

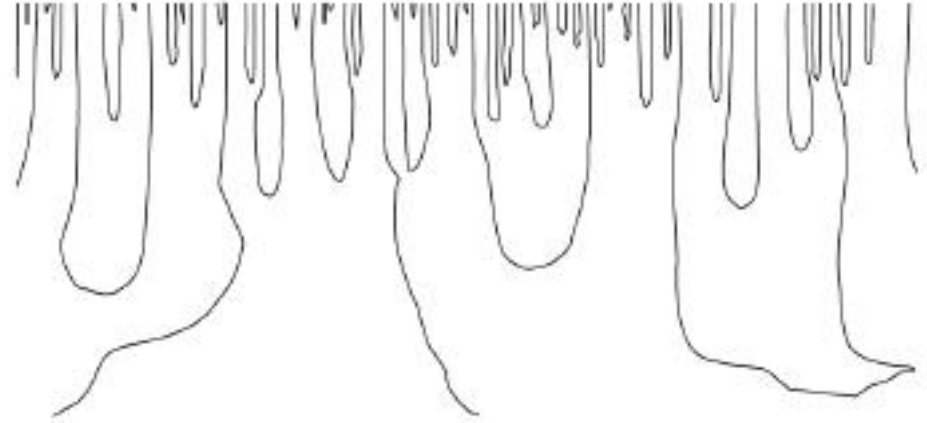
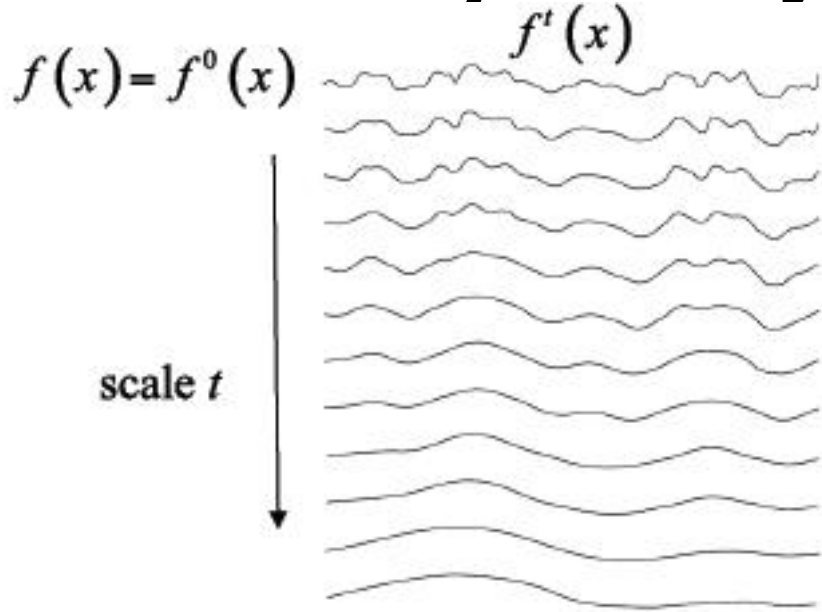
# Scale-Space Feature Detection (Ölçek- Uzay Öznitelik Algılama)



Görüntülerin öznitelikleri tüm ölçeklerde benzer şekilde görünür.

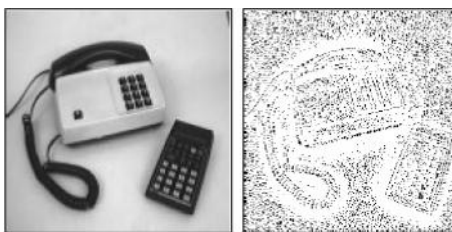
Ölçek uzay gösterimleri, ölçek değişmezliği ve yön değişmezliği özniteliklerinin temelini oluşturur.

# Bir sinyalin ölçek uzay gösterimi

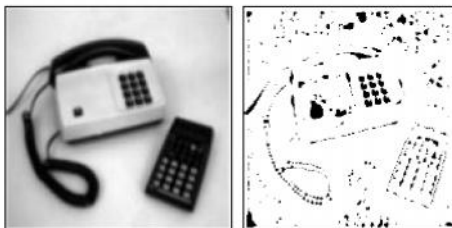


[Witkin 1983]

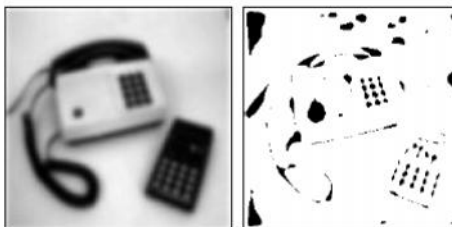
**Gaus filtresiyle art arda düzleştirilerek üretilen sinyaller ve 2nci türevin sıfır geçişleri: daha kaba ölçeklerde daha az öznelilik**



