

```
% 6. Run the feature-based matching object detection on the images from problem (1).
```

```
% read images
% Read the target image containing a cluttered scene.
sceneImage = imread('./q6_image/scene.jpg'); % './q6_image/example_scene.jpg'
sceneImage = rgb2gray(sceneImage); % in some versions, using im2grpy(frameRGB)
% figure;
% imshow(sceneImage);
% title('Image of a Cluttered Scene');
```

```
% Read the reference image containing the object of interest.
boxImage = imread('./q6_image/box.jpg'); % './q6_image/example_box.jpg'
boxImage = rgb2gray(boxImage);
% figure;
% imshow(boxImage);
% title('Image of a Box');
```

```
%% Step-2: Detect feature points in both images.
boxPoints = detectSURFFeatures(boxImage);
scenePoints = detectSURFFeatures(sceneImage);

% Visualize the strongest feature points found in the target image.
figure;
imshow(boxImage);
title('100 Strongest Feature Points from Box Image');
hold on;
plot(selectStrongest(boxPoints, 100));
```

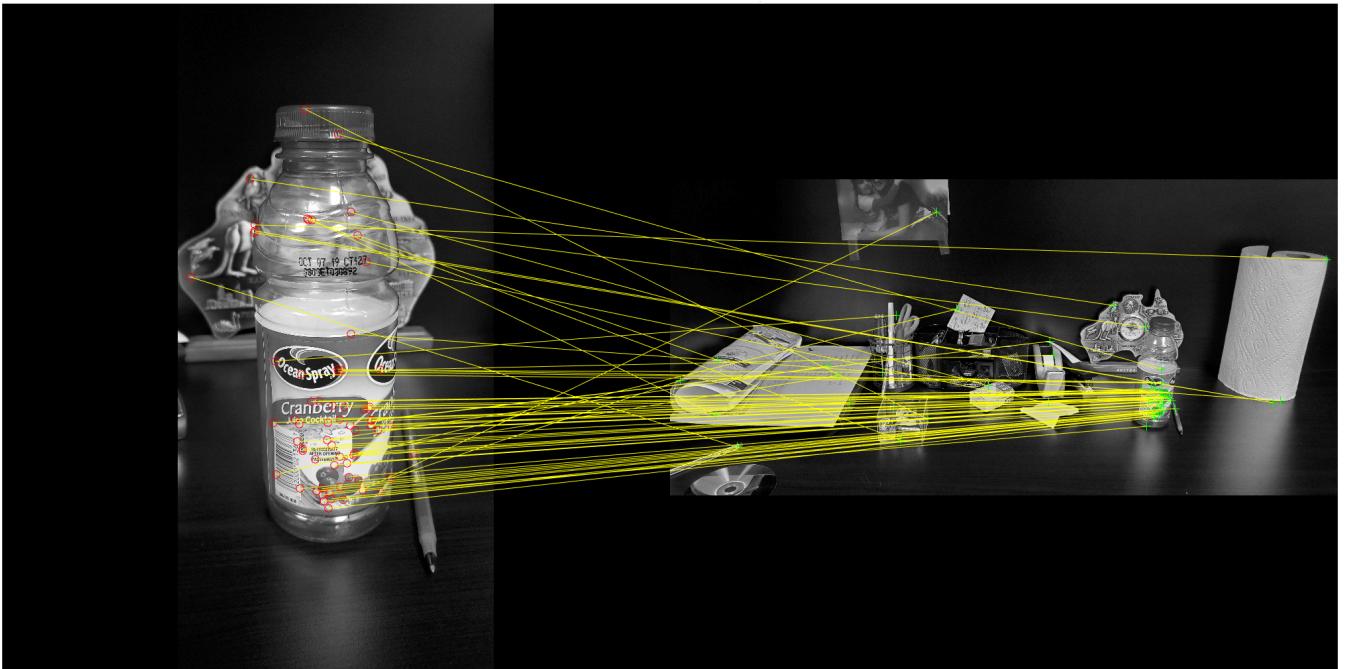


```
% Visualize the strongest feature points found in the target image.  
