Visual Computing:

Image features

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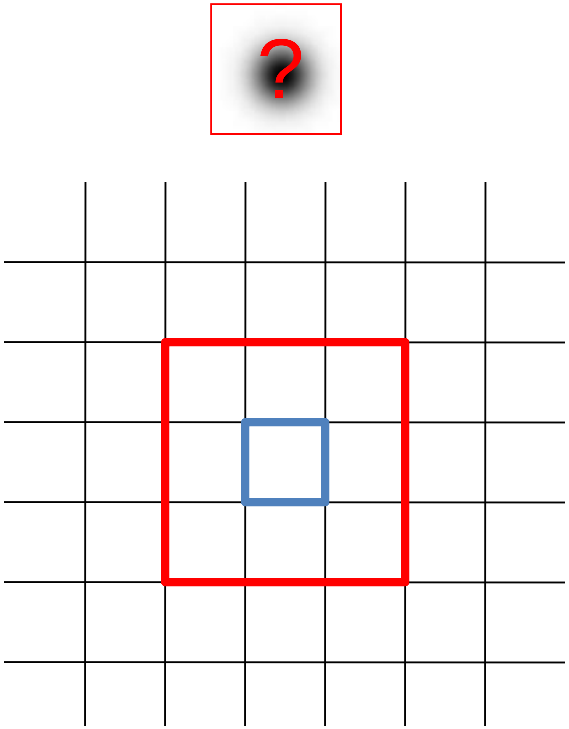
Video link video

Correlation

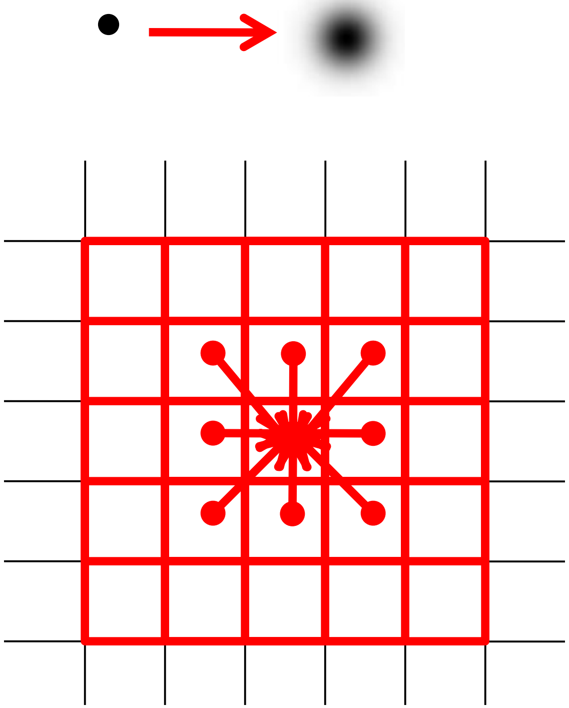
(e.g. Template-matching)



$$I' = \sum_{j=-k}^{k} \sum_{i=-k}^{k} K(i,j) I(x+i, y+j)$$

Convolution

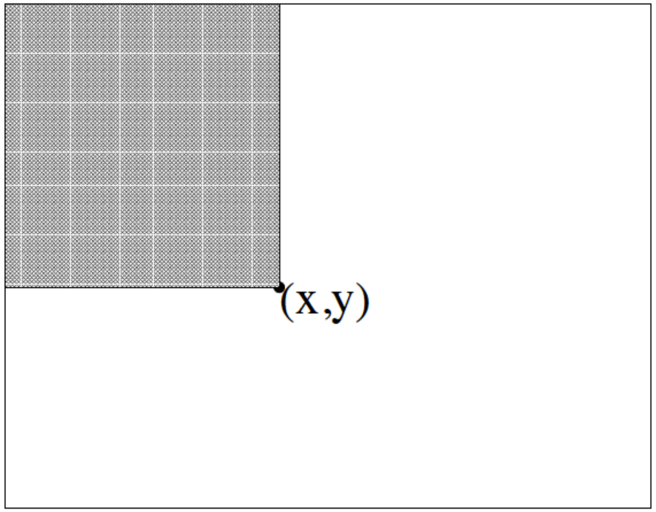
(e.g. point spread function)

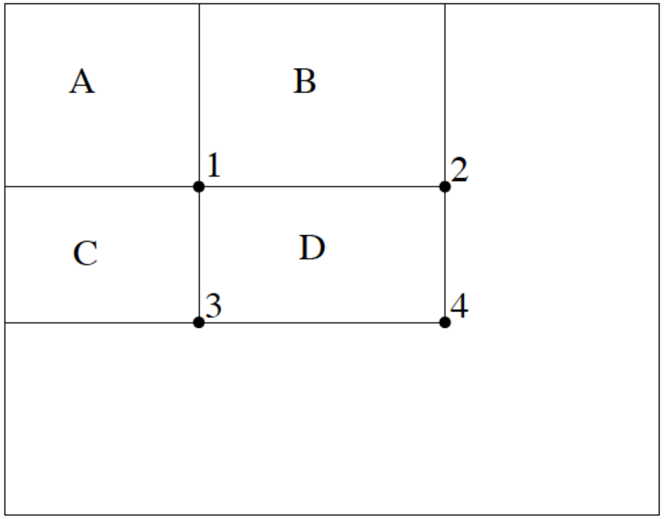


$$I' = \sum_{j=-k}^{k} \sum_{i=-k}^{k} K(i,j) I(x-i, y-j)$$

Integral images

- Integral images (also know as summed-area tables) allow to efficiently compute the convolution with a constant rectangle





II(x,y)= $\int_0^x \int_0^y I(x',y')dx'dy'$

A=II(1)
A+B=II(2)

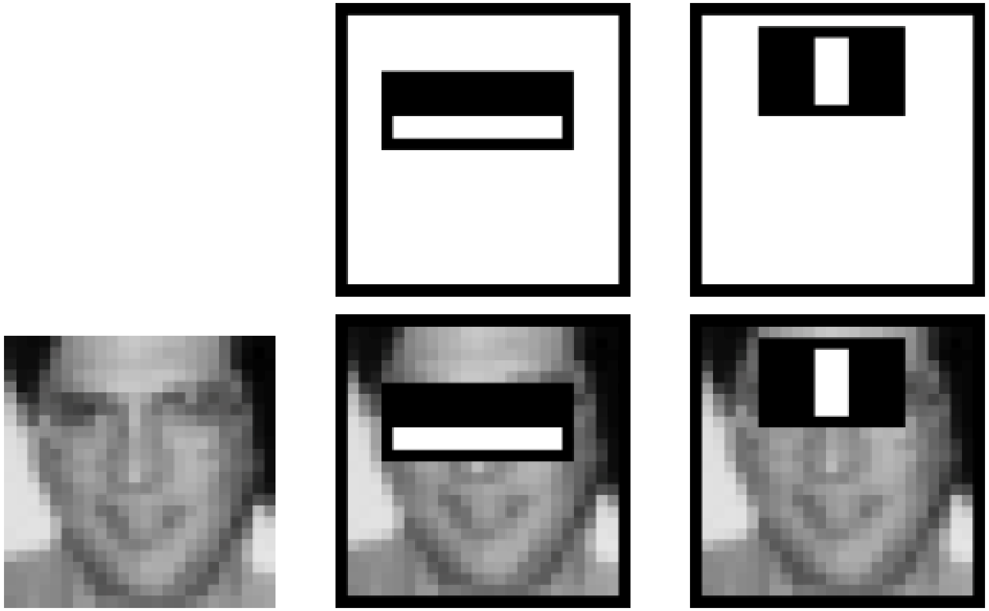
A+C=II(3)
A+B+C+D=II(4)

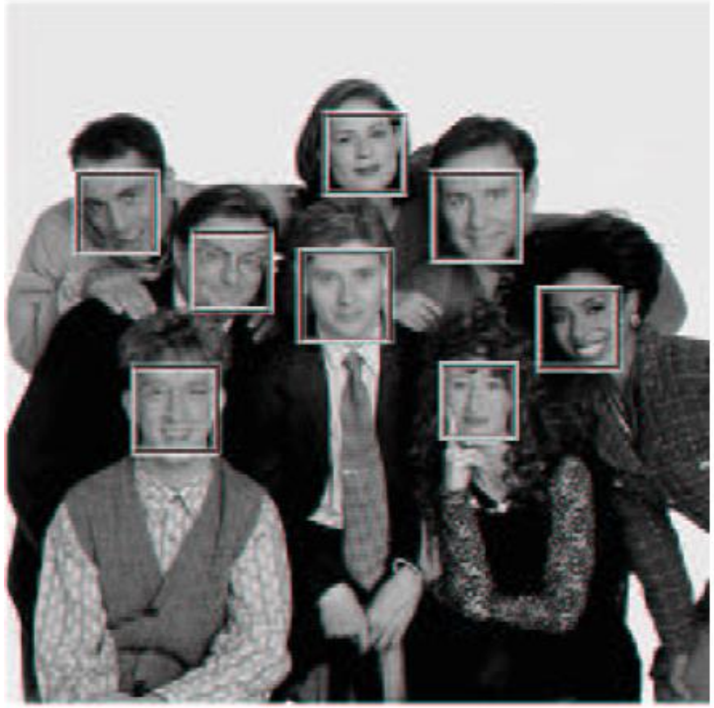
$\boxed{\text{D=II(4)-II(2)-II(3)+II(1)}}$

Figures from Viola and Jones 2001

Viola-Jones cascade face detection

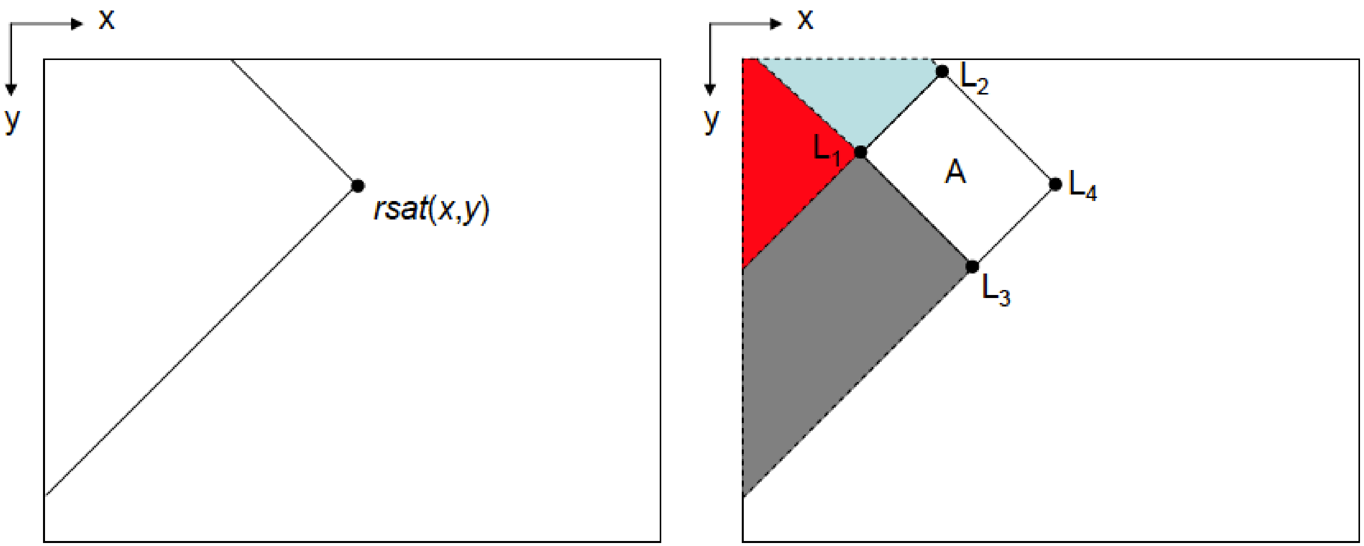
- Very efficient face detection using integral images



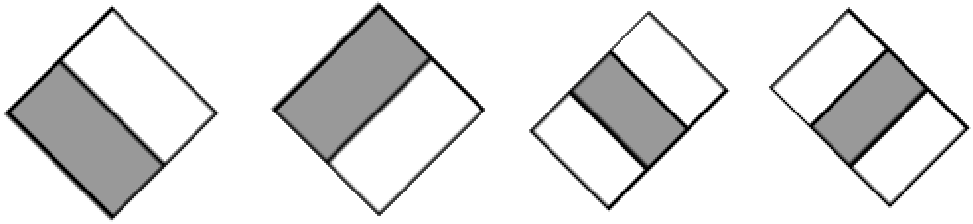


Figures from Viola and Jones 2001

- Also possible along diagonal



(a) (b)



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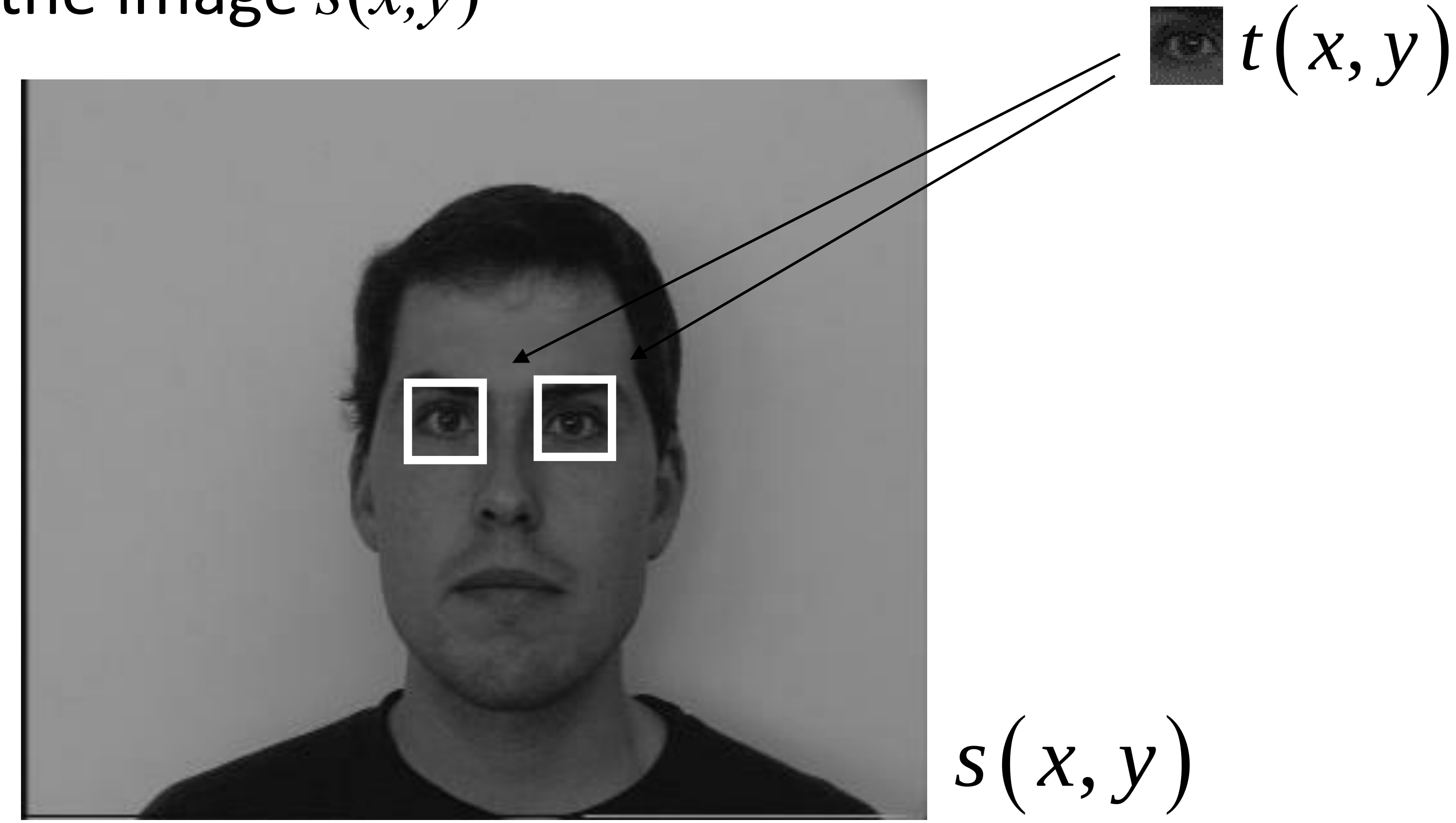
Template matching

- Problem: locate an object, described by a template $t(x,y)$, in the image $s(x,y)$
- Example



Template matching (cont.)

- Search for the best match by minimizing mean-squared error

$$E(p,q) = \sum_{x=-\infty}^{\infty} \sum_{y=-\infty}^{\infty} \left[s(x,y) - t(x-p, y-q) \right]^2$$

$$= \sum_{x=-\infty}^{\infty} \sum_{y=-\infty}^{\infty} \left| s(x,y) \right|^2 + \sum_{x=-\infty}^{\infty} \sum_{y=-\infty}^{\infty} \left| t(x,y) \right|^2 - 2 \sum_{x=-\infty}^{\infty} \sum_{y=-\infty}^{\infty} s(x,y) \cdot t(x-p, y-q)$$

- Equivalently, maximize *area correlation*

$$r(p,q) = \sum_{x=-\infty}^{\infty} \sum_{y=-\infty}^{\infty} s(x,y) \cdot t(x-p, y-q) = s(p,q) * t(-p,-q)$$

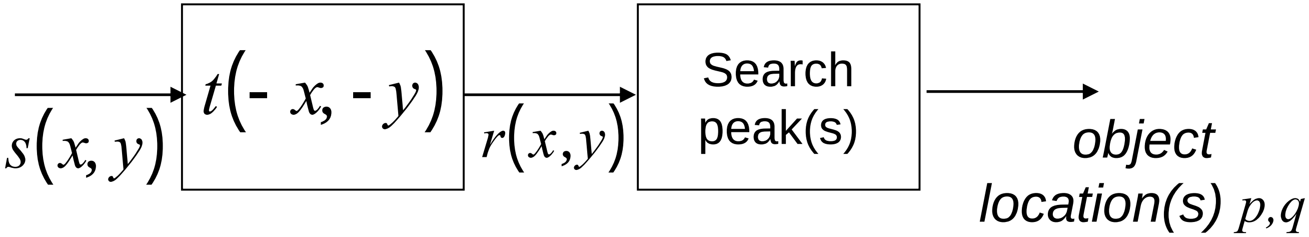
- Area correlation is equivalent to convolution of image $s(x,y)$ with impulse response $t(-x,-y)$

Template matching (cont.)