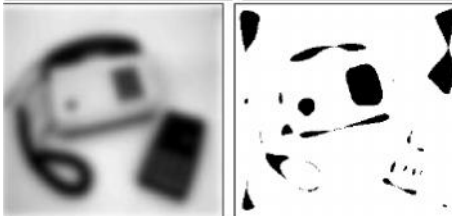
$t = 0$



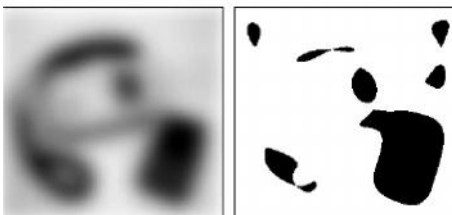
$t = 2$



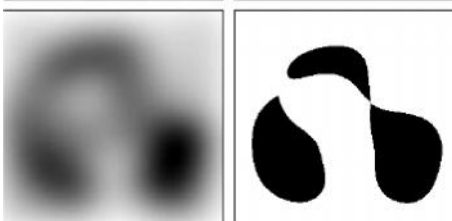
$t = 8$



$t = 32$

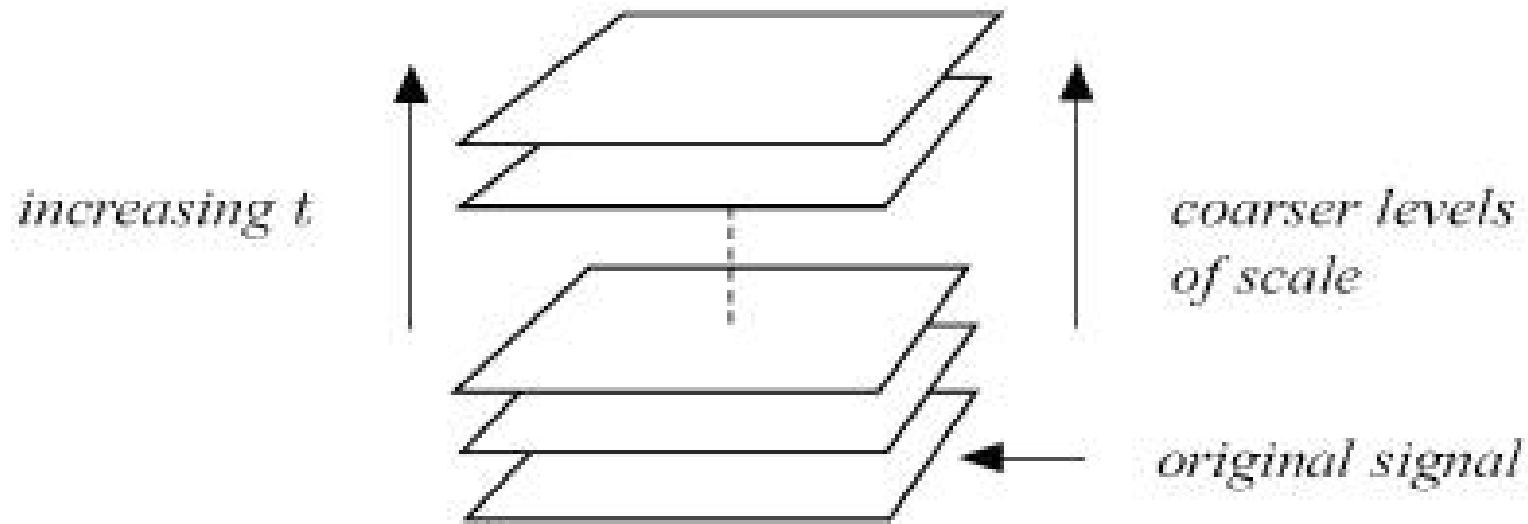


$t = 128$

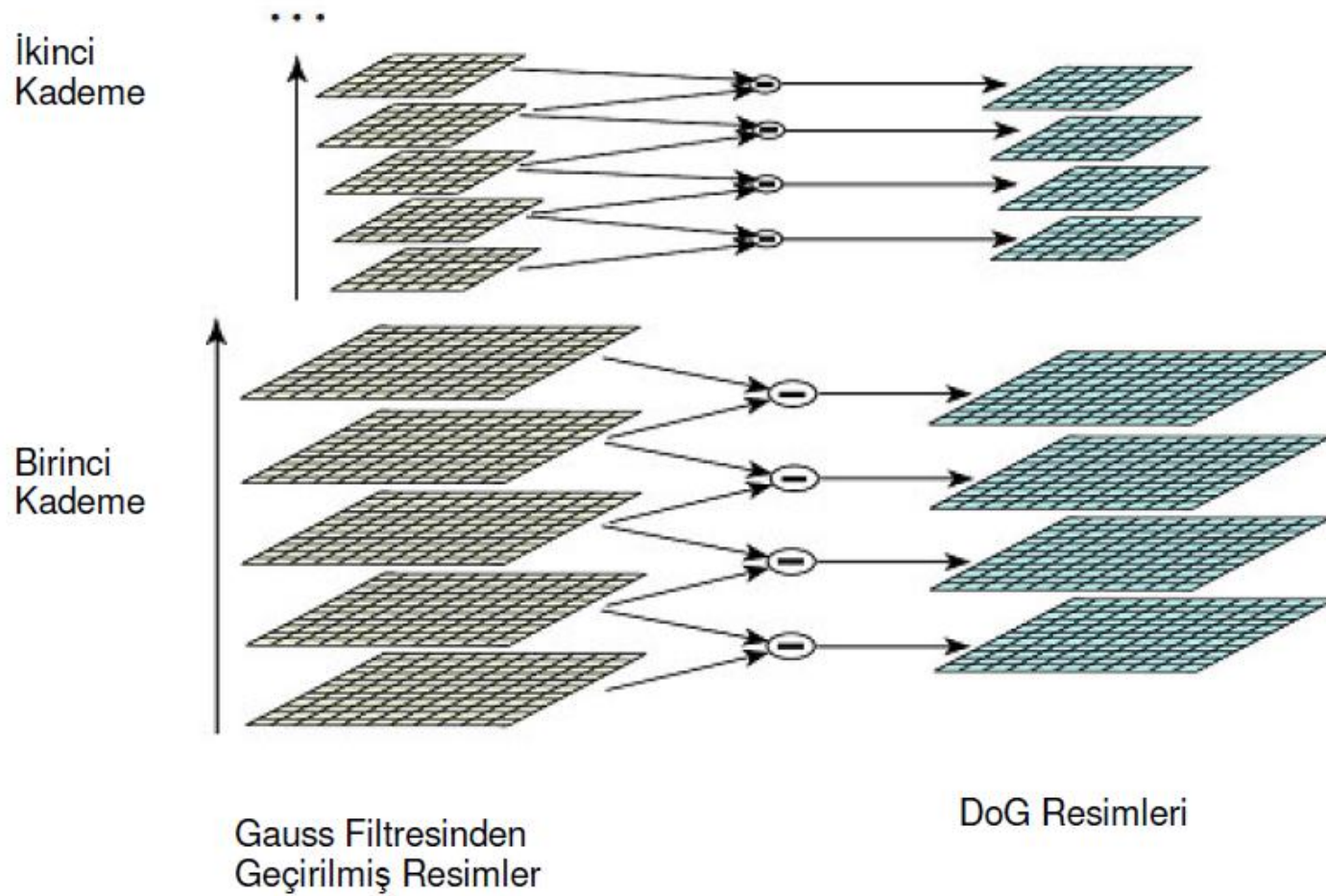


$t = 512$

