

COP507 - Computer Vision & Embedded Systems

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1 Introduction

Make and Model Recognition (VMMR) has been a subject area of interest within computer vision both in industry and academia. The importance of the ability to recognise a variety of vehicles spans across different disciplines and applications such as driver assistance, traffic monitoring, law enforcement and surveillance. As stated by Dehghan et al (2017), this categorisation task has been a problem for classical computing however, a result of great advances in artificial intelligence, this task has been made possible with accuracy rates above 90 percent. The task given was to design and implement a VMMR system with the capability to recognise the make and model of a vehicle based on only the front view (that is, headlights, grill and bumper). Based on the image of a vehicle fed as input, the output of the system should be the make and model of the vehicle. This report explains a practical use of the VMMR system that was implemented, furthermore, it explains the design of the system and any performance restrictions or performance enhancements that will be expected should the system implemented in hardware.

There some basic processes that are essential for any computer vision application. These include pre-processing the acquired images, feature detection and feature extraction. Pre-processing involves making the image data conducive for feature extraction. Some of these processes includes noise reduction, morphological operations, colour correction and image re-sampling. Feature extraction is the process by which key points are obtained from the image. These key points consist of blobs, edges and corners.

2 Preprocessing Tasks

This section discusses the pre-processing tasks that are required to implement the Vehicle Make and Model System in practical scenarios.

2.1 CCTV camera located at the side of a motor way

As a consequence of this system being implemented outdoors, there are certain factors that cannot be controlled prior to the CCTV footage being taken. These factors include illumination, motion blur, problems with focus and the camera being placed at an angle which affects processing of the image. The following subsections explain solutions to these problems found when processing the images taken by the camera.

2.1.1 Skewing & Rotation

Considering the camera is at the side of the motor way, one thing to consider is that the angle at which the camera is placed. Therefore, before performing any feature detection or extraction, the images taken from that camera must be set to the right orientation. This could be done by skewing the image or rotating the image as this will set the image to the right orientation. Traditional mathematical algorithms and formulas exist which can be used to correct the angle of rotation or the degree of skewing required. Considering that since an image can be represented as a matrix of pixel values, affine transformation matrices could be applied to the image to correct the problem (Gonzales & Woods, 2008).

Before these algorithms can be applied to the images, it must be detected whether there is a need to apply skew correction to the images captured. Patel et al. (2015) discuss an approach for skew angle detection and correction

based on the radon transform. The radon transform was used because of its accuracy and low computational cost. The radon function calculates projections of the image matrix in particular directions (Patel et al, 2015). For an image matrix $f(x,y)$ a projection is considered as a collection of line integrals. The line integrals are calculated from various sources along beams, lateral paths, in a specific direction. The skew detection algorithm proposed by Patel et al (2015) is as follows. First of all, the input image is binarised and morphological filling operations are applied. After that, edges are detected using the canny edge detector. This process is used for locating relevant transitions within the image. The radon transform is then applied on the output of the edges detected. Next, a maximum value is searched for within the radon transform coefficients. After that, a skew angle is found from the maximum intensity value that was found from the radon coefficients. The image is then rotated with the skew angle.

2.1.2 Brightness & Colour Correction

Another factor to consider is the lighting conditions. The reason being that, in the day time, pictures taken may or may not have the appropriate lighting. In the night time, the images taken may be very dark. Therefore, in order to make the images conducive for training, the images will need to be made brighter. A remedy to this problem could be applying a brightness adjustment algorithm. According to Szeliski (2010), this can be done by multiplying or adding the image by the constant.

$$g(x) = \alpha f(x) + \beta$$

Where α and β are parameters which influence the contrast and brightness of the image and where α is greater than zero.

Alternatively, colour balancing and correction algorithms can be used to improve the illumination and contrast of the image. Weng et al (2004) introduce

a novel approach of improving white balance in still images. This algorithm is needed especially for images taken at night because, depending on the colour temperature of the street light. The image will appear reddish if the colour temperature of the light source is low, conversely, the image will appear blue if the colour temperature of the light source is high (Weng et al, 2014). Therefore, improving the white balance will make the image appear as though it was captured under canonical lighting.

