UNIVERSITY OF KWAZULU-NATAL (HOWARD COLLEGE)

MASTERS THESIS

Discrete Energy Minimisation Optimisation using Graph Cuts for Fluorescence Microscopy

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A thesis submitted in fulfillment of the requirements for the degree of Master of Science in Engineering

in the

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School of Engineering

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Declaration of Authorship

I, Ryan NAIDOO, declare that this thesis titled, "Discrete Energy Minimisation Optimisation using Graph Cuts for Fluorescence Microscopy" and the work presented in it are my own. I confirm that:

- This work was done wholly or mainly while in candidature for a research degree at this University.
- Where any part of this thesis has previously been submitted for a degree or any other qualification at this University or any other institution, this has been clearly stated.
- Where I have consulted the published work of others, this is always clearly attributed.
- Where I have quoted from the work of others, the source is always given. With the exception of such quotations, this thesis is entirely my own work.
- I have acknowledged all main sources of help.
- Where the thesis is based on work done by myself jointly with others, I have made clear exactly what was done by others and what I have contributed myself.

Signed:

Date:

"Thanks to my solid academic training, today I can write hundreds of words on virtually any topic without possessing a shred of information, which is how I got a good job in journalism."

Dave Barry

UNIVERSITY OF KWAZULU-NATAL (HOWARD COLLEGE)

Abstract

Faculty of Engineering
School of Engineering

Master of Science in Engineering

Discrete Energy Minimisation Optimisation using Graph Cuts for Fluorescence Microscopy

by Ryan NAIDOO

The Thesis Abstract is written here (and usually kept to just this page). The page is kept centered vertically so can expand into the blank space above the title too…

Acknowledgements

The acknowledgments and the people to thank go here, don’t forget to include your project advisor…

Contents

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List of Abbreviations

MIS	**M**edical **I**mage **S**egmentation
ACWE	**A**ctive **C**ontours **W**ithout **E**dges
MAP	**M**aximum **A** **P**osteriori
MRF	**M**arkov **R**andom **F**ield
CRF	**C**onditional **R**andom **F**ield
EM	**E**xpectation **M**aximisation
FIFO	**F**irst-**I**n **F**irst-**O**ut
GMM	**G**uassian **M**ixture **M**odelling
MLP	**M**ulti-**L**ayered **P**erceptron
CED	**C**oherence **E**nhancing **D**iffusion
ORI	**O**ptimised **R**otational **I**nvariance
TV	**T**otal **V**ariation

Physical Constants

Speed of Light $c_0 = 2.997\,924\,58 \times 10^{8}\,\mathrm{m\,s^{-1}}$ (exact)

List of Symbols

a	distance	m
P	power	W ($\mathrm{J\,s^{-1}}$)
ω	angular frequency	rad

For/Dedicated to/To my…

Chapter 1

Introduction

1.1 What is Image Segmentation

definition
history/development of the field
types: region, edge
human segmentation -> Gestalt Groupings
Machine segmentation
Good segmentation vs Bad Segmentation
Goal of Image segmentation
Differences between bottom-up and top-down image segmentation
number of labels (2 labels -> binarization or binary segmentation, etc)

1.2 Gestalt Theory of Visual Perception

A psychological view of visual perception. The aim here is to give a brief realisation of the current understandings of human visual perception. Since image segmentation is predominantly guided by subjective human perception, it is wholesome to understand, at least briefly, what human perception is all about; at least to our current understanding.

[It would be good to get a few experts to manually segment the same images and do a similarity comparison. This will prove that even experts in the same field are subject to their own interpretation of an image. Also compare the manual segmentation to people that are not experts in the field. Discuss, how trustworthy are manual segmentations?]

Gestalt[1] - movement in experimental psychology. Developed in Germany We percieve objects as well-origanised patterns rather than seperate components. Gestalt is a theory that the brain operates wholistically, with self-organising tendencies. "The whole is greater than the sum of its parts." Illusory Contours - The Kanisza triangle as figure ground illusory contours. Three main principles: Grouping(proximity, similarity, continuity, closure), Goodness of Figures, Figure/Ground Relationships.

Goodness of Figure, or the Law of Prägnanz [2].

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[1] Gestalt is the German word mean Organised Whole

[2] Prägnanz is the German word for Pregnant, but in the sense of pregnant with meaning, not with child.

Figure/Ground Relationships: Figure-Foreground, Ground-Background, Contours- "belong" to the Figure. Reversible Figure/Ground Relationship.

Problems with Gestalt Theory: - It is a phenomenological approach. - Some terms are vague. E.g What is the simplest organisation?

In addition to these psychology examples find actual medical examples to compensate the importance.

- principles of grouping
- contrast
- good continuity
- context
- closure
- figure and ground
- symmetry and surroundedness
- prägnanz

Contrast When perception is influenced by comparison. Three types:
Brightness Contrast: The center squares are the same shade of gray. The look different because of their contrasting black and white surrounds.
Colour Contrast: The center squares are the same colour, but appear different because of their different contrasting surrounds.
Size Contrast: The two center circles are the same size, but appear different because of the different sized surrounding circles.

FIGURE 1.1: Gestalt contrast brightness

Context When a stimulus can be interpreted in more than one way, the context resolves the ambiguity. Given the ambiguity of certain 2-D figures, the visual system is strongly influenced by the context within which these figures are presented. An example of Gestalt context is seen in Figure **??**.

Figure Ground Separation of an image into figure and ground. What is in front (figure) and what is behind (ground)? There has to be one figure and one ground. Related to occlusion and thus to depth. Less attention is dedicated to the ground.

Closure We tend to see figures as whole even though lines enclosing them are incomplete.

