

International Journal of Pattern Recognition  
and Artificial Intelligence

Vol. 26, No. 1 (2012) 1255002 (22 pages)

© World Scientific Publishing Company

DOI: 10.1142/S0218001412550026



## EDPF: A REAL-TIME PARAMETER-FREE EDGE SEGMENT DETECTOR WITH A FALSE DETECTION CONTROL

CUNEYT AKINLAR\* and CIHAN TOPAL†

*Computer Engineering Department  
Anadolu University, Eskisehir, Turkey*

\*cakinlar@anadolu.edu.tr

†cihant@anadolu.edu.tr

Received 10 June 2011

Accepted 22 September 2011

We propose a real-time, parameter-free edge/edge segment detection algorithm based on our novel edge/edge segment detector, the edge drawing (ED) algorithm; hence the name edge drawing parameter free (EDPF). EDPF works by running ED with ED's parameters set at their extremes. This produces all edge segments in a given image with numerous false detections. The detected edge segments are then validated by an “*a contrario*” validation step due to the Helmholtz principle, which eliminates invalid detections leaving only “*meaningful*” edge segments.

**Keywords:** Parameter-free edge detection; edge/edge segment detection; boundary/contour detection; edge segment validation; Helmholtz principle; real-time imaging.

### 1. Introduction

Edge detection is a very basic and important problem in image processing, and various edge detection algorithms have been proposed in the literature.<sup>3,6,8,12,20,21,26,30,37,40,41,46,48,49,51–53,56,57,59,63</sup> Many computer vision and image processing applications start by detecting edges in a given image, and use the edge map for further higher level processing such as line segment extraction,<sup>1,11,13,15,18,22,23,27,29,31,34,36,62</sup> shape coding and detection,<sup>16,24,28,33,38,54,58</sup> recognition,<sup>19</sup> registration,<sup>7,61</sup> and many others. The success of the rest of the application depends on the quality of the produced edge map, which is defined to consist of perfectly contiguous, well-localized, nonjittered and one-pixel wide edge segments.<sup>4,5,17,25,32,47,55</sup> The speed of edge detection algorithm is also important especially for real-time applications.

All edge detection algorithms have many parameters that must be set by the user. Choosing the right values for the parameters of an edge detector is not an easy job. Usually, the user is required to choose different sets of parameters for different types of images, which is a heavy burden on the user. Furthermore, traditional edge

*C. Akinlar & C. Topal*

detectors approach the problem of edge detection as finding the discontinuities in the contrast of an image and return all such discontinuities as edge elements (edgels) without regard to whether the returned edgels are in fact on the boundary of a perceptually meaningful structure. This means that if a uniform white noise image is fed into a traditional edge detector, many of the pixels are returned as edgels; but in fact there is no perceptually meaningful structure in a white noise image according to the Gestalt school of perception.<sup>9,10</sup>

Ideally, one would like to have an edge detector that runs fast (real-time if possible), requires no parameter-tuning and returns only perceptually “*meaningful*” edge segments. To satisfy these requirements, Desolneux, Moisan and Morel (DMM)<sup>8</sup> made use of the computational Gestalt theory, and proposed a parameter-free edge detection algorithm. Their idea is to compute all the pieces of all level lines of an image and pick only the “*meaningful*” pieces. A piece of a level line or an edge segment is defined to be “*meaningful*” if the norm of the gradient along the edge segment is high compared to the distribution of the gradient over the entire image.<sup>8–10,40</sup> Although DMM’s algorithm is parameter-free and returns only the perceptually “*meaningful*” edge segments, it not only takes a very long time to execute, but it also leads to over-representation of the edge segments, i.e. multiple edge detections around an edge area.<sup>40</sup>

Despite the problems associated with DMM’s parameter-free edge detector, their edge segment validation mechanism due to the Helmholtz principle is very practical, and can be used for validation of edge segments detected by any edge segment detection algorithm.<sup>8</sup> In this paper, we make use of this edge segment validation method, and propose a *real-time, parameter-free* edge/edge segment detector based on our recently-proposed, novel edge/edge segment detector, the edge drawing (ED) algorithm;<sup>12,57</sup> hence the name edge drawing parameter free (EDPF). EDPF works by running ED with ED’s parameters set at their extremes. This produces all edge segments in a given image with numerous false detections. The detected edge segments are then validated by the “*a contrario*” validation step due to the Helmholtz principle,<sup>8–10,40</sup> which eliminates invalid detections leaving only “*meaningful*” edge segments. We believe that EDPF is a major step forward in the quest for a *real-time, parameter-free* edge segment detector.

The rest of the paper is organized as follows: Sec. 2 describes step-by-step how ED processes an image to produce the final edge map. Section 3 discusses the edge segment validation mechanism due to the Helmholtz principle. Section 4 talks about realizing EDPF by running ED with ED’s parameters set at their extremes. Section 5 analyzes the performance of EDPF from different perspectives, and Sec. 6 concludes the paper.

## 2. Edge/Edge Segment Detection by ED

ED is our recently-proposed, novel, real-time edge/edge segment detection algorithm.<sup>12,57</sup> What makes ED stand out from the existing edge detectors, e.g. Canny,<sup>6</sup> is the following: While the other edge detectors give out a binary edge image as output, where the detected edge pixels are usually independent, disjoint, discontinuous

entities; ED produces a set of edge segments, which are clean, contiguous, connected chains of edge pixels. Thus, while the outputs of other edge detectors require further processing to generate potential object boundaries, which may not even be possible or result in inaccuracies; ED not only produces perfectly connected object boundaries by default, but it also achieves this in blazing speed compared to other edge detector.<sup>12,57</sup>

ED works on grayscale images, and performs edge segment detection in four steps:

- (1) The image is first passed through a filter, e.g. Gauss, to suppress noise and smooth out the image. Our experiments have shown that a  $5 \times 5$  Gaussian filter with a  $\sigma = 1$  makes ED produce the best results. Therefore in all experiments presented in this paper, we assume that the input image is first smoothed with this smoothing kernel.
- (2) The next step is to compute the gradient magnitude and direction at each pixel of the smoothed image. Any of the known gradient operators, e.g. Prewitt,<sup>46</sup> Sobel,<sup>52</sup> Scharr,<sup>51</sup> etc., can be used at this step. The computed gradient map is usually thresholded to eliminate nonedge areas. This is achieved by a “*gradient threshold*” as in all gradient-based edge detectors, e.g. Canny *low* threshold.<sup>6</sup> The remaining pixels constitute what is called the “*edge areas*.” The final edge map will be a subset of the pixels within the edge areas.
- (3) In the third step, we compute a set of pixels, called the *anchors*, which are pixels with a very high probability of being edge elements (edgels). The anchors correspond to pixels where the gradient operator produces maximal values, i.e., the peaks of the gradient map. In the current version of ED, this step is implemented by nonmaximal suppression as in Canny.<sup>6</sup> It should be noted that in traditional nonmaximal suppression employed by Canny, a pixel is considered to be an edgel candidate if its gradient value is bigger than both of its neighbors in the pixel’s gradient direction. However, ED considers a pixel to be an anchor if its gradient value is bigger than both of its neighbors in the pixel’s gradient direction by a certain threshold, called the “*anchor threshold*”.<sup>12,57</sup> This is just to choose more stable anchors to start the linking process.
- (4) In the fourth and final step, ED connects the anchors computed in the third step by drawing edges between them; hence the name *Edge Drawing* (ED). The whole process is similar to children’s dot-to-dot boundary completion puzzles, where a child is given a dotted boundary of an object, and she/he is asked to complete the boundary by connecting the dots. Starting from an anchor (dot), ED makes use of the neighboring pixels’ gradient magnitudes and directions, and walks to the next anchor by going over the gradient maximas. If you visualize the gradient map as a mountain in 3D, this is very much like walking over the mountain top from one peak to the other.<sup>12,57</sup>

Looking at the steps taken by ED, we see that the first three steps are very similar to traditional gradient-based edge detectors such as Canny. But at the fourth step, ED follows a very unorthodox approach: While traditional edge detectors follow a

C. Akinlar & C. Topal

reactive approach and work by eliminating candidate edgels computed in the third step using such techniques as hysteresis, edge thinning, etc., ED follows a *proactive* approach and works by drawing edges between successive anchors. This allows ED to obtain the edges in edge segment form, each consisting of 1-pixel wide, contiguous, connected chain of pixels.

