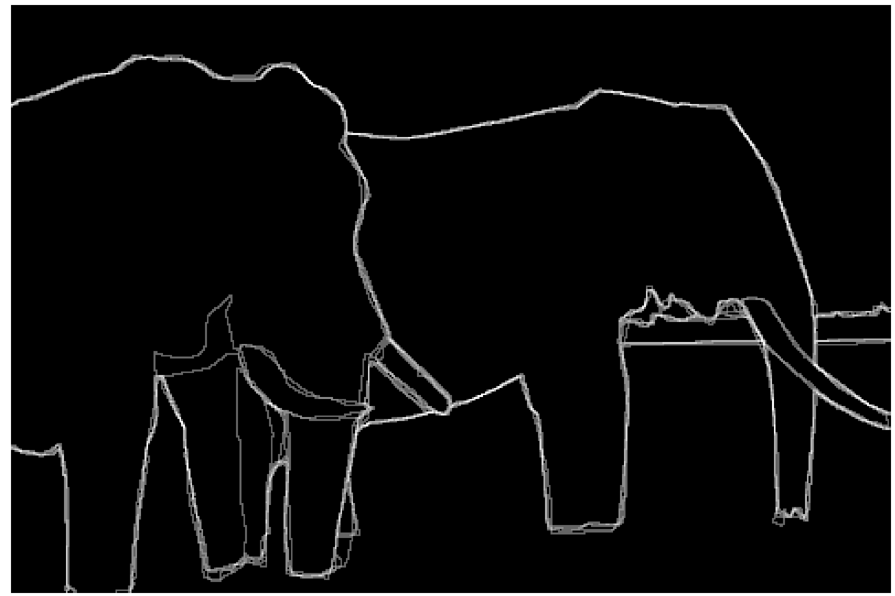
Boundary Detection:
Hough Transform

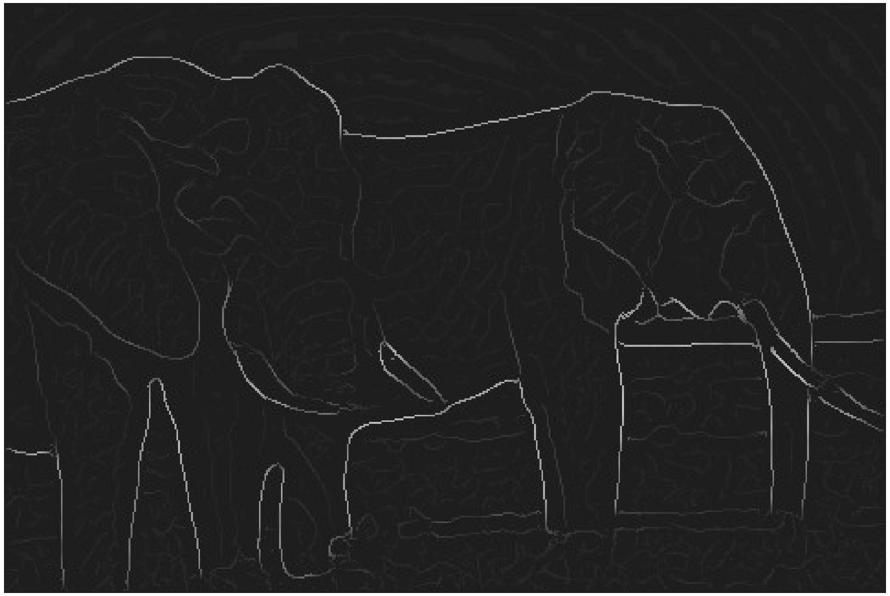
Boundaries of Objects



Human Bounndary marking

http://www.eecs.berkeley.edu/Research/Projects/CS/vision/grouping/segbench/bench/html/images.html