FIGURE 1.2: Gestalt contrast colour

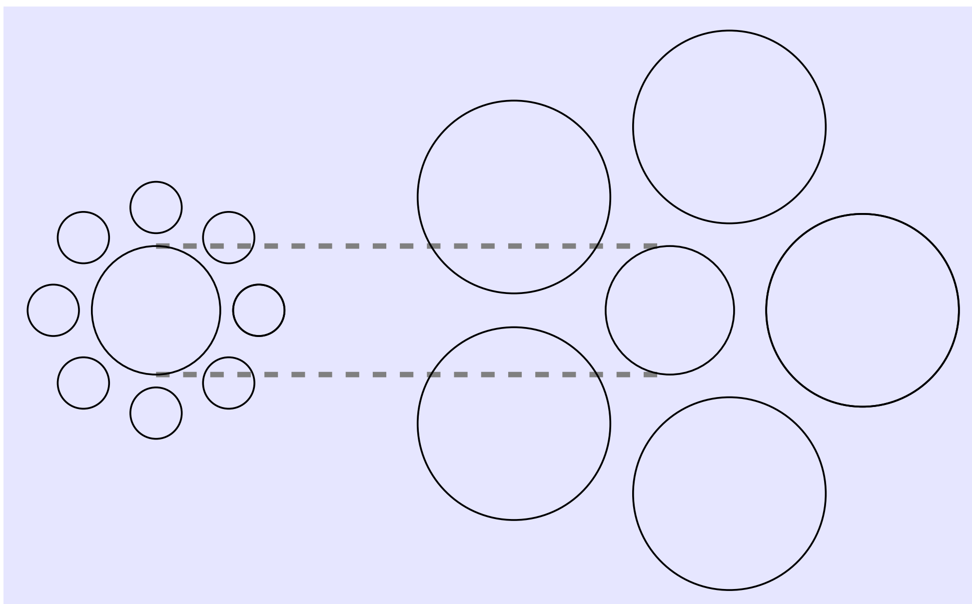

FIGURE 1.3: Gestalt contrast scale

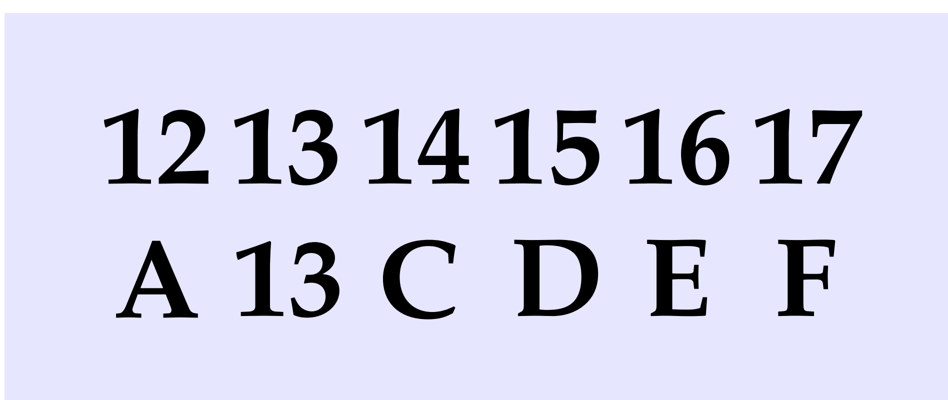

FIGURE 1.4: Gestalt context

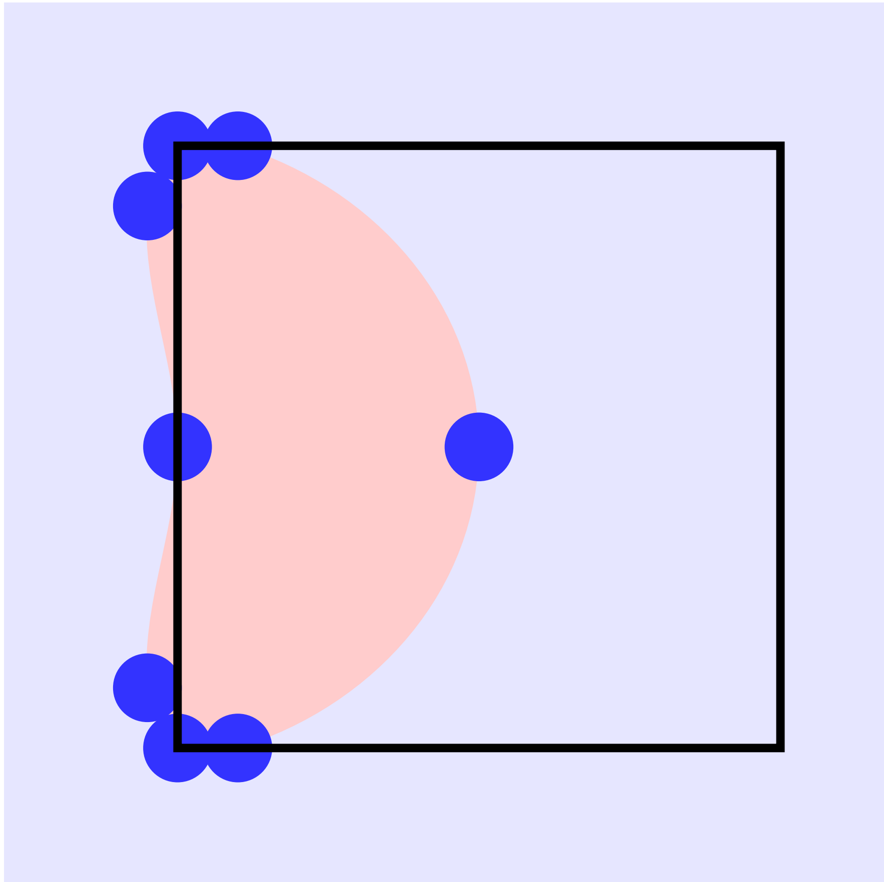

FIGURE 1.5: Gestalt Figure and Ground

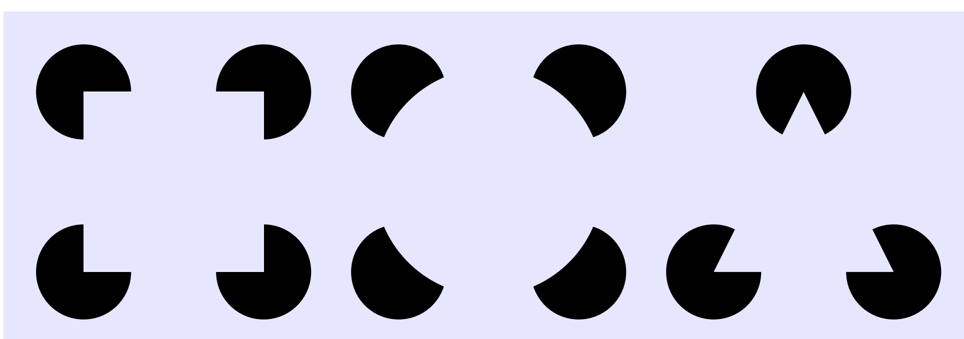

FIGURE 1.6: Gestalt Closure

Good Continuation, or Good Figure Where lines intersect, we tend to see them as continuing along their previous course, rather than suddenly changing direction. As a result we tend to decompose figures into their simplest components.

Perceptual Consistancies 4 types:
Shape Consitency: We tend to see object as holding its essential shape even though the shape of its image changes with our view of it.

Size Consistency: An object appears to retain its essential size event though its image size changes with distance.
Brightness/Lightness Consistency: Object seem to retain about the same brightness or lightness under widely differing levels of illumination.
Colour Consistency: Object appear to retain their essential colour even though illuminated by somewhat differently coloured lights.

Principles of Grouping The principles by which you recognise object as belonging to the same group. They include:
Similarity: Object are recognised as belonging to the same group when they have a similar appearance.
Colour: Object are recognised as belonging to the same group when they have a similar appearance.
Size: Object are recognised as belonging to the same group when they have a similar appearance.
Proximity: We percieve object as belonging to the same group based on their relative distances from one another.
Region: Object are recognised as belonging to the same group when they have a similar appearance.
Connectedness: Object are recognised as belonging to the same group when they have a similar appearance.
Common Fate: We percieve object as belonging to the same group when the same things are happening to them.