- From Cauchy-Schwarz inequality

$$r\left(p,q\right)=\sum_{x=-\infty}^{\infty}\sum_{y=-\infty}^{\infty}s\left(x,y\right)\cdot t\left(x-p,y-q\right)\leq\sqrt{\left[\sum_{x=-\infty}^{\infty}\sum_{y=-\infty}^{\infty}\left|s\left(x,y\right)\right|^{2}\right]\cdot\left[\sum_{x=-\infty}^{\infty}\sum_{y=-\infty}^{\infty}\left|t\left(x,y\right)\right|^{2}\right]}$$

- Equality, iff $s\left(x,y\right)=\alpha\cdot t\left(x-p,y-q\right)$ with $\alpha\geq 0$
- Blockdiagram of template matcher



$s(x,y)$

$t(-x,-y)$

$r(x,y)$

Search peak(s)

object location(s) p,q

- Remove mean before template matching to avoid bias towards bright image areas

Edge detection

- Idea (continous-space): Detect local gradient

$$\left|grad\left(f\left(x,y\right)\right)\right| = \sqrt{\left(\frac{\partial f}{\partial x}\right)^2 + \left(\frac{\partial f}{\partial y}\right)^2}$$

- Digital image:
  use finite differences instead

difference	$\begin{pmatrix} -1 & 1 \end{pmatrix}$
central difference	$\begin{pmatrix} -1 & [0] & 1 \end{pmatrix}$
Prewitt	$\begin{pmatrix} -1 & 0 & 1 \\ -1 & [0] & 1 \\ -1 & 0 & 1 \end{pmatrix}$
Sobel	$\begin{pmatrix} -1 & 0 & 1 \\ -2 & [0] & 2 \\ -1 & 0 & 1 \end{pmatrix}$

lots of slides borrowed from Bernd Girod

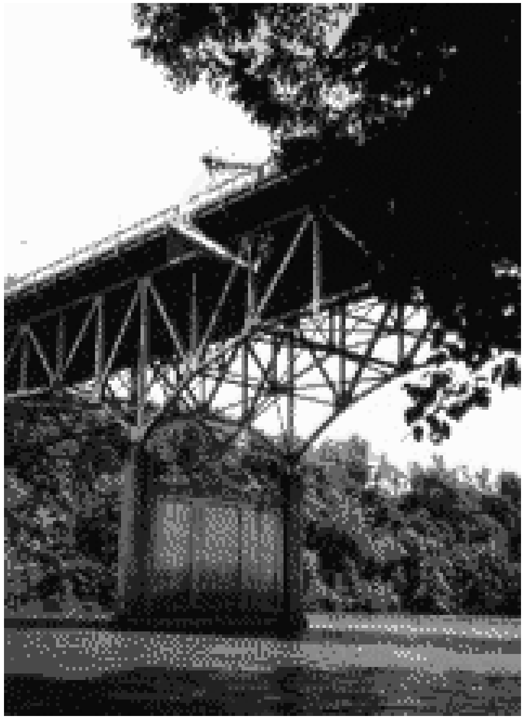
Edge detection filters

Prewitt $$\begin{pmatrix} -1 & 0 & 1 \\ -1 & [0] & 1 \\ -1 & 0 & 1 \end{pmatrix} \quad \begin{pmatrix} -1 & -1 & -1 \\ 0 & [0] & 0 \\ 1 & 1 & 1 \end{pmatrix}$$

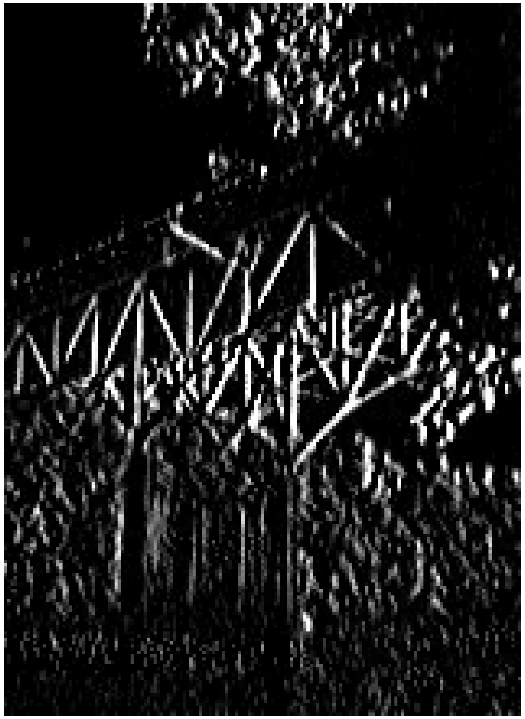
Sobel $$\begin{pmatrix} -1 & 0 & 1 \\ -2 & [0] & 2 \\ -1 & 0 & 1 \end{pmatrix} \quad \begin{pmatrix} -1 & -2 & -1 \\ 0 & [0] & 0 \\ 1 & 2 & 1 \end{pmatrix}$$

Roberts $$\begin{pmatrix} [0] & 1 \\ -1 & 0 \end{pmatrix} \quad \begin{pmatrix} [1] & 0 \\ 0 & -1 \end{pmatrix}$$

Prewitt operator example

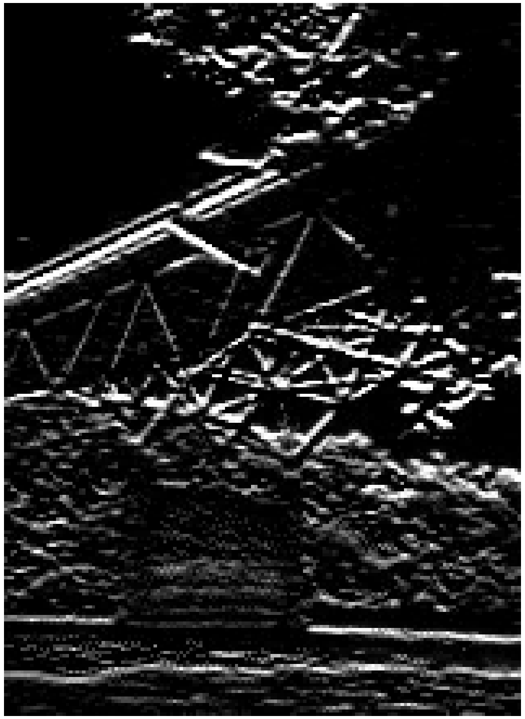


Original *Bridge*
220x160



magnitude of
image filtered with

$$\begin{pmatrix} 1 & 0 & 1 \\ -1 & [0] & 1 \\ -1 & 0 & 1 \end{pmatrix}$$

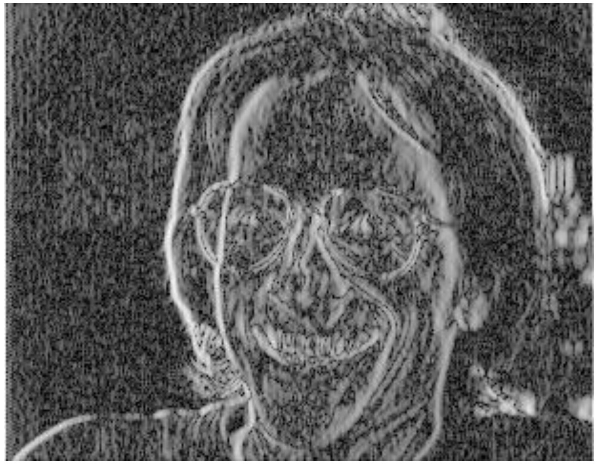


magnitude of
image filtered with

$$\begin{pmatrix} 1 & -1 & -1 \\ 0 & [0] & 0 \\ 1 & 1 & 1 \end{pmatrix}$$

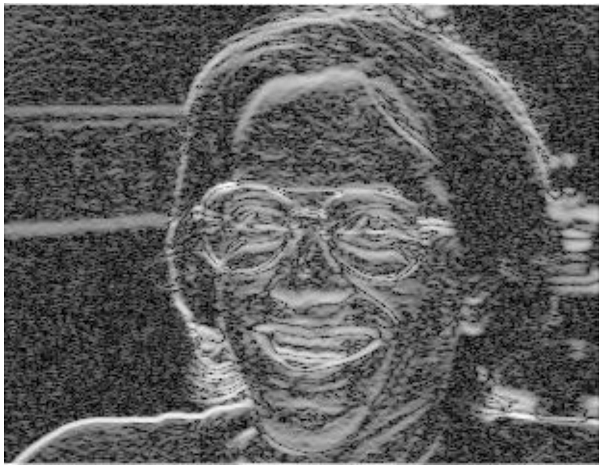
Prewitt operator example (cont.)

Original *Billsface* *310x241*



log magnitude of image filtered with

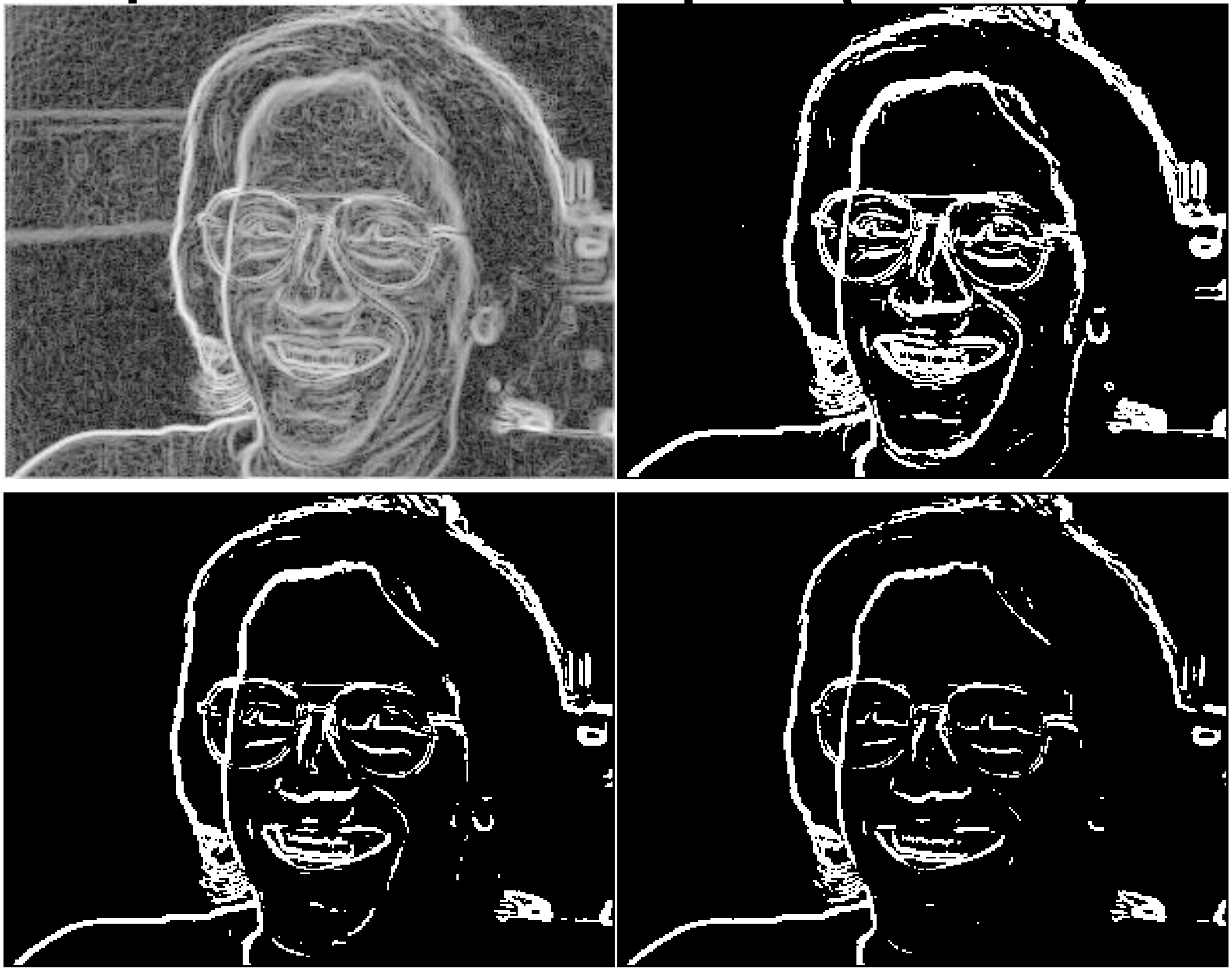
$$\begin{pmatrix} -1 & 0 & 1 \\ -1 & [0] & 1 \\ -1 & 0 & 1 \end{pmatrix}$$



log magnitude of image filtered with

$$\begin{pmatrix} -1 & -1 & -1 \\ 0 & [0] & 0 \\ 1 & 1 & 1 \end{pmatrix}$$

Prewitt operator example (cont.)

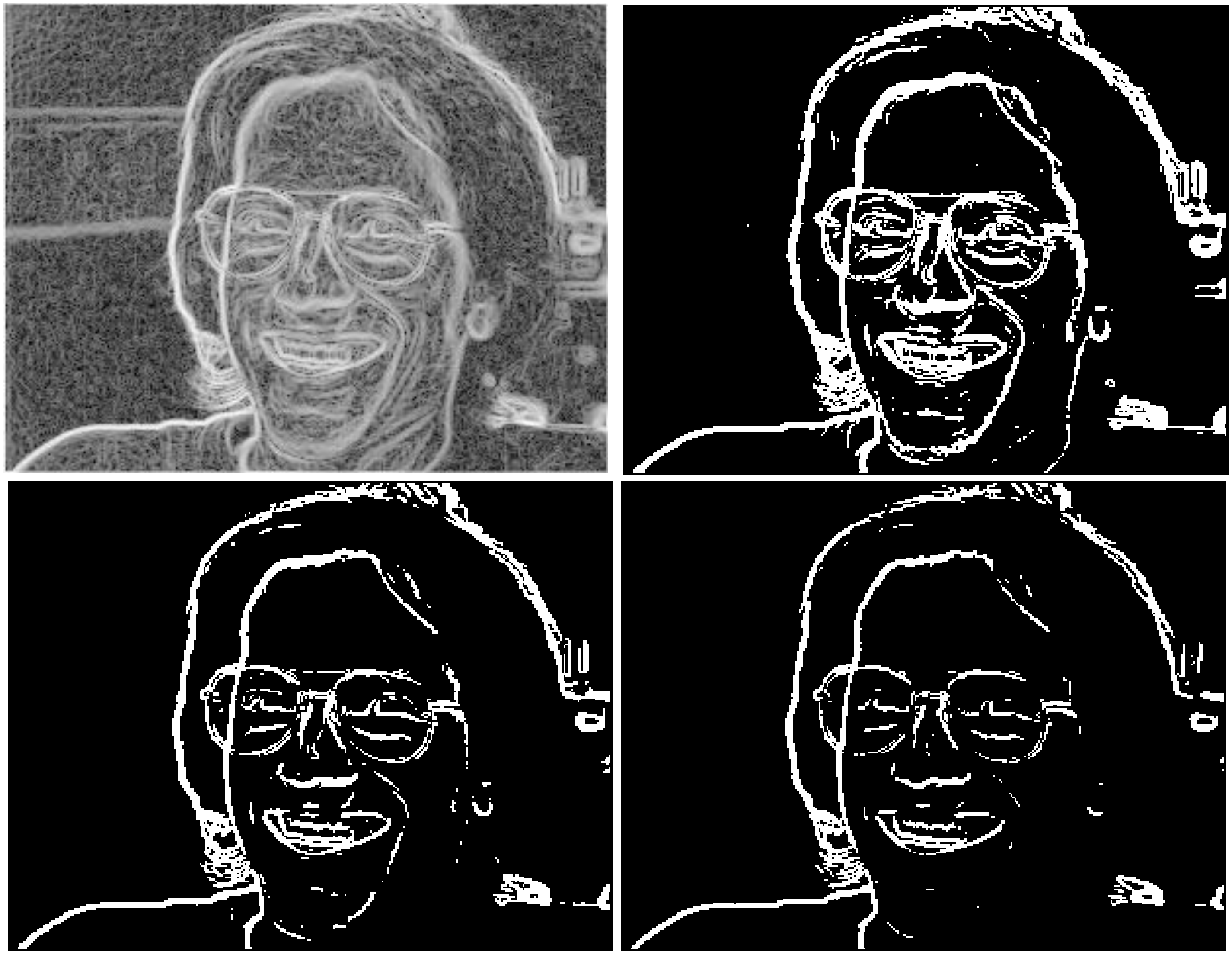


log sum of squared horizontal and vertical gradients

different thresholds

Sobel operator example

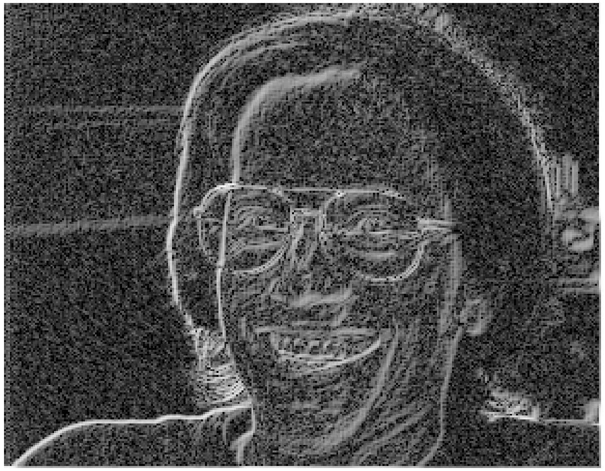
log sum of
squared
horizontal and
vertical
gradients



different
thresholds

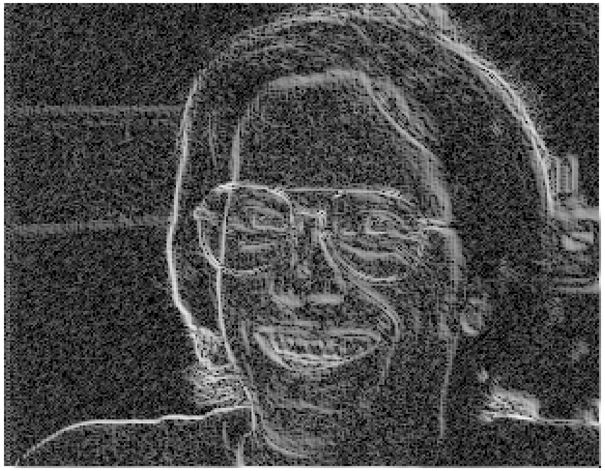
Roberts operator example

Original *Billsface* *309x240*



log magnitude of image filtered with

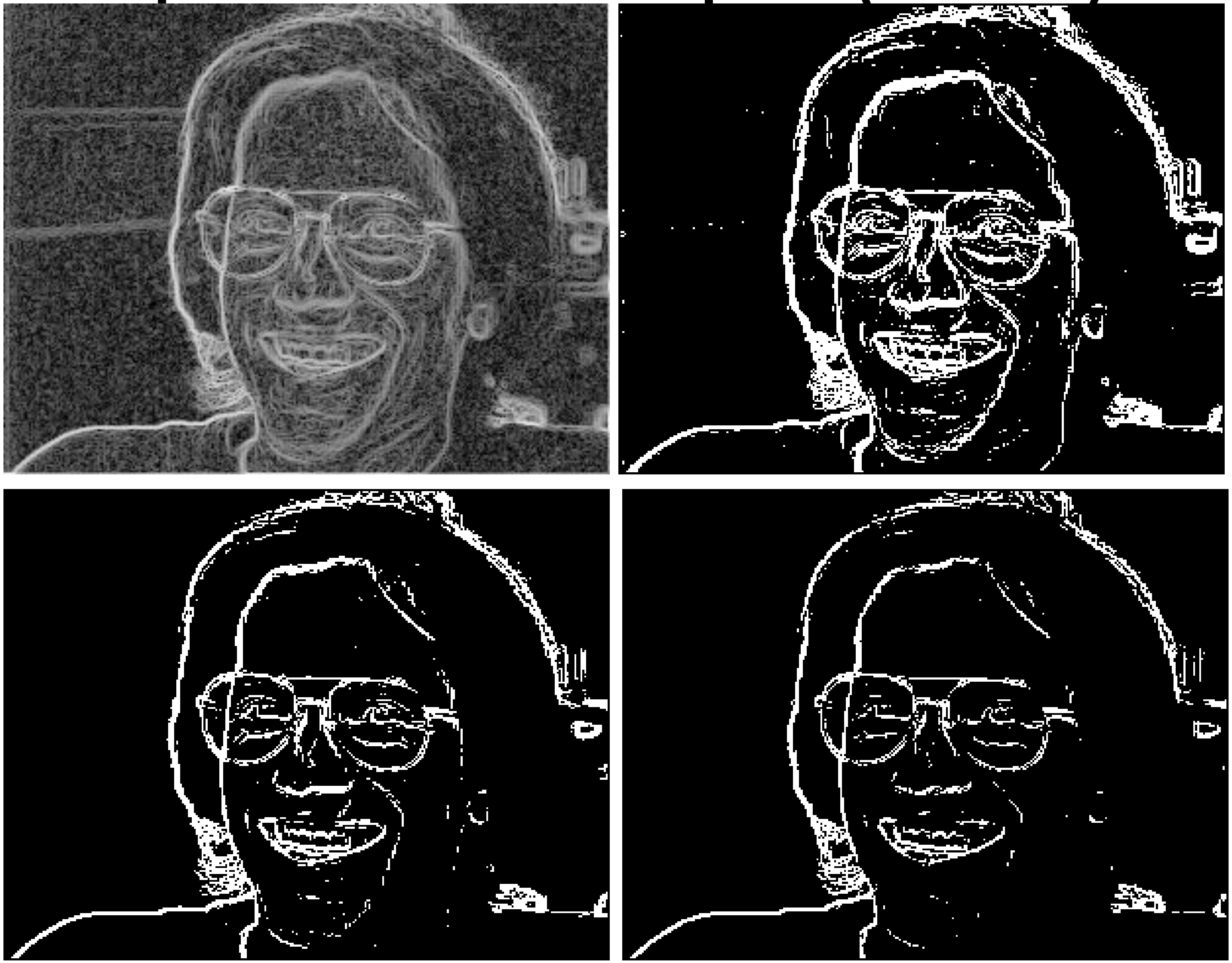
$$\begin{pmatrix} 1 & 0 \\ 0 & -1 \end{pmatrix}$$



log magnitude of image filtered with

$$\begin{pmatrix} 0 & 1 \\ -1 & 0 \end{pmatrix}$$

Roberts operator example (cont.)