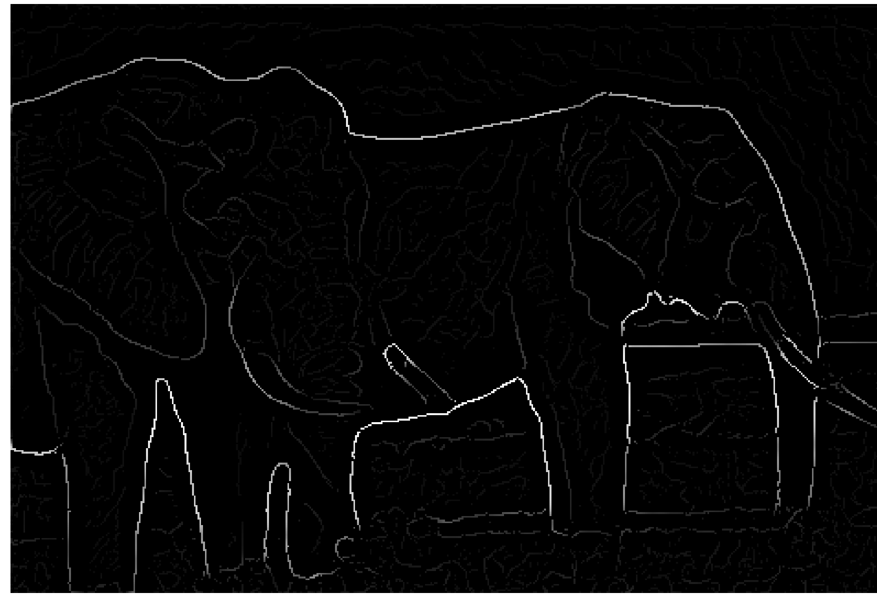
Boundaries of Objects from Edges



Brightness Gradient (Edge detection)