Figure 1 shows ED in action on a  $512 \times 512$  pixels grayscale Lena image. Figure 1(b) shows the thresholded gradient map, i.e. the *edge areas*. Final edge map produced by ED would be a subset of pixels from this map. Figure 1(c) shows a set of anchors obtained by nonmaximal suppression. Clearly, the anchors depict the boundaries of the objects in the image clearly visible to a human observer. The final edge map, shown in Fig. 1(d), is obtained by linking the anchors (see Refs. 12 and 57 for a detailed description of how ED links the anchors to obtain the final edge map).

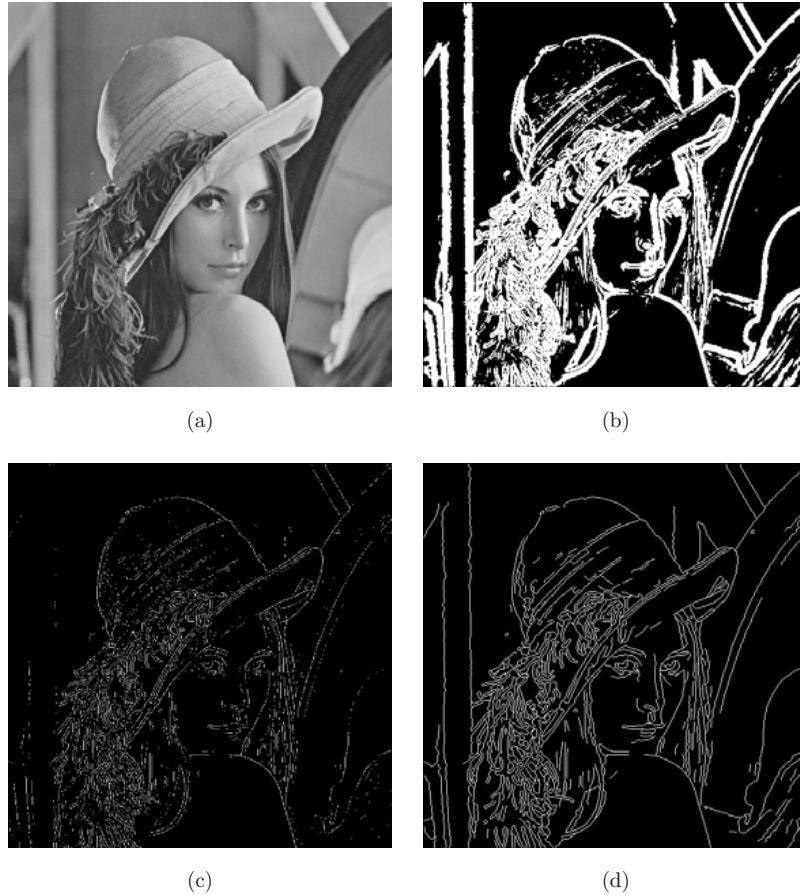


Fig. 1. (a) The grayscale Lena image, (b) thresholded gradient map, (c) anchors and (d) final edge map. Prewitt operator was used to obtain the gradient map. A gradient threshold of 24 and an anchor threshold of 5 were used to obtain the thresholded gradient map and anchors. The final edge map was obtained by ED's smart routing algorithm.<sup>12,57</sup>

As mentioned before, ED not only produces a binary edge map similar to other edge detectors, but it also produces a set of edge segments, each consisting of a linear chain of pixels. Obtaining the edge map as a set of edge segments is very important as this facilitates further processing without any extra effort. Various post-processing alternatives include edge segment validation,<sup>8,40</sup> line segment detection,<sup>1,11,13,15,18,22,23,27,29,31,34,36,62</sup> shape coding and detection,<sup>16,24,28,33,38,54,58</sup> recognition,<sup>19</sup> registration,<sup>7,61</sup> among many others. Edge segment validation is especially important as it lets all *nonmeaningful* segments getting eliminated leaving only “*meaningful*” edge segments. The next section describes how this can be done using the Helmholtz principle.

### 3. Edge Segment Validation by the Helmholtz Principle

According to the computational Gestalt theory<sup>9,10</sup> and due to a perception principle by Helmholtz, a geometric structure (grouping or Gestalt) is perceptually “*meaningful*” if its expectation by chance is very small in a random situation. This is an “*a contrario*” approach, where the objects are detected as outliers of the background model. As shown by Desolneux, Moisan and Morel (DMM),<sup>8</sup> a suitable background model is the one in which all pixels (thus the gradient angles/values) are independent. DMM show that the simplest such background model is the “*Gaussian white noise*.” This means that no meaningful structure is perceptible in a random white noise image, and any large deviation from a white noise image should be perceptible provided this large deviation corresponds to an *a priori* fixed list of geometric structures, i.e. lines, curves, etc.<sup>11,22,23,36</sup>

Using the above principles, DMM<sup>8</sup> proposed an edge detection and validation algorithm. Their idea is to look for all level lines of an image, and select “*meaningful*” ones by comparing the gradient of each piece to the distribution of the gradients over the entire image. This algorithm lends itself to a parameter-free edge detector. But the proposed edge detector is very slow (which makes it unsuitable especially for real-time applications) and it has the problem of over-representation or edge replication; that is, every edge is detected multiple times in slightly different positions.<sup>40</sup> Despite the problems associated with DMM’s parameter-free edge detector, the proposed edge validation method is very practical, and can be used to validate any edge segment for “*meaningfulness*.” In the following, we first describe DMM’s edge segment validation algorithm, and then show how it can be utilized to efficiently validate edge segments detected by EDPF.

Let  $A$  be a discrete image of  $N \times N$  pixels,  $I: A \rightarrow \{0, \dots, 255\}$  be the image’s gray-scale values, and  $g: A \rightarrow [0, +\infty]$  be the norm of its gradient (called the *contrast* hereafter) computed via finite differences. Define  $H$  to be the empirical cumulative distribution of the gradient norm “ $g$ ” on the image as follows<sup>8,10,40</sup>:

$$H(\mu) = \frac{1}{M} \#\{x \in A | g(x) \geq \mu\},$$

*C. Akinlar & C. Topal*

where  $M$  is the total number of pixels where contrast  $\neq 0$ . For an edge segment  $S_i$  with length  $l_i$ , the number of connected pieces  $P$  of  $S_i$  is  $l_i * (l_i - 1)/2$ . We then have the total number of connected pieces of all edge segments  $N_p$  defined as

$$N_p = \sum_i \frac{l_i(l_i - 1)}{2}.$$

Consider a connected piece  $P$  of a segment with length  $l$ , counted in independent points at Nyquist distance, i.e. 2. Let  $\mu$  be the minimum contrast of the points  $x_1, x_2, \dots, x_l$  of  $P$ . Then the number of false alarms (NFA) of this event (edge segment) is defined as  $NFA(P) = N_p * H(\mu)^l$ .<sup>8,10,40</sup>  $P$  is called  $\varepsilon$ -meaningful if  $NFA(P) \leq \varepsilon$ . Intuitively, NFA defines the number of false events (segment detections) under a reasonable noise model. This means that the expectation of the number of segments output by the algorithm when run on a white noise image is  $\leq \varepsilon$ . For all practical purposes, Ref. 8 suggests setting  $\varepsilon$  to 1, which would mean 1 false alarm (detection) for the image.

With these definitions, we validate an edge segment  $S$  detected by ED as follows<sup>8,40</sup>:

- I. For each connected piece  $P$  of  $S$  do:
  - (a) Let  $\mu$  be the minimum contrast on  $P$  and  $l$  its length.
  - (b) Compute  $NFA(P) = N_p * H(\mu)^l$ .
  - (c) If  $NFA(P) \leq \varepsilon$ , then  $P$  is valid.
  - (d) else  $P$  is invalid.
- II. Output the valid pieces  $P$  of  $S$ , and discard others.

