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SCENE DISCOVERY BY MEANS OF K-MEANS CLUSTERING PROCESS AND BPNN WITH MULTISPECTRAL SATELLITE IMAGES

Khaja Mohideen, Mohamed Mustaq Ahmed, Mohemmed Sha, Mohamed Yacoab

***Abstract* - By substantial growths of remote recognizing have permitted the accession of evidence used on land scene discovery at divergent spatial scales. Substantial collections of remote sensing imagery have furnished a concrete foundation for multispectral analysis of the environment and the influence of human activities. The goal of the remote sensing investigation is to measure the areas of the categories in activity information or offer data that can be utilized to guide sampling strategies. Changes on the scene can be identified as changes in the 'spectral space' involved by an image pixel. In this paper, the proposed technique concentrated on the Object-based scene discovery method, which integrates a system for the arrangement of multispectral satellite images into various pre-established scene cover periods. This work incorporates Non-Modified Histogram Equalization (NMHE), K-Means Clustering with Backpropagation neural network (BPNN) to identify the changed areas using remote sensing images. Supervised classification is the technique used for acquiring the results which aims to progress the performance of Back Propagation Neural Network concerning change detection. Experimental results on various multispectral satellite images displays the correctness of the technique and images obtained from different time periods have shown that this approach is comparatively outperforming the conventional change detection method. As a final point, a vigorous and high-comparison scene discovery result can be achieved.**

***Keywords* - Multispectral Remote Sensing, Object-Based Change Detection (OBCD), NMHE, K-Means Clustering, BPNN.**

I. INTRODUCTION

High-resolution land scene discovery has turn out to be extremely familiar through the improvement of remote sensors for Earth interpretations. In general, Land scene discovery identification involves the evaluation of two registered remote sensed multispectral images assimilated in the identical topographical location at two diverse times to recognize transformed regions on the earth's surface. Multispectral remote sensing is normally based on the acquirement of image data of the Earth's surface consecutively in multiple wavelengths. Multispectral remote sensing may be applied to detect the illumination of natural color and Color Infrared (CIR) aerial photography.

A massive number of change detection approaches and strategies, making use of multispectral distantly sensed data, have remained advanced, and more recent practices are still developing [1]. The information from remote sensing satellites produces chances to achieve statistics about land at numerous purposes and have been commonly used for scene detection review. Various techniques have been advanced for land cover scene discovery using pixel-based as well as object-based methods.

Dissimilar to conventional pixel-based techniques, an object-oriented method gives the image as a lot of important objects as opposed to single pixels [2]. Object-based image assessment is rapidly picking up acknowledgment among remote sensors and has set up the striking latent for grouping and variation recognition of great spatial goal multispectral images in various metropolitan conditions [3]. In general, numerous investigators have confirmed that an object-based change detection framework commonly accommodates image segmentation; image objects feature mining, and association and classification which advance the precision and effectiveness of scene discovery [4]. Eventhough there might be a developing concern for the utilization of object-based methodologies for variation location, moderately limited readings have discovered the efficiency and consistency of an object-based system for post-characterization correlation scene recognition, predominantly, utilizing extremely high-spatial-resolution [5].

A unique Land Cover Change Detection (LCCD) methodology established on the combination of Kmeans

Khaja Mohideen is working in the Department of Computer Science and Engineering, Aalim Muhammed Salegh College of Engineering, Chennai, India.
Mohamed Mustaq Ahmed is working in Department of Information Technology, The New College (Autonomous), Chennai, India.
Mohemmed Sha is working with Department of Computer Science, College of Arts and Science, Prince Sattam bin Abdulaziz University, Wadi Al dawaser, Saudi Arabia.
Mohamed Yacoab is working in Department of Information Technology, The New College (Autonomous), Chennai, India.

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clustering and adaptive popular voting (Kmeans_AMV) methods has remained advanced [6]. The K-means_AMV technique comprises of following procedures. To use the relevant data in an effective adaptive way, choose an adaptive region nearby a dominant pixel is created by identifying the spectral likeness among a crucial pixel and its eight adjacent neighboring pixels. Secondly, after the addition for an adaptive area is completed, the K-means clustering technique is functional to decide the marker of every pixel inside the adaptive area. At long last, the prevailing AMV procedure is utilized to improve the marker of the dominant pixel of the adaptive area.