- Missing edge continuity, many spurious edges

Boundaries of Objects from Edges



Multi-scale Brightness Gradient

- But, low strength edges may be very important

Boundaries of Objects from Edges

Image

Machine Edge Detection

Human Boundary Marking

Boundaries in Medical Imaging

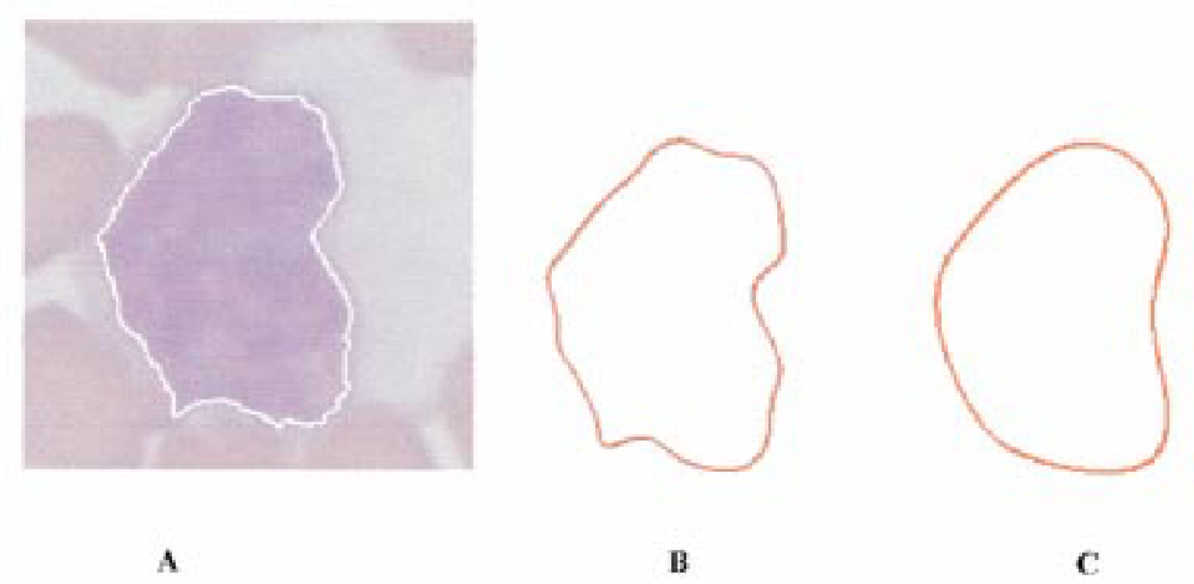
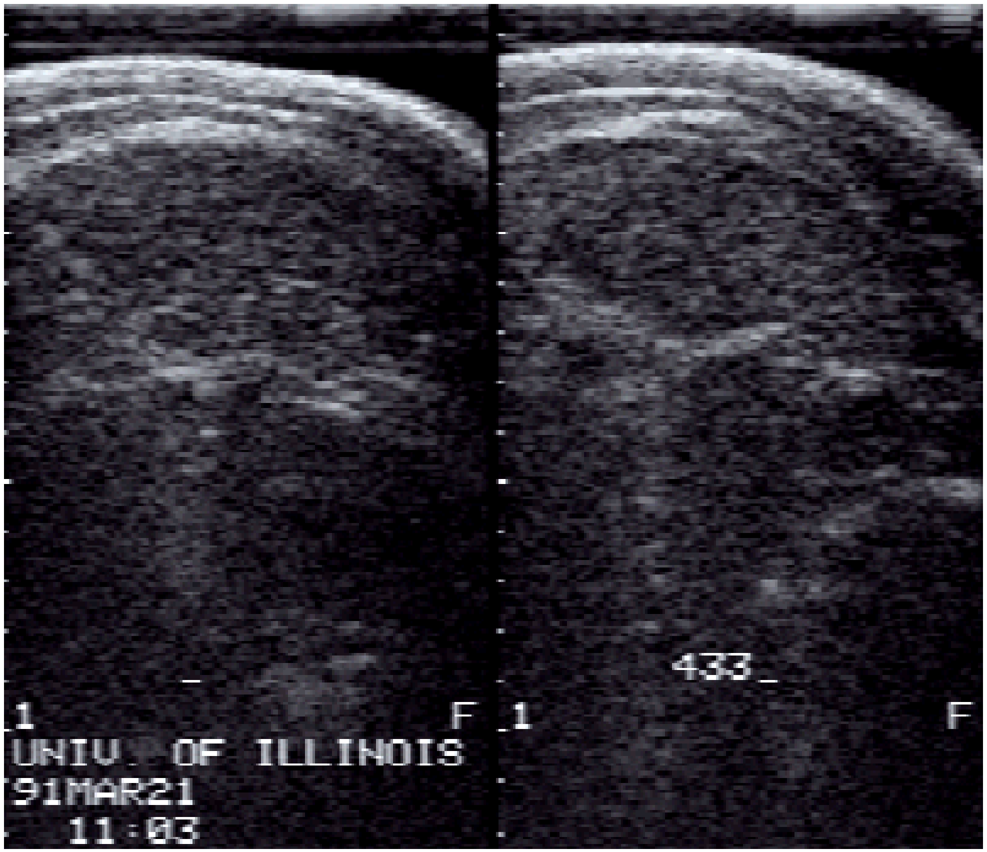


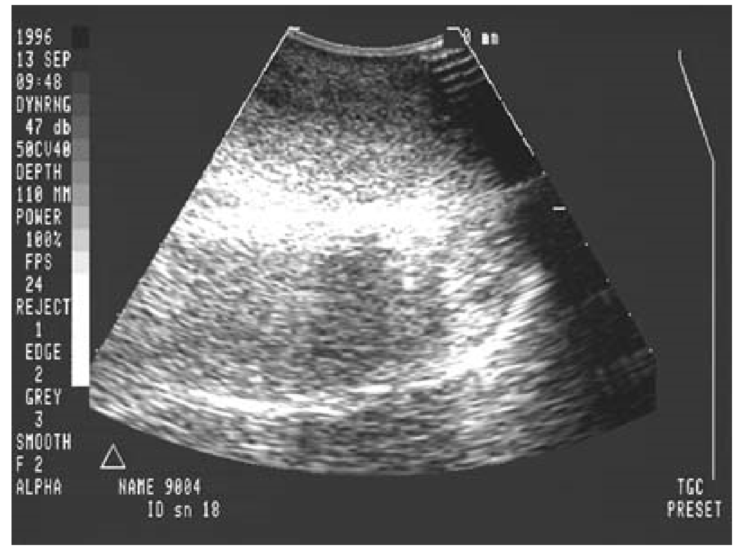
Fig. 2. Representation of a closed contour by elliptic Fourier descriptors. (a) Input. (b) Series truncated at 16 harmonics. (c) Series truncated to four harmonics.

