Project Report

Edge Detection and Character Recognition

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**Abstract**: Edge detection involves extracting the edges or outlines of an image. An edge exists when there is a sharp change in pixel intensities (image brightness) of an image i.e. there is a discontinuity in the image intensity function. Edge detection is important because it can provide us with information about the events and changes in the properties of the world. Discontinuities in image brightness can indicate a change in depth, a change in surface orientation, a change in the material’s properties, and/or a variation in scene illumination. Edge detection can also be used in image enhancement, and this will be one application of edge detection in our project. This project involves an exploration and analysis of the different types of edge detectors and a comparison will be made of the different types of methods. In our project we will develop a demonstration that shows the different types of edge detectors. The user can test our various edge detector algorithms using various types of images: images of the real world, images of computer generated shapes, and the user can even use his/her image. The user can choose to do edge detection with or without noise, and can even experiment with different types of smoothing filters. It is our hope that this demo will educate and generate curiosity and interest in edge detection. It is our intention to provide a comprehensive package about edge detection, and the user can explore the different factors of edge detection in its various permutations. The result of our algorithms will then be applied to image enhancement. An image can be enhanced by adding the edges back to the original image, and this process is called crispening. We will also apply of edge detection algorithm to character recognition.

**1. Introduction**

Edge detection is an important aspect of image processing because it allows us to extract information from an image. The information extracted can tell us about events and changes in the properties of the real world. Edge detection can allow us to filter out the relevant information in an image and this can significantly reduce the amount of data that has to be processed. Edge detection involves identifying the edges or outlines of objects in an image and determining its orientation [2]. An edge exists when there is a sharp change in the image intensity or image brightness; i.e. a discontinuity in the brightness occurs from one pixel to the next. However, edge detection is not a simple matter. Images may have false edges, or they may contain edges that have been fragmented. Some images may have a gradual change in intensities and as such would not produce very good edges, or the image can contain many small edges. Additionally, during acquisition, the image can become corrupted by noise. One of the goals of edge detection is to locate the edges most likely generated by the scene elements rather than the noise of the image. This is because image noise can cause intensity variations which can result in spurious edges.

A good edge detector should suppress most of the “false” edges without destroying the true edges. It should also enhance the edges; i.e. increase the pixel values of the edges. In addition, the edge detector should be able to differentiate between the edges caused by noise and the actual edges of the image. This can be done by thinning the wide edges: if it is not a maximum value it is suppressed (non-maximum suppression), and by thresholding: a minimum value is established to declare a local maximum at the edge.

The goal of our project is to investigate the different types of edge detectors. Using the information gleaned, we will create a demonstration program that will use our edge detection algorithms. We will perform edge detection on various types of images: images of the real world, computer generated images, images with different types of noise, and images that have been smoothed by filters of different sizes and types. We will then use the extracted edges to enhance the image. Finally we will use our edge detection algorithms to recognize characters of the alphabet.

**2. Theory of Edge Detection**

Edges can be generated from different physical sources. But regardless of how the edge was generated, the resultant edge exhibits varying degrees of discontinuities in image intensity [2]. Physical edge sources may arise from different surface properties such as change in color of an object, reflective properties, and change in texture of the object. Edges may also be formed as a result of discontinuities in the distance and the object’s orientation. Edges may also be caused by shadows.

There are many different types of edges; an edge may be a step function, it may be a ridge, a ramp function, or a roof edge (triangular) function. Additionally the width of the edge can vary infinitely. Identifying an edge amounts to finding the change in intensity of the image. As such we can find the first and second derivative of the image intensity function. The first derivative of the image intensity functions produces a high where an edge exists. The second derivative identifies the zero-crossings of the image intensity function.

2.1 First order Edge Filter

If *I(c,r)* represents the image intensity at pixel *(c,r)*, then the first order image gradient can be approximated by:

(2-1)

where the partial derivatives are numerically approximated,

(2-2)

(2-3)

Where *hx* computes the first order horizontal image derivative, and hy computes the first order vertical image derivative. And the gradient and magnitude can be defined by:

(2-4)

From (2-4) and (2-2)

(2-6)

(2-7)

Where gx and gy are the image gradients in the x and y directions respectively, and \* represents a 2D convolution operation.

(2-8)

where θ represents the steepest slope direction

These formulae allow us to compute the image derivatives by convolution. Each method of edge detection has its characteristic mask. These masks are sometimes called *stencils*.