Various kinds of supervised classification prototypes have remained examined in the work, counting with algorithm using decision trees [7], using random forests algorithm [8], [9], and Support Vector Machines (SVMs) algorithms [10].In recent times, with respect to neural network uses, deep learning takes to turn out to be a investigation hotspot, which has concerned great importance due to its actual and admirable feature learning capability. Layers that have been used in deep learning encompass hidden layers of an Artificial Neural Network (ANN) [11]. Back Propagation Neural Networks (BPNN) is usually used as a building blocks for layer-wise supervised learning. [12] Suggested a original revolution discovery technique grounded on deep neural networks, which remained functional to the multispectral image change detection and achieved superior than outdated change detection methods.

In this research paper, we suggest an innovative supervised method dependent on a back-propagation neural network with K-means clustering to control the constraint of the traditional methodologies. We present an innovative framework for multispectral images, which integrates Histogram based image contrast enhancement and ground truth assessment by a neural network. Network representations were set up to keep the idea of the output image close that of the ground-truth after the input image without image handling.

The remaining sections are as follows. Section II portrays about the study of associated mechanisms. Section III depicts about the hypothetical background, the projected structure in detail. In Section IV, comparison, tabulation, and evaluation of the development process were made. Section V briefly summarizes the work and concludes.

II.LITERATURE SURVEY

Im et al work depicts the study of revise detection model based on the study on neighbour correlation pictures or images and classification based on decision trees[13]

Niemayer et al, In this change detection analysis with high resolution imagery based on pixel and object based. Depend on the outcomes, owing to diverse sensor and solar state of affairs at both attainment times the objects be unequal and form varied dimness. Pixel Based Change Detection study might not in a lot of fabricated signal [14].

Sabins et al, Image organization technique be nearly all normally applied to spectral data of a single-date image or to the series of multi-date images. The complexity of image organization methods can vary from the uses threshold value of a single spectral band to the multifaceted statistical value to operate on multivariate data based on decision rules [15].

Peijun Du et al, paper content based on remote sensing applications including, deforestation monitoring, disaster assessment, urban studies. [16].

Deng et al, adopted the performance of combine PCA with shared supervise organization to spot change [17]. It is used to detect temporal changes with fulfilling outcome.

Pol Coppin et al, conclusion are based on multi-spectral, multi-temporal, satellite sensor acquired data have established probable means to detect identify, map irrespective of their causal agents and monitor ecosystem changes [18]. The method and the outcome of digital change detection in the optical domain, has as its major purpose a synthesis state of today’s art.

Xiaodong Li et al, It is an iterative method, proposed to detect land cover changes at both fine-spatial and fine-temporal resolution with the use of a coarse resolution image and a fine resolution land-cover map acquired at different times[26].

III. PROPOSED METHODOLOGY

In this section, the complete design of the projected structure is displayed in Fig. 1. Assumed two multispectral images, the filtering is done by using Bilateral Filtering and the images are created first by utilizing a Non-Parametric Modified histogram leveling strategy. After fusing the equalized histogram, K-means clustering should be done to separate the features according to clusters of each digital image. To exemplify the variance among these methods and to additional prove the legitimacy of the neural network-grounded correlator, a traditional approach should be made grounded on extra ordinary image processing tools on the same data set that

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had been used for building the neural network-based model. At last, the testing tests are taken care of into the system to produce the relating labels to get change discovery results.

1. Pre-processing

The major phase in the image processing comprises pre-processing which is defined as any procedure of which the input entails of sensor facts, and of which the output is a full image. Resizing an image beginning from one-pixel grid to one more is done through an Image interpolation algorithm. Image resizing is used to rise or shrink the entire amount of pixels, after converting a color image into a gray image, the intensity of the pixel in gray image changes.