Detection of cancerous regions.

[Foran, Comaniciu, Meer, Goodell, 00]

Boundaries in Ultrasound Images





Hard to detect in the presence of large amount of speckle noise

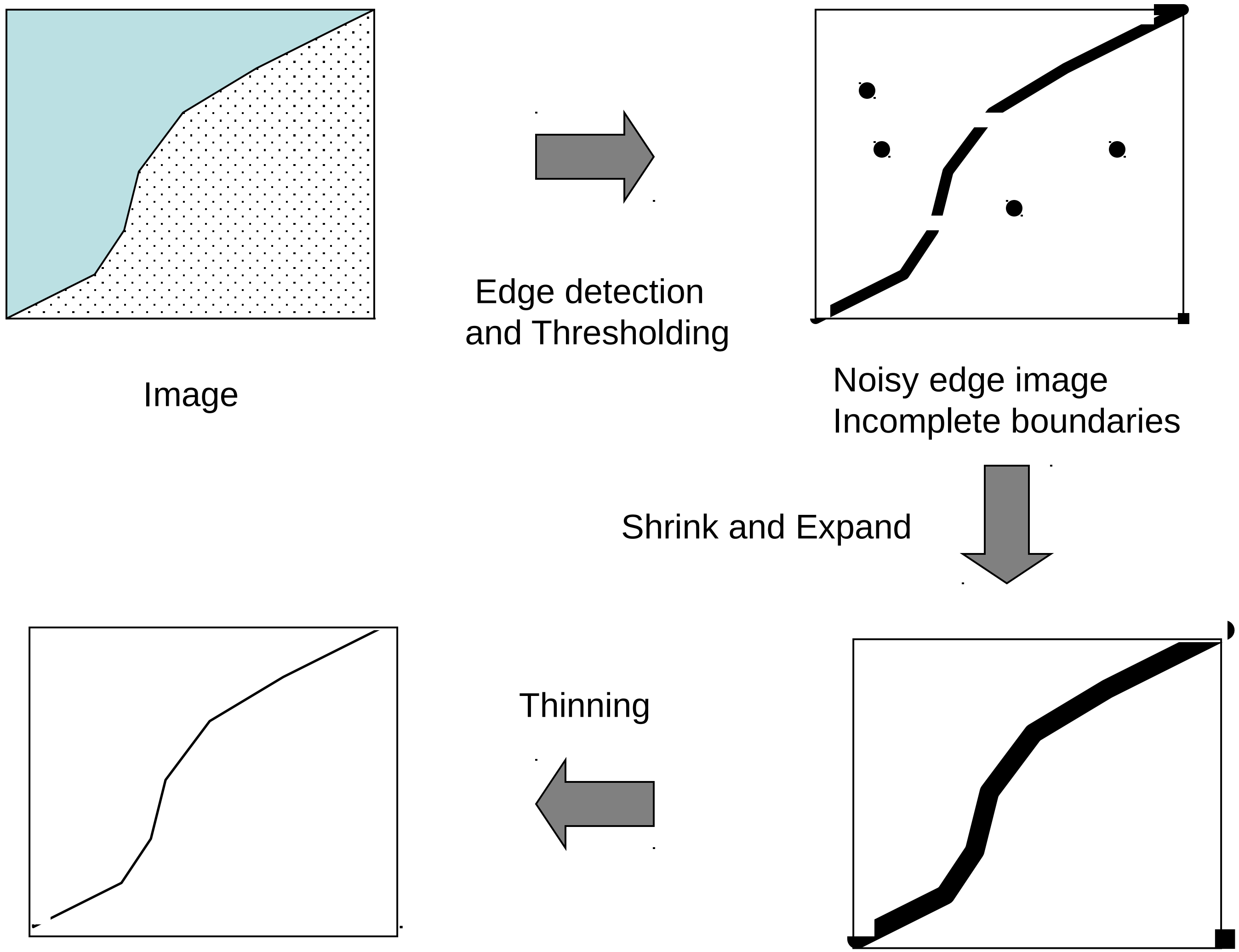
Boundaries of Objects

Sometimes hard even for humans!

Topics

- Preprocessing Edge Images
- Edge Tracking Methods
- Fitting Lines and Curves to Edges
- The Hough Transform

Preprocessing Edge Images



