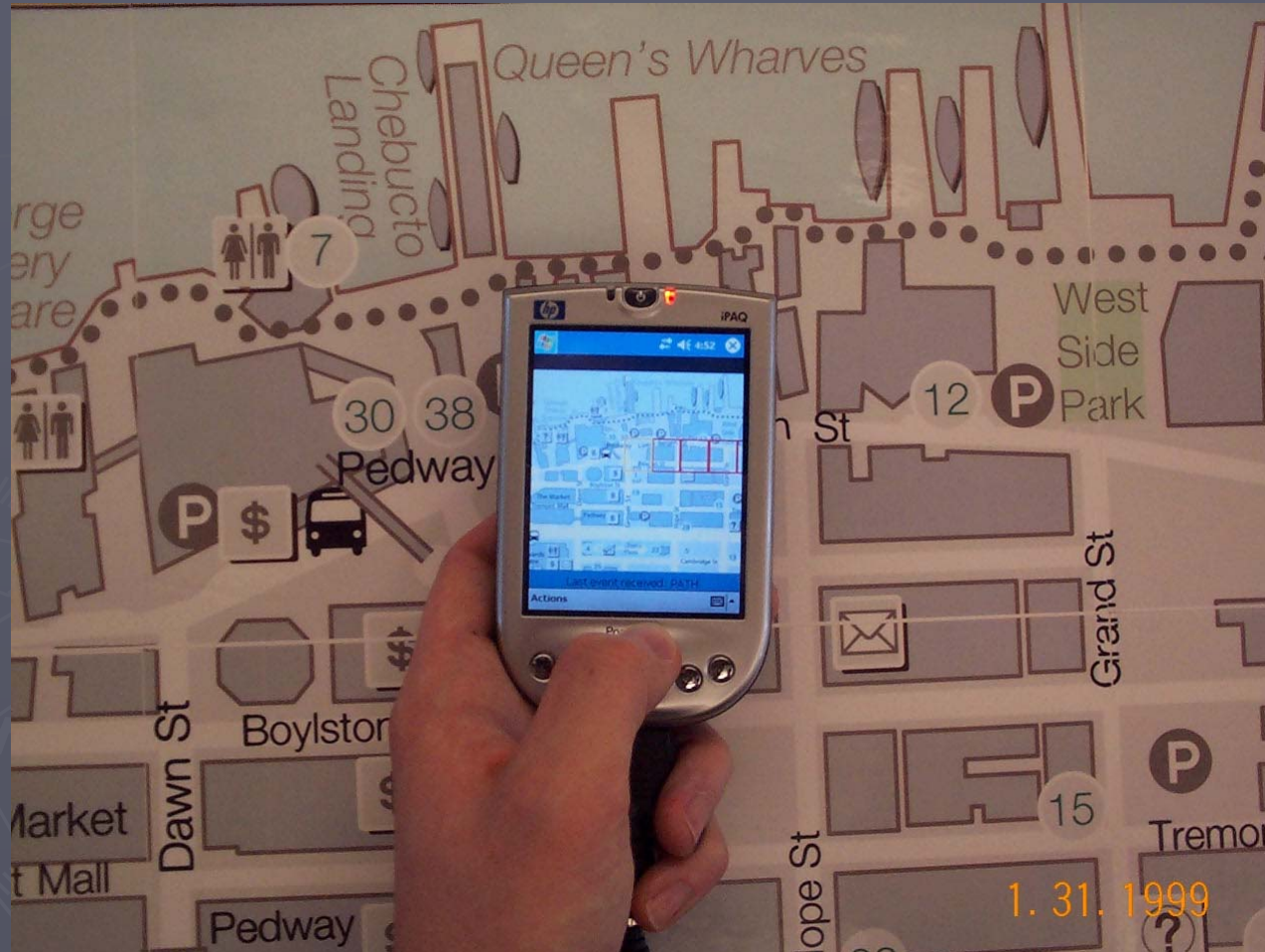
- ▶ Intended to help drive prototype design
  - ▶ Informal, 7 participants
  - ▶ Given mobile phone or PDA, **turned off**
  - ▶ Presented with three maps
  - ▶ Asked to envision interaction
- 
- ▶ *Almost exclusively point and click interaction envisioned*
  - ▶ *Expect lots of interaction with device interface*



# Additional Techniques



# Functional Prototype design



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# Functional Prototype design




Express queries directly    Paper menu controls

# RFID Granularity is limiting

4:55

**Tourist Information**

Back Bay Park



Beacon Street Post Office  
(9, 3)

Maritime Museum of the Atlantic  
Parking South of Sackville Landing  
(11, 2)

Parking North of Salter Street  
(13, 2)