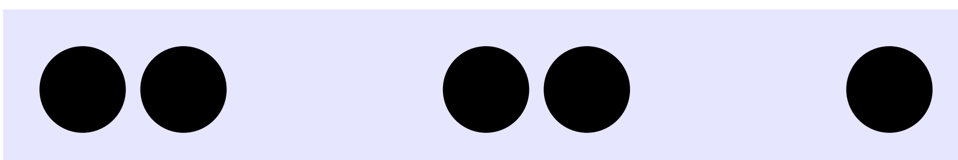

FIGURE 1.7: Gestalt grouping - proximity

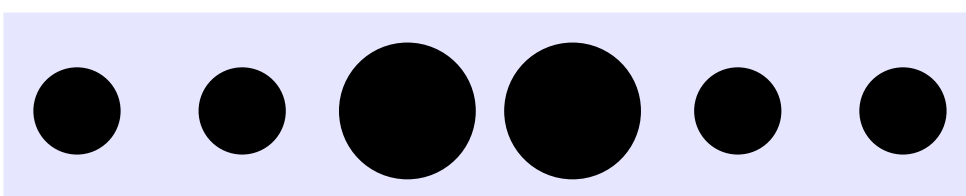

FIGURE 1.8: Gestalt grouping - size

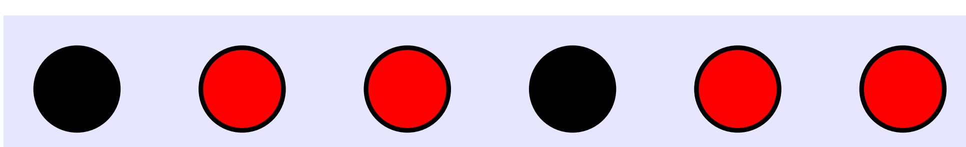

FIGURE 1.9: Gestalt grouping - colour

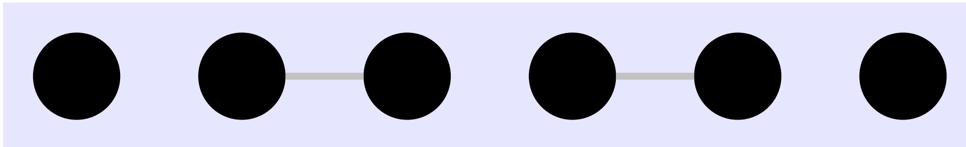

FIGURE 1.10: Gestalt grouping - connectedness

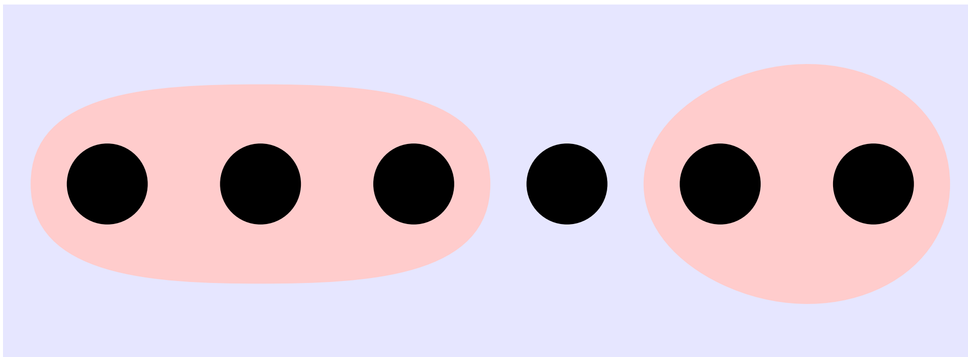

FIGURE 1.11: Gestalt grouping - region

1.3 Energy Minimisation

Brief energy minimisation and what it is. Huge number of problems in vision are inference problems which can be found from energy minimisation. The relation of the concept of energy in physics is not important but useful.

Vision problems are much more complex involving hundreds or even millions of interdependant variables. Some energies precisely model the desired inference problem while some are coarse approximations. Some energies are easy to optimise while others are known to be NP-hard. Once an accurate energy and satisfying algorithm are available, the associated inference problem is essentially solved.

Many of the most important developments in computer vision began with a proposal for a better energy, better algorithm or a combination of both.

1.4 Labelling Problems

What is a labelling problem? Type of labelling problems. What is needed for a labelling problem. What is a discrete labelling problem in vision? What are the type of labels (semantic or related to geometry).

Data driven criteria - Data influences the outcome. These preferences are dereived from machine learning.

Regularisation criteria - When we explicitely prefer some kinds of labelling over others, these criteria are called regularisers. The most prominent in computer vision are spatially coherent labellings. The idea of smoothness in preference to noisy. We know from experience that object and medical data correpsonds to coherent labels more often than not - varies from application to application but has now become a rule of thumb. Because data in computer vision tends to be highly correlated in space.

1.5 Labelling Problems as Energy Minimisation

General case of expressing data-driven and regularisation criteria as concrete energy decisions.

smoothness, neighbourhood, joint probability

Markov Random Field, MAP-MRF problem

1.6 Energy Minimisation Algorithms and Special Cases

Dynamic Programming

Binary Energies with Coherence

1.7 Thesis Overview

The remainder of the thesis outline.

Chapter 2 is where we cover the mathematical foundation to Graph Cut image segmenation.

Chapter 4 is where we cover the mathematical foundation to Graph Cut image segmenation.

Chapter 3 is where we cover the mathematical foundation to Graph Cut image segmenation.

Chapter 5 is where we cover the mathematical foundation to Graph Cut image segmenation.

Chapter 6 is where we cover the mathematical foundation to Graph Cut image segmenation.

Chapter 9 is where we cover the mathematical foundation to Graph Cut image segmenation.

Chapter 10 concludes the thesis with suggestions for further work.

Chapter 2

Mathematical Background

2.1 Graph Theory and Flow Networks

In this section we cover Graph Theory and specifically Flow Networks, which is a branch of Graph Theory, which is fundamental to the understanding of image segmentation via graph cuts. With it roots in Germany where Euler tried to find the solution to the Konigsberg bridge problem, graph theory has since blossomed into a rich field of Mathematics with seemingly endless amounts of application. Graph Theory is a huge topic in mathematics and can be applied to many other sciences. Graph theory is part of another more encompassing field of Mathematics known as Combinatronics. Graph theory and applications are more useful than the average person would recognise. They're used in Google Maps to find shortest routes to destinations, in Molecular Chemistry to model the structure of atoms, and the list goes on for quite a while. It is no surprise that it is also found to be useful in image segmentation.

Graph A graph G is a pair (V, E), where V is the set of nodes/vertices and E is the set of edges consisting of pairs (u, v) where $u, v \in V$. The graph is assumed to be finite i.e. $|V| = n$ and $|E| = m$.