1.1. Bilateral filtering

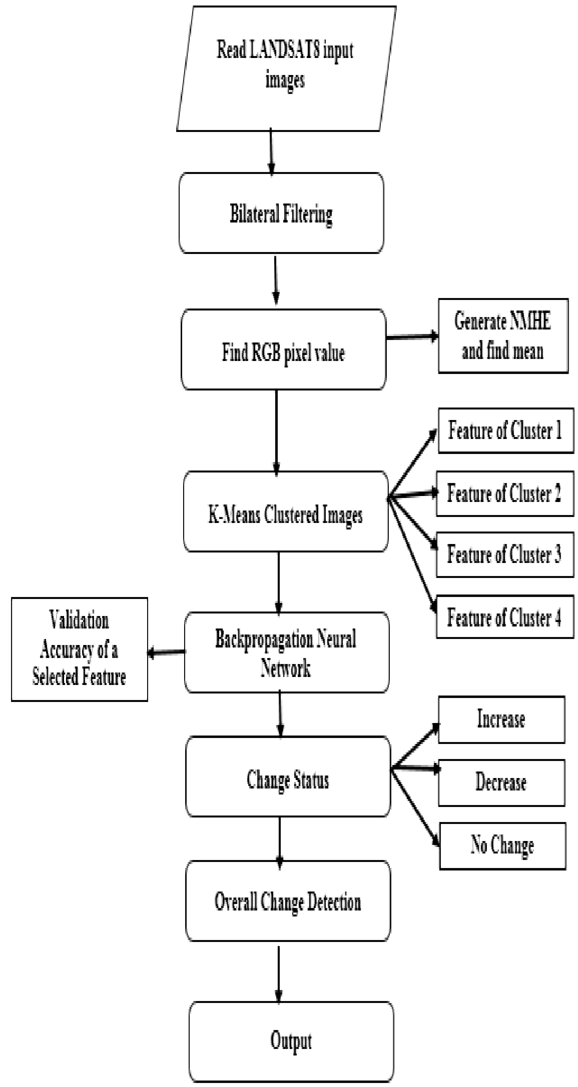
This paper uses an implementation of the bilateral filtering for noise removal [19]. It was the first bilateral filtering method used whose computational and reminiscence difficulty is directly dependent on size of the input and its dimensions. The projected method shows that the bilateral filtering technique is as proficient as the latest edge-preserving filtering strategies, mainly for high-dimensional images. This pass through of a filter is the blend of the spatial and range filter by implementing in cooperation with mathematical and photometric region. In Eq (1), let x signifies a scan line of a grayscale two dimensional (2D) image, then the bilateral clarified rate of x at pixel i is

$$\left(y_i = \sum_{k=0}^{i}\left(R_{k,i}S_{k,i}.x_k\right)\right) \quad (1)$$

Where $R_{k,I} = R(x_k,x_i)$ indicates assortment filter kernel for estimating the series resemblance of pixel k and i, and $S_{k,i} = S(k,i)$ is the spatial filter kernel for evaluating their spatial resemblance.

2. Image Contrast Enhancement

One of the utmost vital quality aspects in satellite images originates from its contrast. Contrast improvement know how to be attained by extending the dynamic range of significant objects in an image [20]. This section discusses the algorithmic construction of the proposed NMHE method in great detail.



2.1 Non-Parametric Modified Histogram Equalization (NMHE)

Image Contrast enhancement can be accomplished by extending the dynamic scope of significant objects in an image. The fundamental reason for contrast enhancement is to fetch out a feature that is enclosed up in an image or to build contrast in a low difference image [21]. There are many procedures for histogram equalization and among those NMHE is the most familiar method used due to its simplicity and efficiency. The Histogram Equalization (HE) method gets a plotting utility to change the unique image to be as near as conceivable to a constant dissemination. The flow of normalized histogram equalization is shown in Fig.2. Let us think through an input image, that is,

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IM ={IM(a, b) |1 ≤a ≤ P, 1 ≤ b ≤ Q}, measuring of dimension P× Q pixels, where IM(a, b) ∈ R the probability density technique of the image is stated by

$$p(x) = nx / J, \text{ for } x = 0, 1, \ldots, N - 1 \quad (2)$$

Where, nx is the number of pixels by means of intensity x and J, the total number of pixels in the image.