log sum of squared diagonal gradients

different thresholds

Laplacian operator

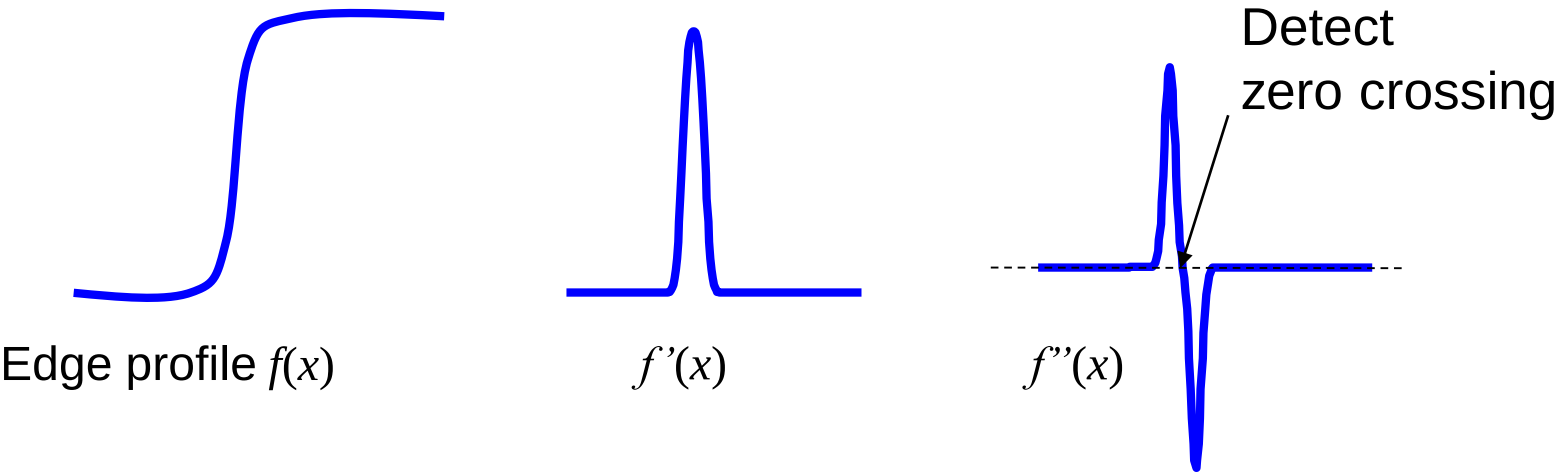
- Detect discontiuities by considering second derivative

$$\boxed{\nabla^2 f(x,y) = \frac{\partial^2 f(x,y)}{\partial x^2} + \frac{\partial^2 f(x,y)}{\partial y^2}}$$

- Isotropic (rotationally invariant) operator
- Zero-crossings mark edge location
- Discrete-space approximation by convolution with 3x3 impulse response

$$\begin{pmatrix} 0 & 1 & 0 \\ 1 & [-4] & 1 \\ 0 & 1 & 0 \end{pmatrix} \quad \text{or} \quad \begin{pmatrix} 1 & 1 & 1 \\ 1 & [-8] & 1 \\ 1 & 1 & 1 \end{pmatrix}$$

1-d illustration of 2nd derivative edge detector



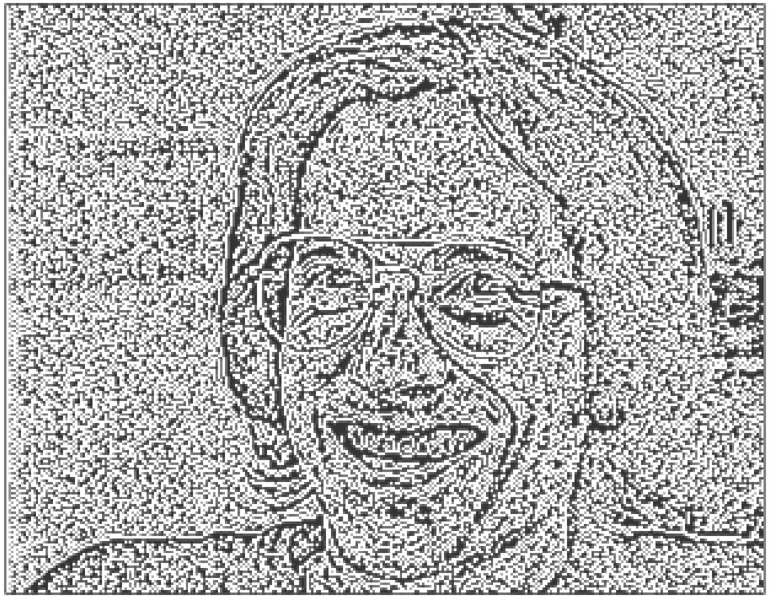
Edge profile $f(x)$

$f'(x)$

$f''(x)$

Detect
zero crossing

Zero crossings of Laplacian



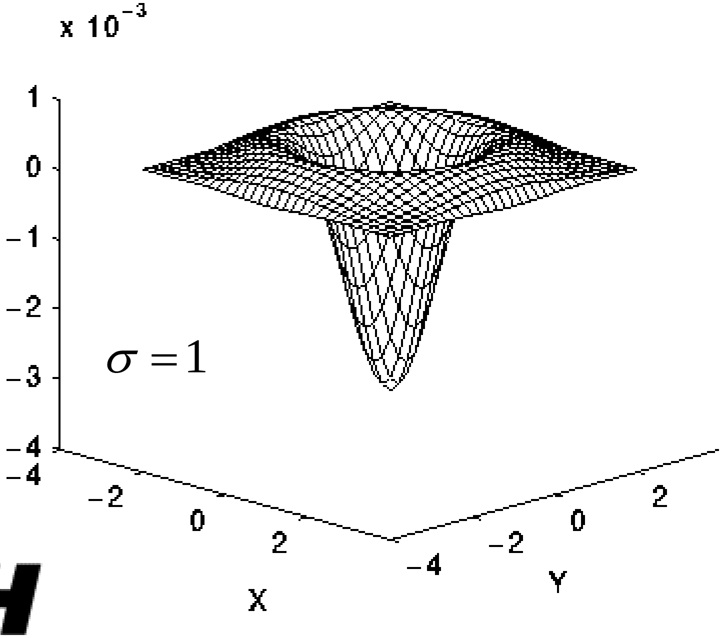
- Sensitive to very fine detail and noise ➔ blur image first
- Responds equally to strong and weak edges
  ➔ suppress "edges" with low gradient magnitude

Laplacian of Gaussian

- Blurring of image with Gaussian and Laplacian operator can be combined into convolution with Laplacian of Gaussian (LoG) operator

$$LoG(x,y) = -\frac{1}{\pi\sigma^4}\left[1-\frac{x^2+y^2}{2\sigma^2}\right]e^{-\frac{x^2+y^2}{2\sigma^2}}$$

- Continuous function and discrete approximation

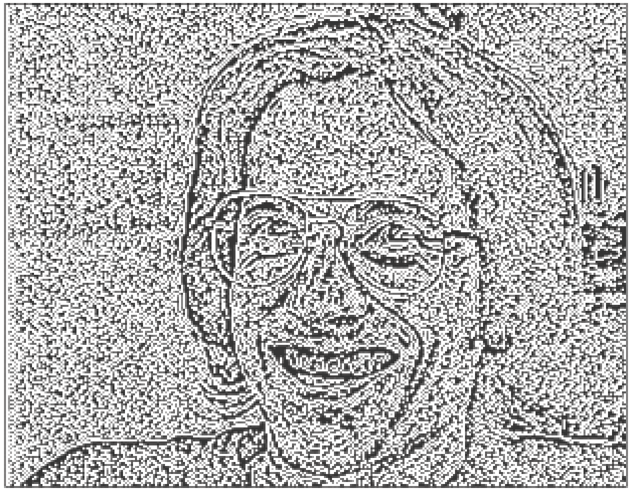


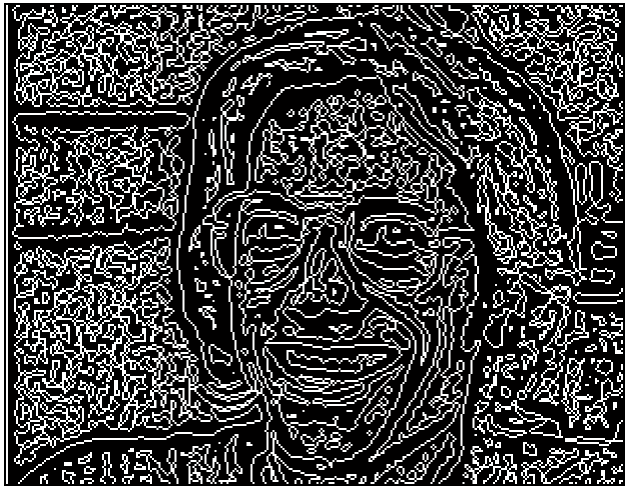
$\sigma = 1.4$

0	1	1	2	2	2	1	1	0
1	2	4	5	5	5	4	2	1
1	4	5	3	0	3	5	4	1
2	5	3	-12	-24	-12	3	5	2
2	5	0	-24	-40	-24	0	5	2
2	5	3	-12	-24	-12	3	5	2
1	4	5	3	0	3	5	4	1
1	2	4	5	5	5	4	2	1
0	1	1	2	2	2	1	1	0

Zero crossings of LoG

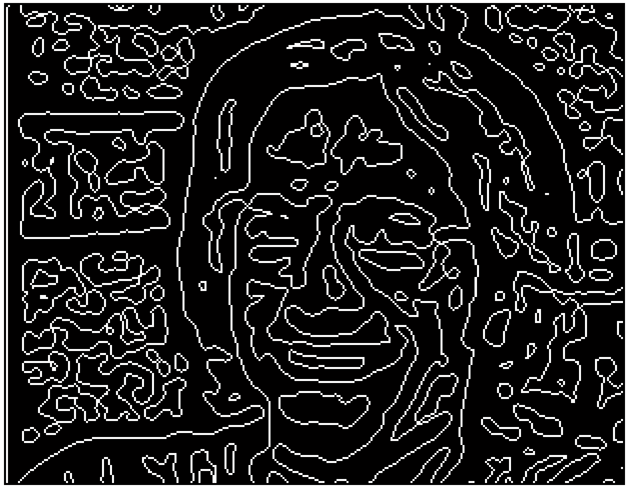
w/o Gaussian

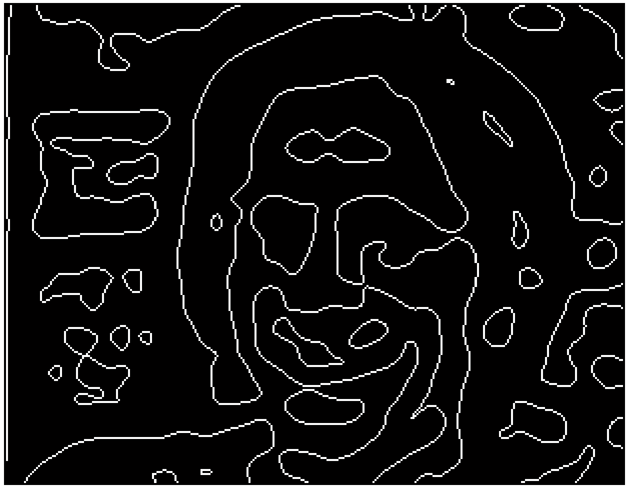




$\sigma = 1.4$

$\sigma = 3$

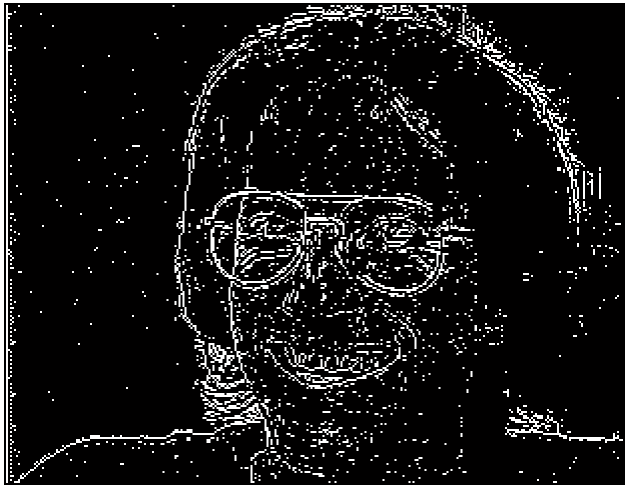


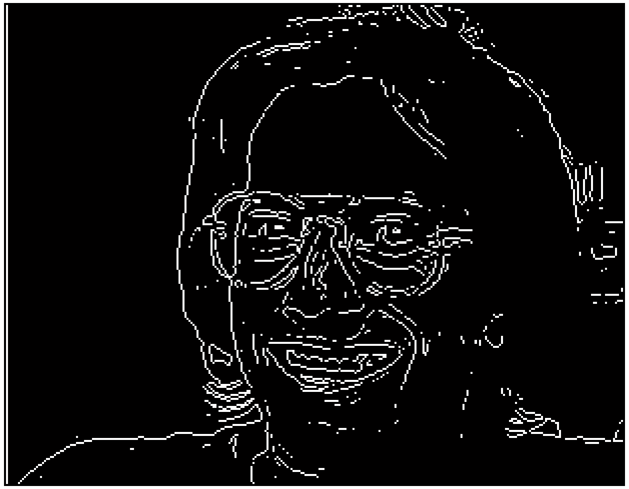


$\sigma = 6$

Zero crossings of LoG – gradient-based threshold

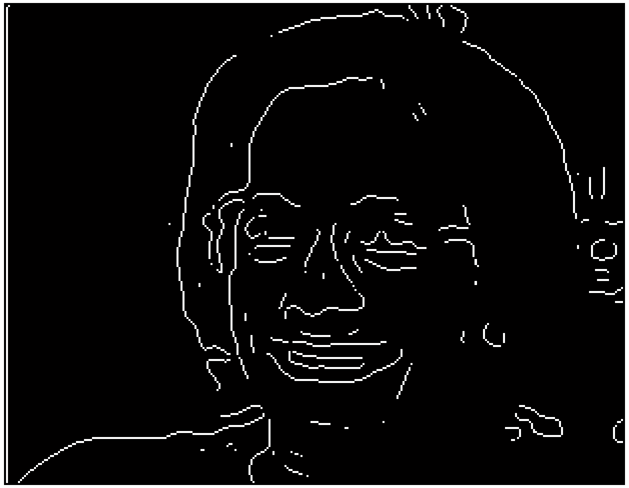
w/o
Gaussian

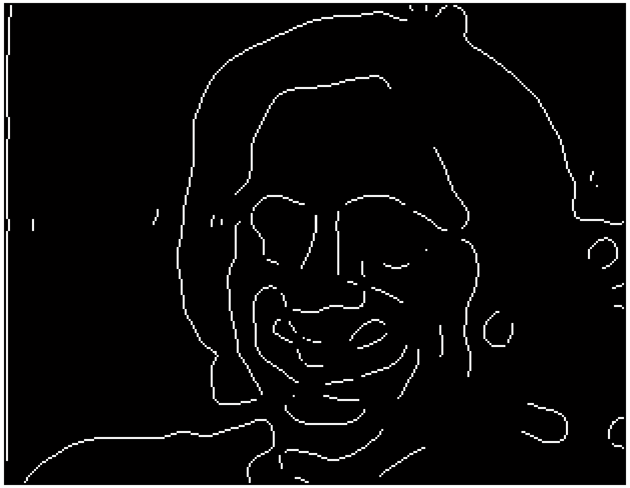




$\sigma = 1.4$

$\sigma = 3$





$\sigma = 6$

Canny edge detector

1. Smooth image with a Gaussian filter
2. Compute gradient magnitude and angle (Sobel, Prewitt . . .)

$$M(x,y)=\sqrt{\left(\frac{\partial f}{\partial x}\right)^2+\left(\frac{\partial f}{\partial y}\right)^2}$$

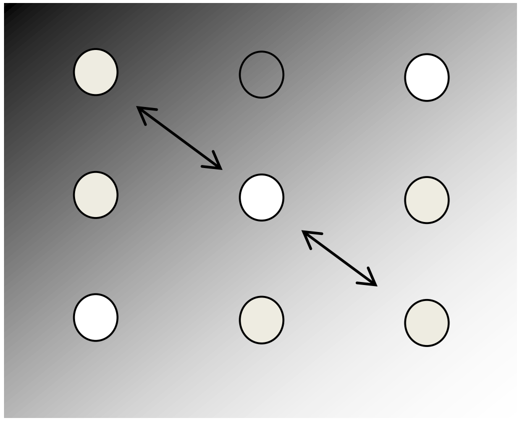
$$\alpha(x,y)=\tan^{-1}\left(\frac{\partial f}{\partial y}\bigg/\frac{\partial f}{\partial x}\right)$$

3. Apply nonmaxima suppression to gradient magnitude image
4. Double thresholding to detect strong and weak edge pixels
5. Reject weak edge pixels not connected with strong edge pixels

[Canny, IEEE Trans. PAMI, 1986]

Canny nonmaxima suppression

- Quantize edge normal to one of four directions: horizontal, -45°, vertical, +45°
- If $M(x,y)$ is smaller than either of its neighbors in edge normal direction ➔ suppress; else keep.