Notice that step I(b) of the algorithm computes a positive real number for each piece  $P$  of a segment  $S$ . This quantity is a *score* of how meaningful the piece is: The closer to zero, the better; that is, pieces with smaller NFA values are more meaningful than those with bigger NFA values. It is worth noting the following two lemmas<sup>8</sup>: (1) For two segments having equal length, the one with the bigger minimum contrast is more meaningful. Since  $0 \leq H(\mu) \leq 1$  and  $H(\mu)$  is a decreasing function,  $H(\mu)$  is smaller for bigger contrast values. Therefore, the proof easily follows from the definition of NFA. (2) For two segments having the same minimum contrast, the longer one is more meaningful. Since  $0 \leq H(\mu) \leq 1$ , the proof easily follows from the definition of NFA. We can also add the following corollary to the second Lemma: If a segment  $S$  of length  $l$  with minimum contrast  $\mu$  is invalid, i.e.  $NFA(S) > 1$ , then no piece  $P$  of  $S$  containing the pixel with the minimum contrast can be valid. This easily follows from the second Lemma as follows: Since any piece  $P$  of  $S$  would be shorter than  $S$ , and any piece  $P$  containing the pixel having the minimum contrast would have the same  $H(\mu)$  as  $S$ ,  $NFA(P) \geq NFA(S)$ ; therefore  $P$  is less meaningful. If  $S$  is invalid, then so is  $P$ .

Computing the NFA for each piece  $P$  of a segment  $S$  would not only take a lot of computational time, but it is also unnecessary due to Lemma 2 and its corollary. Therefore, we use the following recursive algorithm to validate an edge segment  $S$  of length  $l$  consisting of pixels  $x_1, x_2, \dots, x_l$ .

**Symbols used in the algorithm:**

$S$ : Segment to be validated

$l$ : Length of the segment in pixels

$H$ : Cumulative gradient distribution function on the image

$\mu$ : The minimum gradient value on  $S$

ValidateSegment( $S, l$ ) {

I. Compute  $NFA(S) = N_p * H(\mu)^l$

I. **if** ( $NFA(S) \leq 1$ ) **then** return true; // valid segment

II. Let  $1 \leq k \leq l$  be the pixel having the minimum contrast

III. Let  $P1 = x_1, x_2, \dots, x_{k-1}$  and  $P2 = x_{k+1}, x_{k+2}, \dots, x_l$

IV. ValidateSegment( $P1, k-1$ );

V. ValidateSegment( $P2, l-k$ );

} // end-ValidateSegment

The above recursive algorithm runs in linear time to efficiently validate an edge segment. So, after ED computes all edge segments, we simply compute  $N_p$ , total number of connected pieces of all edge segments, and  $H$ , the cumulative gradient distribution function. We then call *ValidateSegment* algorithm for each segment. The invalid (meaningless) pieces of segments are then discarded, and the valid (meaningful) pieces retained.

#### 4. Edge Drawing Parameter Free

To make ED a parameter-free (EDPF) edge detector, we run ED with its parameters set at their extremes. This generates *all* edge segments in a given image with numerous false detections. We then feed all returned edge segments into the edge segment validation algorithm described in Sec. 3, and eliminate all false edge segment detections; thus, returning only the meaningful edge segments as defined by the Helmholtz principle.<sup>8-10,40</sup>

ED has two user-set thresholds: (1) Gradient threshold and (2) anchor threshold.

Gradient threshold is used to eliminate nonedge pixels; that is, pixels where an edgel cannot be located (refer to Fig. 1(b)). These are pixels where the gradient operator produces small values and correspond to flat zones in the image. Nonedge areas must be eliminated from contention after the gradient computation in step 2 of the algorithm.



*C. Akinlar & C. Topal*

The correct value for the Gradient threshold is a tricky question. One idea would be to set Gradient threshold to 0 and leave all pixels as potential edgel candidates. This is not correct due to image quantization errors.<sup>22,23,36</sup> Assuming a quantization noise of “ $n$ ,” what we observe is the image  $i' = i + n$ . Since gradient computation is performed over the observed image  $i$ , we get  $\text{grad}(i') = \text{grad}(i) + \text{grad}(n)$ . Thus, if the gradient value of a pixel is smaller than or equal to  $\text{grad}(n)$ , then we can assume that the gradient change at the pixel is due to quantization error and eliminate this pixel from among the potential edgel candidates.

The value of  $\text{grad}(n)$  depends on the gradient operator used to compute the image’s gradient map. Consider the Prewitt operator<sup>46</sup> computing the gradient at a pixel  $P$  as follows:

$$g_x(P) = \begin{bmatrix} -1 & 0 & 1 \\ -1 & 0 & 1 \\ -1 & 0 & 1 \end{bmatrix} * P,$$

$$g_y(P) = \begin{bmatrix} -1 & -1 & -1 \\ 0 & 0 & 0 \\ 1 & 1 & 1 \end{bmatrix} * P,$$

$$\text{grad}(P) = \sqrt{g_x(P)^2 + g_y(P)^2}.$$

Since the maximum quantization error between two pixels occurs when the pixel pair have quantization errors of  $-1$  and  $1$ , respectively,<sup>23</sup> the maximum gradient value due to quantization error in the  $x$  direction  $g_x(n) * P$  would be equal to  $2 + 2 + 2 = 6$ . Similarly,  $g_y(n) * P$  would be equal to  $6$ . Then,  $\text{grad}(n) * P = \sqrt{6^2 + 6^2} = 8.48$ . Therefore, when the Prewitt operator (default for EDPF) is used to compute the gradient map, we set the gradient threshold to  $8.48$  and eliminate all pixels whose gradient values are smaller than this threshold. For other gradient operators, e.g. Sobel,<sup>52</sup> Scharr,<sup>51</sup> Gradient threshold can be computed similarly.

Anchor threshold is used in selection of the anchors. Recall from Sec. 2 that ED performs nonmaximal suppression with a threshold to compute the anchors. If the gradient value of a pixel within the edge areas is bigger than both of its neighbors by “Anchor threshold” in the pixel’s gradient direction, then the pixel is assumed to be anchor. With EDPF, we do not want to miss any anchors. So, we set Anchor threshold to  $0$ , and perform traditional nonmaximal suppression. Thus, all maximas of the gradient map are selected as anchors.

After the computation of the anchors, we sort the anchors with respect to their gradient values, and start the edge linking process with the anchor having the maximum gradient value from among the remaining anchors. We perform anchor sorting by “counting sort” since the maximum gradient value is a small fixed value. The reason to start anchor linking with the anchor having the maximum gradient value is based on the observation that the NFA values for segments consisting of pixels with big gradient values will be closer to zero; that is, such segments will be more meaningful. So, our goal is to extract such segments during early stages of edge



segment extraction. As the major edge segments are extracted from the image, the remaining segments will be short and consist of *weak* pixels, i.e. pixels having small gradient values. We can then expect these weak segments to get eliminated during validation. Thus, we will end up with long meaningful segments at the end.

## 5. Experiments

We analyze EDPF's performance in six steps. In Sec. 5.1, we compare and contrast EDPF's edge segments before and after edge segment validation. In Sec. 5.2, we compare the quality of EDPF's edge maps to that of the famous Canny<sup>6</sup> edge detector, and also compare their running time performance. In Sec. 5.3, we look at the effects of different gradient operators on EDPF's final edge map. In Sec. 5.4, we analyze EDPF's performance on noisy images. In Sec. 5.5, EDPF's performance as a boundary or contour detector is analyzed, and the results are compared with several state of the art boundary/contour detection algorithms both visually and quantitatively using *F-measure*<sup>60</sup> as a yardstick. Finally, in Sec. 5.6, line segment extraction from EDPF's edge segments are discussed, and the extracted line segments are compared with the state of the art line segment detector (LSD) by Grompone von Gioi.<sup>22,23,36</sup>

### 5.1. Edge maps produced by EDPF

As discussed in Sec. 4, EDPF works by running ED with all ED's parameters set at their extremes. This generates many edge segments with numerous false detections, which are eliminated during segment validation leaving only the meaningful segments.