In our project we have investigated five first order edge detectors. Other types of edge detectors exist, but it is beyond the scope of this project to explore them all. The edge detectors we chose to implement were chosen because of their accuracy, popularity, and ease of implementation. The edge detectors we chose to implement are:

1. The Roberts Cross Edge detector
2. The Prewitt Edge detector
3. The Sobel Edge detector
4. The Scharr Edge detector
5. The Canny Edge detector

2.1.1 The Roberts Cross Edge Detector

The image derivative filters of the Roberts Cross method are:

, (2-6)

Where *hx* computes the first order horizontal image derivative, and hy computes the first order vertical image derivative. If we take the first order derivatives in 45 and 135 degrees, we obtain the Roberts Cross edge operator:

(2-7)

The Roberts Cross method uses the approximation of the gradient to identify an edge. Convolving with the operator in (2-7) computes the sum of the differences between diagonally adjacent pixels and finds the discrete derivative for each pixel. The output of this convolution produces the gradient of the image. This method identifies a change of intensity in the diagonal direction. We can see from (2-7) that the kernel is small and contains only integers so the edges are simple to compute using this method. However, one of the disadvantages of the Roberts Cross method is that is highly sensitive to noise.

2.1.2. The Prewitt Edge Detector

To make our edge detector more robust to noise, we can first preprocess the image to remove some of the noise. This preprocessing is done using a simple smoothing operator. If *s* is the smoothing operator and *h* represents the difference operator, from equations (2-6) and (2-7), we have

(2-8)

which states that the image gradient can more accurately be found by smoothing the image and then applying the image derivative filter. Note that because of the associative property of convolution, equation (2-8) can be rewritten as:

(2-9)

Hence we can see that is the smoothed difference operator. The simplest smoothing operator is the averaging operator and if an image is smoothed with the following impulse response:

(2-10)

and the resulting image is convolved with the first order horizontal derivative hx in equation (2-6), we have the classical horizontal Prewitt operator.

(2-11)

and the vertical Prewitt operator is generated in a similar fashion

(2-12)

The Prewitt edge detector calculates the maximum response of the set of convolution filters (2-9) & (2-10) to find the local edge orientation for each pixel. One kernel is sensitive to edges in the vertical direction and one is sensitive to edges in the horizontal direction.

2.1.3 The Sobel Edge Detector

The Sobel edge detector is relatively inexpensive in terms of computational complexity. This algorithm is based on finding the gradient of the image intensity at each point which gives the direction of the largest possible increase from light to dark and the rate of change in that direction. The result shows how “abruptly” or “smoothly” the image changes at that point. It also shows how likely that part of the image represents an edge and how the edge is likely to be oriented. So the magnitude (likelihood of an edge) calculation is more reliable.

If instead of the simple averaging filter, we choose to smooth the image with a weighted smoothing filter such as:

(2-13)

where the center pixels are weighted more heavily (x2). So if we convolve *s* and *h*, we get:

(2-14)

(2-15)

And these are the kernel for the Sobel operator.

2.1.4 The Scharr Edge Detector

Even though the Sobel operator reduces artifacts associated with a pure central difference operator, it does not have perfect rotational symmetry. The Scharr operator optimizes this property. Scharr operators are formed by an optimization minimizing weighted mean squared angular error in the Fourier domain. The optimization is done using the condition that the resulting filters are numerically consistent. Hence they are derivative kernels as well as symmetrical constraints. The kernels of the Scharr operator are:

(2-16)

(2-17)

2.1.5 The Canny Edge Detector

The Canny edge detector, also known as the optimal edge detector, is probably the most used edge detector. The algorithm is based on an improvement of previously existing edge detectors. Canny Edge detection is performed by doing the following steps:

1. First smooth the image with a Gaussian smoothing filter to remove noise
2. Find the image gradient of each pixel – this highlights the regions with high spatial derivatives
3. Track along these regions and suppress any pixel that is not at a maximum
4. Apply hysteresis – use two thresholds, if the magnitude is below the first threshold, set the current pixel value to zero (make it a non-edge), if the magnitude is above the high threshold, it is determined to be an edge. If there are any magnitudes between the two thresholds, search for a path from this pixel to a pixel with a gradient above the second threshold, if such a path exists, the pixel is defined as an edge, if not, the pixel is defined as a non-edge.

2.2 Second order Edge Filter

The place where the first order image derivative of a step edge is maximum is exactly the place where the second derivative has a zero-crossing. The isotropic generalization of the second derivative in 2D is the Laplacian. The Laplacian of the image intensity *I(c,r)* is:

(2-18)

This Laplacian operation does not provide the strength of the edge point; neither does it give the edge direction. This is typically solved by using the first order image gradient as well. The second order image derivative is more sensitive to noise than the first order image derivative. In our project we explored one second order edge detection algorithm:

**3. Methodology**

**4. Results**

**5. Conclusion**