figure;  
imshow(sceneImage);  
title('300 Strongest Feature Points from Scene Image');  
hold on;  
plot(selectStrongest(scenePoints, 300));
```



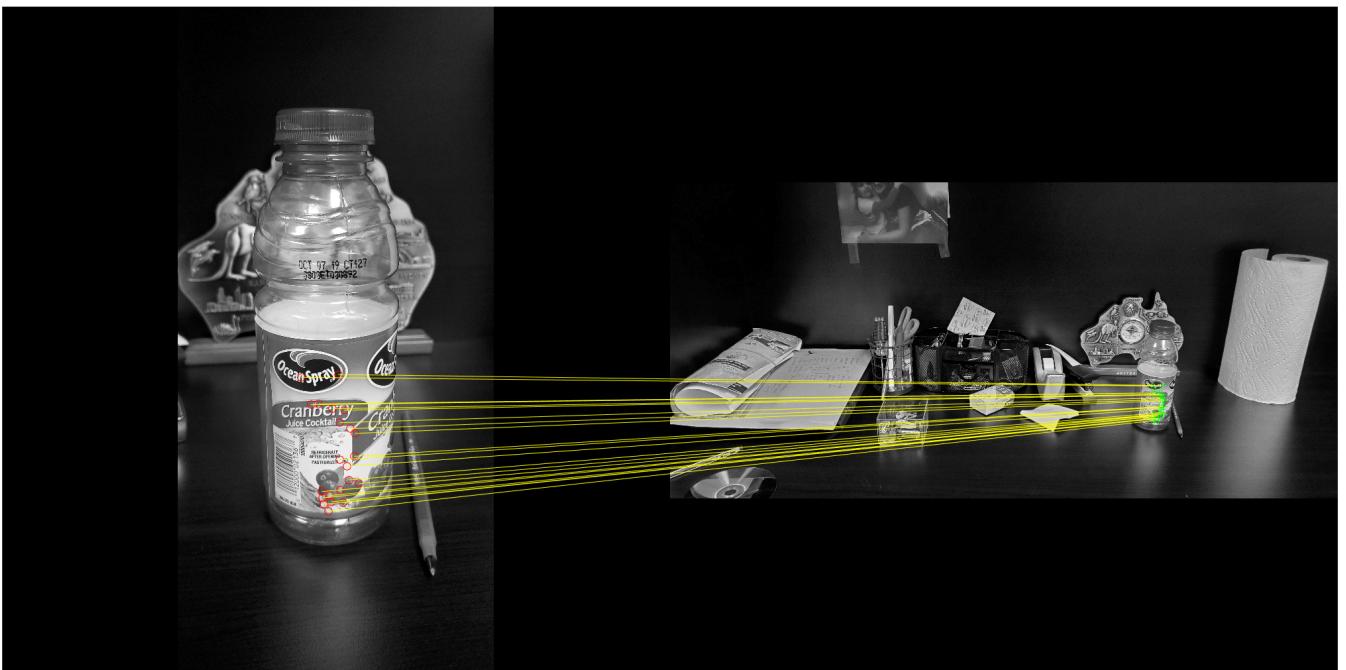
```
% Step-3: Extract feature descriptors at the interest points in both images.  
[boxFeatures, boxPoints] = extractFeatures(boxImage, boxPoints);  
[sceneFeatures, scenePoints] = extractFeatures(sceneImage, scenePoints);
```

```
% Step-4: Match the features using their descriptors.  
boxPairs = matchFeatures(boxFeatures, sceneFeatures);  
  
% Display putatively matched features.  
matchedBoxPoints = boxPoints(boxPairs(:, 1), :);  
matchedScenePoints = scenePoints(boxPairs(:, 2), :);  
figure;  
showMatchedFeatures(boxImage, sceneImage, matchedBoxPoints, ...  
    matchedScenePoints, 'montage');  
title('Putatively Matched Points (Including Outliers)');
```



```
% Step 5: Locate the Object in the Scene Using Putative Matches
[tform, inlierBoxPoints, inlierScenePoints] = estimateGeometricTransform(matchedBoxPoints, matc

figure;
showMatchedFeatures(boxImage, sceneImage, inlierBoxPoints, ...
    inlierScenePoints, 'montage');
title('Matched Points (Inliers Only)');
```



```
% Get the bounding polygon of the reference image.
boxPolygon = [1, 1;... % top-left
              size(boxImage, 2), 1;... % top-right
              size(boxImage, 2), size(boxImage, 1);... % bottom-right
              1, size(boxImage, 1);... % bottom-left
              1, 1]; % top-left again to close the polygon

% Transform the polygon into the coordinate system of the target image.
% The transformed polygon indicates the location of the object in the scene.
newBoxPolygon = transformPointsForward(tform, boxPolygon);
```

```
% Display the detected object.
figure;
imshow(sceneImage);
hold on;
line(newBoxPolygon(:, 1), newBoxPolygon(:, 2), 'Color', 'y');
title('Detected Box');
```