Figure 2 shows the edge maps produced by EDPF for four different images. Prewitt gradient operator is used to obtain the edge maps. Figure 2(b) shows the detected edge segments before the validation is employed. These edge maps contain many edge segments with numerous false detections. Figure 2(c) shows the final edge maps after validation. Clearly, the final results contain seemingly all (as observed by a human) edge segments. The eliminated edge segments are beyond the meaningfulness limit as defined by the Helmholtz principle. To see more results produced by EDPF, the reader may perform additional tests at EDPF's web site.<sup>14</sup>

### 5.2. EDPF versus OpenCV Canny

In this section, our goal is to compare the edge maps produced by EDPF to that of the famous Canny edge detector, which has been shown to produce the best results in many situations<sup>5,17</sup> and is generally accepted to be the de-facto edge detection algorithm for many computer vision and image processing applications. Among various implementations of Canny's edge detector, we selected OpenCV implementation<sup>42</sup> for two reasons: First, a standard implementation frees the reader from any suspicion about potential implementation discrepancies as anyone can download OpenCV freely. Second, and more importantly, OpenCV implementation of Canny is

*C. Akinlar & C. Topal*

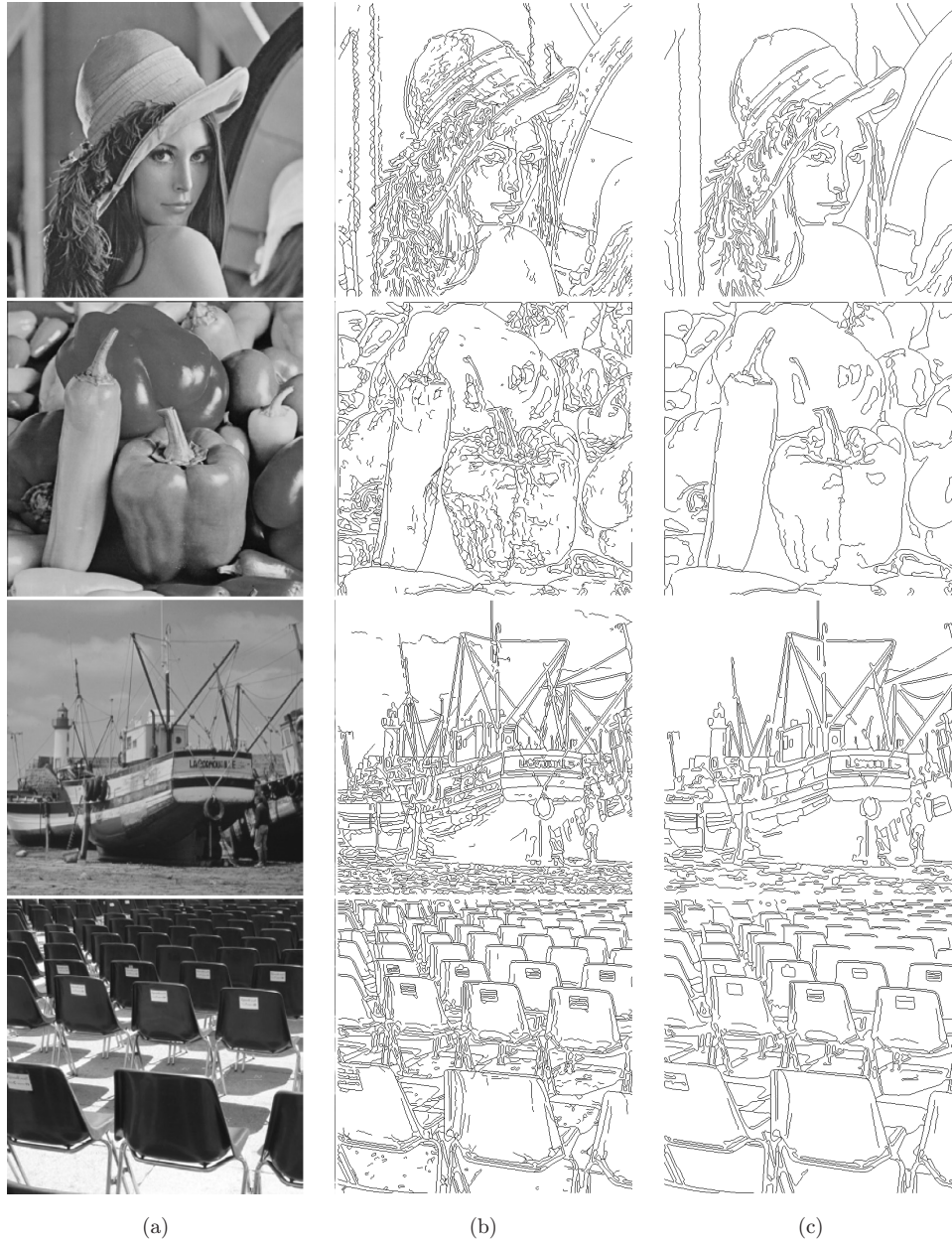


Fig. 2. (a) Original images (512 × 512), (b) EDPF's edge maps before edge segment validation and (c) EDPF's final edge maps after edge segment validation. Prewitt gradient operator is used to obtain the edge maps. Notice how clean and complete the edge maps are.

the only edge detector that can match our algorithm in terms of speed and real-time applicability.

Figure 3 shows the edge maps produced by OpenCV Canny and EDPF for four different images. The first three rows show natural images. It is clear from EDPF's results that EDPF extracts all perceptually visible boundaries in all images and achieves this in blazing real-time speed. Notice that EDPF's edge segments are of very high quality consisting of 1-pixel wide, contiguous chain of pixels. Comparing EDPF's edge maps to that of OpenCV Canny, we see that OpenCV Canny's results not only consist of many noisy notch-like structures, but they also contain some missing parts circled in the edge maps. Specifically, the vertical line in the Lena image, and the curb in the Street image are not detected by OpenCV Canny. These are low contrast areas and are filtered out during gradient thresholding in the case of OpenCV Canny. We can reduce Canny's thresholds to detect these areas, but that would cause more invalid detections in other parts of the images, and the quality of Canny's edge maps would get worse.

The last row in Fig. 3 shows a Gaussian white noise image and its edge maps. According to the Gestalt perception theory, no meaningful structure is visible in this image. But notice that OpenCV Canny's edge map contains a lot of meaningless edgels. However, EDPF's edge map contains no detections at all consistent with the theory. Notice that EDPF eliminates many noise-like detections around anisotropic structures such as tree leaves, grass, carpet, fluffy parts of Lena's hat, etc.

As for the running time performance of EDPF and OpenCV Canny, we see that OpenCV Canny is faster than EDPF; however, EDPF still runs real-time for all images in Fig. 3. Specifically, EDPF takes only 16 ms for the Lena image, 11 ms for the Street image, 17 ms for the Boy&Girl image and 32 ms for the white noise image. All and all, EDPF runs only two times slower than OpenCV Canny.

Notice that EDPF's results are returned as a set of edge segments, each consisting of a linear, contiguous chain of pixels. The number of edge segments returned by EDPF for each image in Fig. 3 is given under EDPF's edge maps. These linear chains are readily available for further higher-level processing. In Sec. 5.6, we will use these edge segments to extract line segments, which are important for applications such as stereo matching, image compression, registration, etc.

### **5.3. The effects of the gradient operator on EDPF's edge segments**

As we stated in Sec. 2, EDPF is independent of the gradient operator and can run with a gradient map computed by any of the well-known gradient operators, i.e. Prewitt, Sobel, Scharr. In this section, our goal is to show the performance of EDPF under different gradient operators.

Figure 4 shows EDPF's edge maps with Prewitt, Sobel and Scharr gradient operators for four different images. As seen from the results, EDPF produces all perceptually visible structures in all images, and the results are almost identical for different gradient operators. Since the computation of the Prewitt operator is the fastest, we use Prewitt as the default gradient operator for EDPF.