Edge Tracking Methods

Adjusting a priori Boundaries:

Given: Approximate Location of Boundary

Task: Find Accurate Location of Boundary

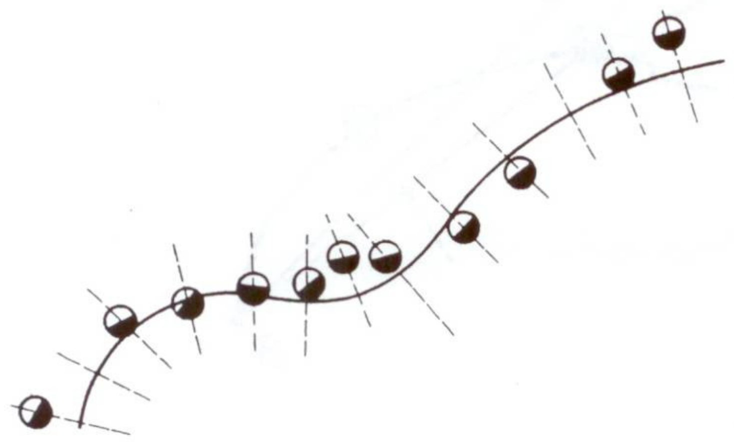


Fig. 4.2 Search orientations from an approximate boundary location.

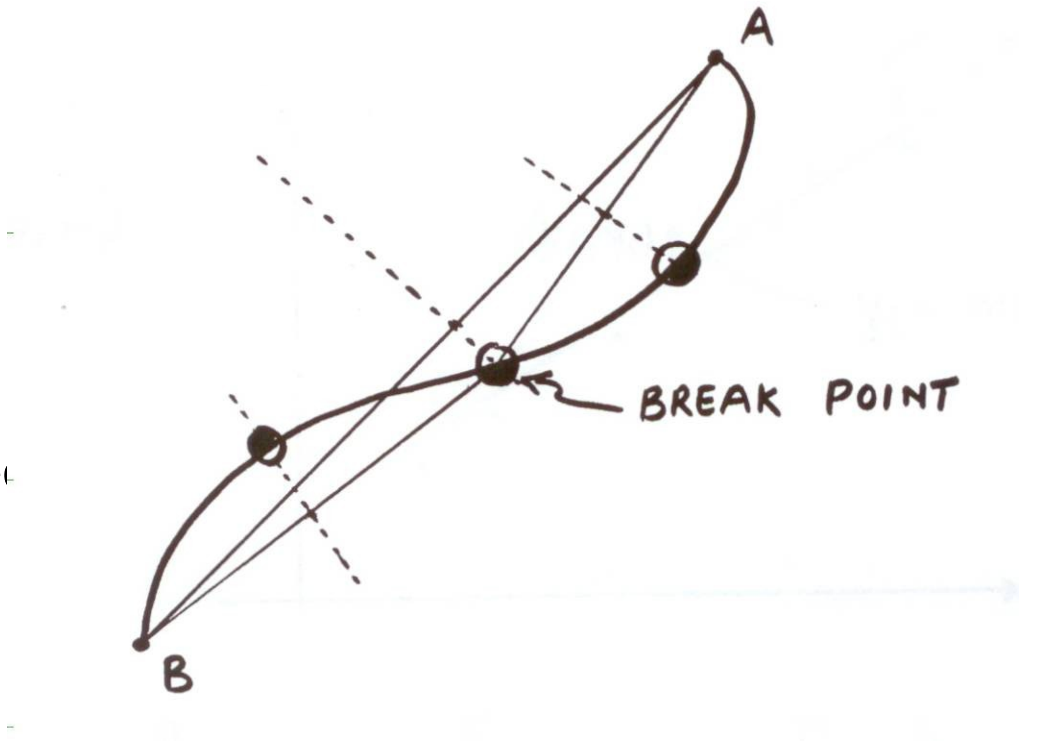
- Search for STRONG EDGES along normals to approximate boundary.
- Fit curve (eg., polynomials) to strong edges.

