

Table of Contents

Preface	11
Isabelle BLOCH	
Chapter 1. Definitions	13
Isabelle BLOCH and Henri MAÎTRE	
1.1. Introduction	13
1.2. Choosing a definition	13
1.3. General characteristics of the data	16
1.4. Numerical/symbolic	19
1.4.1. Data and information	19
1.4.2. Processes	19
1.4.3. Representations	20
1.5. Fusion systems	20
1.6. Fusion in signal and image processing and fusion in other fields	22
1.7. Bibliography	23
Chapter 2. Fusion in Signal Processing	25
Jean-Pierre LE CADRE, Vincent NIMIER and Roger REYNAUD	
2.1. Introduction	25
2.2. Objectives of fusion in signal processing	27
2.2.1. Estimation and calculation of a law <i>a posteriori</i>	28
2.2.2. Discriminating between several hypotheses and identifying	31
2.2.3. Controlling and supervising a data fusion chain	34
2.3. Problems and specificities of fusion in signal processing	37
2.3.1. Dynamic control	37
2.3.2. Quality of the information	42
2.3.3. Representativeness and accuracy of learning and <i>a priori</i> information	43
2.4. Bibliography	43

Chapter 3. Fusion in Image Processing	47
Isabelle BLOCH and Henri MAÎTRE	
3.1. Objectives of fusion in image processing	47
3.2. Fusion situations	50
3.3. Data characteristics in image fusion	51
3.4. Constraints	54
3.5. Numerical and symbolic aspects in image fusion	55
3.6. Bibliography	56
Chapter 4. Fusion in Robotics	57
Michèle ROMBAUT	
4.1. The necessity for fusion in robotics	57
4.2. Specific features of fusion in robotics	58
4.2.1. Constraints on the perception system	58
4.2.2. Proprioceptive and exteroceptive sensors	58
4.2.3. Interaction with the operator and symbolic interpretation	59
4.2.4. Time constraints	59
4.3. Characteristics of the data in robotics	61
4.3.1. Calibrating and changing the frame of reference	61
4.3.2. Types and levels of representation of the environment	62
4.4. Data fusion mechanisms	63
4.5. Bibliography	64
Chapter 5. Information and Knowledge Representation in Fusion Problems	65
Isabelle BLOCH and Henri MAÎTRE	
5.1. Introduction	65
5.2. Processing information in fusion	65
5.3. Numerical representations of imperfect knowledge	67
5.4. Symbolic representation of imperfect knowledge	68
5.5. Knowledge-based systems	69
5.6. Reasoning modes and inference	73
5.7. Bibliography	74
Chapter 6. Probabilistic and Statistical Methods	77
Isabelle BLOCH, Jean-Pierre LE CADRE and Henri MAÎTRE	
6.1. Introduction and general concepts	77
6.2. Information measurements	77
6.3. Modeling and estimation	79
6.4. Combination in a Bayesian framework	80
6.5. Combination as an estimation problem	80
6.6. Decision	81

6.7. Other methods in detection	81
6.8. An example of Bayesian fusion in satellite imagery	82
6.9. Probabilistic fusion methods applied to target motion analysis	84
6.9.1. General presentation	84
6.9.2. Multi-platform target motion analysis	95
6.9.3. Target motion analysis by fusion of active and passive measurements	96
6.9.4. Detection of a moving target in a network of sensors	98
6.10. Discussion	101
6.11. Bibliography	104
Chapter 7. Belief Function Theory	107
Isabelle BLOCH	
7.1. General concept and philosophy of the theory	107
7.2. Modeling	108
7.3. Estimation of mass functions	111
7.3.1. Modification of probabilistic models	112
7.3.2. Modification of distance models	114
7.3.3. <i>A priori</i> information on composite focal elements (disjunctions)	114
7.3.4. Learning composite focal elements	115
7.3.5. Introducing disjunctions by mathematical morphology	115
7.4. Conjunctive combination	116
7.4.1. Dempster's rule	116
7.4.2. Conflict and normalization	116
7.4.3. Properties	118
7.4.4. Discounting	120
7.4.5. Conditioning	120
7.4.6. Separable mass functions	121
7.4.7. Complexity	122
7.5. Other combination modes	122
7.6. Decision	122
7.7. Application example in medical imaging	124
7.8. Bibliography	131
Chapter 8. Fuzzy Sets and Possibility Theory	135
Isabelle BLOCH	
8.1. Introduction and general concepts	135
8.2. Definitions of the fundamental concepts of fuzzy sets	136
8.2.1. Fuzzy sets	136
8.2.2. Set operations: Zadeh's original definitions	137
8.2.3. α -cuts	139
8.2.4. Cardinality	139
8.2.5. Fuzzy number	140