[Canny, IEEE Trans. PAMI, 1986]

Canny thresholding and suppression of weak edges

- Double-thresholding of gradient magnitude

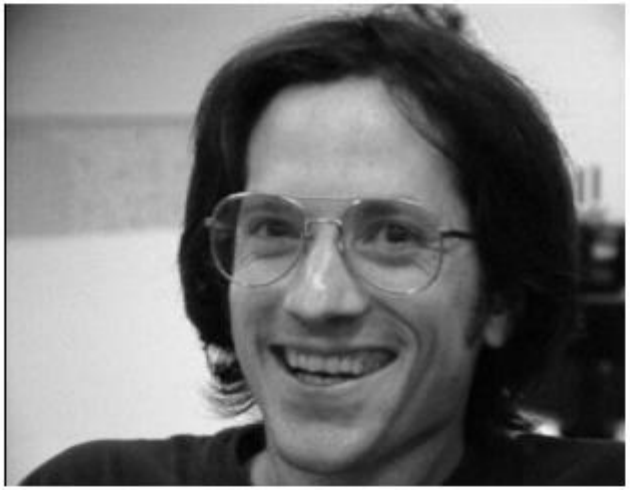
Strong edge: $M(x,y) \geq \theta_{high}$

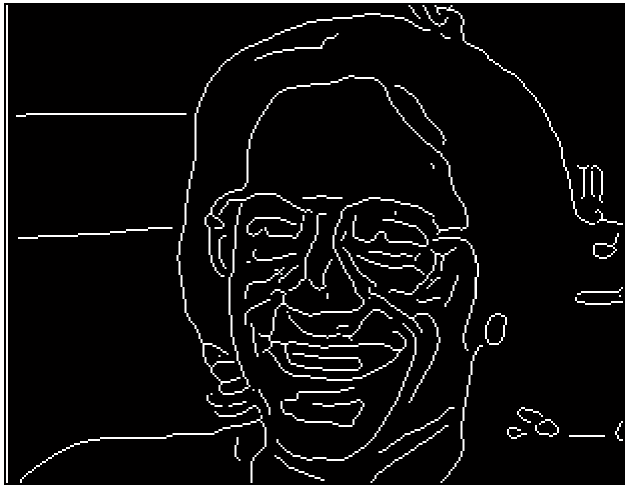
Weak edge: $\theta_{high} > M(x,y) \geq \theta_{low}$

- Typical setting: $\theta_{high} / \theta_{low} = 2...3$
- Region labeling of edge pixels
- Reject regions without strong edge pixels

[Canny, IEEE Trans. PAMI, 1986]

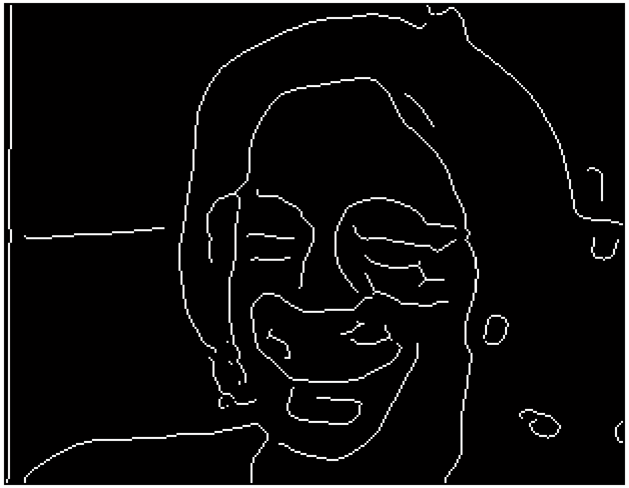
Canny edge detector

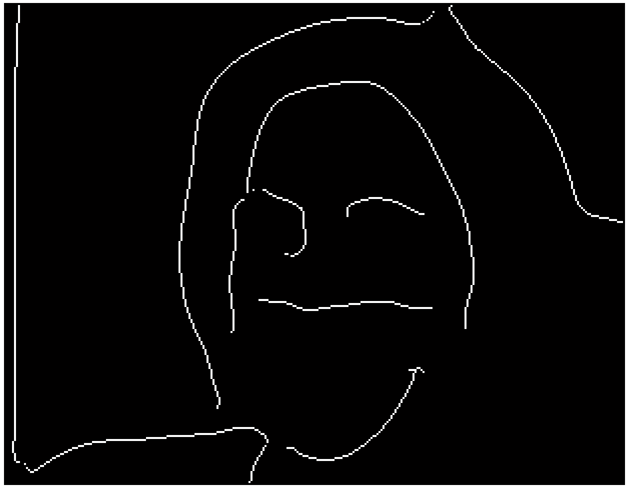




$\sigma = 1.4$

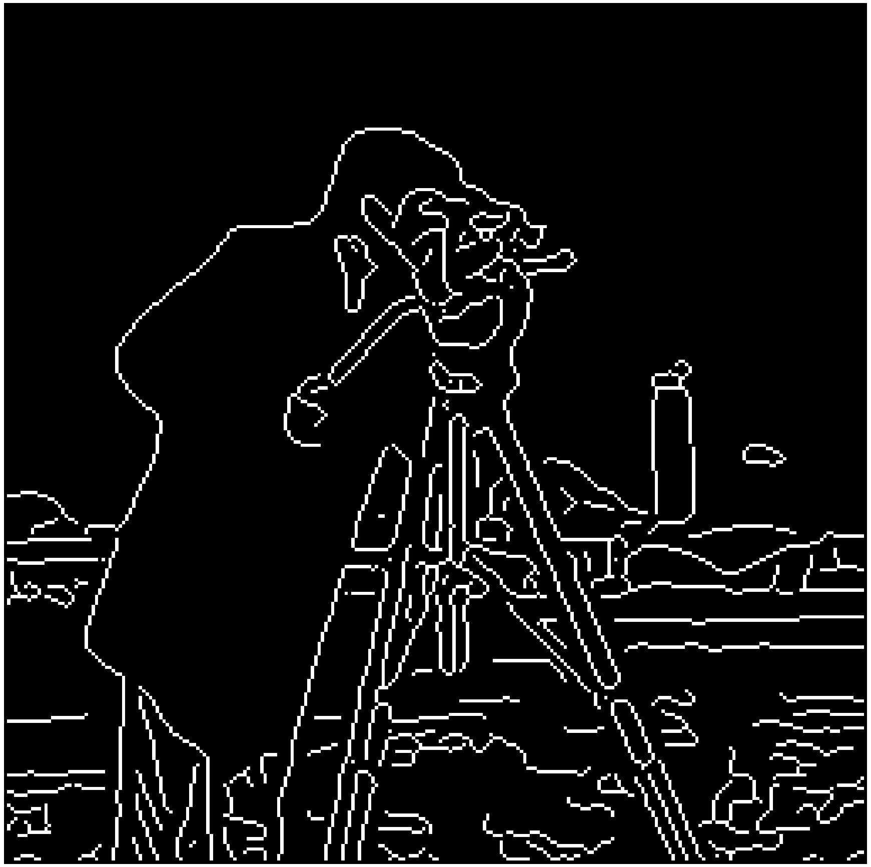
$\sigma = 3$





$\sigma = 6$

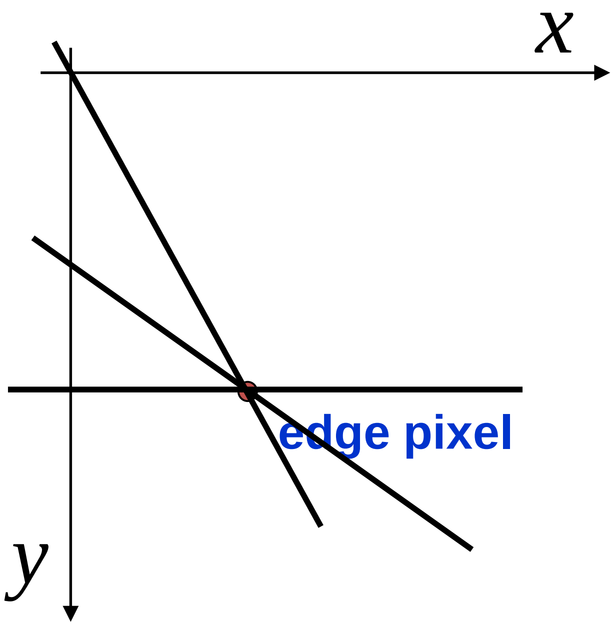
Canny edge detector

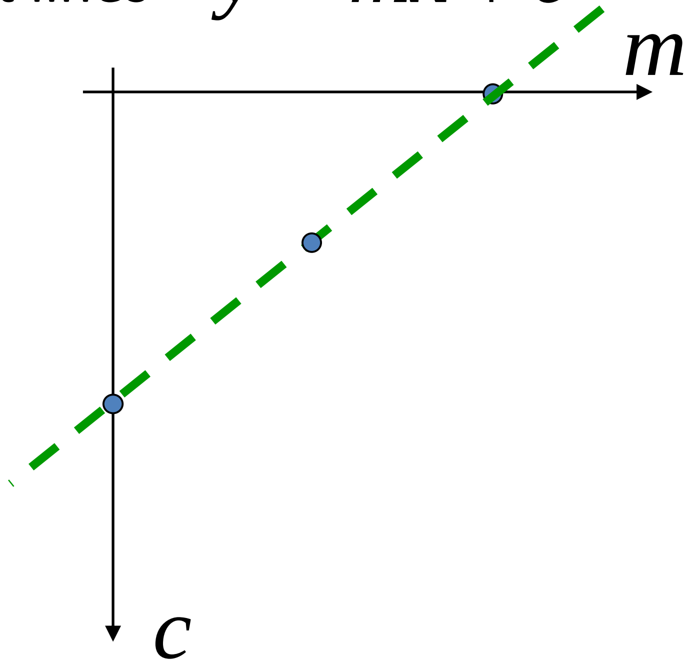


$\sigma = 1.4$

Hough transform

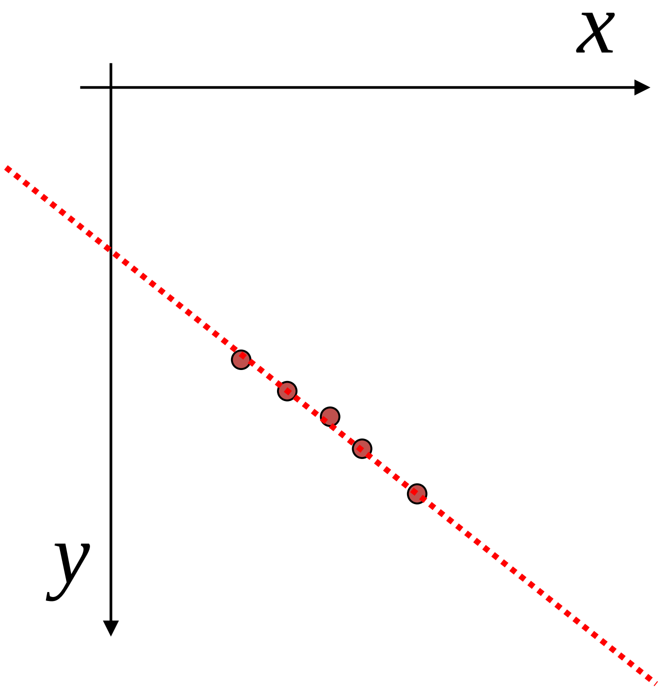
- Problem: fit a straight line (or curve) to a set of edge pixels
- Hough transform (1962): generalized template matching technique
- Consider detection of straight lines $y = mx + c$

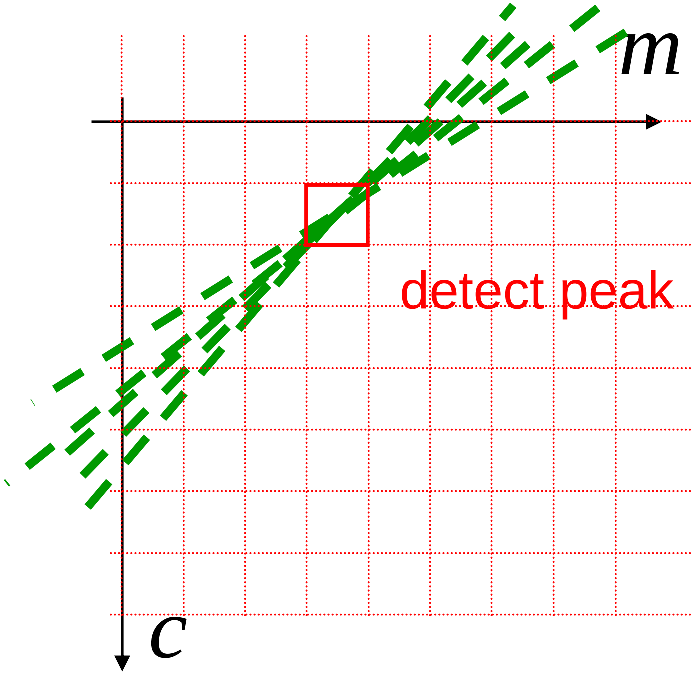




Hough transform (cont.)

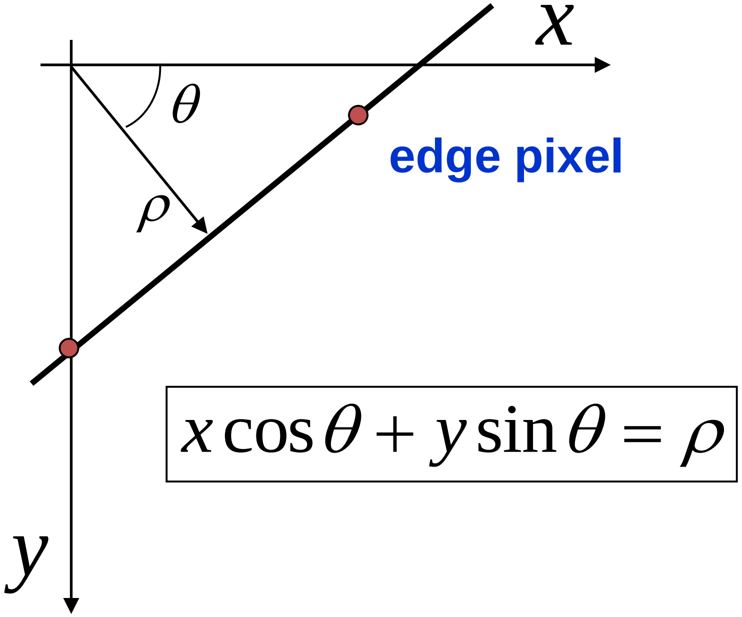
- Subdivide (m,c) plane into discrete "bins," initialize all bin counts by 0
- Draw a line in the parameter space m,c for each edge pixel x,y and increment bin counts along line.
- Detect peak(s) in (m,c) plane



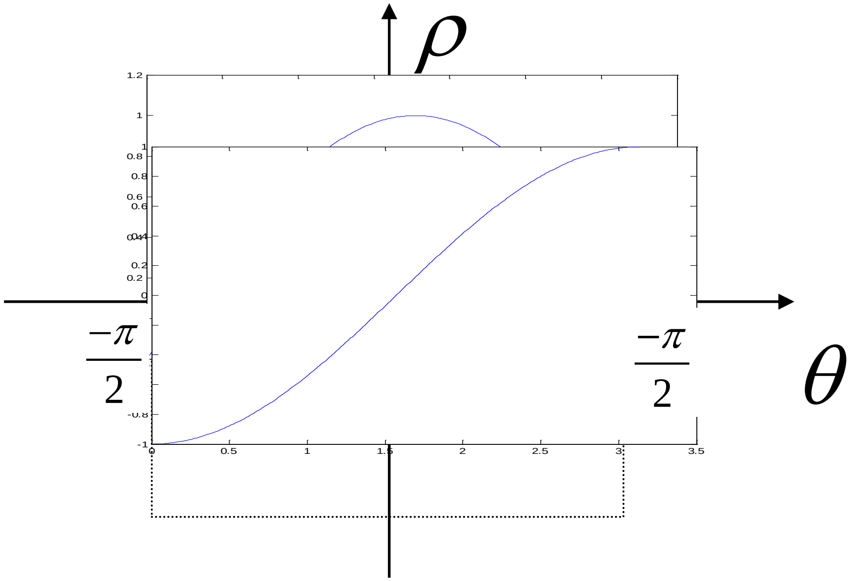


Hough transform (cont.)

- Alternative parameterization avoids infinite-slope problem

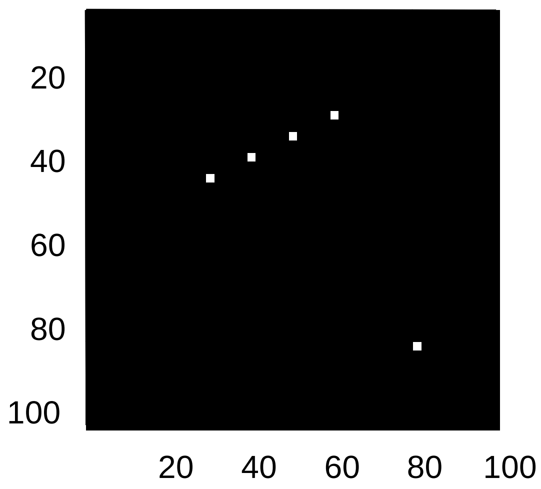


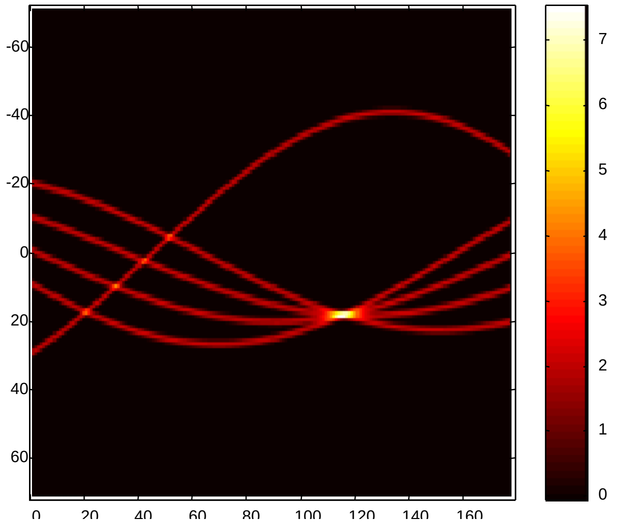
$$\boxed{x\cos\theta + y\sin\theta = \rho}$$