Edge Tracking Methods

Divide and Conquer:

Given: Boundary lies between points A and B

Task: Find Boundary

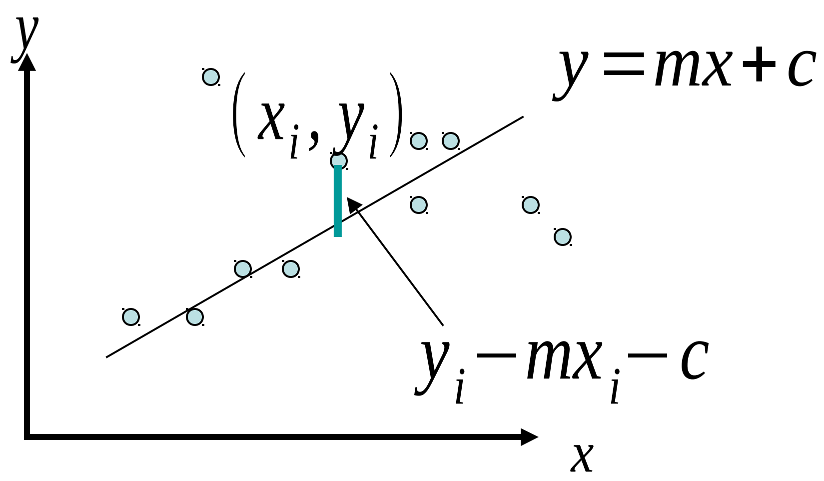


- Connect A and B with Line
- Find strongest edge along line bise
- Use edge point as break point
- Repeat

Fitting Lines to Edges (Least Squares)

Given: Many (x_i, y_i) pairs

Find: Parameters (m, c)



Minimize: Average square distance:

$$E = \sum_i \frac{(y_i - mx_i - c)^2}{N}$$

Using:

$$\frac{\partial E}{\partial m} = 0 \;\wedge\; \frac{\partial E}{\partial c} = 0$$