8 Information Fusion

8.3. Fuzzy measures	142
8.3.1. Fuzzy measure of a crisp set	142
8.3.2. Examples of fuzzy measures	142
8.3.3. Fuzzy integrals	143
8.3.4. Fuzzy set measures	145
8.3.5. Measures of fuzziness	145
8.4. Elements of possibility theory	147
8.4.1. Necessity and possibility	147
8.4.2. Possibility distribution	148
8.4.3. Semantics	150
8.4.4. Similarities with the probabilistic, statistical and belief interpretations	150
8.5. Combination operators	151
8.5.1. Fuzzy complementation	152
8.5.2. Triangular norms and conorms	153
8.5.3. Mean operators	161
8.5.4. Symmetric sums	165
8.5.5. Adaptive operators	167
8.6. Linguistic variables	170
8.6.1. Definition	171
8.6.2. An example of a linguistic variable	171
8.6.3. Modifiers	172
8.7. Fuzzy and possibilistic logic	172
8.7.1. Fuzzy logic	173
8.7.2. Possibilistic logic	177
8.8. Fuzzy modeling in fusion	179
8.9. Defining membership functions or possibility distributions	180
8.10. Combining and choosing the operators	182
8.11. Decision	187
8.12. Application examples	188
8.12.1. Example in satellite imagery	188
8.12.2. Example in medical imaging	192
8.13. Bibliography	194
Chapter 9. Spatial Information in Fusion Methods	199
Isabelle BLOCH	
9.1. Modeling	199
9.2. The decision level	200
9.3. The combination level	201
9.4. Application examples	201
9.4.1. The combination level: multi-source Markovian classification	201
9.4.2. The modeling and decision level: fusion of structure detectors using belief function theory	202

9.4.3. The modeling level: fuzzy fusion of spatial relations	205
9.5. Bibliography	211
Chapter 10. Multi-Agent Methods: An Example of an Architecture and its Application for the Detection, Recognition and Identification of Targets	213
Fabienne EALET, Bertrand COLLIN and Catherine GARBAY	
10.1. The DRI function	214
10.1.1. The application context	215
10.1.2. Design constraints and concepts	216
10.1.3. State of the art	216
10.2. Proposed method: towards a vision system	217
10.2.1. Representation space and situated agents	218
10.2.2. Focusing and adapting	219
10.2.3. Distribution and co-operation	220
10.2.4. Decision and uncertainty management	221
10.2.5. Incrementality and learning	221
10.3. The multi-agent system: platform and architecture	222
10.3.1. The developed multi-agent architecture	222
10.3.2. Presentation of the platform used	222
10.4. The control scheme	224
10.4.1. The intra-image control cycle	224
10.4.2. Inter-image control cycle	226
10.5. The information handled by the agents	227
10.5.1. The knowledge base	227
10.5.2. The world model	229
10.6. The results	231
10.6.1. Direct analysis	232
10.6.2. Indirect analysis: two focusing strategies	235
10.6.3. Indirect analysis: spatial and temporal exploration	237
10.6.4. Conclusion	240
10.7. Bibliography	241
Chapter 11. Fusion of Non-Simultaneous Elements of Information: Temporal Fusion	245
Michèle ROMBAUT	
11.1. Time variable observations	245
11.2. Temporal constraints	246
11.3. Fusion	247
11.3.1. Fusion of distinct sources	247
11.3.2. Fusion of single source data	248
11.3.3. Temporal registration	249
11.4. Dating measurements	249

11.5. Evolutionary models	250
11.6. Single sensor prediction-combination	252
11.7. Multi-sensor prediction-combination	253
11.8. Conclusion	257
11.9. Bibliography	257
Chapter 12. Conclusion	259
Isabelle BLOCH	
12.1. A few achievements	259
12.2. A few prospects	260
12.3. Bibliography	261
Appendices	263
A. Probabilities: A Historical Perspective	263
A.1. Probabilities through history	264
A.1.1. Before 1660	264
A.1.2. Towards the Bayesian mathematical formulation	266
A.1.3. The predominance of the frequentist approach: the “objectivists”	268
A.1.4. The 20 th century: a return to subjectivism	269
A.2. Objectivist and subjectivist probability classes	271
A.3. Fundamental postulates for an inductive logic	272
A.3.1. Fundamental postulates	273
A.3.2. First functional equation	274
A.3.3. Second functional equation	275
A.3.4. Probabilities inferred from functional equations	276
A.3.5. Measure of uncertainty and information theory	276
A.3.6. De Finetti and betting theory	277
A.4. Bibliography	280
B. Axiomatic Inference of the Dempster-Shafer Combination Rule	283
B.1. Smets’s axioms	284
B.2. Inference of the combination rule	286
B.3. Relation with Cox’s postulates	287
B.4. Bibliography	289
List of Authors	291
Index	293