For a d-bit image, there are 2d = N intensity levels and the transformation method is specified by

$$TM(x) = [(N - 1)\, c(x) + 0.5] \quad (3)$$

Thus, an growth in output level TM(x) is in a straight line associated to the likelihood of the existence of the kth grey-level such that

$$\Delta T(x) = TM(x) - TM(x - 1) \sim (N - 1)p(x) \quad (4)$$

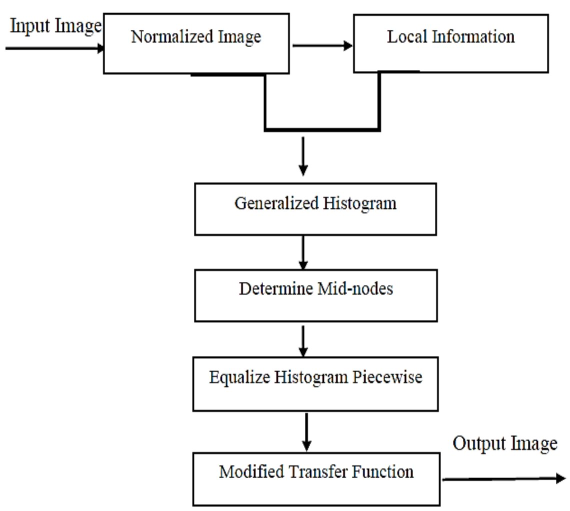

Fig.2. Flow of Histogram Equalization

An NMHE technique has been intended to develop the differentiation of a picture, which changes the image by an adaptive change instead of taking care of any optimization issue. The procedure uniqueness depends on the usage of image's information to calculate a sharp increase permitted to improve histogram, then matched toward condense the image through improved graphical attributes.

3. Clustering Model

Clustering is the task of data objects (records) into collections (called clusters) with the goal that data objects from the similar cluster are more like each other than objects from different groups. Assumed an image this technique partitions them into K groups or clusters. The mean of every group is reserved and then each point p is added to the group where the transformation among the point and the mean is smallest. Subsequently clustering works on hue estimations it is typically used in separating a scene into dissimilar objects [22]. The grouping is finished by limiting the separations among the data and the relating group centroid.

3.1 K-Means Clustering Phase of the Proposed System

K-means clustering process is an unsupervised algorithm and it is utilized to segment the concern region from the background (i.e.) unlabelled data is utilized (information without characterized classes or groups).

Kmeans clustering is a system to arrange or to aggregate the things dependent on traits/topographies into K groups where K is a positive integer number. The assemblage is finished by limiting the separations among the data and the relating group centroid. The expanse that resolve remain used here is the *L*2 distance

$$d(x, y) = \Sigma i\,(xi - yi)^2 \quad (5)$$

The K-means algorithm essentially comprises of the following stages:

Table.1. Proposed K-means algorithm

Step 1: Initialization: K chosen, an initial set of K so-called centroids, i.e. Partition the data points into K clusters randomly.

Step 2: Find the centroids of each cluster, i.e. every point of the data set is assigned to its nearest centroid

Step 3: For each data point:

– Calculate the distance from the data point to each cluster.

– Assign the data point to the closest cluster.

Step 4: Recompute the centroid of each cluster.

Step 5: Repeat steps 2 and 3 until there is no further change in the assignment of data points (or in the centroids).

The goal of grouping investigation is to assemble information in such a way that related objects are in one group and objects of dissimilar clusters are diverse [23].

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The target of this calculation is to discover clusters in the data, with the quantity of collections characterized through the variable K. This cycle mechanism repeatedly allocate every data point to one of K bunches dependent on the features that are specified. Data points are assembled grounded on the feature similitude

Thus, the procedure is halted when the smallest shift is beneath a threshold.

The outcomes of the K-means grouping procedure are:

1. The centre of mass of uniform density of the K clusters, which can be developed to name new data

2. Markers for the training information (every data point is relegated to a solitary collection)

As opposed to characterizing clusters before taking a look at the data, clustering permits us to discover and examine the gatherings that have been framed naturally. The "Selecting K" division underneath portrays how the amount of clusters can be resolved. Every centroid of a group is an assortment of feature esteems which describes the successive sets. Inspecting the centroid feature loads can be utilized to subjectively infer what sort of groups each cluster signifies.

4. Feature Extraction:

The highlights remained pulling out as of the pre-handled image. In the first place, the allusion image or picture with its necessary data is created. The image is separated as N roughly indistinguishable measured components. This image component is separated for testing and form the training set with remaining N-1 sets. The neural network be accomplished by means of the balanced training set. Let say , if N=10, at that point 90% of the ground truth information features are reserved starting from the training set and remaining 10% features of the ground truth information is occupied from the testing set.