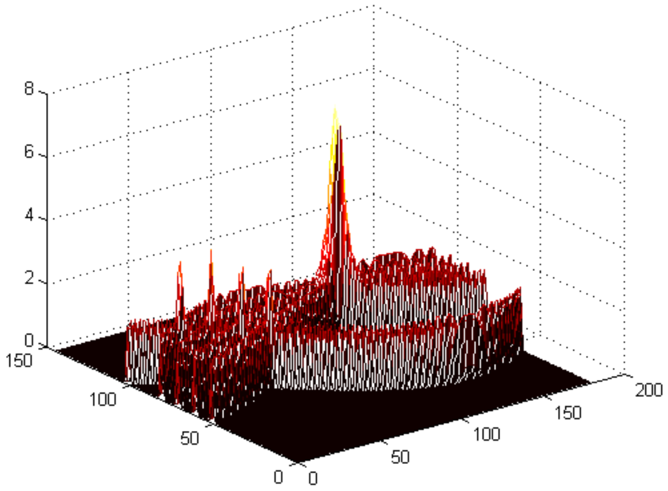


Hough transform Example A

Original image



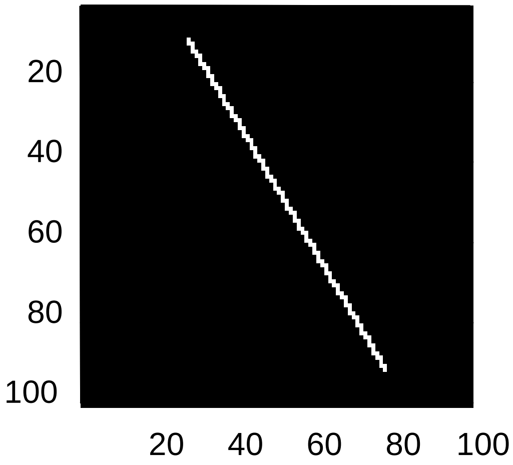


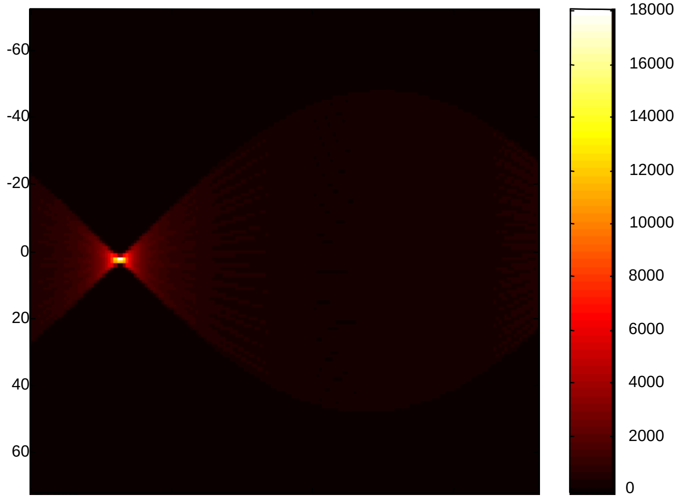


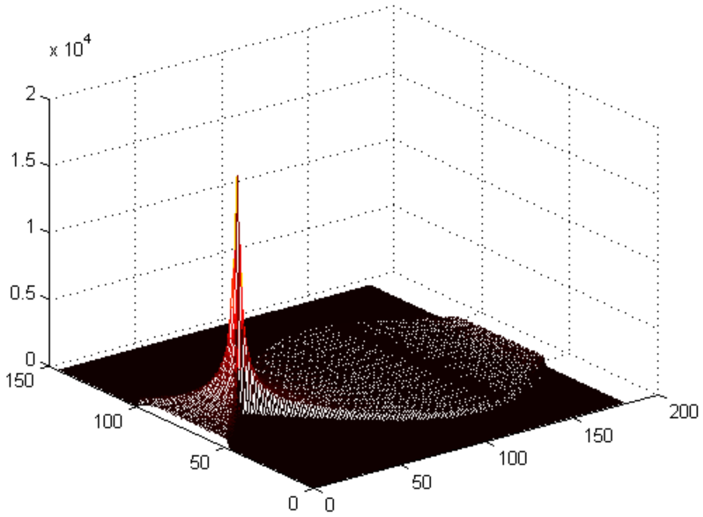
Courtesy: P. Salembier

Hough transform Example B

Original image

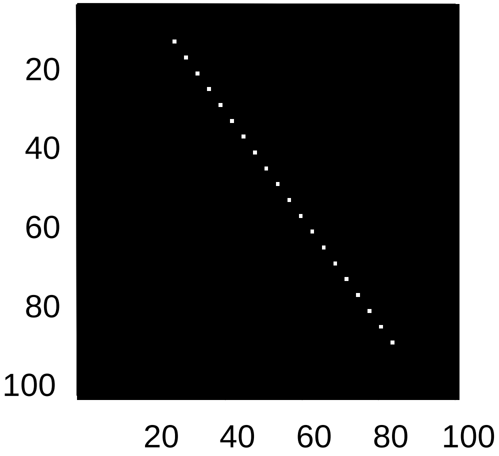


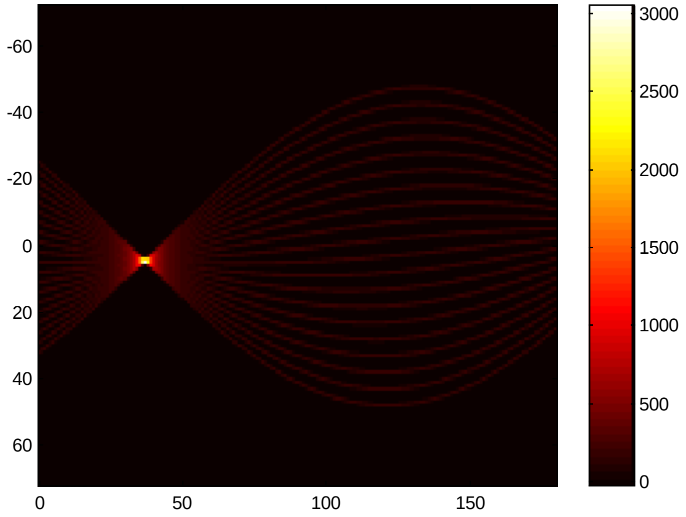


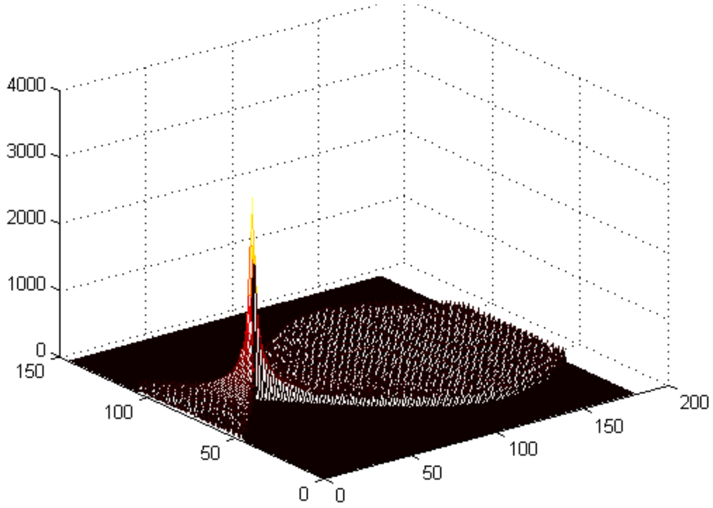


Courtesy: P. Salembier

Hough transform Example C


Original image

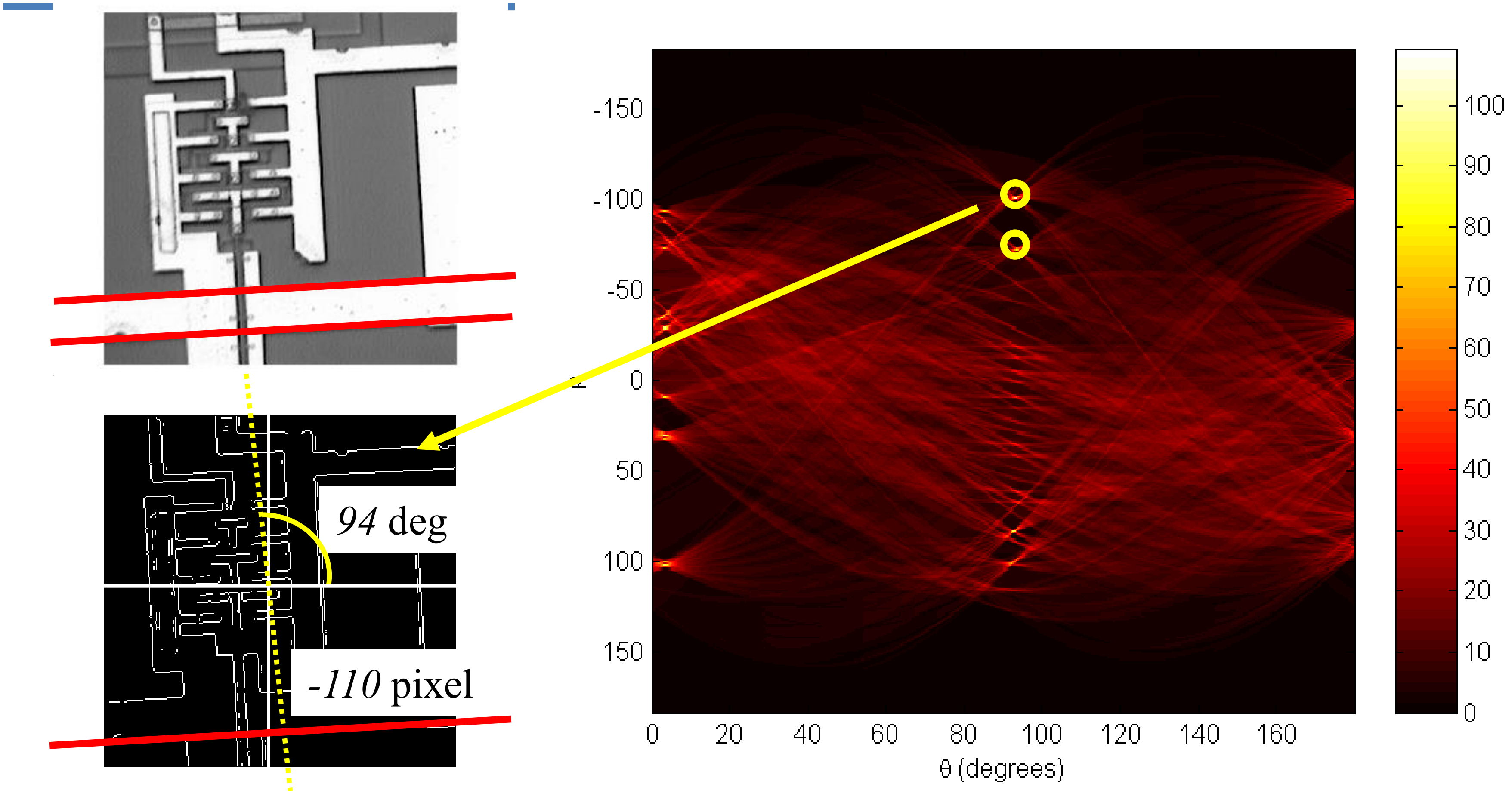




Courtesy: P. Salembier

Hough transform example

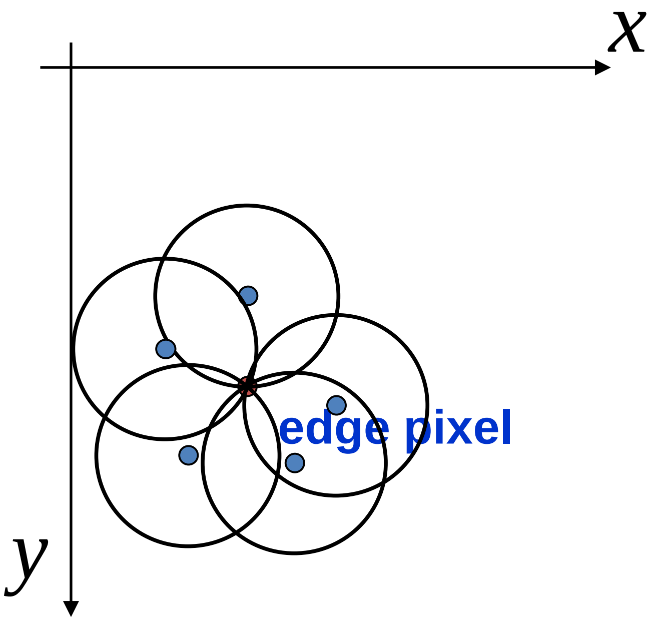
Original IC image (256x256)

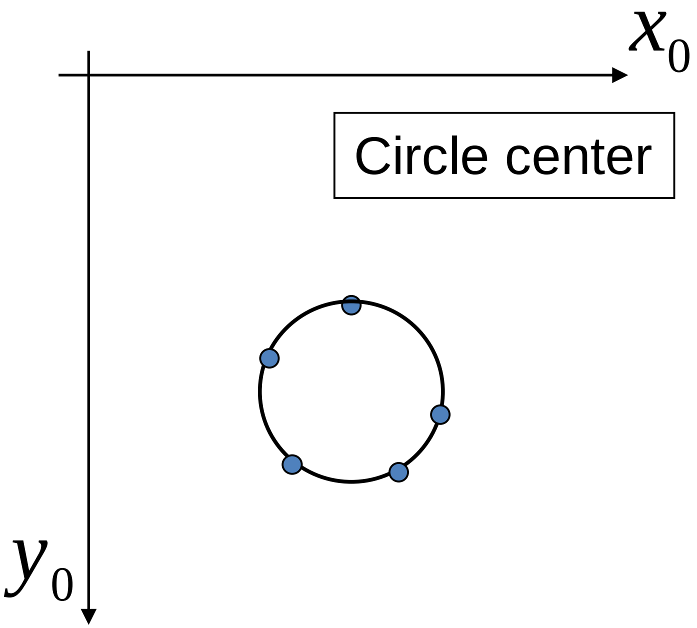


Edge detection (Prewitt)

Circle detection by Hough transform

- Find circles of fixed radius r

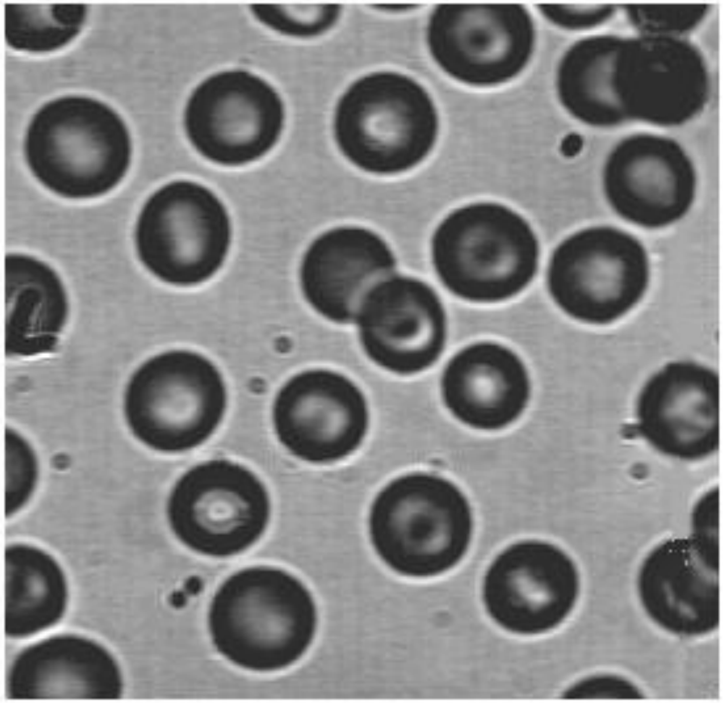




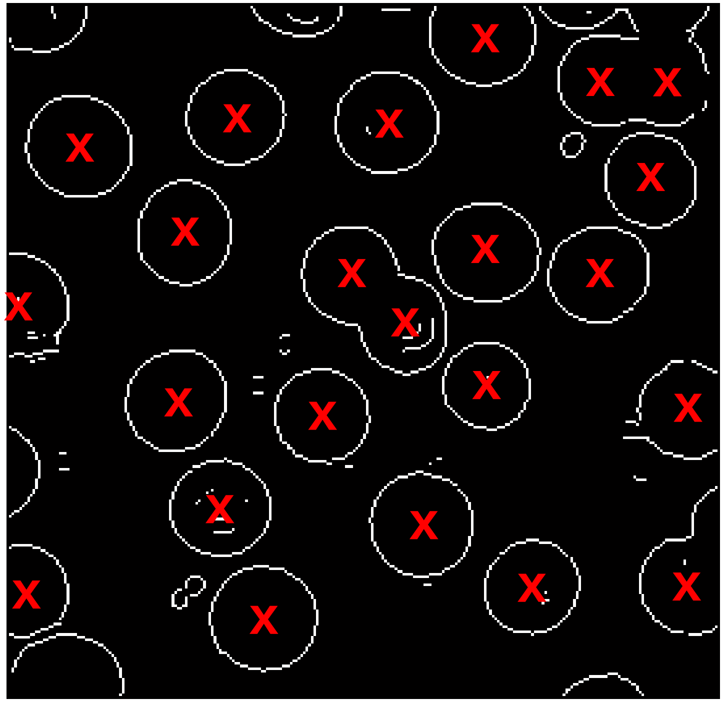
- For circles of undetermined radius, use 3-d Hough transform for parameters (x_0, y_0, r)

Example: circle detection by Hough transform

Original *blood* image

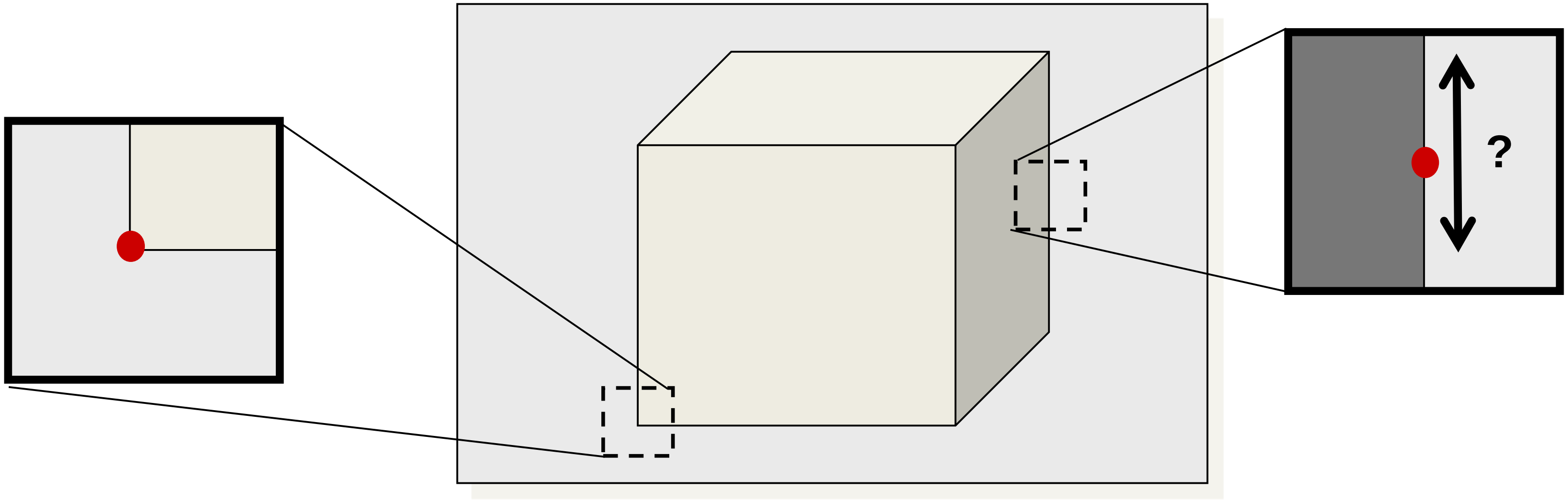


Prewitt edge detection



Detecting corner points

- Many applications benefit from features localized in (x,y)
- Edges well localized only in one direction ➔ detect corners



- Desirable properties of corner detector
  - Accurate localization
  - Invariance against shift, rotation, scale, brightness change
  - Robust against noise, high repeatability

What patterns can be localized most accurately?