*C. Akinlar & C. Topal*

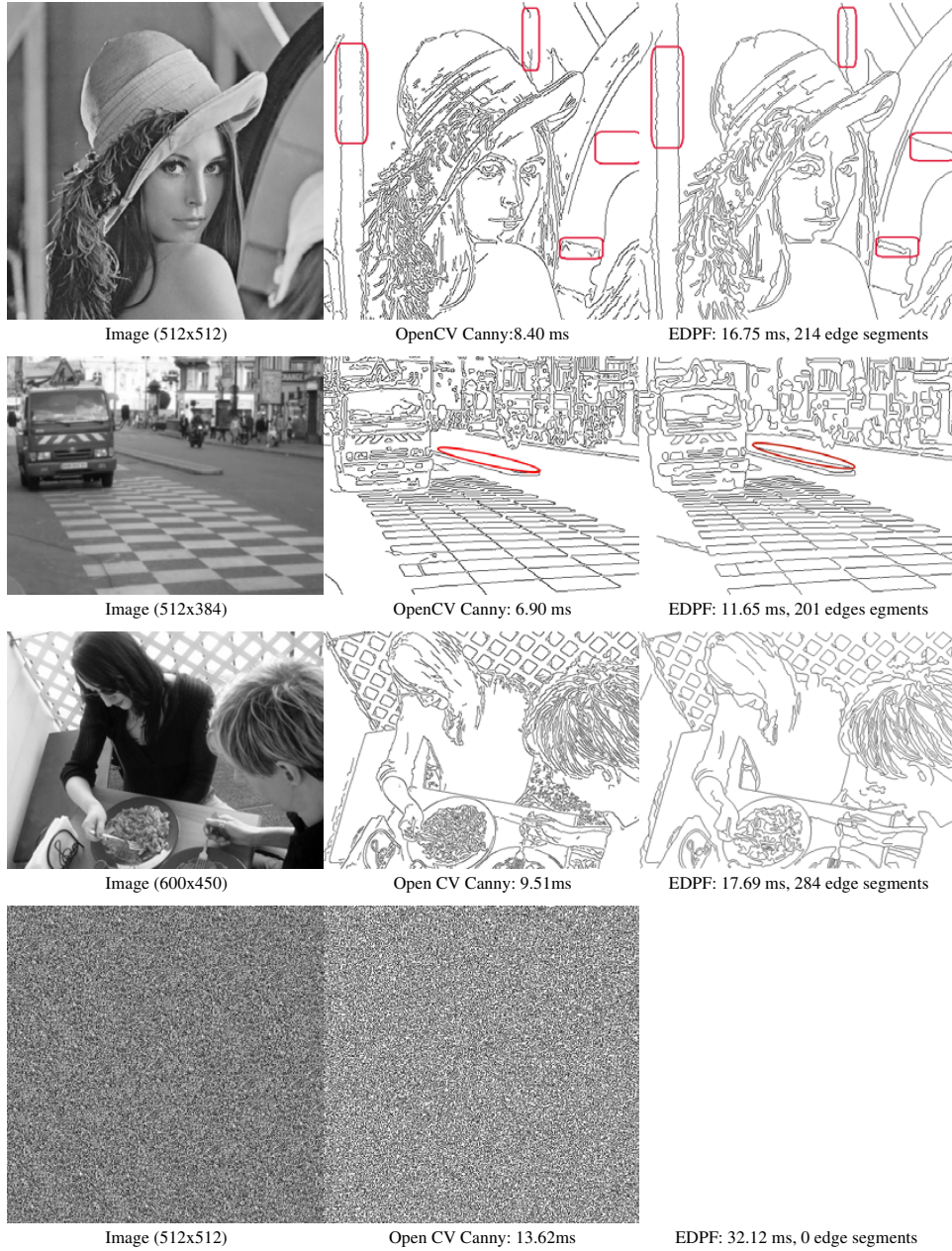


Fig. 3. Original images; OpenCV Canny's edge maps with low threshold = 30, high threshold = 60; and EDPF's edge maps. The processing times have been obtained in a PC with 2.2 GHz Intel E4500 CPU and 2GB RAM. In all cases, the images were first smoothed by a  $5 \times 5$  Gaussian kernel with  $\sigma = 1$  before being fed into the edge detection algorithms.



*A Real-time Parameter-free Edge Segment Detector with a False Detection Control*

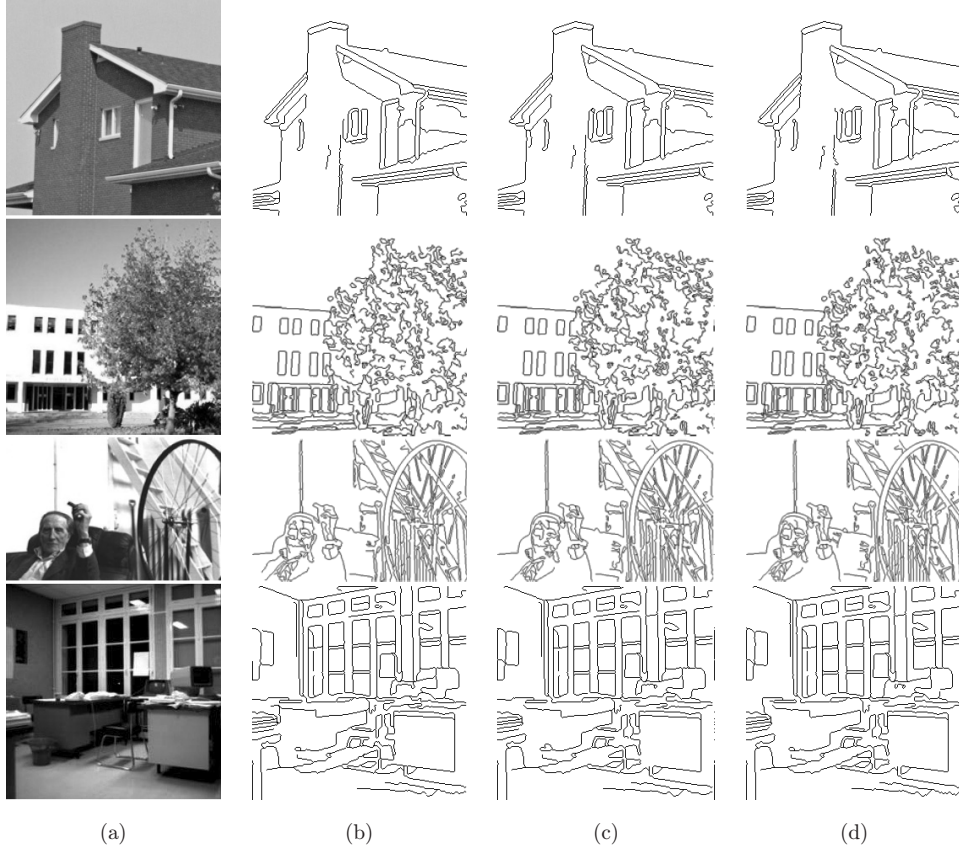


Fig. 4. (a) Original images. (b)–(d) EDPF's edge maps with Prewitt, Sobel and Scharr gradient operators, respectively.

#### 5.4. EDPF's performance on noisy images

Noisy images are very tough cases for typical edge detectors. Since the noise causes many discontinuities in an image, a typical edge detector produces many invalid edgel detections. To evaluate the performance of EDPF on noisy images, we have taken an image, added increasing amounts of Gaussian white noise to the image and fed the resulting noisy images to EDPF and OpenCV Canny.

Figure 5 shows the edge maps produced by OpenCV Canny and EDPF for an image containing a house as the amount of noise in the image is increased. Specifically, the image in the first row contains no noise; the images in the second, third and fourth rows contain 5%, 10% and 15% Gaussian white noise, respectively. In no noise and low noise cases (rows one and two), both OpenCV Canny and EDPF produce high-quality edge maps. But in high noise cases (rows three and four), OpenCV Canny produces almost completely garbage edge maps, but EDPF is able to eliminate noisy parts of the image and return the general structure of the house, albeit by