In an **undirected graph**, the edge (u, v) and (v, u) are not distinct. That is, they refer to the same edge. However, in a **directed graph**, the two edge are now distinct. In a directed graph with edge (u, v), u is known as the **tail** and v is know as the **head**. In directed graphs, edges, also known as arcs, are depicted by placing arrowheads at the head of the edge. Given an edge $e = (u, v)$, u and v are said to be **incident** on e. A graph is said to be **simple** if it does not contain any self-loops. A **self-loop** is an edge with of its end points being the same vertex.

Degree The degree of a vertex v is the number of edges incident on it. $deg(v) = |\{(u, v), (v, u) \in E\}|$. A self-loop counts for 2.

If a graph is directed, also known as a **digraph**, then a node v has an **in-degree** $d_{in}(v)$ and an **out-degree** $d_{out}(v)$. A digraph is said to be **balanced** if $d_{in}(v) = d_{out}(v), \forall v \in V$.

Subgraph A graph $G' = (V', E')$ is said to be a sub-graph of $G = (V, E)$, denoted as $G' \subseteq G$, if $V' \subseteq V$ and $E' \subseteq E$.

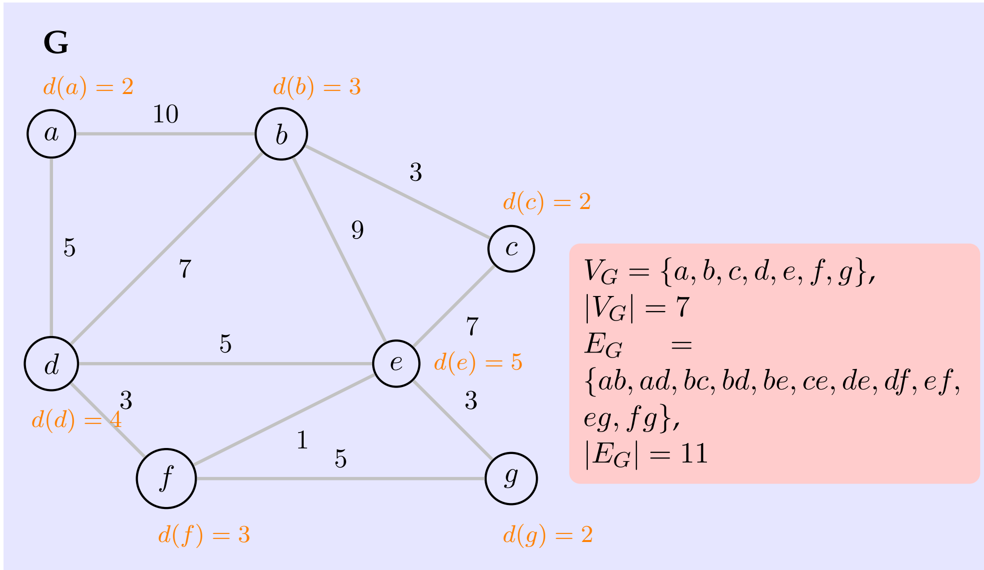

FIGURE 2.1: Undirected weighted graph **G**. The degree of each node is shown next to the corresponding node. The graph is simple. The red box shows the vertex set, V_G, and edge set, E_G, and their corresponding norm.

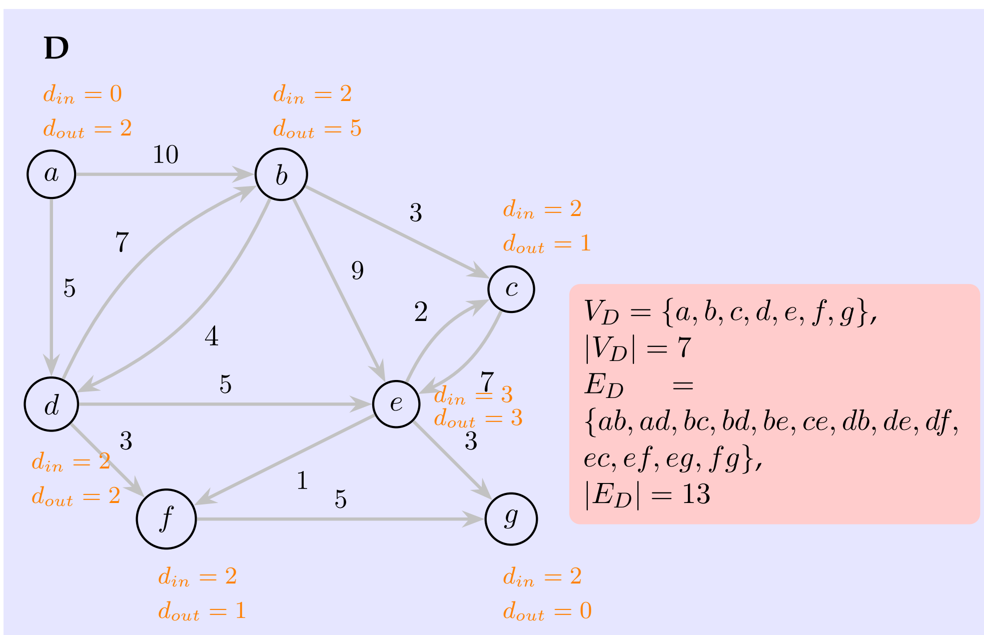

FIGURE 2.2: Directed weighted graph (Digraph) **D**. The in-degree and out-degree is shown next to each node. The graph is simple and not balanced. The red box shows the vertex set, V_D, and edge set, E_D, and their corresponding norm.

Clique A clique is a maximal subgraph.