- Local displacement sensitivity

$$S(\Delta x, \Delta y) = \sum_{(x,y)\in window} \left[f(x,y) - f(x+\Delta x, y+\Delta y) \right]^2$$

- Linear approximation for small $\Delta x, \Delta y$

$$f(x+\Delta x, y+\Delta y) \approx f(x,y) + f_x(x,y)\Delta x + f_y(x,y)\Delta y$$

$f_x(x,y)$ – horizontal image gradient
$f_y(x,y)$ – vertical image gradient

$$S(\Delta x, \Delta y) \approx \sum_{(x,y)\in window} \left[\begin{pmatrix} f_x(x,y) & f_y(x,y) \end{pmatrix} \begin{pmatrix} \Delta x \\ \Delta y \end{pmatrix} \right]^2$$

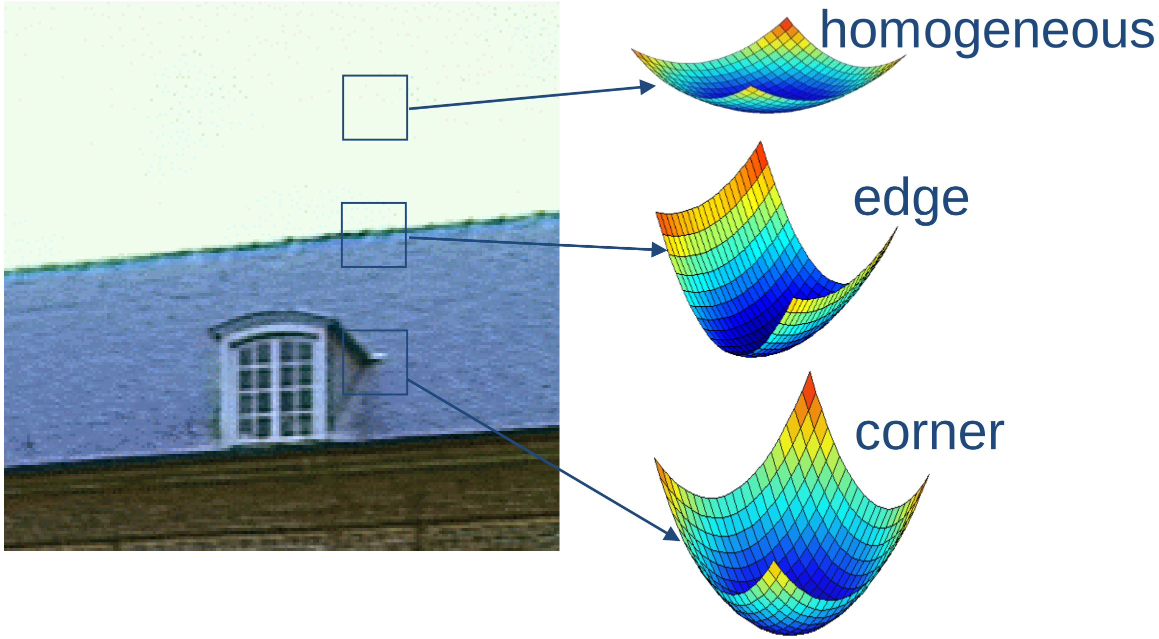
$$= \begin{pmatrix} \Delta x & \Delta y \end{pmatrix} \left(\sum_{(x,y)\in window} \begin{bmatrix} f_x^2(x,y) & f_x(x,y) f_y(x,y) \\ f_x(x,y) f_y(x,y) & f_y^2(x,y) \end{bmatrix} \right) \begin{pmatrix} \Delta x \\ \Delta y \end{pmatrix}$$

$$= \begin{pmatrix} \Delta x & \Delta y \end{pmatrix} \mathbf{M} \begin{pmatrix} \Delta x \\ \Delta y \end{pmatrix}$$

- Iso-sensitivity curves are ellipses

Feature point extraction

$$SSD \approx \Delta^\top \mathbf{M} \Delta$$



Find points for which the following is large

$$\min \Delta^\top \mathbf{M} \Delta \text{ for } \|\Delta\| = 1$$

i.e. maximize eigenvalues of M

Keypoint detection

Often based on eigenvalues λ_1, λ_2 of "structure matrix" (aka "normal matrix" aka "second-moment matrix")

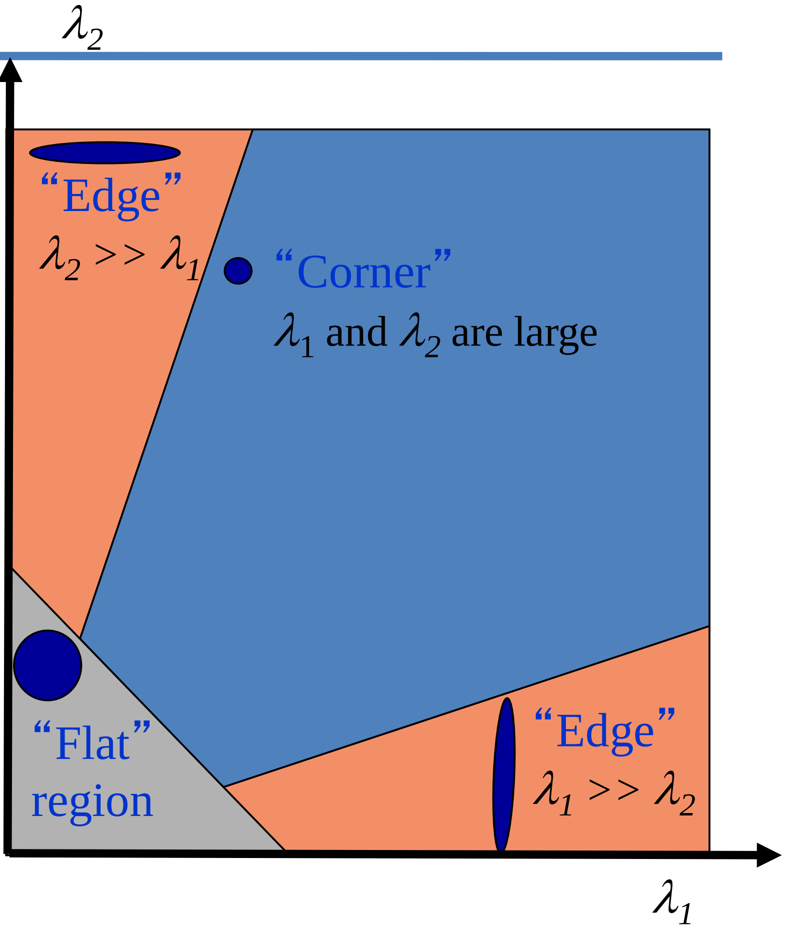
$$\mathbf{M} = \begin{bmatrix} \sum_{(x,y)\in window} f_x^2(x,y) & \sum_{(x,y)\in window} f_x(x,y)\, f_y(x,y) \\ \sum_{(x,y)\in window} f_x(x,y)\, f_y(x,y) & \sum_{(x,y)\in window} f_y^2(x,y) \end{bmatrix}$$

$f_x(x,y)$ – horizontal image gradient
$f_y(x,y)$ – vertical image gradient

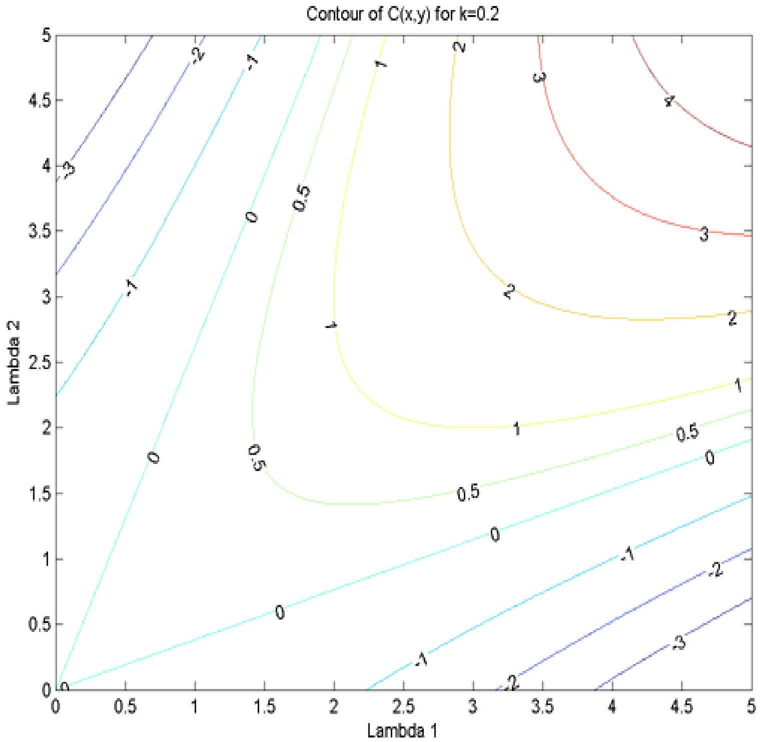
Measure of "cornerness"

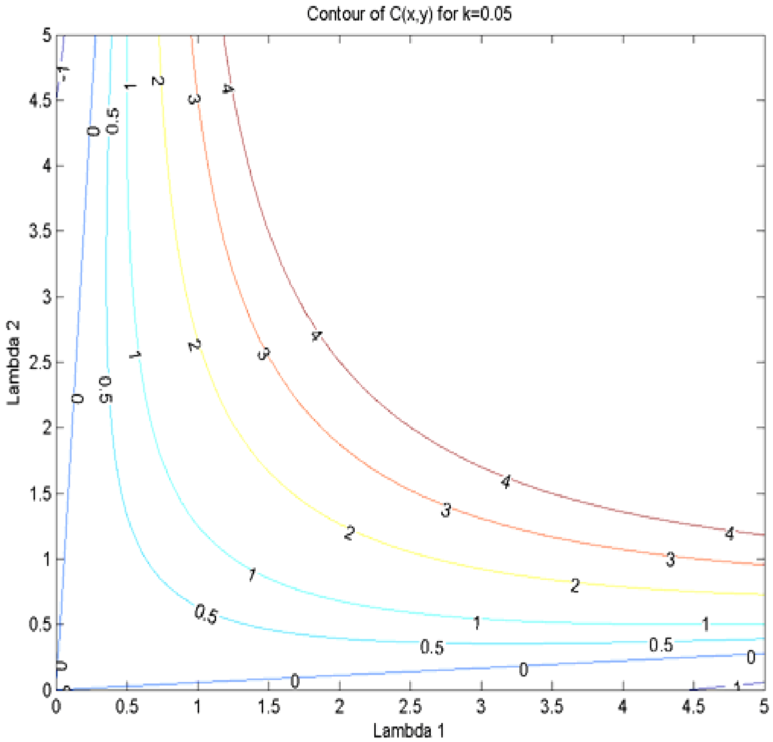
$$\begin{aligned} C(x,y) &= \det(\mathbf{M}) - k \cdot \left(trace(\mathbf{M})\right)^2 \\ &= \lambda_1\lambda_2 - k\cdot(\lambda_1 + \lambda_2) \end{aligned}$$

[Harris, Stephens, 1988]



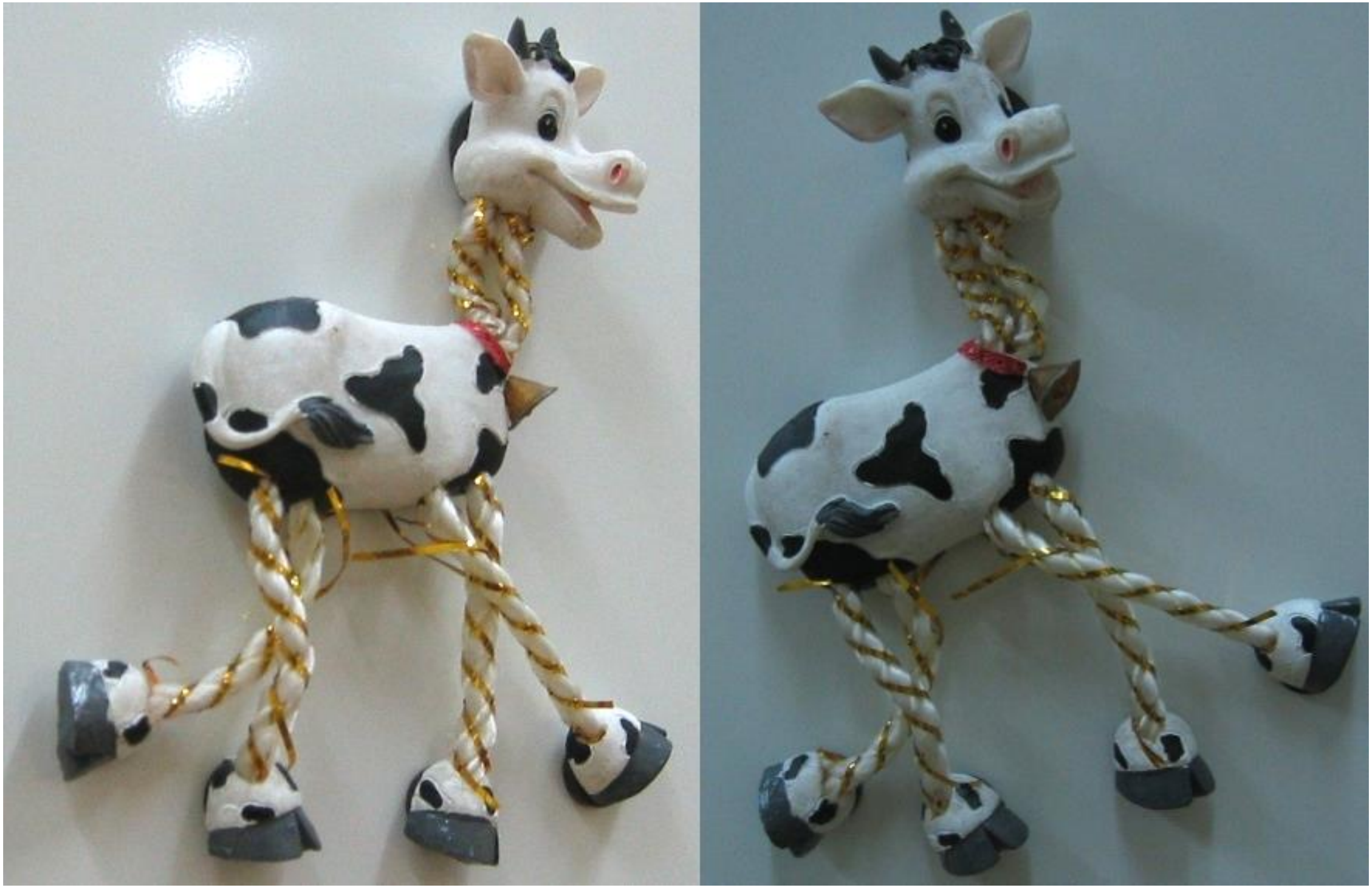
Contour plot of Harris cornerness


Contour of C(x,y) for k=0.2

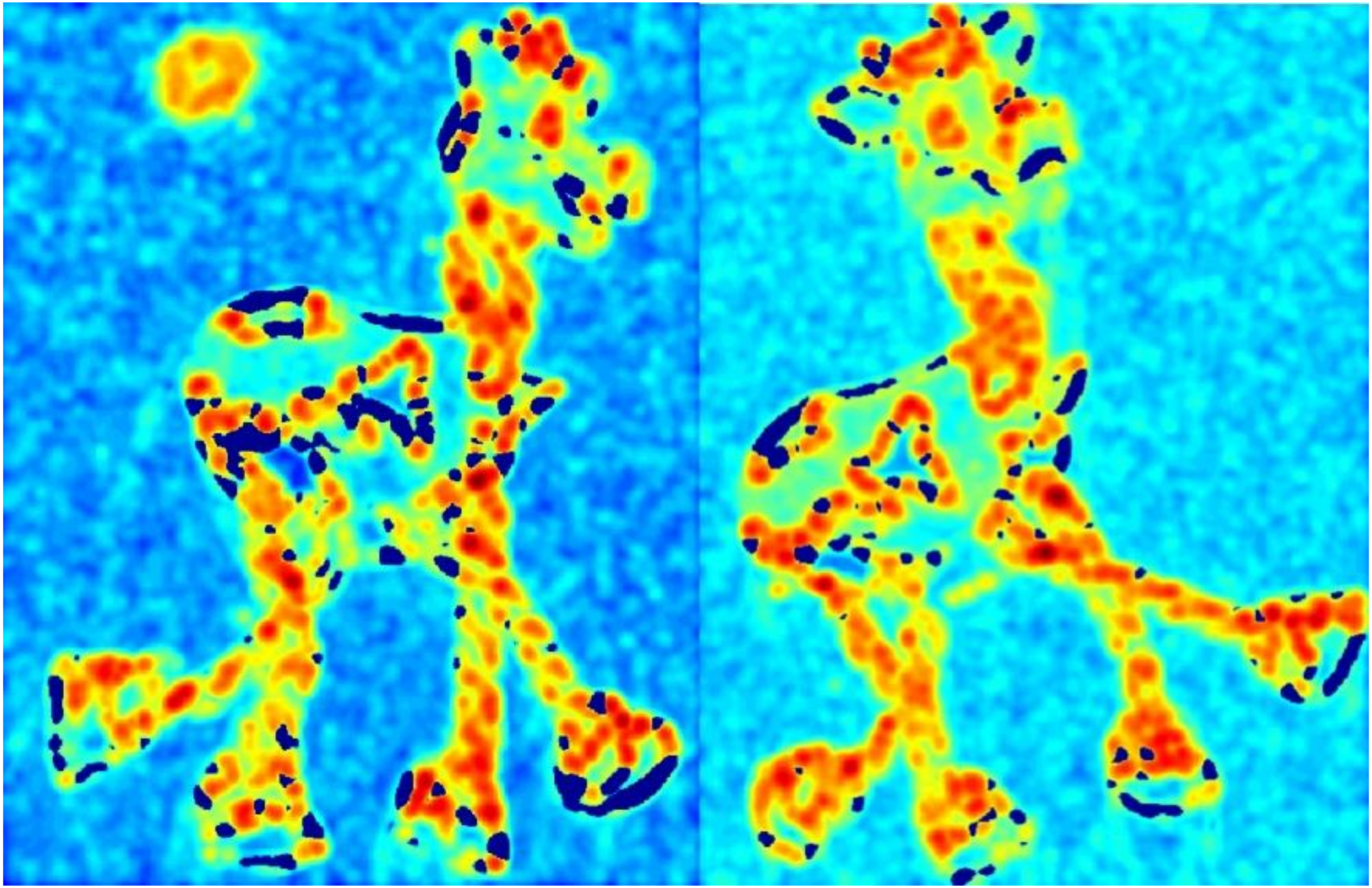

Contour of C(x,y) for k=0.05

$$C(x, y) = \det(\mathbf{M}) - k \cdot \left(trace(\mathbf{M})\right)^2$$
$$= \lambda_1 \lambda_2 - k \cdot \left(\lambda_1 + \lambda_2\right)$$