5. Back Propagation Neural Network Phase of the Proposed System

BPNN is a Feed-Forward Network, which is a typical technique for preparing ANN [24]. BPNN has excellent nonlinear approximation capability. Starting an ideal output, the linkage gains on or after numerous data inputs. The errors are back propagated to the input layer from the BPNN. The BPNN has a input layer, output layer, and several unseen optional layers The amount of vertex or nodes in the participation with production layers is categorized by the problem itself [25]. The input, hidden and output layers of BPNN are shown in Fig.3.

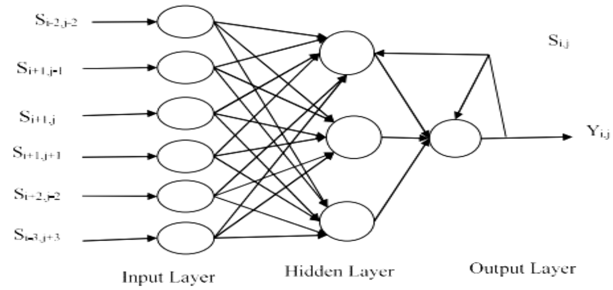

Fig. 3. Structure of BPNN

Selecting the quantity of unseen layers and the quantity of nodes in every unknown layer is significant and generally, it comes with understanding (trial and error method) [26].

The training set of rules of backpropagation contains four stages viz., 1. Setting the values of weights 2. Feed forward 3. Back propagation of bugs or errors 4. Update the data weights and biases. The bias work similar to weights on the linking on or after units display the output as one always. To set the duration of initialization of weights, the random values are assigned by feed forwarding through the layers. The variation between the acquired and concrete values is premeditated as fault and backpropagated. By assigning a maximum initial weight a faster learning rate can be achieved measuring 90% rate. The weights may tend to change. it is understood that if the initial weights minimum or very low subsequently the learning rate will end up in minimum or slow mode. To achieve the best output results, assign the initial weights starting from - 0.5 to 0.5(minus 0.5 to plus 0,5) or -1 to 1.

In this work, BPNN is carefully chosen for validating accuracy since the numerical formula obtainable be pragmatic to all network and no need any particular features of the functions to be learnt since the weights updating is automatic. But if the hidden neurons are increased, the number of variables for error function increases, which increases computing time.

5.1. Accuracy Assessment

The improved utilization of remote sensing data and live out has made spectral investigation quicker and advance influential, however the expanded complexity additionally produces enhanced prospects for miscalculation. Previously, accurateness valuation was no shorter an unease in image classification trainings. Due to the

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expanded opportunities for inaccuracy offered by using digital imagery, still, accuracy assessment has turn out to be further significant than ever. The comprehensive accuracy of the classified image matches how every one of the pixels is characterized against the actual land protection situations assimilated from their relating ground truth information.

IV. Experimental Settings

1. Real Datasets

In order to verify the efficiency of the supervised scene detection in LANDSAT8 images, actual data groups are chosen for experiments to show the performance of the study. An area with 4800 * 2644 resolution of multispectral LANDSAT8 images were used in this study. Anniversary dates were selected to reduce sun angles and periodic differences. The multitemporal images have a spatial resolution of 10m. A color combination of the two multitemporal images was shown in Fig.4.

Landsat-8's essential 2 sensors are the Operational Land Imager (OLI) and Thermal Infrared Sensor (TIRS). These two devices cable to derive up with 11 total spectral bands. Seven of the 11 spectral groups are necessarily reliable with ETM+ (Enhanced Thematic Mapper) perceived on Landsat-7. Landsat-8 bands are coastal, blue, green, red, NIR, SWIR-1, SWIR-2 and cirrus. These 8 bands have a ground goal of thirty meters. The panchromatic band extents a superior spectral series and comprises a resolution of 15 meters. Band 10 & 11 from TIRS are extended wavelength infrared. These bands consume a thicker firmness of hundred meters.