# Görüntülerin ölçek uzay gösterimi



# SIFT ( Ölçek uzayın oluşturulması)



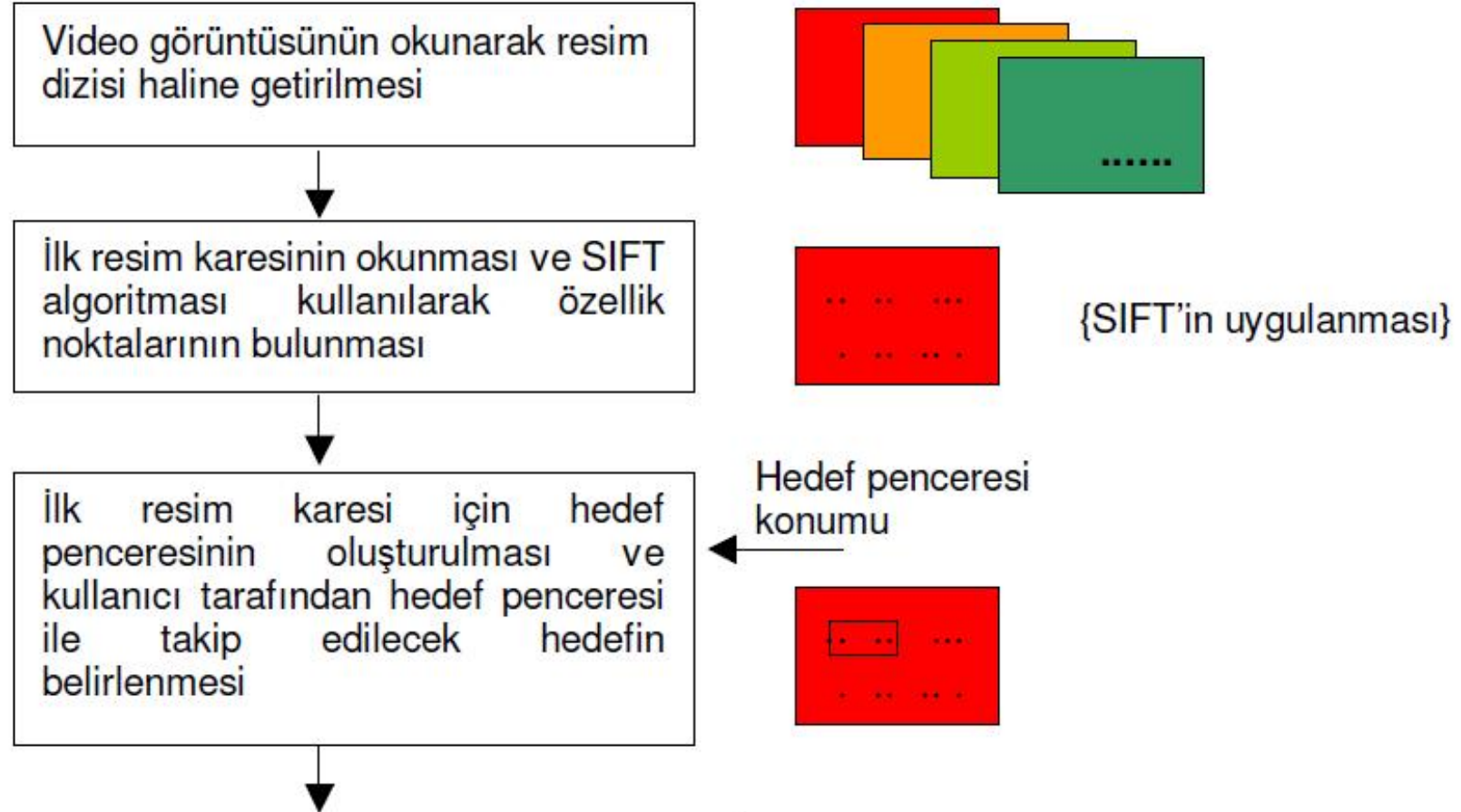
# SIFT (Scale Invariant Feature Transform)