*C. Akinlar & C. Topal*

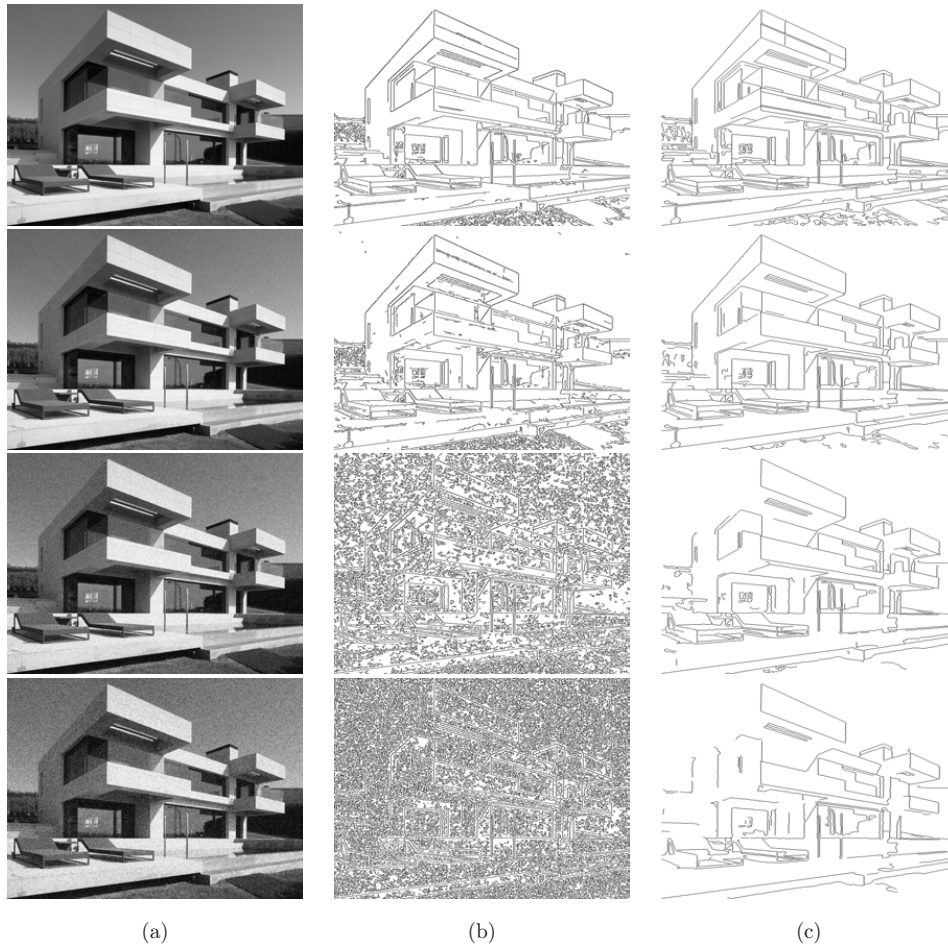


Fig. 5. (a) Original image. First row — no noise; second, third and fourth rows — 5%, 10% and 15% Gaussian white noise added respectively, (b) OpenCV Canny's edge maps with low threshold = 30, high threshold = 60, (c) EDPF's edge maps.

missing some parts such as the long roof line on the left. The reason for EDPF missing some valid boundaries in high noise cases has to do with ED's anchor linking step.<sup>12,57</sup> Recall from Sec. 2 that ED works by computing a set of stable anchors and linking these anchors by a smart routing algorithm. The linking step makes use of pixel's gradient magnitudes and directions. In low noise cases, Gaussian smoothing is able to take care of the noise so that the gradient magnitudes and directions are not adversely affected. However, in high noise cases, the noise on the boundary of an object (such as the roof line on the left) diverts the anchor linking direction towards noisy parts of the image. This causes short, noisy edge segment formations, which get eliminated during segment validation. Despite such potential boundary misses in high noise images, EDPF is still able to detect many of the meaningful boundaries of

the objects in the given images as seen from EDPF's edge map results. It is also important to note that EDPF may miss some valid boundaries, but it never returns meaningless edge segment formations (as defined by the Helmholtz principle) no matter how much noise is present in the image.

### 5.5. EDPF as a boundary/contour detector

EDPF can be used as a boundary/contour detector for image segmentation.<sup>2,39,43–45,60</sup> In this section, we quantitatively evaluate the quality of the edge maps produced by EDPF, and compare them to a few state of the art boundary/contour detection algorithms. For the purposes of evaluation, we will use the RUG database,<sup>50</sup> which contains 40 natural images and their hand-drawn ground-truth segmentation data.

Figure 6 shows six images from the RUG database<sup>50</sup> and each row in Fig. 6 corresponds to boundaries/contours detected by a different algorithm. The second row shows the hand-drawn ground-truth segmentation data. The third row shows

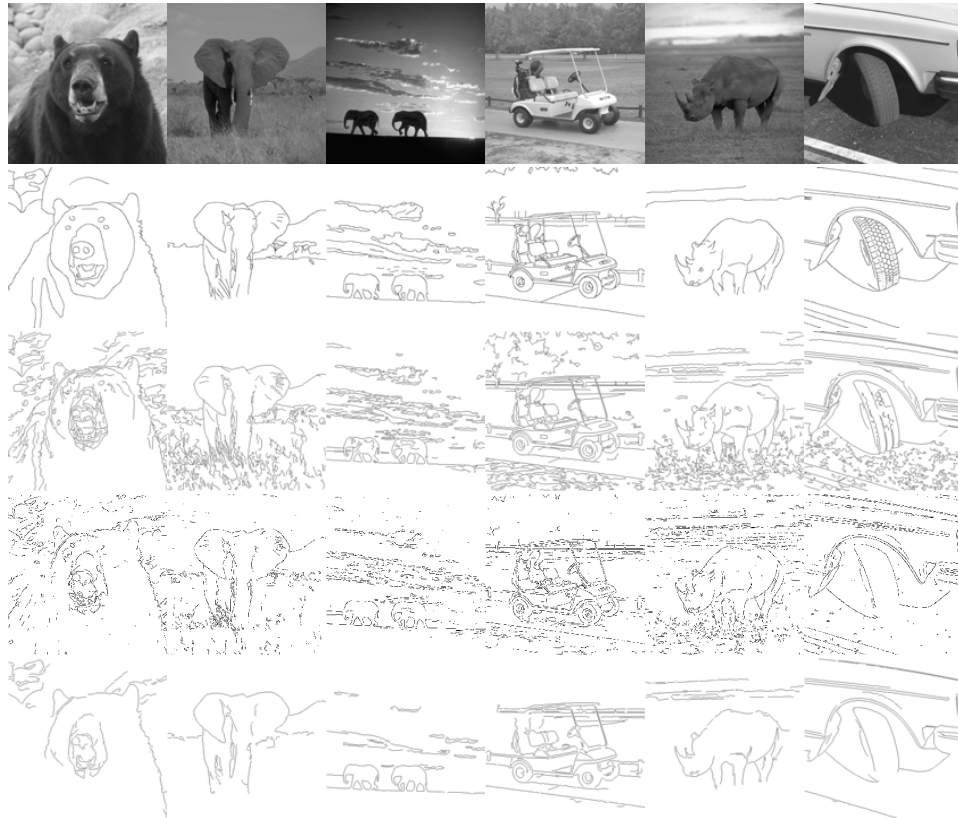


Fig. 6. (First row) Six test images, (second row) Ground Truth contours, (third row) Contours detected with EDPF, (fourth row) Contours detected with edge detection and image segmentation system (EDISON),<sup>39</sup> (fifth row) Contours detected with adaptive pseudo dilation (APD).<sup>43</sup>



*C. Akinlar & C. Topal*

the contours detected by EDPF, the fourth row shows the contours detected edge detection and image segmentation system (EDISON),<sup>39</sup> and the fifth row shows the contours detected by adaptive pseudo dilation (APD)<sup>43</sup> algorithm. The results for the ground-truth data, EDISON and APD were taken from APD's Web site.<sup>50</sup> We stress that EDPF is a general purpose edge/edge segment detection algorithm; whereas both EDISON and APD are specifically tailored towards boundary/contour detection and image segmentation. Comparing EDPF's contours to ground-truth data we observe that EDPF seems to detect most of the contours present in the ground-truth data, but EDPF also detects some superfluous contours especially around anisotropic structures in the background such as grass, trees and clouds. EDISON, although specifically designed for image contour detection and image segmentation problems, does not seem to perform any better than EDPF. APD seems to produce cleaner contours, but at the expense of missing some details in the images.

To quantitatively compare the performance of EDPF, EDISON and APD on the RUG database, we use the famous *F-measure* metric.<sup>2,43,60</sup> Let DC be the set of contour pixels detected by an algorithm, and GT be the set of pixels in the ground-truth data. Define precision ( $P$ ) and recall ( $R$ ) as follows:

$$R = \frac{\text{card}\{\text{DC} \cap \text{GT}\}}{\text{card}\{\text{GT}\}}; \quad P = \frac{\text{card}\{\text{DC} \cap \text{GT}\}}{\text{card}\{\text{DC}\}}.$$

*F-measure*, defined as the harmonic mean of  $P$  and  $R$ ,  $F = 2PR/(P + R)$ , measures the performance of a boundary detection algorithm: The bigger the value of *F-measure*, the better the algorithm is in detecting the boundaries compared to hand-drawn ground-truth segmentation data.

Table 1 shows the Recall, Precision and *F-measure* averages for 40 images in the RUG database for EDPF,<sup>14</sup> EDISON<sup>39</sup> and APD [59].<sup>43</sup> According to *F-measure* metric, APD has the best performance while EDPF and EDISON have the same performance. The findings are consistent with the visual tests shown in Fig. 6: EDPF and EDISON detect most of the contours present in the ground-truth data (high recall), but also detect many superfluous contours (low precision). APD on the other hand produces much cleaner boundaries (high precision), but misses on many of the contours (low recall). We would like to stress that although EDPF is a general purpose edge/edge segment detection algorithm and is parameter-free, its performance is not worse than EDISON, which is a boundary/contour detection algorithm specifically tailored towards image segmentation problems. Given that EDPF has

Table 1. Recall, Precision and *F-measure* averages for 40 images in the RUG database for EDPF,<sup>14</sup> EDISON<sup>39</sup> and APD.<sup>43</sup>

Algorithm	Recall average	Precision average	<i>F-Measure</i> average
EDPF	0.75	0.30	0.41
EDISON <sup>39</sup>	0.74	0.30	0.41
APD <sup>43</sup>	0.46	0.70	0.54

high recall rate, EDPF's edge segments can further be processed after initial detection, and many superfluous detections found in the background can be eliminated. Such post-processing would increase the precision rate of EDPF and result in a much higher *F-measure* ratio. Tailoring EDPF towards such specific image segmentation problems is out of the scope of this paper, and is left as future work.