Network A network $N = (V, E)$ is a directed graph with a source node s, a

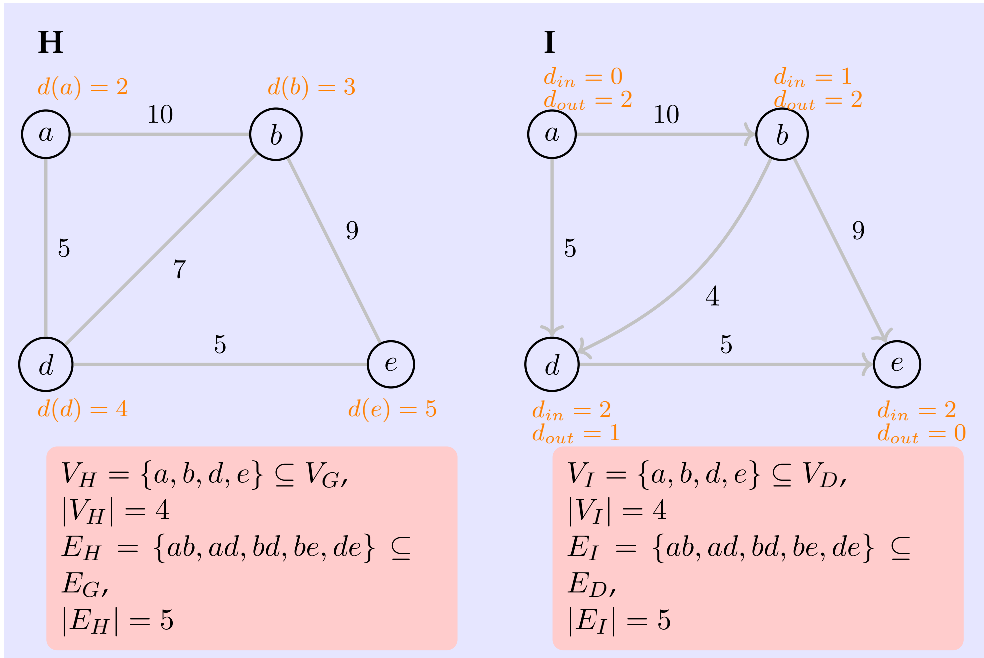

FIGURE 2.3: Undirected weighted graph **H** is a subgraph of **G** in Figure XX, $\mathbf{H} \subseteq \mathbf{G}$. Directed weighted graph **I** is a subgraph of **D** in Figure XX, $\mathbf{I} \subseteq \mathbf{D}$. The degree of each node is shown next to the corresponding node. The red box shows the vertex set, the edge set and their corresponding norms.

sink node t and a strictly positive capacity on every edge. That is, for each edge $e \in E$, the capacity, $c(.)$, obeys $c(e) \in \Re^+$.

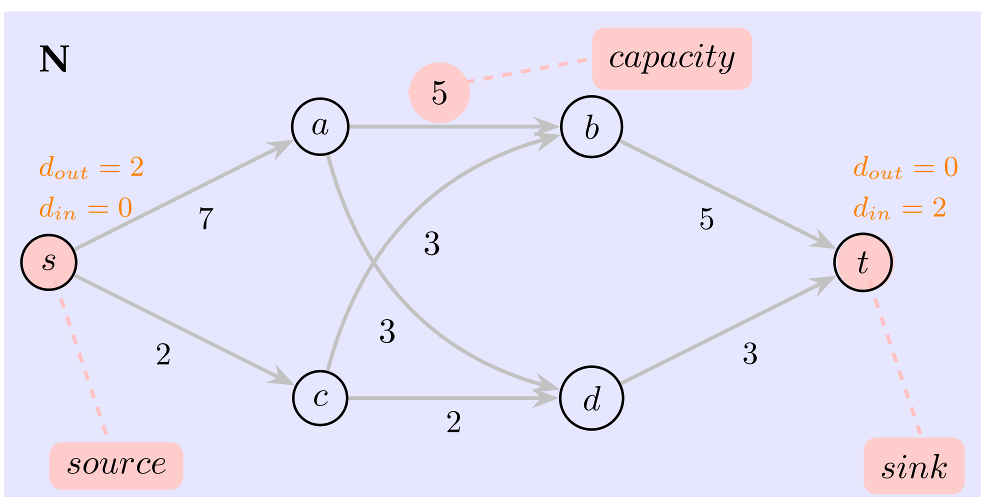

FIGURE 2.4: Network **N** with no flow. The in-degree and out-degree for the source, **s**, and the sink, **t**, are shown next to the corresponding node.

The **source node** only has out-going edges, $d_{in}(s) = 0$ and $d_{out}(s) \geq 0$. The **sink node** only has incoming edges, $d_{in} \geq 0$ and $d_out = 0$.

Flow A flow $f : V^2 \longrightarrow \Re^+$ is associated with each edge $e = (u, v)$ such that:

1. for each edge $e \in E$ we have $0 \leq f(e) \leq c(e)$. That is, the flow is positive and cannot excees the capacity of the edge.
2. for each intermediate node $v \in V \setminus \{s, t\}$ the in- and out-flow of that node $\sum_{u \in V^-(v)} f(u, v) = \sum_{u \in V^+(v)} f(v, u)$.

The **total flow** F of a network is then what leave the source s or reaches the sink t:

$$F(N) := \sum_{u \in V} f(s, u) - \sum_{u \in V} f(u, s) = \sum_{u \in V} f(u, t) - \sum_{u \in V} f(t, u) \tag{2.1}$$

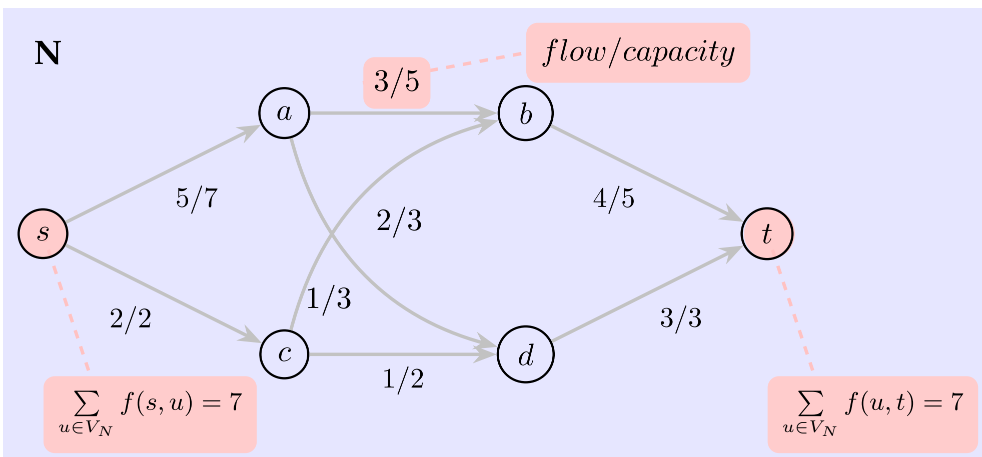

FIGURE 2.5: Network **N** with flow. The flow out of the source node, **s**, is equal to the flow into the sink node, **t**. For all other nodes, the flow-in is equal to the flow-out. This is the conservation of flow principle. This is only part of the network. The remaining part is the residual graph which shows the amount of reverse flow is available on an edge.

Cut A cut of a network $N = (V, E)$ is a partitioning of the vertex set $V = P \bigcup \bar{P}$ into two disjoint sets P containining the source node s and $\bar{P}$ containing the sink node t. $P \bigcap \bar{P} = \emptyset$.

The **capacity** of a cut is the sum of the edges $(u, v) \in V$ where $u \in P$ and $v \in \bar{P}$:

$$\kappa(P, \bar{P}) = \sum_{u \in P; v \in \bar{P}} c(u, v) \tag{2.2}$$

Maximal Flow The largest amount of flow that can be sent through the source that is able to reach the sink is known as the maximal flow.