Back Bay Park

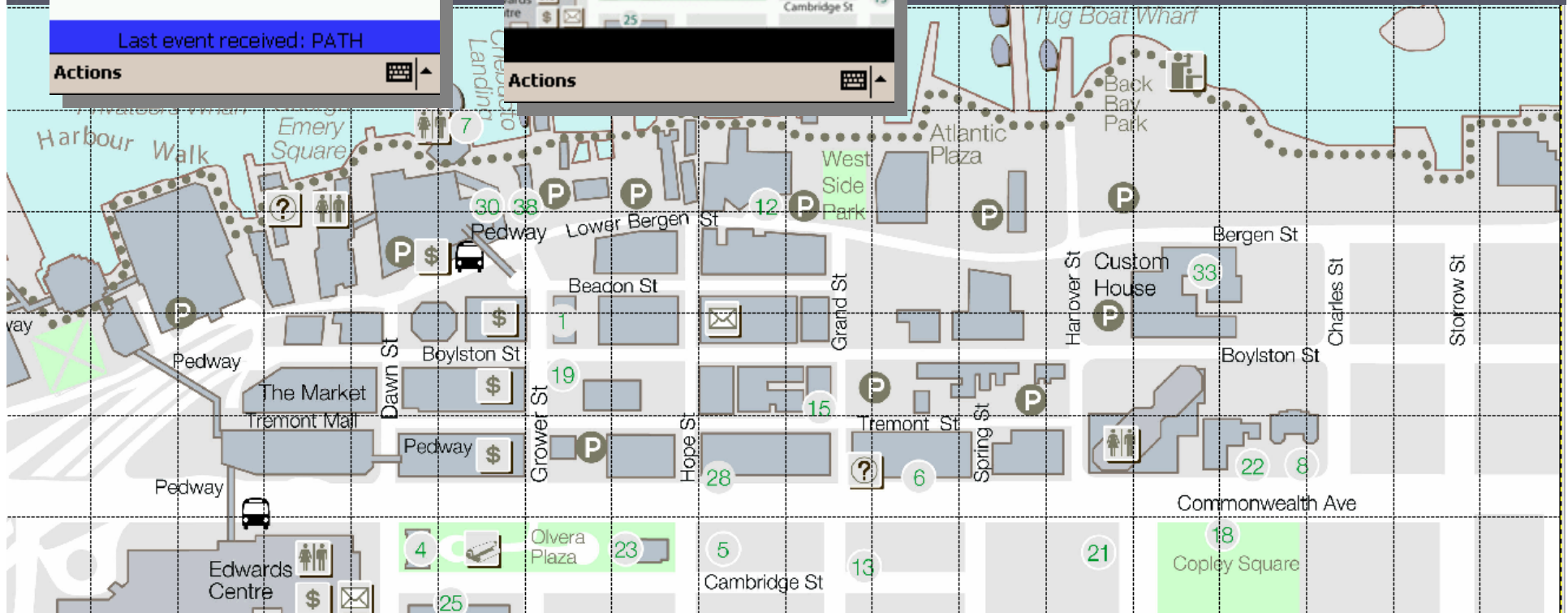
Last event received: PATH

**Actions**

1:36



**Actions**





# Possible improvements

- ▶ Increase pointing resolution
- ▶ Permit lens functionality
  - Requires precise location and orientation, track movement

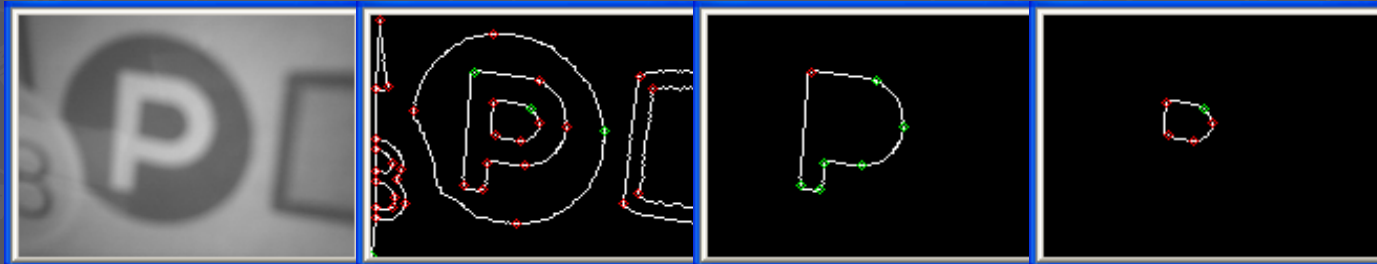
	Resolution	Orientation	Distance	Motion
RFID	Coarse	No	Partial	Yes (coarse)
Vision	Fine* ^	Yes	Yes*	Theoretically.
RFID+Vision	<b>Fine*</b>	Yes	Yes*	<b>Yes...</b>