### 5.6. Line segment detection from EDPF's edge segments

As we stated in Sec. 5.2, EDPF returns its output both as a binary edge map similar to traditional edge detection algorithms, and also as a set of edge segments, each comprised of a linear, contiguous chain of pixels. In this section, we show how to make use of EDPF's edge segments to extract all line segments in a given image in an efficient manner. We also compare our results to the fastest line segment extraction algorithm in the literature; the LSD by Grompone von Gioi *et al.*<sup>22,23,36</sup>

Figure 7 shows five natural images (column one) and EDPF's edge segments for each image (column two). To extract line segments from EDPF's edge segments, we simply walk over the linear chain of pixels making up an edge segment and fit a line segment to these pixels using the standard least squares line fitting algorithm.<sup>35</sup> A line segment is extended for as long as the line fit error stays within a certain threshold, e.g. 1 pixel error. When the error exceeds this threshold, we output a line segment and recursively use the rest of the edge segment pixels to extract more line segments. This process continues until all edge segments are processed (see Refs. 1 and 13 for more details on line segment extraction from a given edge segment).

The third column in Fig. 7 shows the line segments extracted from EDPF's edge segments. The numbers under each image shows the total number of extracted line segments and the total running time for the entire process. This running time includes the time for edge segment detection by EDPF, line segment extraction from EDPF's edge segments, and line segment validation due to the Helmholtz principle.<sup>11,22,23,36</sup> We see from the results that not only EDPF's line segments are very well localized, but also the total running time is very low. Specifically, all line segment detections can be performed in real time.

The last column in Fig. 7 shows the line segments detected by the famous LSD by Grompone von Gioi *et al.*<sup>22,23,36</sup> LSD works by growing line support regions by combining pixels having similar gradient orientations. Region growing continues until the error exceeds a certain threshold, at which point the line support region is validated using the Helmholtz principle and a line segment is output if validated. LSD is known to be the fastest line segment detection algorithm in the literature, and produces no false detections.

Comparing EDPF's line segments to those of LSD, we see that not only EDPF's line segments are better than LSD's but EDPF's line segment extraction algorithm runs up to seven times faster than LSD. Pay particular attention to the last row in Fig. 7, which is the noisy house image. For this image, EDPF detects many long line segments; whereas LSD is not able to detect many of the visible line segments in the

*C. Akinlar & C. Topal*



Fig. 7. Original images (column one), EDPF's edge segments (column two), line segments extracted from EDPF's edge segments (column three) and LSD's line segments (column four). The processing times have been obtained in a PC with 2.2 GHz Intel E4500 CPU and 2GB RAM.

image. Note that neither EDPF nor LSD has any false detections because both validate their line segments with a validation algorithm due to the Helmholtz principle (see Refs. 22, 23 and 36 for details on line segment validation due to the Helmholtz principle). We conclude that line segment extraction from EDPF's edge segments is a huge improvement from the current state of the art line segment extraction algorithms and would be very suitable for the next generation computer

vision algorithms. We stress that this is all made possible by EDPF's clean, contiguous, well-localized edge segments.

## 6. Conclusion

We present a real-time, parameter-free edge/edge segment detection algorithm based on our novel edge/edge segment detector, the edge drawing (ED) algorithm; hence the name edge drawing parameter free (EDPF). The edge segments produced by EDPF are of high-quality consisting of clean, contiguous, well-localized, one-pixel wide edges. The edge segments are also “*meaningful*” as defined by the Helmholtz principle; that is, they are guaranteed to reside on the boundaries of perceptually visible Gestalt structures. Experiments on many different images and many more that the reader may perform online<sup>14</sup> show that EDPF produces good results with many different sets of images. We believe that EDPF is a major step forward in the quest for a parameter-free edge/edge segment detector, and would be very suitable for the next generation real-time computer vision and image processing applications.

## References

1. C. Akinlar and C. Topal, EDLines: Realtime line segment detection by edge drawing (ED), *IEEE Int. Conf. on Image Processing (ICIP)*, 2011.
2. P. Arbelaez, M. Maire, C. Fowlkes and J. Malik, Contour detection and hierarchical image segmentation, *IEEE Trans. Pattern Anal. Mach. Intell.* **33**(5) (2011).
3. F. Bergholm, Edge focusing, *IEEE Trans. Pattern Anal. Mach. Intell.* **9**(6) (1987).
4. K. Bowyer, C. Kranenburg and S. Dougherty, Edge detector evaluation using empirical ROC curves, *Comput. Vis. Image Understand.* **84**(1) (2001).
5. D. J. Bryant and D. W. Bouldin, Evaluation of edge operators using relative and absolute grading, *Int. Conf. Pattern Recognition and Image Processing*, Chicago, 1979, pp. 138–145.
6. J. Canny, A computational approach to edge detection, *IEEE Trans. Pattern Anal. Mach. Intell.* **8**(6) (1986) 679–698.
7. X. Dai and S. Khorram, A feature-based image registration algorithm using improved chain-code representation combined with invariant moments, *IEEE Trans. Geosci. Remote Sens.* **37**(5) (1999).
8. A. Desolneux, L. Moisan, and J. M. Morel, Edge detection by Helmholtz principle, *J. Math. Imag. Vis.* **14**(3) (2001) 271–284.
9. A. Desolneux, L. Moisan and J. M. Morel, *From Gestalt Theory to Image Analysis: A Probabilistic Approach* (Springer, 2008).
10. A. Desolneux, L. Moisan and J. M. Morel, Gestalt theory and computer vision, in *Seeing, Thinking and Knowing* (Kluwer Academic Publishers, 2004), pp. 71–101.
11. A. Desolneux, L. Moisan, and J. M. Morel, Meaningful Alignments, *Int. J. Comput. Vis.* **40**(1) (2000) 7–23.
12. Edge Drawing Web Site, <http://ceng.anadolu.edu.tr/CV/EdgeDrawing>.
13. EDLines Web Site, <http://ceng.anadolu.edu.tr/cv/EDLines>.
14. EDPF Web Site, <http://ceng.anadolu.edu.tr/CV/EDPF>.
15. A. Etemadi, Robust segmentation of edge data, *Int. Conf. on Image Processing and its Applications*, 1992, pp. 311–314.