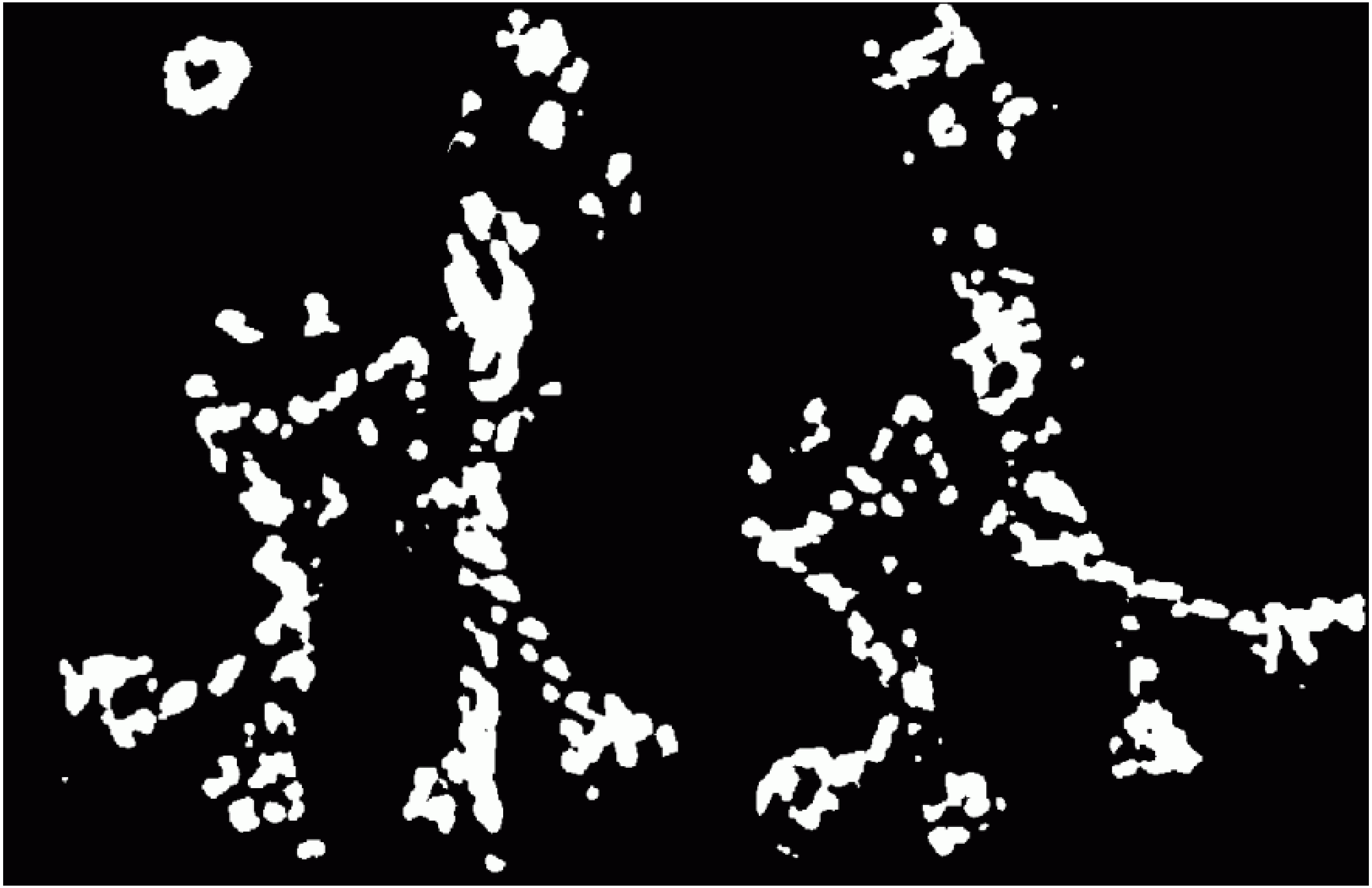
Keypoint Detection: Input



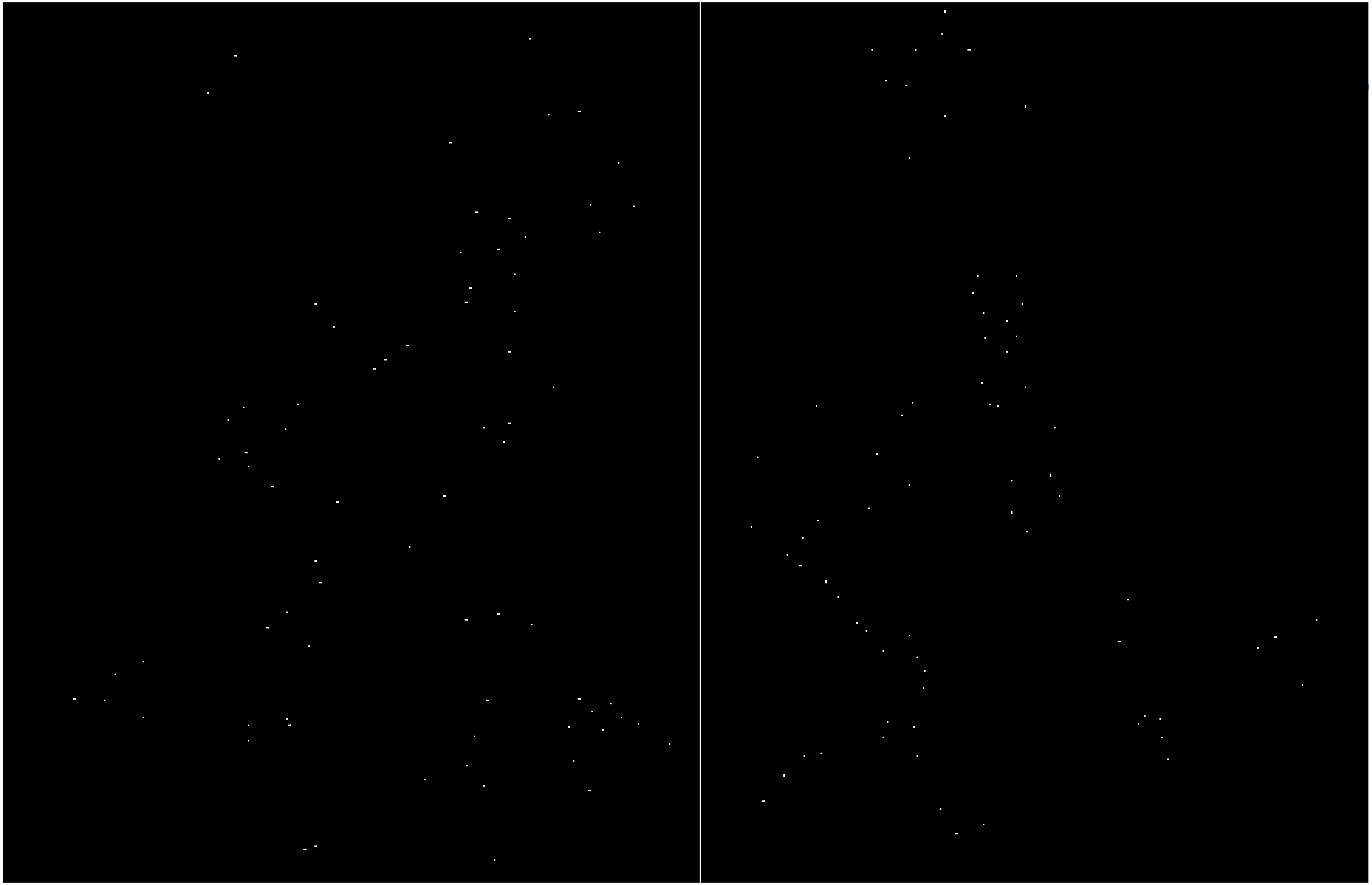
Harris cornerness



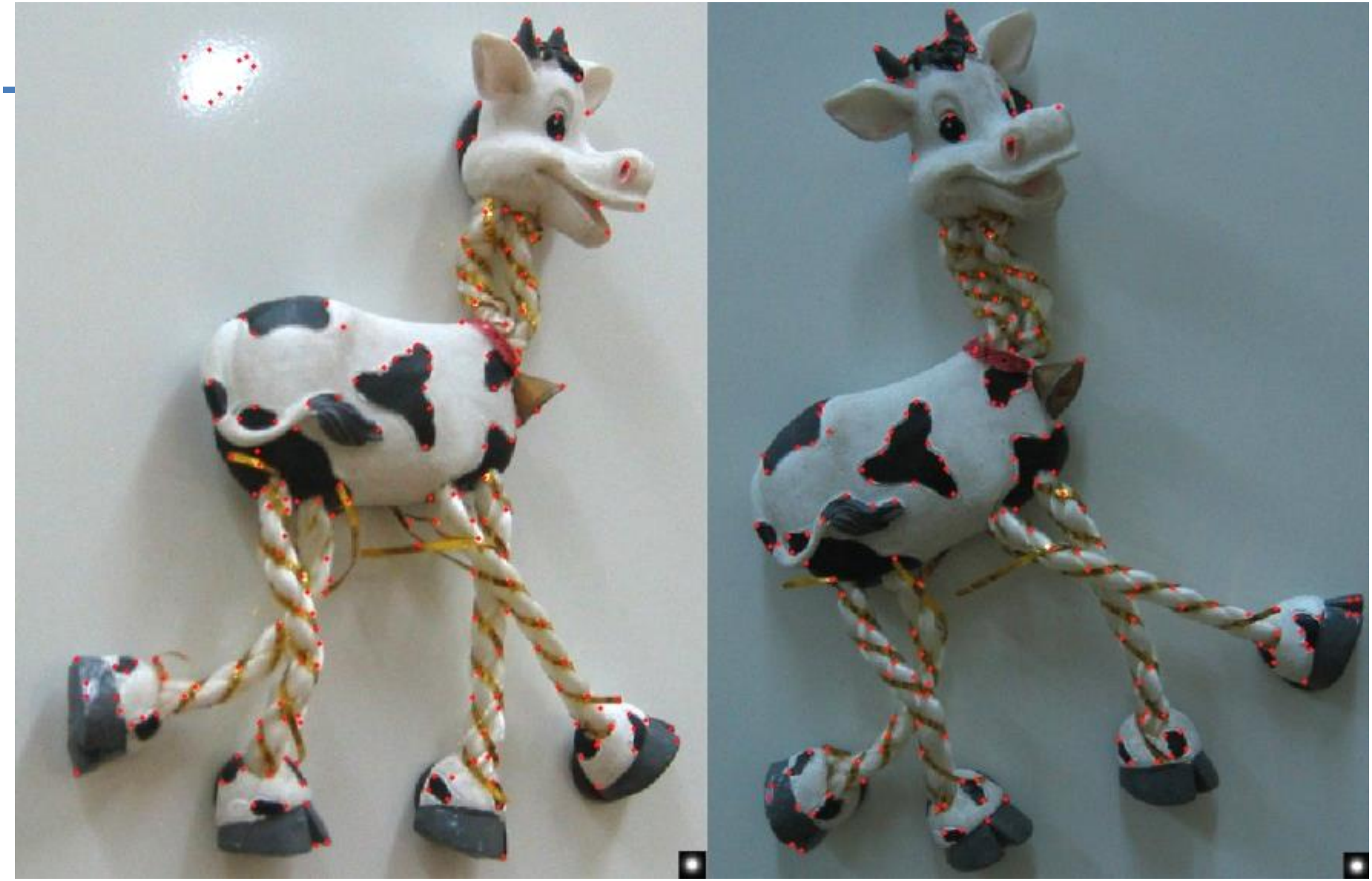
Thresholded cornerness



Local maxima of cornerness



Superimposed keypoints



Better localization of corners

- Give more importance to central pixels by using Gaussian weighting function

$$\mathbf{M} = \sum_{(x,y)\in window} G(x-x_o, y-y_o, \sigma)\begin{bmatrix} f_x^2(x,y) & f_x(x,y)\,f_y(x,y) \\ f_x(x,y)\,f_y(x,y) & f_y^2(x,y) \end{bmatrix}$$

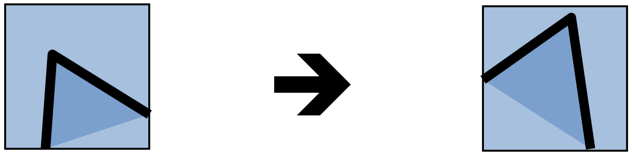
e.g. 5x5,$\sigma = 0.7$

- Compute subpixel localization by fitting parabola to *cornerness* function

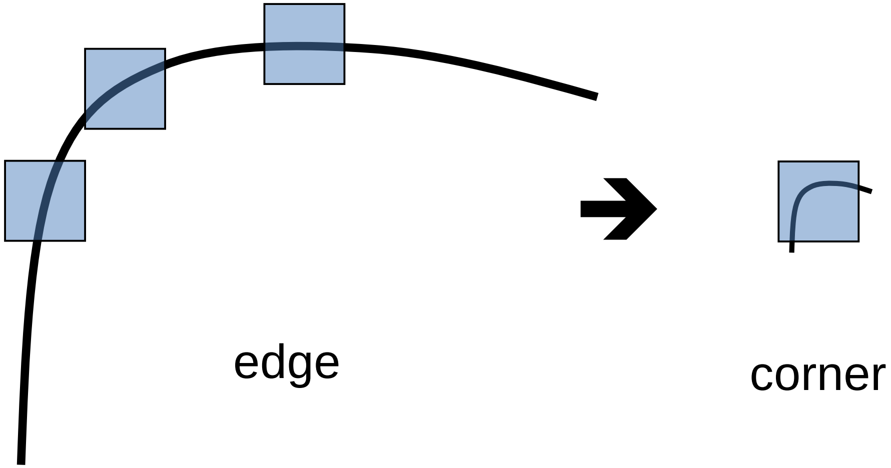
Robustness of Harris corner detector

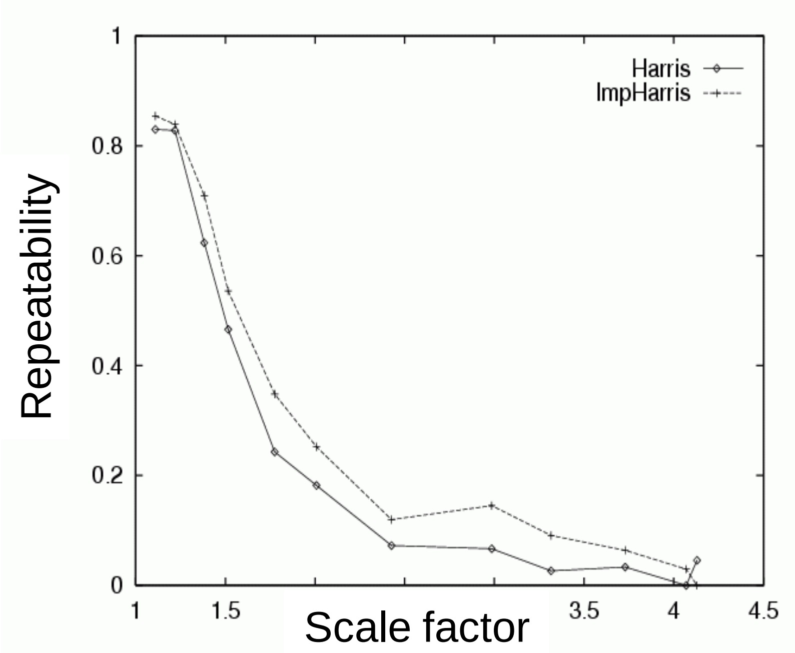
- Invariant to brightness offset: $f(x,y) \rightarrow f(x,y) + c$

- Invariant to shift and rotation



- Not invariant to scaling



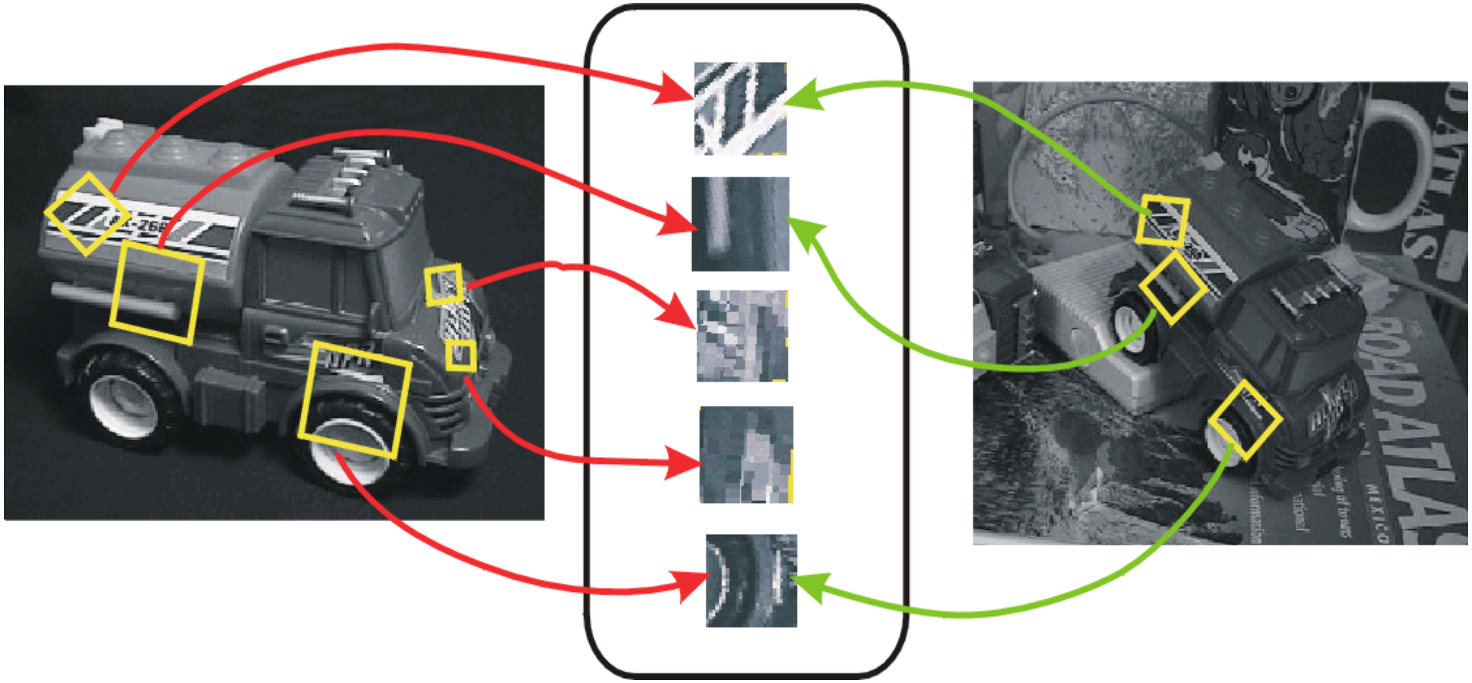


[Schmid, 2000]

Lowe's SIFT features

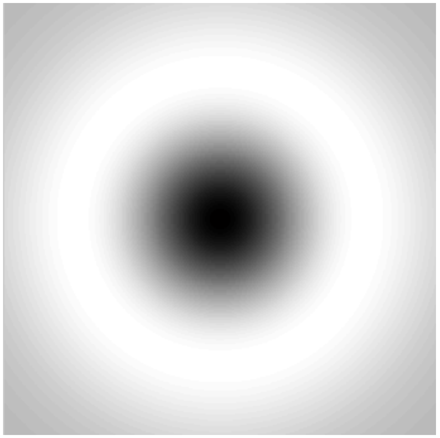
(Lowe, ICCV99)

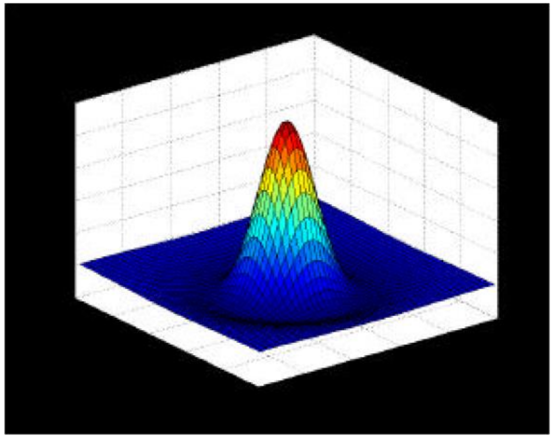
Recover features with position, orientation and scale



Position

- Look for strong responses of DoG filter (Difference-Of-Gaussian)
- Only consider local maxima

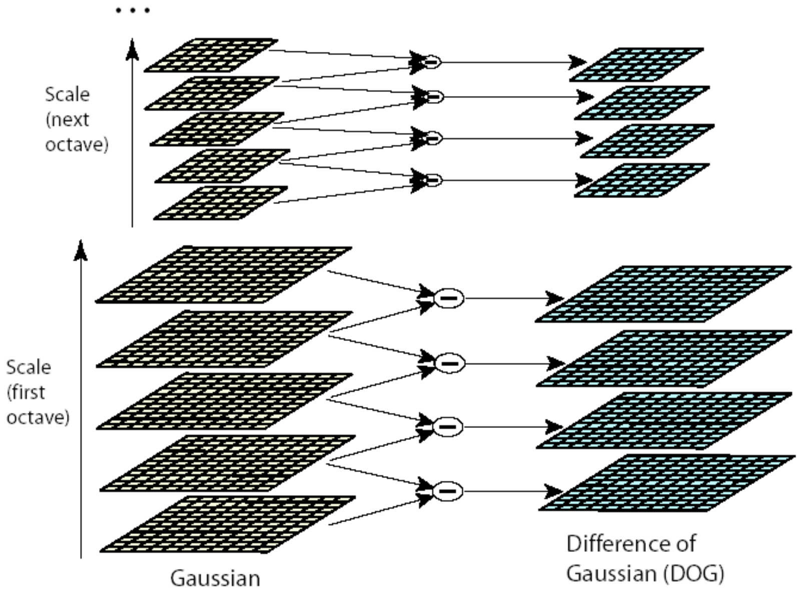


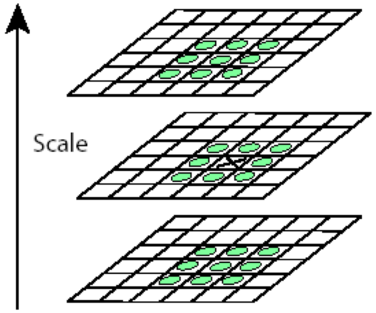


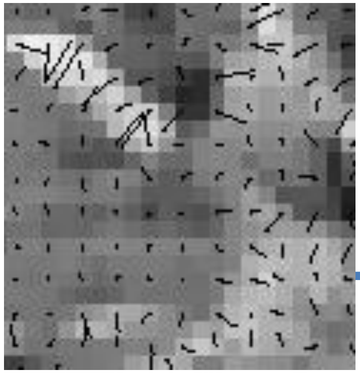
$$\mathrm{DOG}(x,y) = \frac{1}{k} e^{-\frac{x^2+y^2}{(k\sigma)^2}} - e^{-\frac{x^2+y^2}{\sigma^2}} \qquad k = \sqrt{2}$$