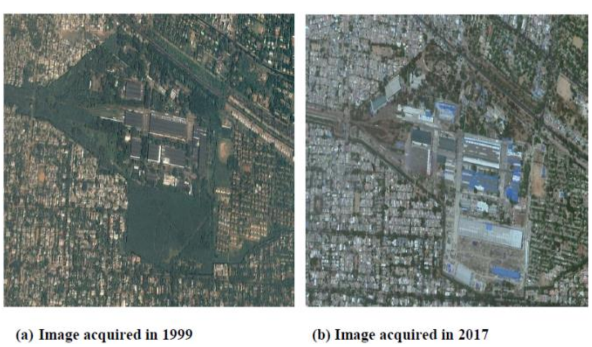

Fig.4. Avadi Dataset of input LANDSAT8 images

2. Performance of Neural Network System

To verify the efficacy of the projected methods, the challenges were made for multispectral change detection on a real data set.

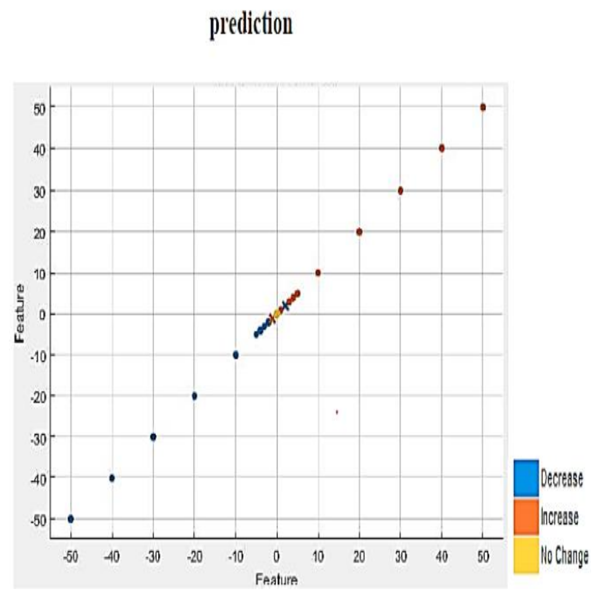

Fig.5. Scatter Plot

In Fig.5, one can view the results of neural network. After training a neural network, the scatter plot shifts on or after exposing the data to viewing prototypical calculations as decrease, increase and no change.

3. Performance Metrics

a) Accuracy

Accuracy refers to the ability of neural network. It calculate the class label appropriately and the accuracy of the predictor states to how well a given predictor can estimate the value of projected attribute for a new data. It is the quantity of precise estimates made dispersed by the complete number of calculations made, multiplied by 100 to turn it into a percentage. Accuracy is one measurement for assessing classification prototypes. Familiarly, accuracy is the division of estimates our model got precise. Formally, accuracy has the succeeding characterization:

Accuracy=Number of correct estimates/Total number of predictions

Here, the following Table.2, predicts the accuracy of the neural networks in %. These comparison on performance was made for Avadi, Chetpet and Nerkundram datasets.

It shows clearly that among these neural networks, Back Propagation Neural Network is considered as the best one and it gives better accuracy result.

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Table.2. Accuracy of Avadi, Chetpet and Nerkundram Dataset for various neural networks

Neural Network	Accuracy		
	Chetpet	Avadi	Nerkundram
Back Propagation	94	98	96
Ensemble–RUS Boosted	66.7	60	53
KNN -Coarse	86	33	33
SVM-Cubic	80	73.3	80
Tree-Complex Tree	90	93	93

In the below Fig.6, comparison on accuracy was made for three datasets using various neural networks and among that BPNN has obtained better accuracy of 98% in Avadi, 94% in Chetpet and 96% in Nerkundram city

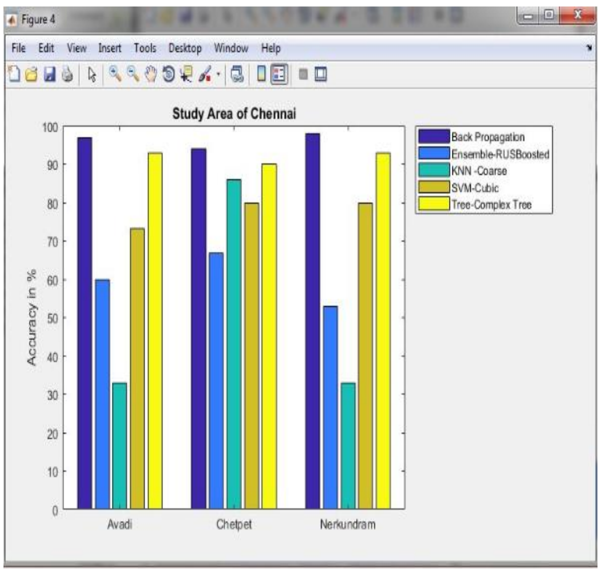

Fig.6. Comparison on Accuracy of Avadi, Chetpet and Nerkundram dataset for various neural networks