The proposed solution works in two stages that is, white point detection and white point adjustment. utilises a dynamic threshold for identifying white points within the image. The process begins by converting the image from the RGB colour space to the YC_bC_r . Depending on the colour characteristics, a near white region composed of several candidate reference white points is chosen. The candidate points are chosen by computing the mean values of C_b and C_r (Weng et al, 2014). The white reference points are then selected depending on the brightness values of candidate white points (top 10 percent) near the white region. After the white reference points have been chosen, the Von Kries model is used to fine-tune the image. This model is used to scale each individual R , G and B channel separately. Channel gains are obtained from the average values of reference white points. Luminance is maintained throughout the image at the same intensity by using the maximum luminance value to compute channel gains. Each pixel value is adjusted by multiplying each pixel with the computed gain (Weng et al, 2014).

2.1.3 Motion blur removal

Motion blur is a phenomenon which occurs when there are inconsistencies between the speed of the moving object and the rate at which the camera captures frames. The problem with motion blur is that, it attenuates the image signal. Removing the motion blur from the image involves two processes. Firstly, estimating the amount by which the image has been blurred and thereafter, recovering a more realistic image using deconvolution (point-

wise division in the frequency domain). Cho (2010) proposes a method of deconvolution referred to as iterative distributed reweighting (IDR) for removing motion blur. This method enhances the visual quality of reconstructed images as compared with traditional deconvolution algorithms used for removing motion blur.

Cho (2010) suggests the estimation of the blur kernel by examining edges within the blurred image. The edges within the blurred image encode estimations of the blur kernel from which the blur can be removed using the inverse radon transform. Using the edge information in this case will yield desirable results because, the object of interest is a man made object and man made objects consist of many edges. As a result of the loss of high frequency information, prior information concerning natural images is used to fill out the missing information. This is done using content aware image priors rather than sparse priors because, content aware prior adjusts its features to local textures and hence, it increases the quality of textures within the reconstructed images (Cho, 2010). After this has been completed, a maximum a posteriori (MAP) estimator is used to restore the image using piecewise smooth features, however, since the MAP does not always accurately reconstruct rich textures, IDR is used to improve the depiction of rich textures.

2.1.4 Shake Removal

In the process of capturing images, the camera could be susceptible to shaking especially in windy conditions. This is a problem because, the camera shaking causes non-uniform blurring cannot be handled effectively by blind convolution algorithms (Hirsch et al, 2011). They suggest a fast single image blind deconvolution algorithm which is a combination of both constraints of Projective Motion Path Blur (PMPB) models and the effectiveness of the Efficient Filter Flow (EFF) framework. In order to recover a sharper version of the image, EFF estimates a non-static blur as the total of various blur

patches. The blur kernels are created using homographies. The homographies are then applied to a grid of pixels. This makes it possible to generate possible camera shakes via a combination of various homographies of a point grid (Hirsch et al, 2011). Different views of a point grid are created by using a homography. This splits the views into local blur kernels which are constrained to only linear combinations.

Given a blurred image, an unknown sharp image can be reconstructed in two steps: (1) blur estimation for non-stationary PSFs and (2) sharp image recovery through a non-blind deconvolution process suited to non-static blurs. The first step of the algorithm aims at retrieve the motion which the camera undertook during exposure provided only the blurry image. This involves a prediction phase, to lower the blur effect and improve image quality bilateral filtering, a blur parameter estimation phase to identify camera motion features which correctly describe the blurred image from the previous step and a latent image estimation using non-blind deconvolution (Hirsch et al, 2011). Blur parameters are approximated by finding the most appropriate non-static blur which converts the immediate image estimate into the recorded blurry image. Sharp image updates are applied repeatedly during the blur estimation phase. After the blur parameters have been approximated and set, the final sharp image is reconstructed by replacing the image prior of the sharp image update phase with a more natural image prior which is formed on sparsity of gradient images (Hirsch et al, 2011). stationary non-blind deconvolution is then used in the non-stationary case to retrieve the sharp image.

2.2 Dedicated camera installed at entrance to indoor car park

Similar to the CCTV camera located at the side of the road, this system is affected by certain factors which may affect the quality of the images captured by the camera although not as much as an outdoor system. For instance, location at which the camera is placed can be controlled and hence it is placed at the best location possible (that is, the entrance of the car park).

2.2.1 Noise Removal

3 Reference List

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