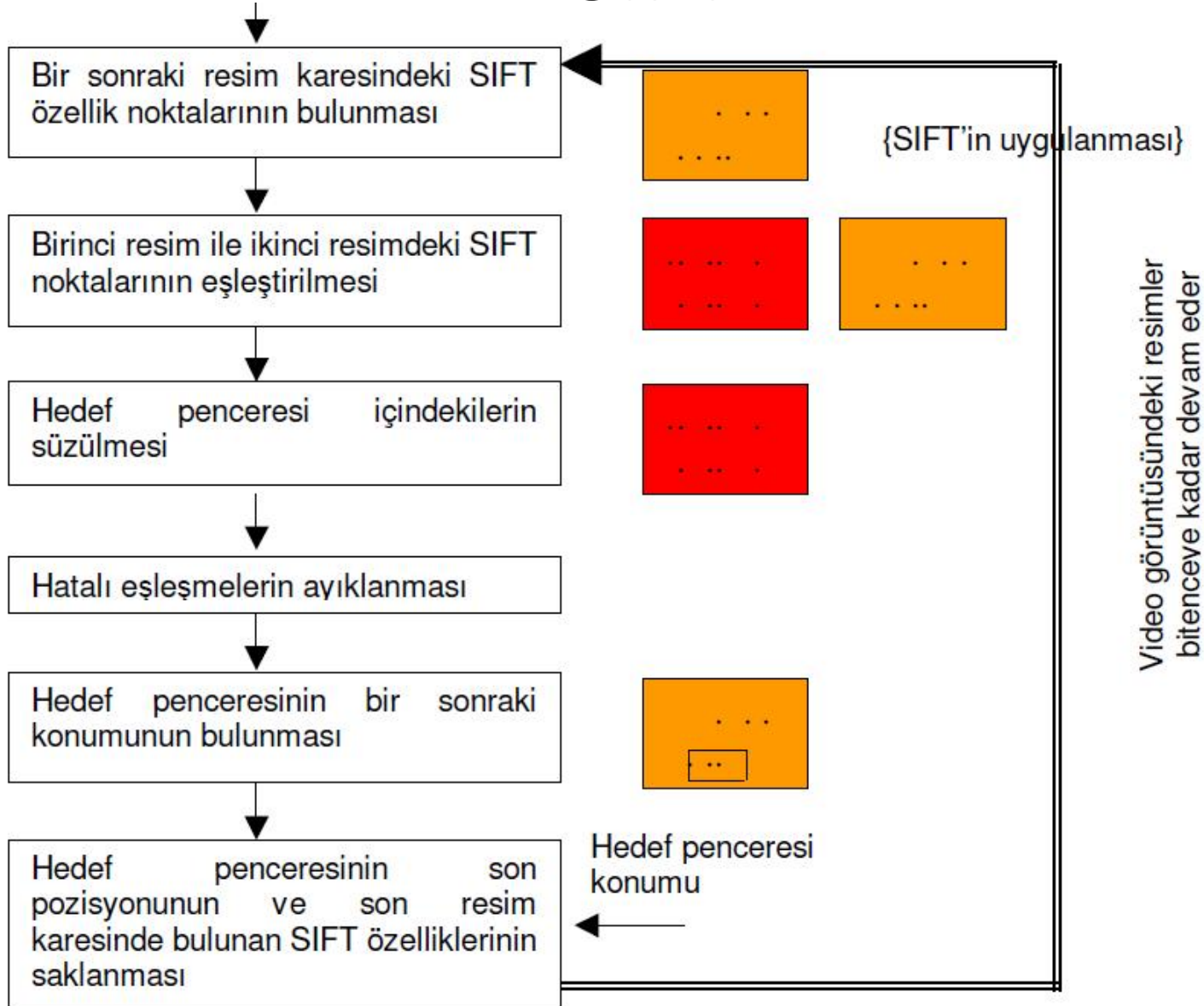


# SIFT

Hedef takibinde kullanılan programın akış şeması aşağıda verilmiştir.