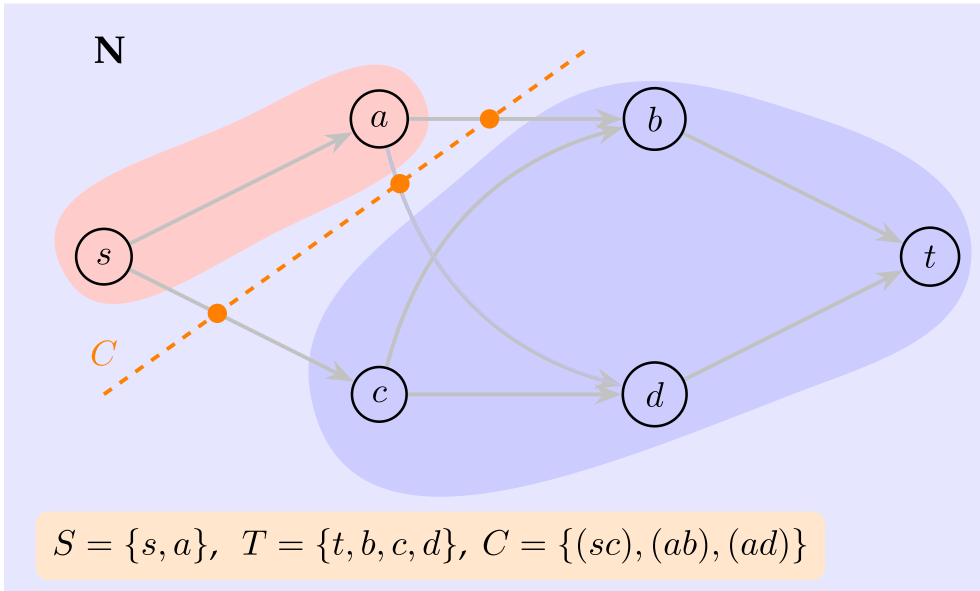

FIGURE 2.6: Network **N** with with a valid cut **C**. The nodes within the red region are reachable from the source and the nodes within the blue region are able to reach the sink. The cut set, **C**, is show in the orange filled block.

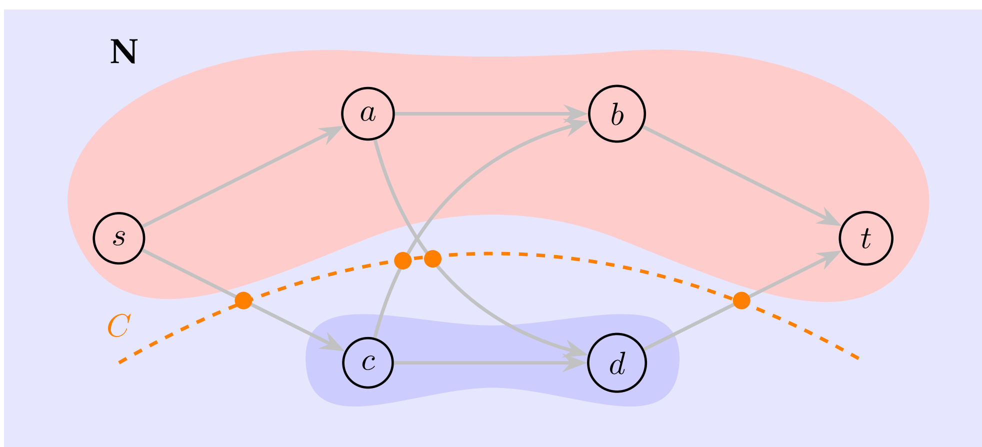

FIGURE 2.7: Network **N** with with a invalid cut **C**. The cut does not partition source node **s** and sink node **t** into distinct sets.

Minimal Cut A cut C on a network $N = (V, E)$ is a minimal cut if there exists no other cut C' where $\kappa(C') < \kappa(C)$.

In the next section we show that the Maximal Flow problem and the Minimal Cut problem are duals of each other, commonly known as the Max-Flow/Min-Cut problem.

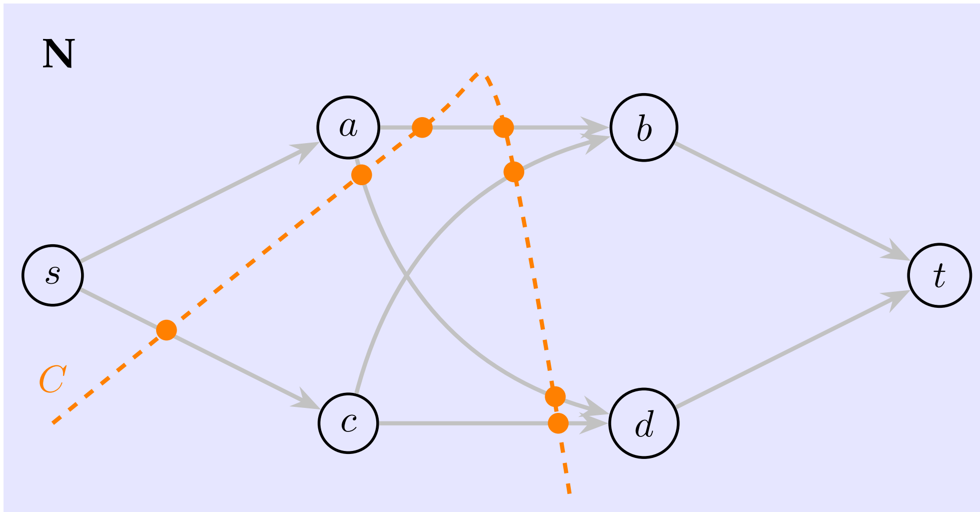

FIGURE 2.8: Network **N** with with a invalid cut **C**. The cut partition partitions the graph into more than two sets and the cut intersects the edges ab and ad twice.

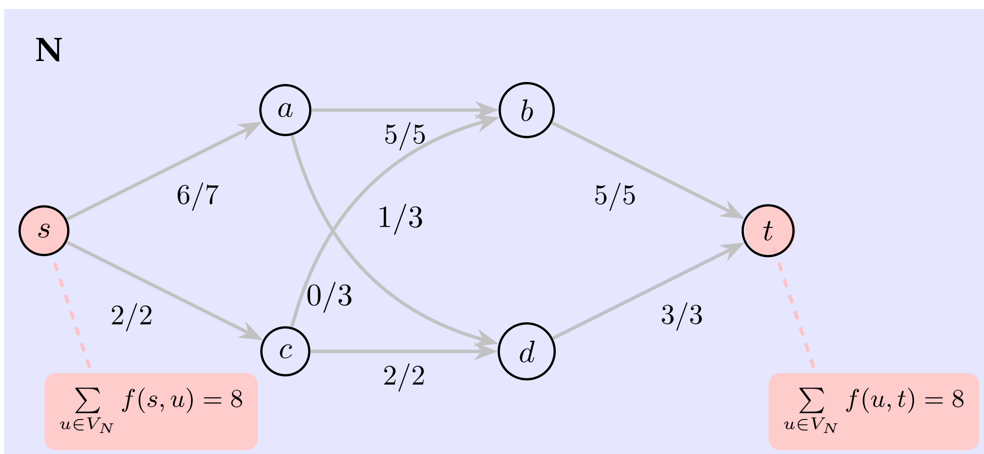

FIGURE 2.9: Network **N** with maximum flow. There is no way to push more flow out of the source into the sink without breaking the rules for conservation of flow.