b) Prediction Speed

This refers to the computational cost in producing and using the neural network. It was measured in obs/sec.

Prediction speed of neural networks in obs/sec is shown in Table.3 and Fig.7. These comparisons on performance was made for Avadi, Chetpet and Nerkundram datasets

Table.3. Prediction Speed of Avadi, Chetpet and Nerkundram Dataset for various neural networks

Neural Network	Prediction Speed		
	Chetpet	Avadi	Nerkundram
Back Propagation	380	550	450
Ensemble –RUS Boosted	91	230	80
KNN -Coarse	300	330	320
SVM-Cubic	270	190	230
Tree- Complex Tree	79	480	410

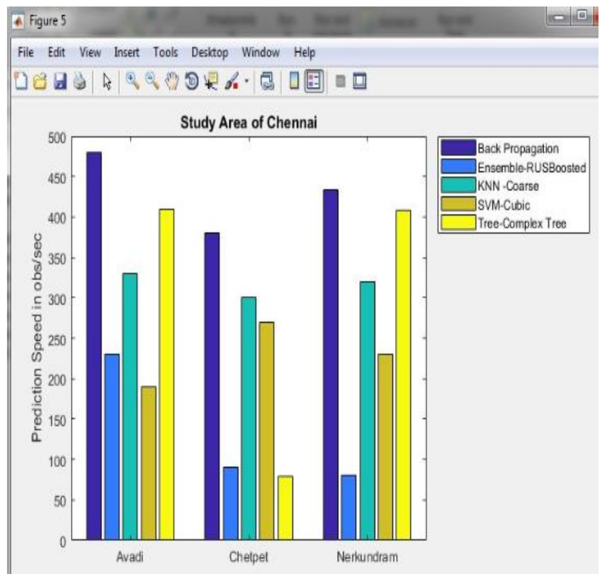

Fig.7. Comparison graph on Prediction speed of Avadi, Chetpet and Nerkundram dataset for various neural networks

c) Training time

Due to the huge assortment of preparing times, just the request comparative with the quickest calculation for each dataset is affirmed. The quickest process is shown by a ‘0’. An procedure that is between 10x−1 to 10x epochs as gentle is demonstrated by the estimation of x. Overall, the fastest algorithm is BPNN, followed closely by Ensemble RUS Boosted, KNN –Coarse, SVM-Cubic, Tree-Complex Tree.

Training time of various neural networks was made in sec and it is shown in following Table.4 and Fig.8. These comparisons on performance were made for Avadi, Chetpet and Nerkundram datasets.

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Table.4. Training Time of Avadi, Chetpet and Nerkundram Dataset for various neural networks

Neural Network	Training Time		
	Chetpet	Avadi	Nerkundram
Back Propagation	0.05	0.05	0.03
Ensemble –RUS Boosted	7.234	7.234	8.0431
KNN -Coarse	1.6029	1.6029	1.6515
SVM-Cubic	2.436	2.436	2.4489
Tree- Complex Tree	1.3594	1.3594	1.1669

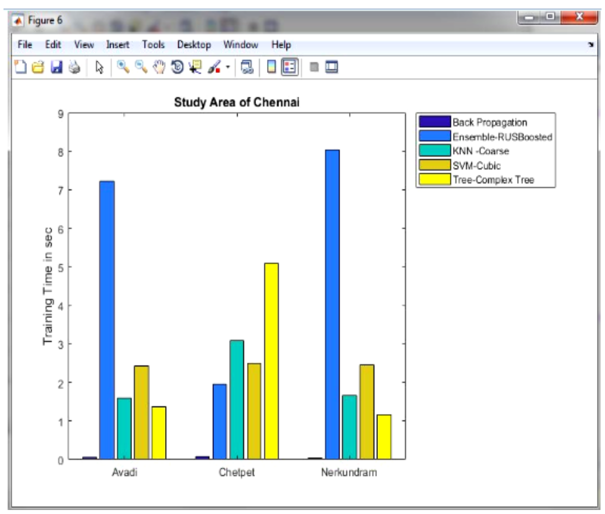

Fig.8. Performance graph of Training Time on Avadi, Chetpet and Nerkundram dataset for various neural networks

