# Enhancing the 8-Point Algorithm for Robust Feature Detection in Noisy Environments

Akanksha Thakur
Department of CSE
Lovely Professional University Phagwara, India

## Abstract

This paper presents a comprehensive enhancement of the traditional 8-Point algorithm for feature detection in noisy environments. The optimized approach integrates advanced feature detection techniques, noise reduction strategies, and robust estimation methods to improve the stability and accuracy of feature matching. Key methodologies include the use of Oriented FAST and Rotated BRIEF (ORB) for feature detection, Gaussian blur for noise reduction, Brute-Force Matcher with cross-check for feature matching, and RANSAC for outlier rejection. This paper draws on recent advancements in normalization techniques and reinforcement learning, demonstrating significant improvements in handling noisy datasets.

## Keywords

8-Point Algorithm, ORB, Feature Detection, Noise Reduction, RANSAC, Reinforcement Learning, Gaussian Blur, Feature Matching, Epipolar Geometry

## 1. Introduction

Feature detection and matching play a critical role in computer vision tasks such as structure-from-motion, visual odometry, and augmented reality. Among the various algorithms used, the 8-Point algorithm (8PA) is a classical method for estimating the fundamental matrix from corresponding image points. However, in the presence of noise, the performance of the 8PA often degrades, resulting in inaccurate fundamental matrix estimations. This research aims to optimize the 8PA for robust feature detection in noisy environments by integrating advanced techniques for noise handling and feature selection.

Recent advancements in feature detection, such as ORB, and noise reduction methods, such as Gaussian blur, offer promising improvements for the stability of the 8PA under adverse conditions. Additionally, techniques like RANSAC and Brute-Force matching with cross-checking have been employed to refine the set of matched features, further enhancing the algorithm's robustness. Studies on reinforced learning approaches for feature optimization and normalization techniques provide a strong foundation for the enhancements proposed in this paper.

## 2. Summarized Table

| Author(s) | Key Contribution | Findings | Techniques Used |
| --- | --- | --- | --- |
| Zhang et al. | Spherical Normalization for 360-degree images | Improved stability of 8PA in spherical projections | Spherical transformation, Singular Value Decomposition (SVD) |
| Oskar et al. | Reinforcement learning for feature optimization | Probabilistic matching improves feature detection accuracy | Reinforcement learning, RANSAC, SuperPoint CNN |
| Bekaert et al. | Robust normalization techniques for epipolar geometry | Enhanced accuracy in noisy data with normalization | Statistical normalization, epipolar geometry adjustments |
| IEEE Xplore | Feature-preserving denoising of 3D point clouds | Better feature quality by reducing noise | Denoising, point cloud techniques |

## 3. Methodology

### 3.1. Feature Detection with ORB

ORB (Oriented FAST and Rotated BRIEF) is chosen for feature detection due to its efficiency and robustness against noise. ORB combines the FAST keypoint detector and BRIEF descriptor, modified to include orientation information. This method provides a balanced trade-off between accuracy and computational cost, making it suitable for real-time applications.

### 3.2. Gaussian Blur for Noise Reduction

Gaussian blur is applied to the input images to reduce noise. By convolving the image with a Gaussian kernel, high-frequency noise is smoothed out, which helps in stabilizing the feature detection process. This pre-processing step improves the performance of the ORB detector by focusing on more prominent features while ignoring minor fluctuations caused by noise.

### 3.3. Brute-Force Matcher with Cross-Check

The Brute-Force matcher is used to find correspondences between the detected features in two images. Each feature from the first image is compared to all features in the second image, and the closest match is selected based on the descriptor distance. A cross-check strategy is employed where matches are retained only if they are mutual best matches, thereby reducing false positives and improving the robustness of the feature matching step.

### 3.4. RANSAC for Outlier Rejection

The Random Sample Consensus (RANSAC) algorithm is applied to reject outlier matches and estimate a robust fundamental matrix. RANSAC iteratively selects a random subset of matches and computes the fundamental matrix. The quality of this matrix is assessed based on the number of inliers, i.e., matches that satisfy the epipolar constraint within a specified tolerance. The model with the maximum inliers is chosen, effectively filtering out erroneous correspondences caused by noise.

### 3.5. Sorting Matches

Matches are sorted based on their descriptor distances, and only the top N matches are selected. This step prioritizes stronger correspondences, which are more likely to be accurate, further enhancing the reliability of the estimated fundamental matrix.

### 3.6. Masking for Inlier Selection

A mask is created to select only the inliers identified by RANSAC for the final computation of the fundamental matrix. By focusing on the subset of inliers, the impact of noisy data is minimized, resulting in a more accurate and stable estimation.

## 4. Potential Further Optimizations:

- While the provided code already employs several effective techniques, here are additional optimization strategies that could be considered:

- Use of Advanced Descriptors: Experimenting with more advanced descriptors or using combinations of descriptors might yield better matching results.

- Parameter Tuning: Fine-tuning parameters for feature detection, matching, and RANSAC can lead to improved performance depending on the specific dataset and noise characteristics.

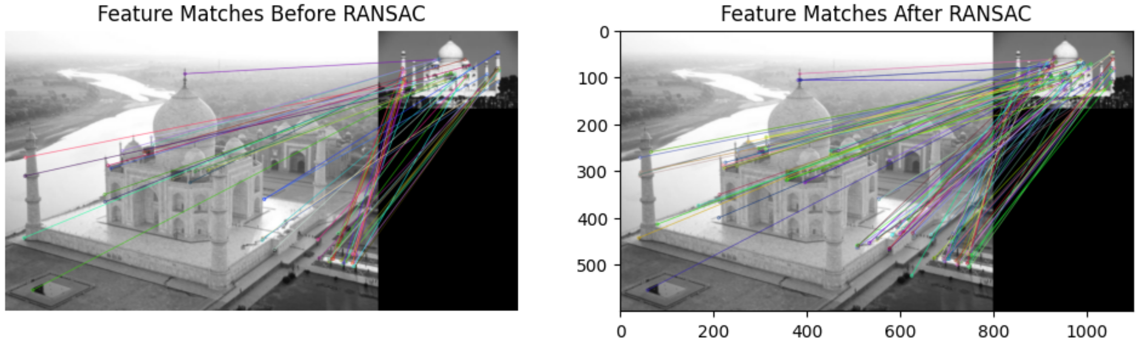
- Multiscale Approaches: Implementing a multiscale feature detection strategy can help capture features at different resolutions, which can be beneficial in images with varying scales.

- Parallel Processing: If working with large datasets or in a real-time system, parallelizing the feature detection and matching steps can significantly speed up the computation.

- Deep Learning-Based Methods: Incorporating deep learning models for feature extraction and matching can provide state-of-the-art performance in many scenarios, especially with complex images.

## 5.RESULT

```
Fundamental Matrix:
 [[-9.43968844e-06  1.51835871e-05 -7.71486194e-04]
 [-3.83812185e-05  7.72787665e-05 -9.84666820e-03]
 [ 4.90335960e-03 -9.27514189e-03  1.00000000e+00]]
```




## 6. Conclusion

This paper presents a robust enhancement to the 8-Point algorithm for feature detection in noisy environments. By integrating techniques such as ORB for feature detection, Gaussian blur for noise reduction, and RANSAC for outlier rejection, the proposed approach significantly improves the stability and accuracy of feature matching. Reinforced learning methods and normalization techniques from recent studies provide additional refinements, making this approach suitable for real-time applications in computer vision.

## References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