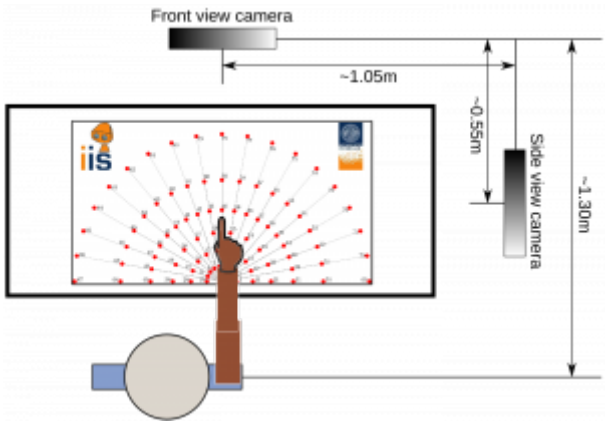
Innsbruck Multi-View Hand Gesture (IMHG) Dataset

Hand gestures constitute a natural forms of communication in human-robot interaction scenarios. They can be used to delegate tasks from a human to a robot. To facilitate human-like interaction with robots, a major requirement for advancing in this direction is the availability of a hand gesture dataset for judging the performance of the algorithms.

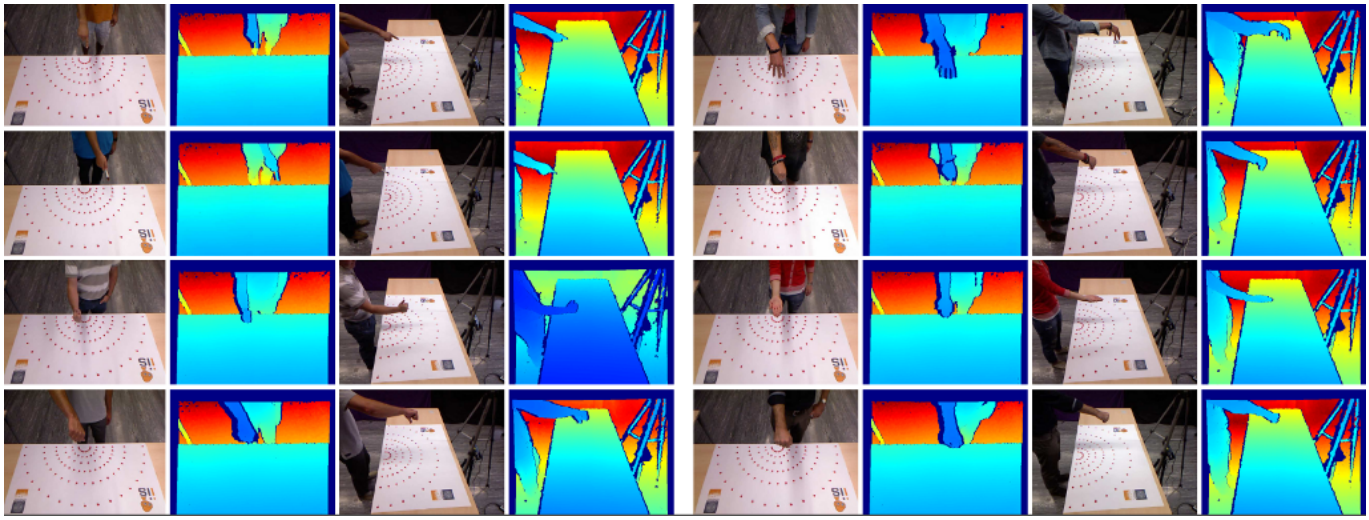
Dataset Features

- 22 participants performed 8 hand gestures in the context of human-robot interaction scenarios taking place at close proximity.
- 8 hand gestures categorized as:
  1. 2 types of deictic gestures with the ground truth location of the target pointed at,
  2. 2 symbolic gestures,
  3. 2 manipulative gestures,
  4. 2 interactional gestures.
- A corpus of 836 test scenarios (704 reference gestures with ground truth, and 132 other gestures).
- Hand gestures recorded from two views (frontal and lateral) using an RGB-D Kinect sensor.
- The data acquisition setup can be easily recreated using a polar coordinate pattern as shown in the figure below to add new hand gestures in the future.



- Soon to be released publicly.
- Currently available for Download (~888MB) with authentication.

Sample Scenarios



Gestures recorded from frontal and side view. *T-B*: Finger pointing, Tool pointing, Thumb up (approve), Thumb down (disapprove), Grasp open, Grasp close, Receive, Fist (stop).

Reference

Dadhichi Shukla, Özgür Erkent, Justus Piater, A Multi-View Hand Gesture RGB-D Dataset for Human-Robot Interaction Scenarios. International Symposium on Robot and Human Interactive Communication, 2016 PDF.

BibTex

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@InProceedings{Shukla-2016-ROMAN,
title = {{A Multi-View Hand Gesture RGB-D Dataset for Human-Robot
Interaction Scenarios}},
author = {Shukla, Dadhichi and Erkent, Ozgur and Piater, Justus},
booktitle = {{International Symposium on Robot and Human Interactive
Communication}},
year = 2016,
month = 8,
publisher = {IEEE},
doi = {10.1109/ROMAN.2016.7745243},
note = {New York, USA},
url = {https://iis.uibk.ac.at/public/papers/Shukla-2016-ROMAN.pdf}
}
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Acknowledgement

This research has received funding from the European Community's Seventh Framework Programme FP7/2007-2013 (Specific Programme Cooperation, Theme 3, Information and Communication Technologies) under grant agreement no. 610878, 3rd HAND.

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Last update: **2018/09/03 19:35**