Scale

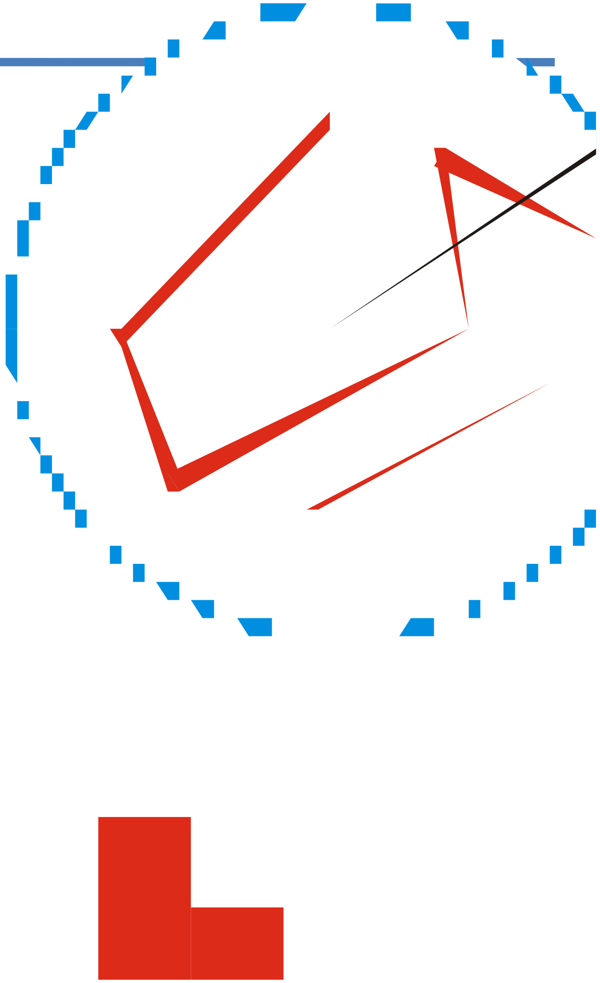
- Look for strong responses of DoG filter (Difference-of-Gaussian) over scale space
- Only consider local maxima in both position and scale
- Fit quadratic around maxima for subpixel accuracy







Orientation



- Create histogram of local gradient directions computed at selected scale
- Assign canonical orientation at peak of smoothed histogram
- Each key specifies stable 2D coordinates (x, y, scale, orientation)

Minimum contrast and “cornerness”

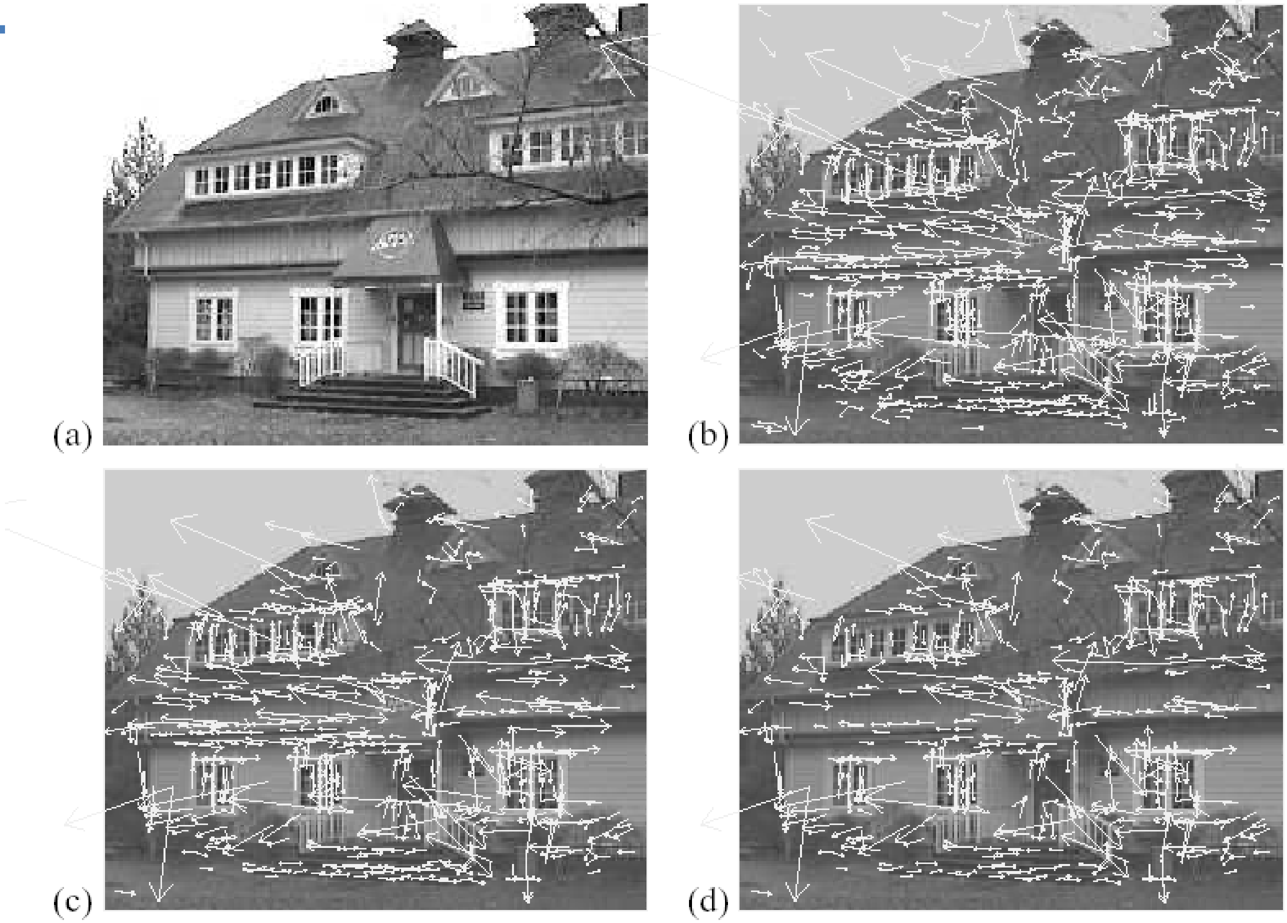
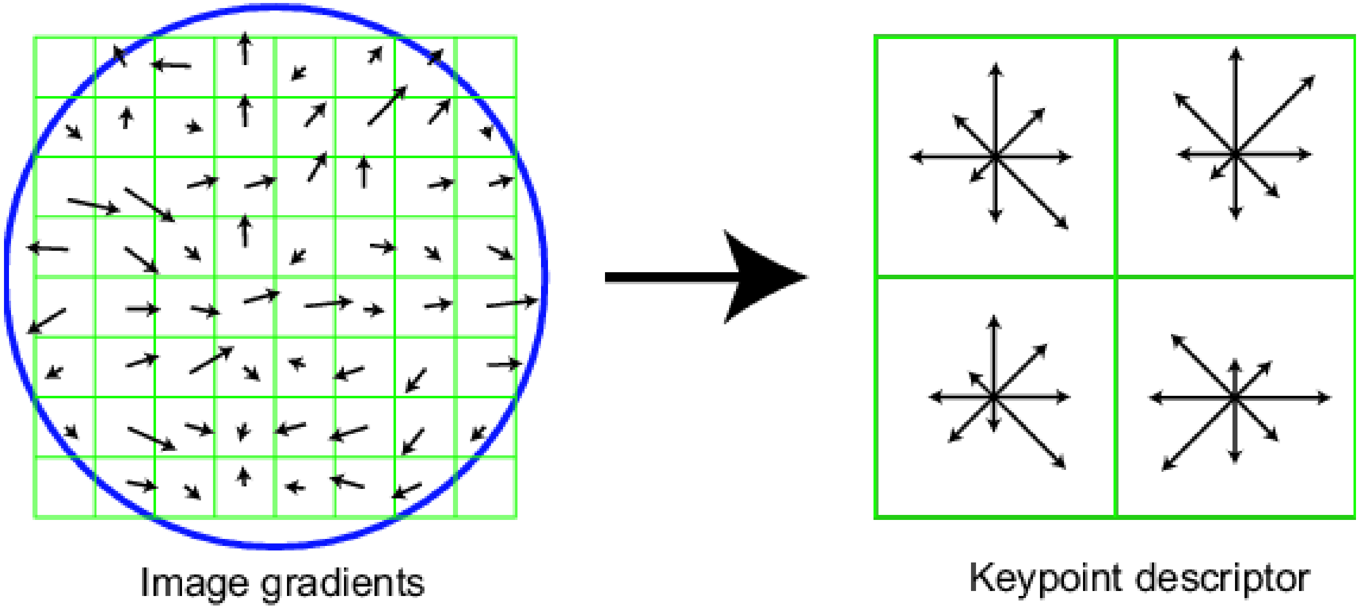


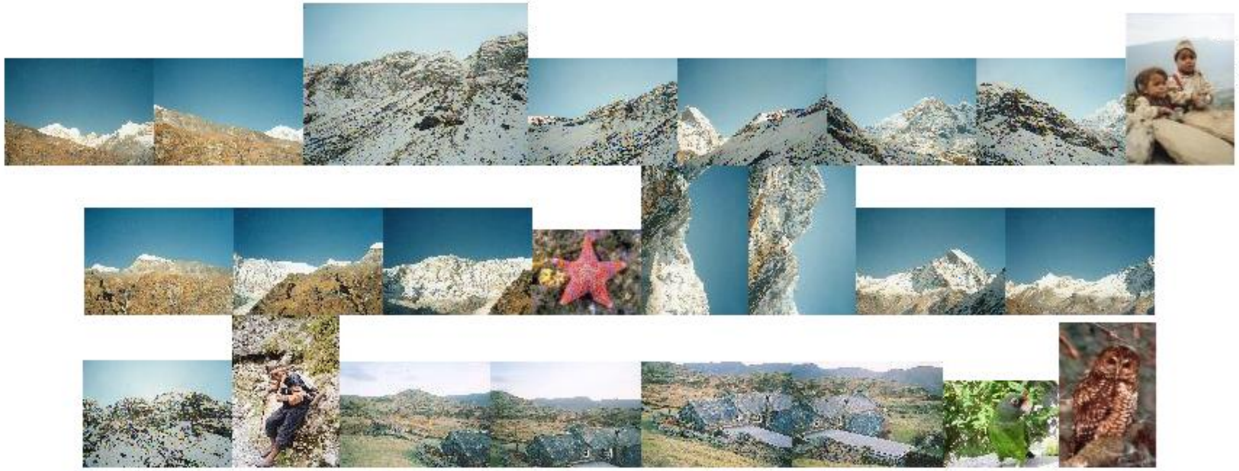
Figure 5: This figure shows the stages of keypoint selection. (a) The 233x189 pixel original image. (b) The initial 832 keypoints locations at maxima and minima of the difference-of-Gaussian function. Keypoints are displayed as vectors indicating scale, orientation, and location. (c) After applying a threshold on minimum contrast, 729 keypoints remain. (d) The final 536 keypoints that remain following an additional threshold on ratio of principle curvatures.

SIFT descriptor

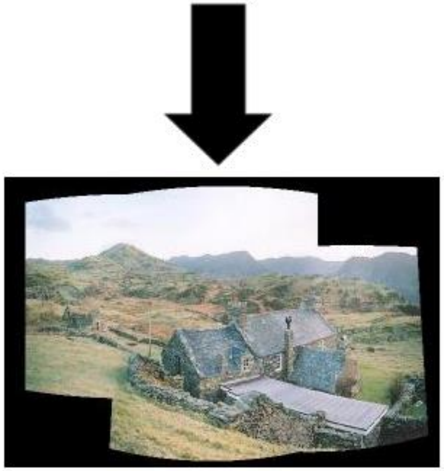
- Thresholded image gradients are sampled over 16x16 array of locations in scale space
- Create array of orientation histograms
- 8 orientations x 4x4 histogram array = 128 dimensions



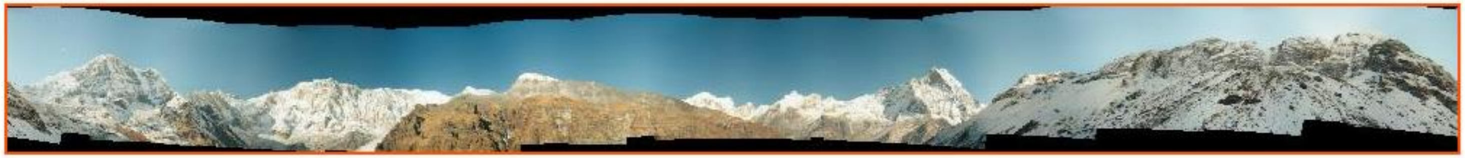
Example 1



Input images (zip 1.1Mb)



Output panorama 1



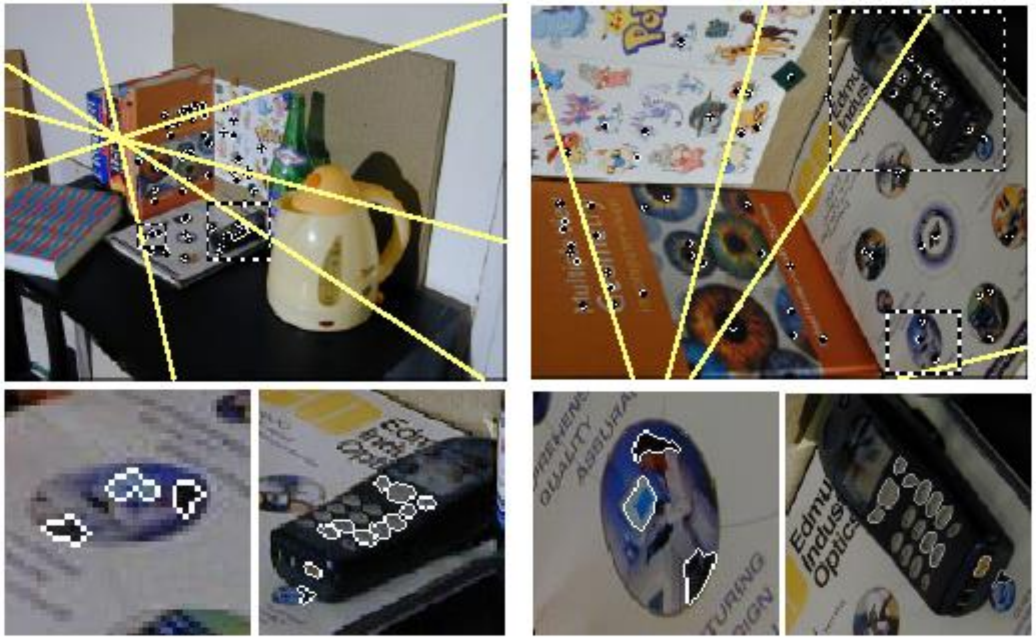
Output panorama 2 : Image | Panorama

http://www.cs.ubc.ca/~mbrown/autostitch/autostitch.htm

http://cvlab.epfl.ch/~brown/autostitch/autostitch.html

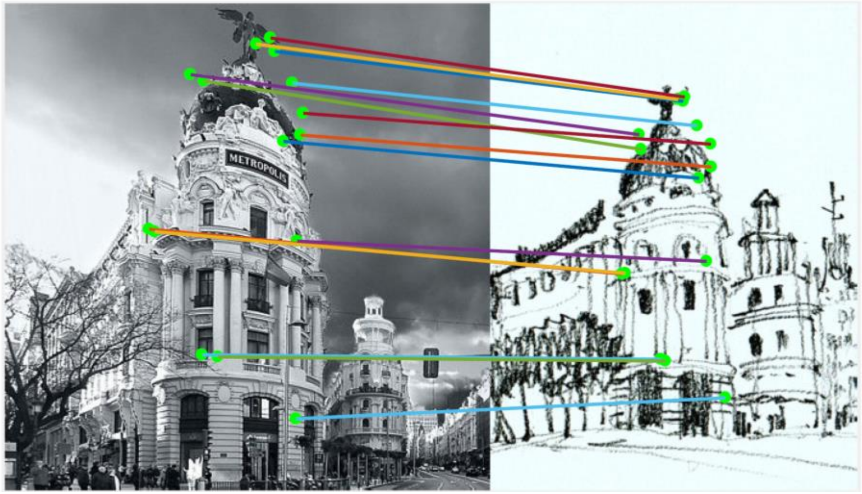
Matas et al.' s maximally stable regions

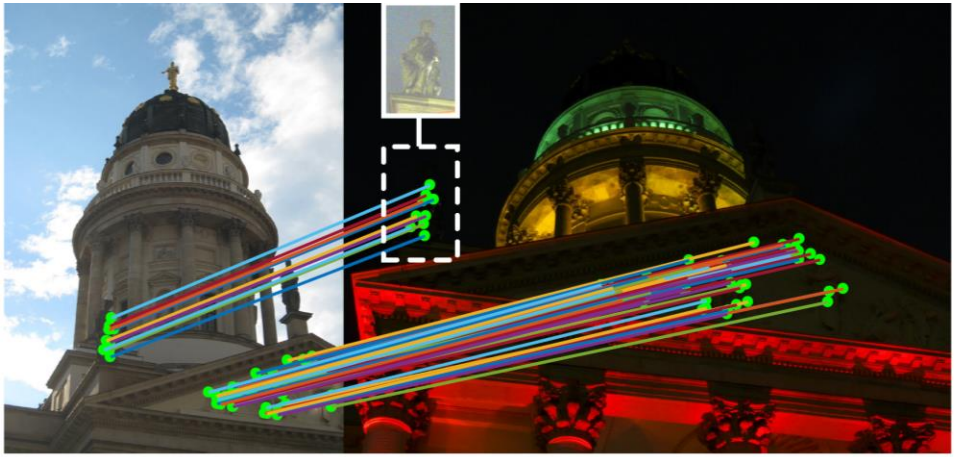
- Look for extremal regions



http://cmp.felk.cvut.cz/~matas/papers/matas-bmvc02.pdf

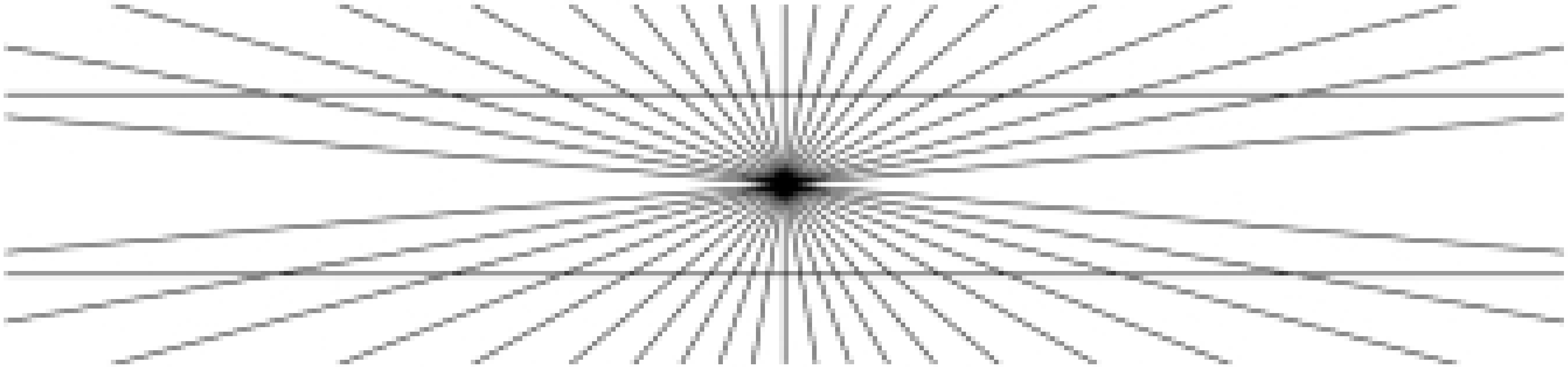
Image features in the era of deep learning





Dusmanu et al., D2-Net: A Trainable CNN for Joint Description and Detection of Local Features, CVPR 2019

Next week:
Fourier transform



Video