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# Edge Detection

Leonhard Applis

TH Nürnberg

05.11.2018

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Figure: Felix

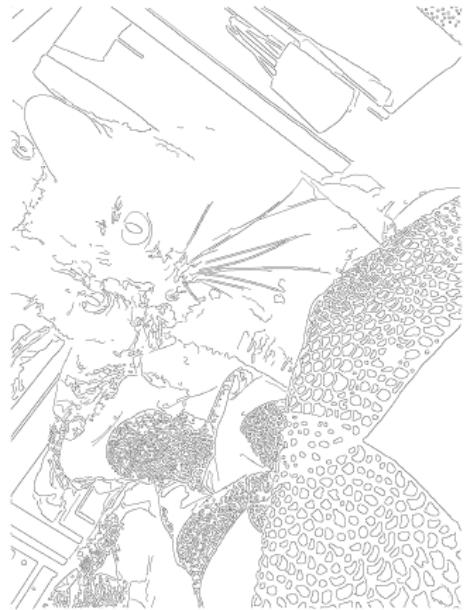


Figure: Felix's Edges

# Problem I: Contrast



**Figure:** High Contrast Felix



**Figure:** Low Contrast Felix

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# Problem II: Smoothness



Figure: Smooth Felix

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# Problem III: Noise



Figure: Salted Felix

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# Definition

In Image Processing, an edge can be defined as a set of contiguous pixel positions where an abrupt change of intensity, gray- or color-values occur. Edges represent boundaries between objects and background. Sometimes, the edge-pixel-sequence may be broken due to insufficient intensity difference.(Malay K. Pakhira )

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# Requirements

- ① color values known (for example only grayscale)
- ② picture scale known
- ③ loaded as pixelmatrix

# One dimensional approach

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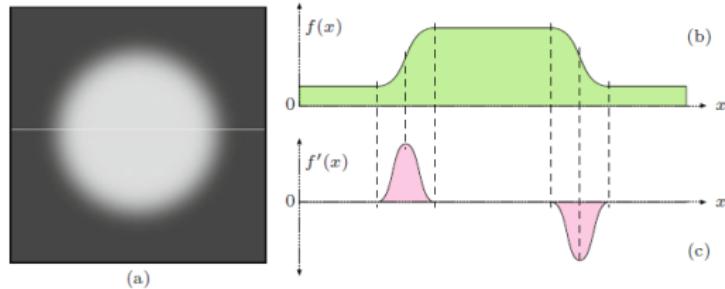


Figure: One dimensional image function and derivation

Only applicable with known, steady functions

# Approximating discrete derivation

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Problem: the image function is discrete, therefore we need to approximate the derivation

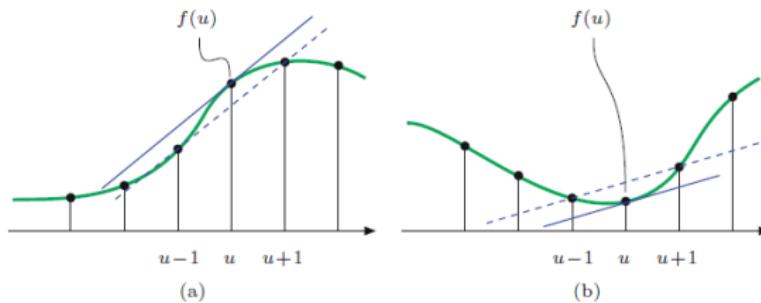


Figure: Approximation of the derivation for discrete imagefunctions

$$\frac{df}{dx}(u) \approx \frac{f(u+1) - f(u-1)}{(u+1) - (u-1)} = \frac{f(u+1) - f(u-1)}{2}$$

# Two dimensional approach

If working with full images, we got two dimensions and therefore two partial derivations:

$$I_x = \frac{\partial I}{\partial x}(u, v), I_y = \frac{\partial I}{\partial y}(u, v)$$