C. Akinlar & C. Topal

- 1 16. V. Ferrari, L. Fevrier, F. Jurie, and C. Schmid, Groups of adjacent contour segments for  
object detection, *IEEE Trans. Pattern Anal. Mach. Intell.* **30**(1) (2008).
- 3 17. J. R. Fram and E. S. Deutsch, On the quantitative evaluation of edge detection schemes  
and their comparison with human performance, *IEEE Trans. Comput.* **24**(6) (1975)  
616–628.
- 5 18. H. Freeman, Computer processing of line drawing images, *Comput. Surv.* **6** (1974) 57–98.
- 7 19. Y. Gao and M. K. H. Leung, Face recognition using line edge map, *IEEE Trans. Pattern  
Anal. Mach. Intell.* **24**(6) (2002) 764.
- 9 20. M. Gokmen and C. C. Li, Edge detection and surface recon-struction using refined  
regularization, *IEEE Trans. Pattern Anal. Mach. Intell.* **15**(5) (1993) 492–498.
- 11 21. P. H. Gregson, Using angular dispersion of gradient direction for detecting edge ribbons,  
*IEEE Trans. Pattern Anal. Mach. Intell.* **15** (1993) 682–696.
- 13 22. R. Grompone von Gioi, J. Jakubowicz, J. M. Morel and G. Randall, LSD: A line segment,  
Technical report, Centre de Mathematiques et de leurs Applications (CMLA), Ecole  
Normale Superieure de Cachan (ENS-CACHAN) (2008).
- 15 23. R. Grompone von Gioi, J. Jakubowicz, J. M. Morel, and G. Randall, LSD: A fast line  
segment detector with a false detection control, *IEEE Trans. Pattern Anal. Mach. Intell.*  
**32**(4) (2010) 722–732.
- 17 24. L. Gupta and M. D. Srinath, Contour sequence moments for the classification of closed  
planar shapes, *Pattern Recogn.* **20**(3) (1987) 267–272.
- 19 25. M. D. Heath, S. Sarkar, T. Sanocki and K. W. Bowyer, A robust visual method for  
assessing the relative performance of edge-detection algorithms, *IEEE Trans. Pattern  
Anal. Mach. Intell.* **19** (1997) 1338–1359.
- 21 26. W. E. Higgins and C. Hsu, Edge detection using 2D local structure information, *Pattern  
Recogn.* **27**(2) (1994) 277–294.
- 23 27. P. Hough, Method and means for recognizing complex patterns, US Patent 306954  
(1962).
- 25 28. J. Iivarinen, M. Peura, J. Säreälä and A. Visa, Comparison of combined shape descriptors  
for irregular objects, in *Proc. of the Eight British Machine Vision Conf.* (UK, 1997).
- 27 29. J. Illinworth and K. Kittler, A survey of the hough transform, *Comput. Vis., Graph.,  
Image Process.* (1988) 87–107.
- 29 30. L. A. Iverson and S. W. Zucker, Logical/linear operators for image curves, *IEEE Trans.  
Pattern Anal. Mach. Intell.* **17**(10) (1995) 982–996.
- 31 31. W. J. Kang, X. Ding, and J. Cui, Fast straight-line extraction algorithm based on  
improved Hough transform, *Opto-Electron. Eng.* (2007) pp. 105–108.
- 33 32. T. Kanungo, M. Y. Jaisimha, J. Palmer and R. M. Haralick, A methodology for quan-  
titative performance evaluation of detection algorithms, *IEEE Trans. Image Process.*  
**4**(12) (1995) 1667–1674.
- 35 33. S. Kiranyaz, M. Ferreira and M. Gabbouj, A generic shape/texture descriptor over  
multiscale edge field: 2-D walking ant Histogram, *IEEE Trans. Image Process.* **17**(3)  
(2008) 377.
- 37 34. N. Kiryati, Y. Eldar and A. M. Bruchstein, Probabilistic hough transform, *Pattern  
Recogn.* **24** (1991) 303–316.
- 39 35. Least Squares Line Fitting, [http://en.wikipedia.org/wiki/Least\\_Squares](http://en.wikipedia.org/wiki/Least_Squares).
- 41 36. LSD: A Line Segment Detector Web Site, [http://www.ipol.im/pub/algo/gjmr\\_line\\_segment\\_detector](http://www.ipol.im/pub/algo/gjmr_line_segment_detector).
37. D. C. Marr and E. Hildreth, Theory of edge detection, in *Proc. Royal Soc. London* (1980).
38. S. Marshall, Review of shape coding techniques, *Image Vis. Comput.* **7**(4) (1989)  
281–294.

- 1 39. P. Meer and B. Georgescu, Edge detection with embedded confidence, *IEEE Trans. Pattern Anal. Mach. Intell.* **23**(12) (2001) 1351–1365.
- 3 40. E. Meinhardt-Llopis, Edge detection by selection of pieces of level lines, in *Proc. Int. Conf. Image Processing (ICIP)* (2008), pp. 613–616.
- 5 41. V. S. Nalwa and T. O. Binford, On detecting edges, *IEEE Trans. Pattern Anal. Mach. Intell.* **8**(6) (1986) 699–714.
- 7 42. OpenCV 2.1, <http://opencv.willowgarage.com>.
- 9 43. G. Papari and N. Petkov, Adaptive pseudo dilation for gestalt edge grouping and contour detection, *IEEE Trans. Image Process.* **17**(10) (2008) 1950–1962.
- 11 44. G. Papari and N. Petkov, Edge and line oriented contour detection: State of the art, *Image Vis. Comput.* **29** (2011) 79–103.
- 13 45. G. Papari, P. Campisi, N. Petkov and A. Neri, A biologically motivated multiresolution approach to contour detection, *EURASIP J. Adv. Signal Process.* (2007).
- 15 46. J. M. S. Prewitt, Object enhancement and extraction, in *Picture Processing and Psychopictorics*, eds. B. Lipkin and A. Rosenfeld (Academic Press, 1970).
- 17 47. V. Ramesh and R. M. Haralick, Performance characterization of edge detectors, in *Proc. SPIE, Applications of Artificial Intelligence X: Machine Vision and Robotics*, Vol. 1708 (1992), pp. 252–266.
- 19 48. K. R. Rao and J. Ben-Arie, Optimal edge detection using expansion matching and restoration, *IEEE Trans. Pattern Anal. Mach. Intell.* **16**(12) (1994) 1169–1182.
- 21 49. C. A. Rothwell, J. L. Mundy, W. Hoffman and V. D. Nguyen, Driving vision by topology, *Int. Symp. Computer Vision*, Coral Gables, Nov. 1995, pp. 395–400.
- 23 50. RUG database, <http://www.cs.rug.nl/~imaging/APD/rug/rug.html>.
- 25 51. H. Scharr, Optimal operators in digital image processing, Ph.D. thesis, Heidelberg Univ. (2000).
- 27 52. I. Sobel and G. Feldman, A 3x3 isotropic gradient operator for image processing, in *Pattern Classification and Scene Analysis* (John Wiley and Sons, 1973), pp. 271–272.
- 29 53. V. Srinivasan, Edge detection using neural networks, *Pattern Recogn.* **27**(12) (1994) 1653–1662.
- 31 54. J. S. Stahl and S. Wang, Edge grouping combining boundary and region information, *IEEE Trans. Image Process.* **16**(10) (2007) 2590.
- 33 55. R. N. Strickland and D. K. Cheng, Adaptable edge quality metric, *Optical Eng.* **32**(5) (1993) 944–951.
- 35 56. P. J. Tadrous, A simple and sensitive method for directed edge detection, *Pattern Recogn.* **28**(10) (1995) 1575–1586.
- 37 57. C. Topal, C. Akınlı and Y. Genç, Edge drawing: A heuristic approach to robust real-time edge detection, in *Proc. of Pattern Recognition (ICPR)* (2010), pp. 2424–2427.
- 39 58. F. van der Heijden, Edge and line feature extraction based on covariance models, *IEEE Trans. Pattern Anal. Mach. Intell.* **17**(1) (1995) 16.
- 41 59. F. vander Heijden, Edge and line feature extraction based on covariance models, *IEEE Trans. Pattern Anal. Mach. Intell.* **17**(1) (1995) 16–33.
60. S. Wang, F. Ge and T. Liu, Evaluating edge detection through boundary detection, *EURASIP J. Appl. Signal Process.* **1** (2006) 1–15.
61. M. Xia and B. Liu, Image registration by Super-curves, *IEEE Trans. Image Process.* **13** (5) (2004) 720.
62. L. Xu, E. Oja and P. Kultanen, A new curve detection method: Randomized Hough Transform (RHT), *Pattern Recogn. Lett.* **11**(5) (1990) 331–338.
63. D. Ziou and S. Tabbone, A multiscale edge detector, *Pattern Recogn.* **26**(9) (1993) 1305–1314.



*C. Akinlar & C. Topal*



**Cuneyt Akinlar** received his B.Sc. degree in Computer Engineering from Bilkent University in 1994; M.Sc. and Ph.D. degrees in Computer Science from the University of Maryland, College Park in 1997 and 2001, respectively. He is currently an Assistant Professor in Anadolu University, Computer Engineering Department (AU-CENG). Before joining AU-CENG, he worked at Panasonic Technologies, Princeton, NJ, and Siemens Corporate Research, Princeton, NJ as student intern and research scientist between 1999 and 2003.

His current research interests include real-time image processing and computer vision algorithms, high-performance computing, storage systems and computer networks.



**Cihan Topal** received his B.Sc. degree in Electrical Engineering and M.S. degree in Computer Engineering, both from Anadolu University, in 2005 and 2008, respectively. He worked as a student intern at Siemens Corporate Research, Princeton, New Jersey.

He is currently working at Anadolu University Computer Engineering Department, Turkey, towards his Ph.D. degree. His research interests are in the area of image processing and computer vision applications, and pattern recognition.