\* Depends on resolution of image

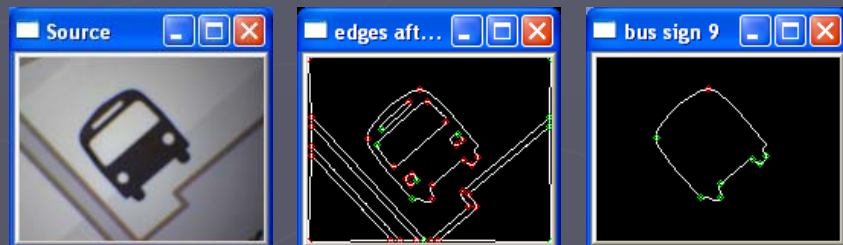
^ Depends on ability to determine location from sample image

# Using Icon Recognition

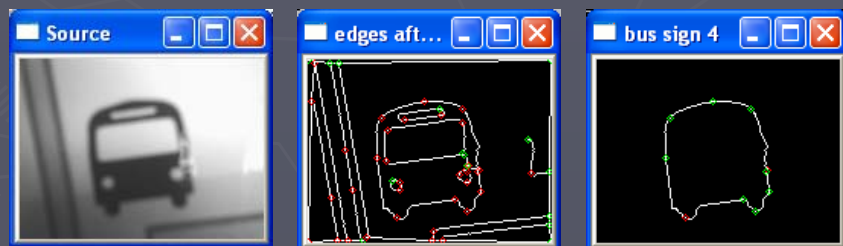
## ► Generic Edge Tokens (GETs)



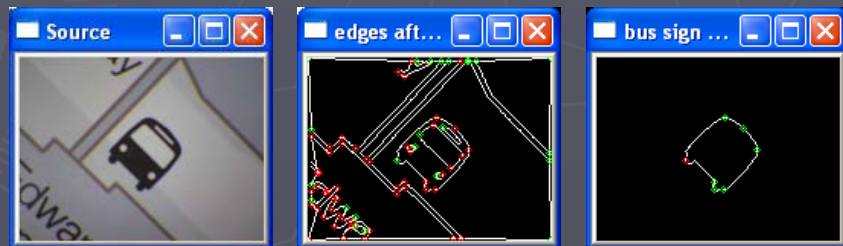
# Method is rotation-independent



Rotation =320.91



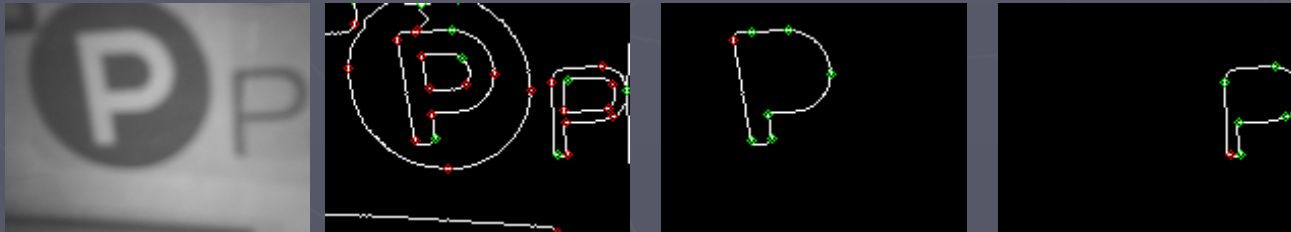
Rotation=352.24



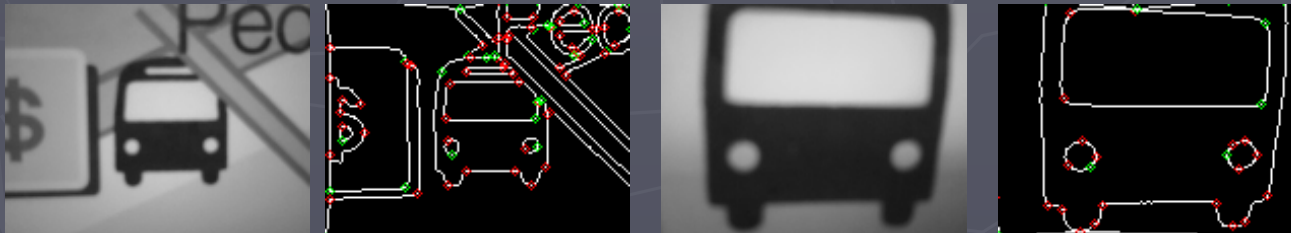
Rotation=41.82

# Issues

## ▶ False positives



## ▶ Missed icons



# Image Testing Sets

- ▶ Base set
- ▶ Rotation
- ▶ Distance
- ▶ Lighting



# Testing Results

<i>Image Set</i>	$N_{correct}$	$N_{recog}$	$N_{all}$	<i>recall</i>	<i>precision</i>
Base image	19	20	20	95%	95%
1 (rotation)	9	9	10	90%	100%
2 (distance)	8	9	10	80%	89.9%
3 (lighting)	38	39	42	90.5%	97.2%

# Resolving icons to map locations

- ▶ Relative placement to other icons
  - Must be within range of camera
  - Must find a set of relations that uniquely determines *which* icon is being recognized
- ▶ By giving a course position, RFID grid can reduce space of possibilities

# Questions?

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