V. CONCLUSION

In this paper, numerous strategies for distinguishing the transformation in distant sensing images have remained deliberate. It is discovered that there are numerous procedures for recognizing the variation in the images. These performances can be characterized into object and spatial grounded systems. In classification built strategies, the image is initially grouped into various classes and afterward the classes are matched with the consistent classes to identify the change. For enhanced scene discovery, images are initially upgraded and afterward computation of the scene discovery has been completed. For improved assessment production, it is essential, to precisely identify the variation in earth's exterior scenes for enhanced contemplation among human and natural occurrences. Consequently, in view of the outcomes, it is determined that the object centered strategies is the best strategy method which have been considered and executed.

The forthcoming progress of this work is on the manner to advance the renovation discovery accurateness for remote perceiving images by integrating the new sceneries with the projected system. The proposed technique can be additionally adjusted inorder to enroll the images without anyone else and afterward identifying the scene. The proposed strategy has remained verified on modest RGB images. The technique can be additionally improved to spot the modification in multispectral images. There is an added extent of decrease in complete error and rise in the precision and training time estimation of the extended procedure. The future framework can be altered so as to actualize it on ongoing time imaging devices. The adjustment should likewise be possible in such a manner that the images are compacted spontaneously before to spot the scene. This improvisation might be very accommodating to recognize the change in image more precisely.

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Biographical Notes:

Khaja Mohideen K. received his B.Sc (Computer Science) and M.C.A (Master of Computer Applications) from Jamala Md. College affiliated to Bharathidasan University, Tiruchirapalli, India in 1991 and 1994 respectively. Completed his M.Phil in Computer Science from Periyar University Salem, India. Completed his M.E. Computer Science and Engineering from University College of Engineering, Tiruchirapalli, India. Currently working **as Assistant Professor and Head in the Department of Computer Science and Engineering at Aalim Muhamed Salegh College of Engineering , Chennai, India**. His area of interest includes Web Databases, Cloud Computing, and Distributed Computing.

Dr. Mohamed Mustaq Ahmed. A is presently working as Assistant professor in the Department of Information Technology, The New College, Chennai. Dr. Mustaq has obtained his Doctorate in Computer science from Dravidian University, India. Currently his research work involves Image Processing using CNN, Web service Integration, Big data Analysis. His reputed publication deals with visual information retrieval system. He is possessing a continuous teaching experience of more than 15 years for under graduate, post graduate in India which also includes 9 years in abroad teaching experience for cultural diversity students. He also served as Head of the department in ISM, Mohamed Sathak college of arts and science till November 2020

Dr. Mohemmed Sha M received M.C.A in Computer Applications in the year 2000 from Manonmaniam Sundaranar University, India. He completed his M.Phil in Computer Science in 2005 from Bharathidasan University, India and Ph.D in Computer Applications from Manonmaniam Sundaranar University, Tirunelveli, India. His research focuses on Evaluating the Quality of Web services and Big Data Analytics. His reputed publications deals with selection of quality oriented web services based on its functionality and Big Data analytics in health care systems. He served as a principal of Achariya School of Business and Technology, Pondicherry for 6 years. Now he is working as an Assistant Professor in Prince Sattam bin Abdulaziz University, Saudi Arabia.

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Dr. Mohamed Yacoab received his M.C.A in Computer Applications from Bharathidasan University, India. He completed his M.Tech (IT) in Information Technology from Punjabi University, India and PhD in Computer Science from Karpagam University, India. His research focuses on Wireless Sensor Networks, Web services composition, Data mining and Neural Networks. He served as Academician in India, Oman and Saudi Arabia for the span of two decades. Currently working as an Assistant Professor in department of Information Technology The New College (Autonomous) , Chennai, India

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