2.2 Markov Random Fields

In this section we review MRF's as a pure mathematical/statistical tool used used specifically for vision. That is, we only cover the necessary concepts related to understanding the problem of modelling images for analysis and inference purposes. In sub-section 1 we cover the basics, in sub-section 2 we cover how to model an image using MRF, and in sub-section 3 we cover how to find the MAP, or a close enough approximation, to the MRF.

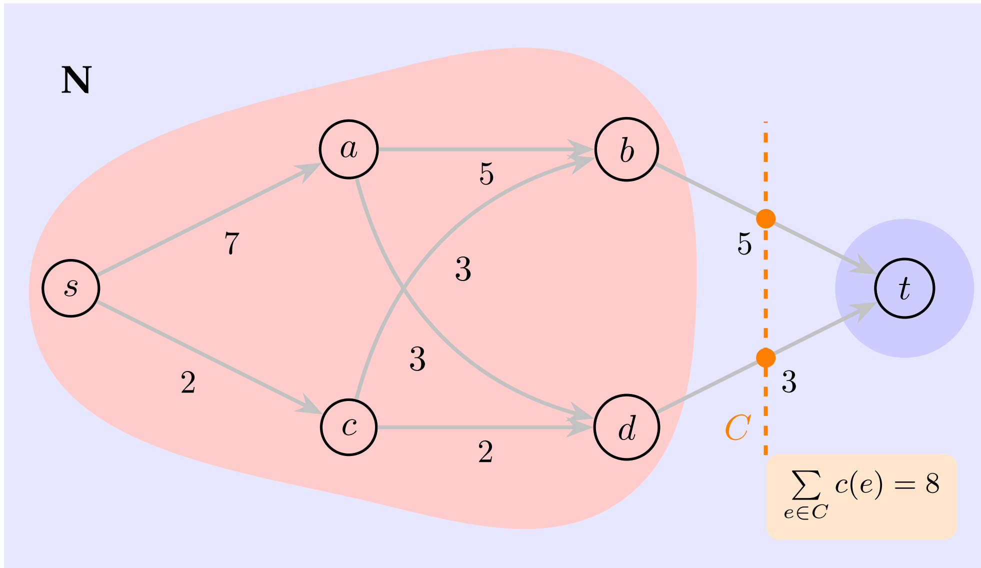

FIGURE 2.10: Network **N** with minimal cut **C**. The sum of the capacity of all the edges in the cut set is the minimum of all possible valid cuts on the network **N**.

2.2.1 Markov Random Fields Theory and Concepts

MRF theory and concepts. Purely mathematical/statistical. Markov Properties Markov Blankets

2.2.2 Markov Random Fields in Image Modelling for Segmentation

Modelling the joint probability of of image using MRFs. Nearby pixels exhibit high correlation in natural images. This is where we can take advantage of Markov Modelling.

2.2.3 MAP-MRF Approxiamtion via Graph Cuts

How to make MAP estimates on the MRF. How does the graph-cut approach ensure an MAP solution.

2.3 Max-Flow/Min-Cut Problem

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2.4 Modelling Images as MRFs

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2.4.1 Sub-modularity Conditions for Discrete Systems

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2.4.2 Connectivity

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2.4.3 Distance Metrics

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Euclidean Distance

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Riemannian Distance

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Learned Distance from Seeds

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2.5 Max-Flow/Min-Cut Algorithms

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2.5.1 Ford-Fulkerson

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Algorithm 1 Euclid's algorithm

```
procedure EUCLID(a, b)                    ▷ The g.c.d. of a and b
    r ← a mod b
    while r ≠ 0 do                        ▷ We have the answer if r is 0
        a ← b
        b ← r
        r ← a mod b
    end while
    return b                              ▷ The gcd is b
end procedure
```

2.5.2 Dinic/Edmond-Karp

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2.5.3 Push-Relabel

Originally developed by Andrew V. Goldberg and Robert E. Tarjan. Previous algorithms, such as Ford-Fulkerson, used the concept of residual networks and augmenting paths to determine max-flow. Push-Relabel used the concept of preflow to determine max-flow instead of augmenting paths. Sometimes referred as the Preflow-Push Algorithm. Preflow is a concept originally developed by A.V. Karzanov.

The algorithm works at converting a preflow, f, into a normal flow and then terminates. This flow also turns out to be the maximum flow. Goldberg and Tarjan defined a generic Push-Relabel algorithm which solves the maximum flow problem.

Preflow A preflow is a real-valued function, f, on vertice pairs. The total flow into a vertex can exceed the flow out of a vertex but not vice versa.

A preflow where all $v \in V - \{s,t\}$ has a flow excess of zero, $e_f(v) = 0$, is a normal flow. The preflow function is also referred to as the **s-t preflow**.

Preflow must satisfy:

1. Capacity Constraint
   $\forall u, v \in V, f(u,v) \leq c(u,v)$

2. Antisymmetry/Skew Symmetry
   $\forall u, v, \in V, f(u,v) = -f(v,u)$

3. Nonnegative Constrain
   The flow into $v \in V - \{s\}$ must be greater than or equal to the flow out of v. $\forall u \in V, v \in V - \{s\}, \sum f(u,v) > 0$

Flow Excess Flow excess, $e_f(v)$, is the net flow into v where $v \in V$ for some preflow f.

$$e_f(v) = \begin{cases} \infty & \text{if } v = s \\ \sum_{u \in V} f(u,v) & \text{if } v \in V - \{s\} \end{cases}$$

Active Vertex An active vertex/node is a vertex v which satisfies all of the properties:

1. Not a source or sink, $v \in V - \{s,t\}$
2. Positive flow excess, $e_f(v) > 0$
3. Has a valid label, $d(v) < \infty$

Push-Relabel also uses the concept of a residual graph, $G_f = (V, E_f)$.

Residual Capacity The residual capacity of a preflow is defined as $r_f(v,w) = c(v,w) - f(v,w)$.

Residual Edges The residual edges for a preflow f is defined as the set of edges with positive residual capacity. $E_f = \{(v,w)\} | r - f(v,w) > 0$.

Labelling Push-Relabel also use a valid labelling function, d, to determine which vertex pairs should be selected for the push operation.

A valid labelling , d, is a nonnegative integer function applied to all vertices to denote a label. The labelling is often referred as the height or distance from the sink node, t. This function is sometimes compared to the physical intuition that liquids naturally flow downhill.

A valid labelling for a preflow consists of:

1. For $v \in V, 0 \leq d(v) \leq \infty$
2. $d(s) = |V|$ (source condition)
3. $d(t) = 0$ (sink condition)
4. $d(v) = d(w) + 1$ for every residual edge $(v,u) \in E_f$

A labelling d and a preflow f are said to be compatible id d adheres to the properties above.

The algorithm pushes flow excess starting at the source, s, along all vertices towards the sink, t. The algorithm maintains a compatible vertex labelling function, d, to the preflow, f. The labelling is usedto determine where to puch the flow excess. The algorithm repeatedly performs either a push or a relabel operation so long as there is an active vertex in G_f.