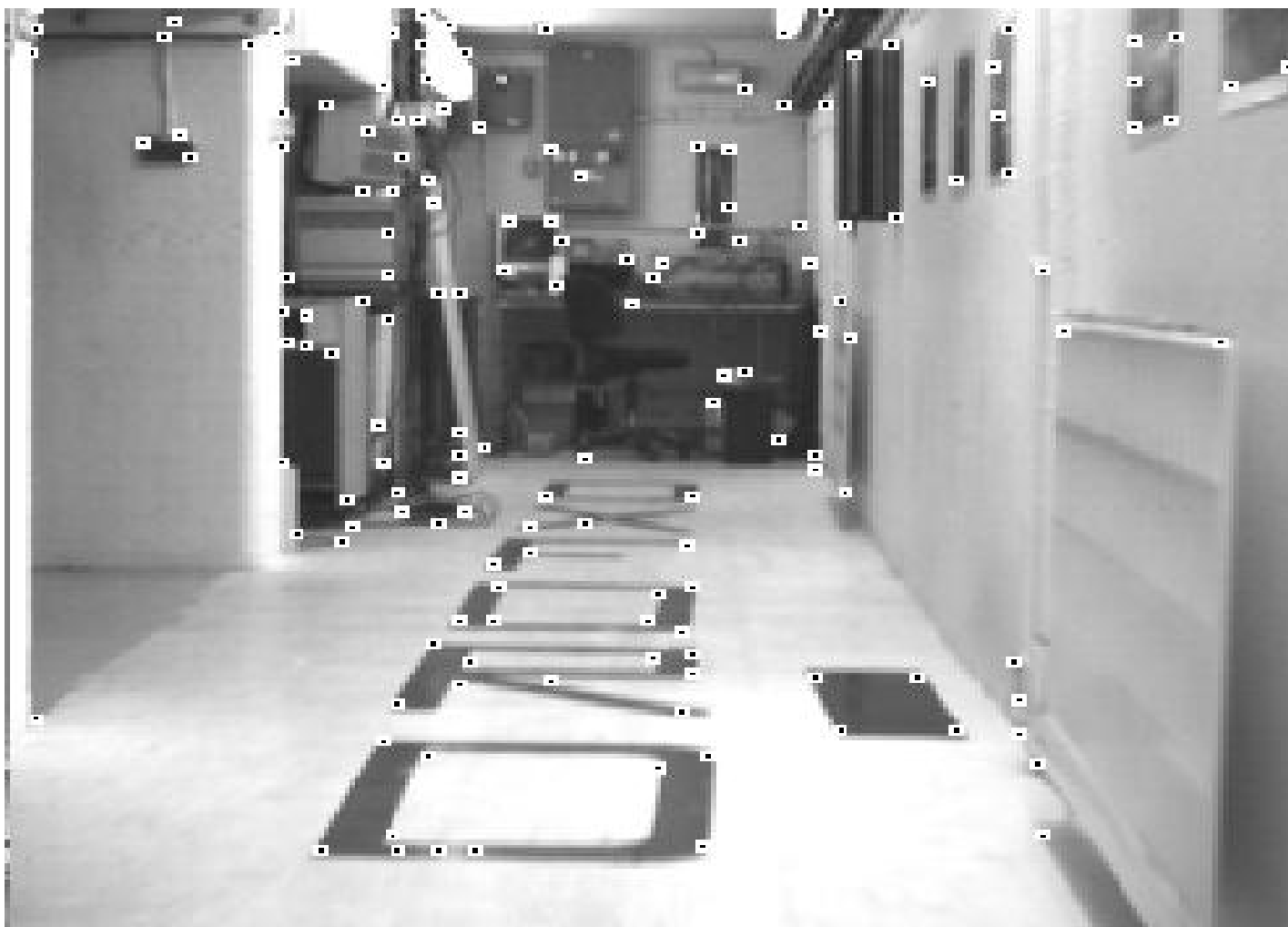


# SIFT



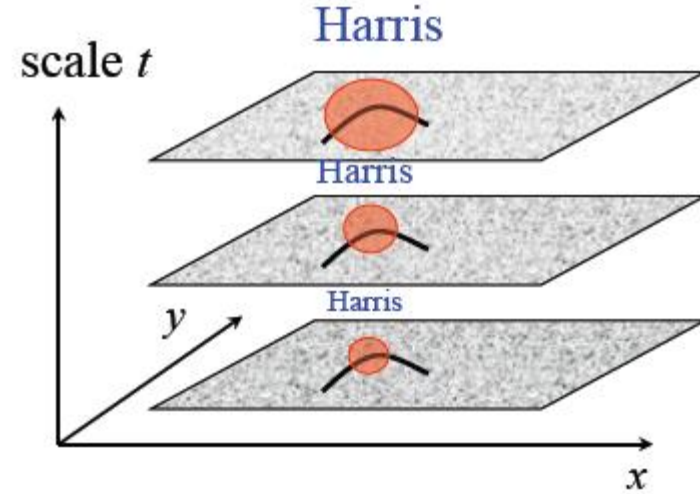


# HARRIS



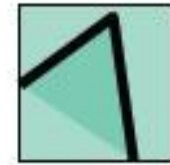
# Otomatik ölçek seçimi ile “blob” (Damla) algılama

Ölçek uzay gösterimi tüm ölçekleri sağlar; peki hangi ölçek anahtar nokta algılama için en iyidir?

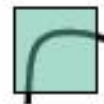
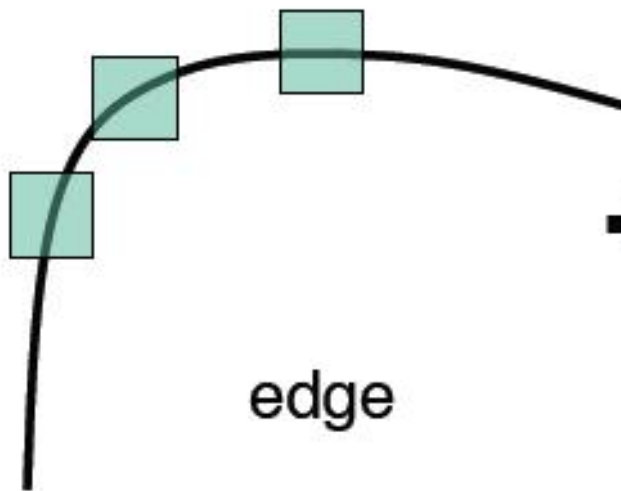