the **gradient** at the point  $(u, v)$  is

$$\nabla I(u, v) = \begin{pmatrix} I_x(u, v) \\ I_y(u, v) \end{pmatrix}$$

And the **magnitude** is

$$|\nabla I| = \sqrt{I_x^2 + I_y^2}$$

# Example

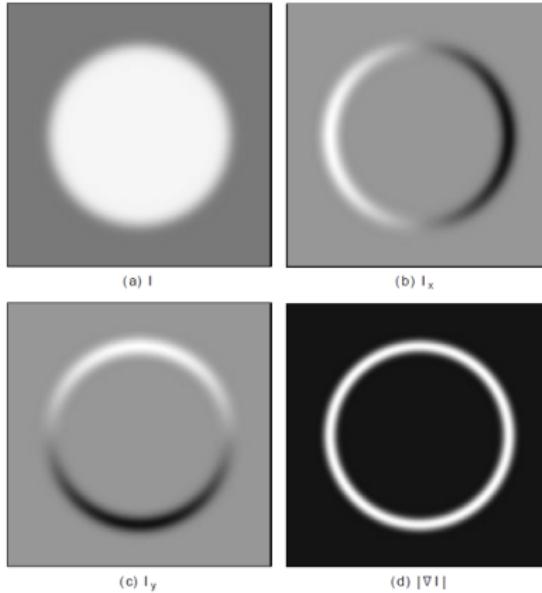


Figure: Visualisation of simple gradient-based edgedetection

# Example with Felix



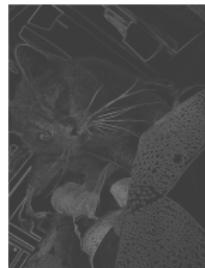
(a)  $I$



(b)  $I_x$



(c)  $I_y$



(d)  $|\nabla I|$

Figure: Simple Filters applied to Felix<sup>1</sup>

<sup>1</sup> All images have a 50% increased brightness

# Implementation with filters

Expressing the gradient as a *linear filter* is simple:

$$I_x = [-0.5 \quad 0 \quad 0.5]$$

$$I_y = \begin{bmatrix} -0.5 \\ 0 \\ 0.5 \end{bmatrix}$$

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# Prewitt Operator

Idea: Include neighborhood

$$H_x^P = \begin{bmatrix} -1 & 0 & 1 \\ -1 & 0 & 1 \\ -1 & 0 & 1 \end{bmatrix} \quad H_y^P = \begin{bmatrix} -1 & -1 & -1 \\ 0 & 0 & 0 \\ 1 & 1 & 1 \end{bmatrix}$$

$$\nabla I^P(u, v) \approx \frac{1}{6} \cdot \begin{pmatrix} (I * H_x^P)(u, v) \\ (I * H_y^P)(u, v) \end{pmatrix}$$

# Sobel

Idea: Include neighbourhood but weight center more

$$H_x^S = \begin{bmatrix} -1 & 0 & 1 \\ -2 & 0 & 2 \\ -1 & 0 & 1 \end{bmatrix} \quad H_y^S = \begin{bmatrix} -1 & -2 & -1 \\ 0 & 0 & 0 \\ 1 & 2 & 1 \end{bmatrix}$$

$$\nabla I^S(u, v) \approx \frac{1}{8} \cdot \begin{pmatrix} (I * H_x^S)(u, v) \\ (I * H_y^S)(u, v) \end{pmatrix}$$

# Comparison with Felix

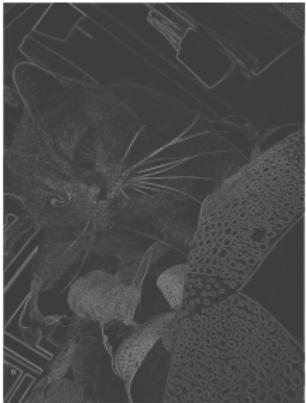


Figure: Simple edge filter<sup>a</sup>

<sup>a</sup>Only the first Picture has increased brightness

# Evaluations

**general magnitude:**  $E(u, v) = \sqrt{I_x^2(u, v) + I_y^2(u, v)}$   
holds for every Operator

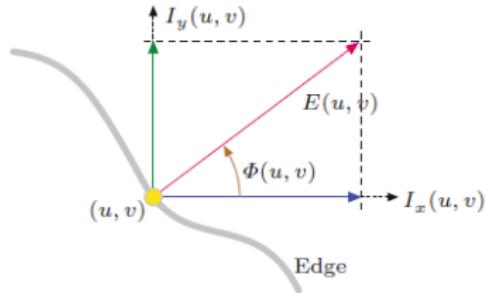


Figure: Visualisation of edge direction

$$\Phi(u, v) = \tan^{-1} \left( \frac{I_y(u, v)}{I_x(u, v)} \right) = \arctan(I_x(u, v), I_y(u, v))$$

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