Push Operation The push operation is used to move flow from one vertex to another. The transfer of excess can be performed across the vertex pair $(v, w) \in E_f$ if:

1. v is an active vertex
2. the edge has positive residual capacity, $r_f(v, w) > 0$
3. the label distance $d(v) = d(w) + 1$

This allows the algorithm to move δ excess flow: $\delta = min(e_f(v), r_f(v, w))$ from v to w. A push is considered **saturating** if no more flow can be sent over the edge, $\delta = r_f(v, w)$. A push is considered to be **non-saturating** if all the excess from v the push over the dge and the edge still has some cpacity, $\delta = e_f(v)$.

Algorithm 2 Push Operation

Input: Preflow f, labels d, and (v, w) where $v, w \in V$
Output: Preflow f
Applicable: if $v \in V - \{s, t\}$, $d(v) < \infty$, $e_f(v) > 0$, $r_f(v, w) > 0$ and $d(v) = d(w) + 1$

procedure PUSH(v, w)
  $\delta := min(e_f(v), r_f(v, w)$
  $f(v, w) := f(v, w) + \delta$
  $f(w, v) := f(w, v) - \delta$
  $e_f(v) := e_f(v) - \delta$
  $e_f(w) := e_f(w) + \delta$
  return f
end procedure

Relabel Operation The relabel operation is used to increase the label value of a single active vertex so that excess flow can be pushed out of the active vertex. The relabel operation is performed when all the residual edges of the active vertex have positive residual capacity, $r_f(v, w) > 0$. This implies that v's label is less than or equal to all vertices, $d(v) \leq d(w)$, meaning that no push operation across the edges is possible given the push condition $d(v) = d(w) + 1$.

The relabel operation for some vertex v selects the smallest label for the vertices with positive residual edges, $r_f(v, w) > 0$. The active vertex is then assigned the smallest label value $+1$ such that $d(v) := mind(v) + 1|(v, w) \in E_f$. This will alow the vertex v to potentially push its excess flow to atleast one of the othe vertices during the algorithm's next iteration.

The algorithm initialises the following values in the residual graph before the push andrelabel operations in the main loop.

1. Initialise the preflow of all edges in the residual graph
2. Initialise the labellings such that:
   (a) $d(s) = |V|$

Algorithm 3 Relabel Operation

Input: Preflow f, labels d, and $v \in V - \{s, t\}$
Output: Labels d
Applicable: if $v \in V - \{s, t\}$, $d(v) < \infty$, $e_f(v) > 0$, and $\forall w \in V, r_f(v, w) > 0$ which implies $d(v) \leq d(w)$

procedure RELABEL(v)
  if $\{(v, w) \in E_f\} \neq 0$ **then**
    $d(v) := min(d(w) + 1 | (v, w) \in E_f)$
  else
    $d(v) := \infty$
  end if
  return d
end procedure

(b) $d(v) = 0$for $v \in V - \{s\}$

3. Performs saturation, pushes along all residual edges out of the source $(s, v) \in E_f$ and $v \in V$.

Once complete the algorithm repeatedly performs either a push or a relabel operation against all vertices. The algorithm continues until no operation can be performed. The algorithm terminates when there are no more active vertices.

The analaysis and the proof of correctness of the Push-Relabel algorithm can be found in Appendix B.

Push-Relabel Speed Optimisation Heuristics

Discharge Push-Relabel also use a valid labelling function ,d, to determine which vertex pairs should be selected for the push operation.

FIFO Push-Relabel also use a valid labelling function ,d, to determine which vertex pairs should be selected for the push operation.

Highest Label First Push-Relabel also use a valid labelling function ,d, to determine which vertex pairs should be selected for the push operation.

Global Relabel Push-Relabel also use a valid labelling function ,d, to determine which vertex pairs should be selected for the push operation.

Gap Relabel Push-Relabel also use a valid labelling function ,d, to determine which vertex pairs should be selected for the push operation.

2.5.4 Alpha-Beta Swap

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Algorithm 4 Push-Relabel Main-loop

Input: Network flow graph $G = (V, E)$, s, t and c
Output: Maximum flow f

procedure MAIN(v)
  for all $(v, w) \in (V - \{s\})(V - \{s\})$ **do**
    $f(v, w) := 0$
    $f(w, v) := 0$
  end for

  for all $v \in V$ **do**
    $f(s, v) := r_f(s, v)$
    $f(v, s) := -r_f(s, v)$
  end for

  $d(s) = |V|$

  for all $v \in V - \{s\}$ **do**
    $d(v) := 0$
    $e_f(v) := f(s, v)$
  end for

  While there exists an active vertex
  while $\exists v \in V - \{s, t\}$ **do** ▷ with either applicable PUSH() or RELABEL() operation
    Perform either a PUSH or a RELABEL operation on v
  end while

  return f
end procedure

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2.5.5 Alpha-Expansion

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Chapter 3

Introduction to Fluorescence Microscopy

Chapter 4

Interactive Segmentation on Single Channel Data

4.1 Seeding

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4.2 Estimating Probability Distributions

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4.2.1 Expectation Maximisation (Guassian Mixture Modelling)

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Fixed-Distribution Modelling

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Automatically Determining the Optimal Number of Mixtures

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4.2.2 Naive Bayesian Classification

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4.2.3 Supervised Learning for Multi-Layered Perceptron

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4.3 Single-Channel Data

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4.4 Multi-Channel Data

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Chapter 5

Automatic Graph Cut Segmentation

5.1 Determining FG and BG seeds/probability distributions

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5.2 Determining Optimal Paramters Settings

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5.3 Single-Channel Data

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5.4 Multi-Channel Data

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Chapter 6

Graph Cut Solution to ACWE Chan-Vese Segmentation

Chapter 7

Texture Segmentation

Chapter 8

Combining Intensity and Texture on Multi-Layerd MRF Models

Chapter 9

Pre-Processing and Post-Processing Techniques

9.1 Removal of Artifacts using Connected Components

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9.2 Anisotropic Diffusion

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9.2.1 Coherence Enhancing Diffusion

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9.2.2 Coherence Enhancing Diffusion with Optimised Rotational Invariance

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9.3 Poisson Denoising

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9.3.1 Total-Variation Denoising

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9.4 Contrast Enhancement

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Chapter 10

Conclusion and Future Work

10.1 Removal of Artifacts using Connected Components

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10.2 Anisotropic Diffusion

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10.2.1 Coherence Enhancing Diffusion

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10.2.2 Coherence Enhancing Diffusion with Optimised Rotational Invariance

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10.3 Poisson Denoising

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10.3.1 Total-Variation Denoising

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10.4 Contrast Enhancement

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Appendix A

Proof of Maximum Flow - Minimum Cut Equivalence

Write your Appendix content here.

Appendix B

Push-Relabel Algorithm Analysis and Proof of Correctness

Write your Appendix content here.