# HARRIS algılayıcı

- Invariant to shift and rotation



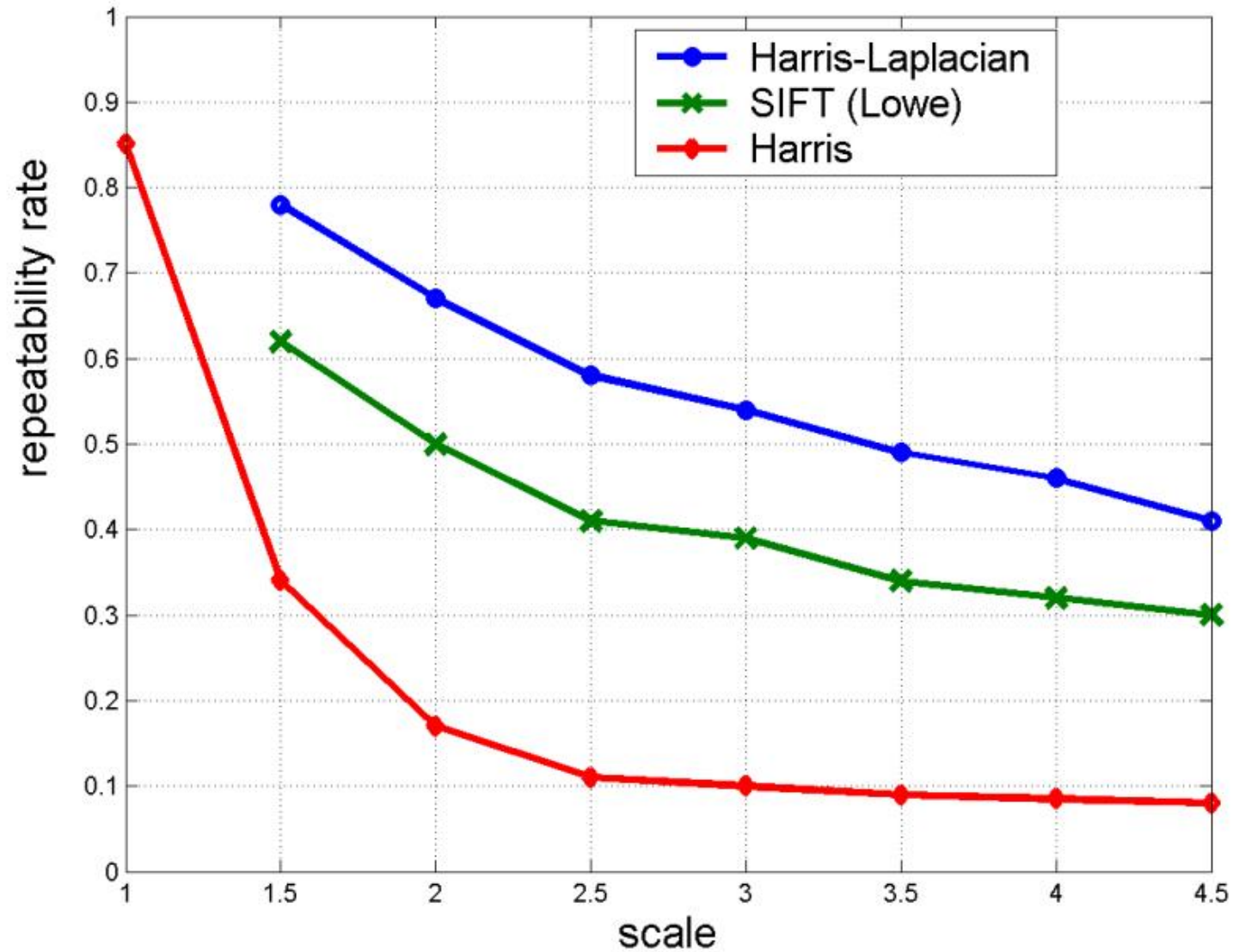
- Not invariant to scaling



edge

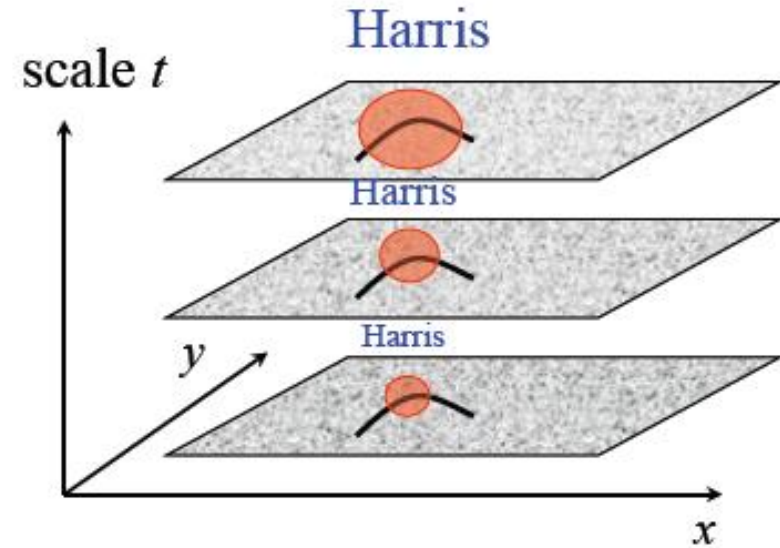
corner

# Ölçeklemeye dayanıklılık



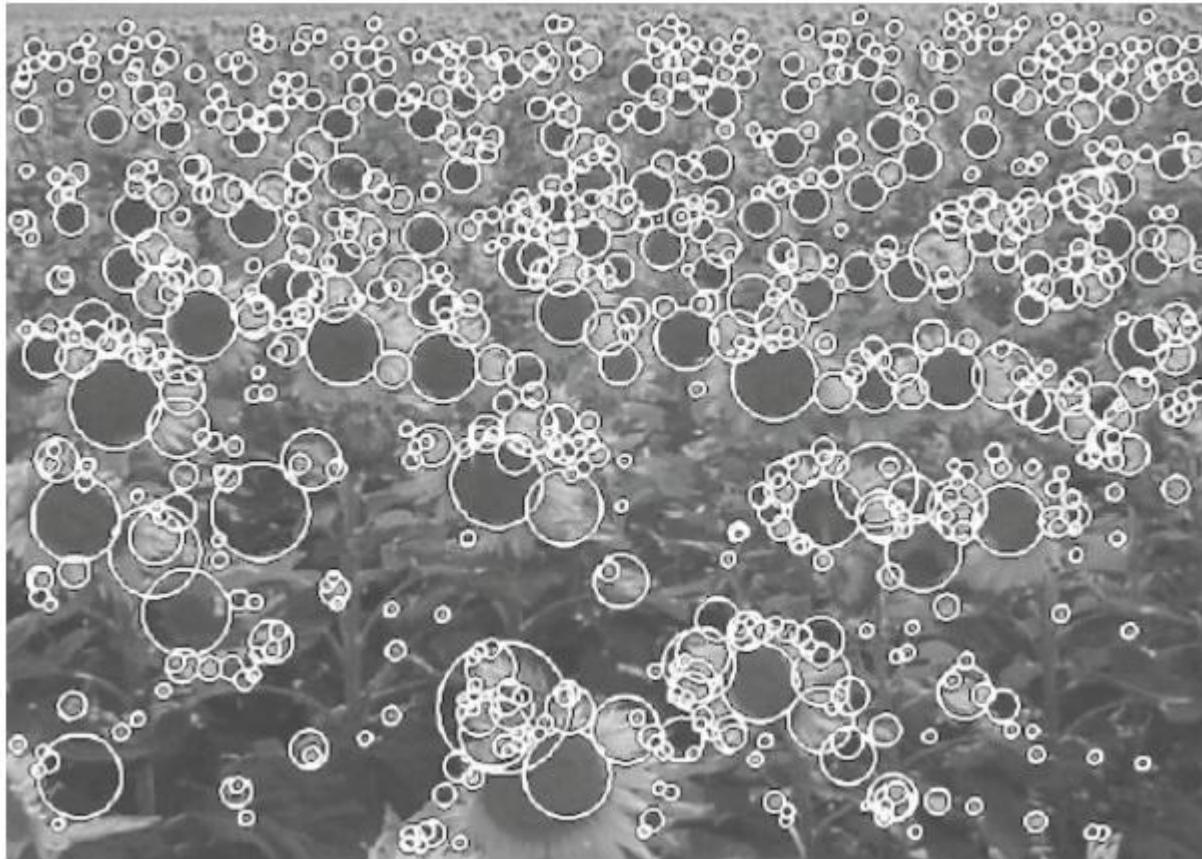
## Harris Laplace'ı;

1. Harris köşesini ilk ölçekte algılar
2. **Her bir Harris köşesi için karakteristik ölçeği normalleştirilmiş Laplace ölçeğinin maksimumu gibi algılar**
3. Anahtar noktayı uzaysal bölgede yerelleştirmek için Harris algılayıcıyı uygular
4. **2 ve 3. maddeleri yakınsama oluncaya kadar uygular**





# SURF Blob detection



# SIFT and SURF

Method	Time	Scale	Rotation	Blur	Illumination	Affine
SIFT	common	best	best	best	common	good
SURF	best	good	common	good	best	good