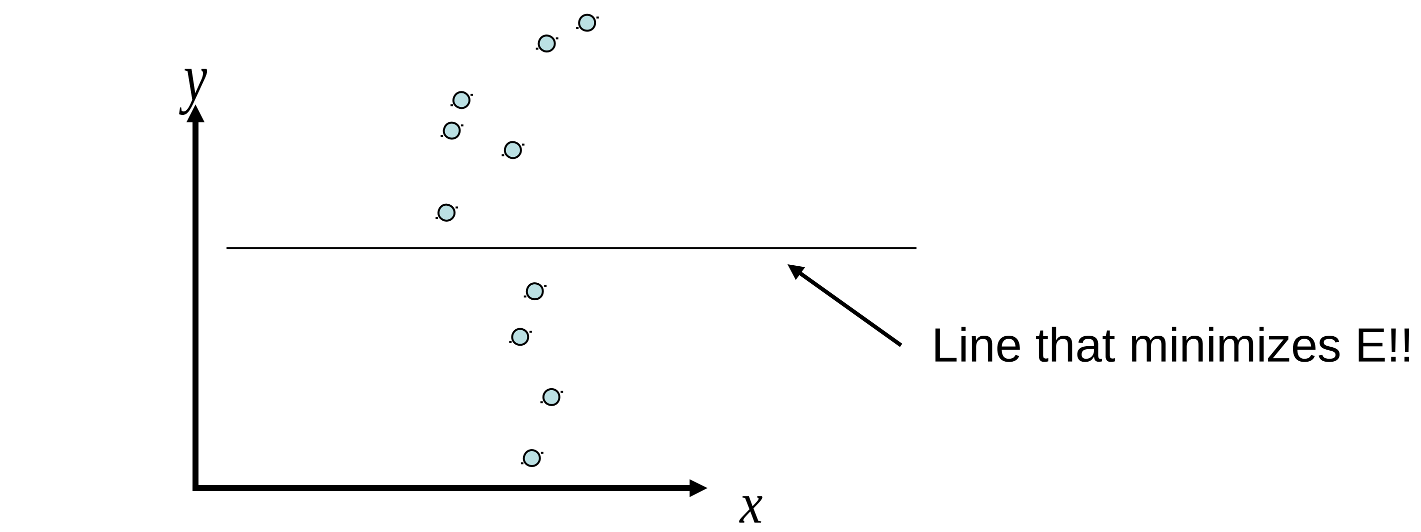
$$c = \bar{y} - m\,\bar{x}$$

$$m = \frac{\sum_i (x_i - \bar{x})(y_i - \bar{y})}{\sum_i (x_i - \bar{x})^2}$$

Note:

$$\bar{y} = \frac{\sum_i y_i}{N} \qquad \bar{x} = \frac{\sum_i x_i}{N}$$

Problem with Parameterization

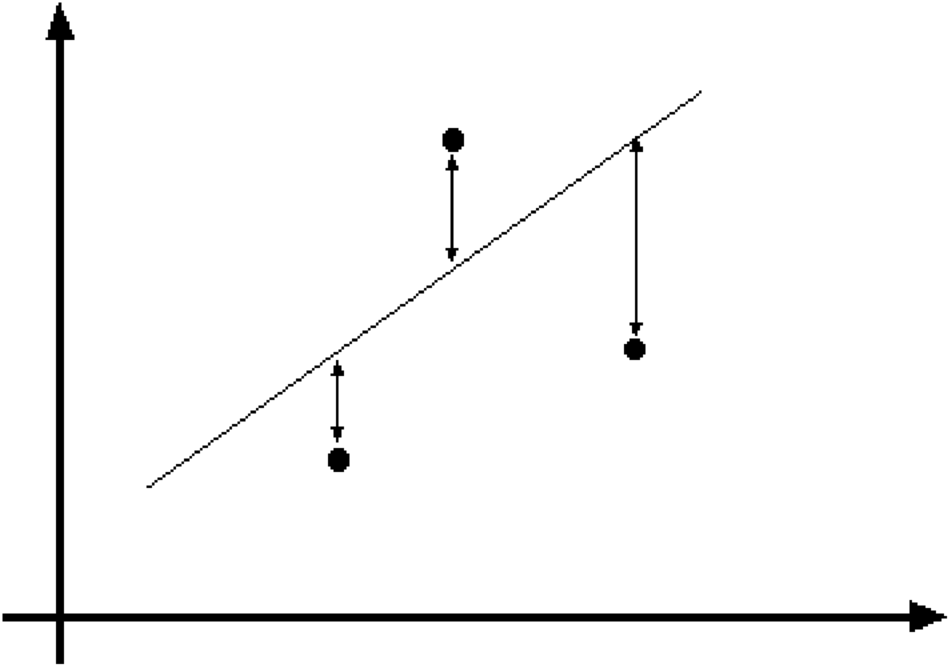


Solution: Use a different parameterization

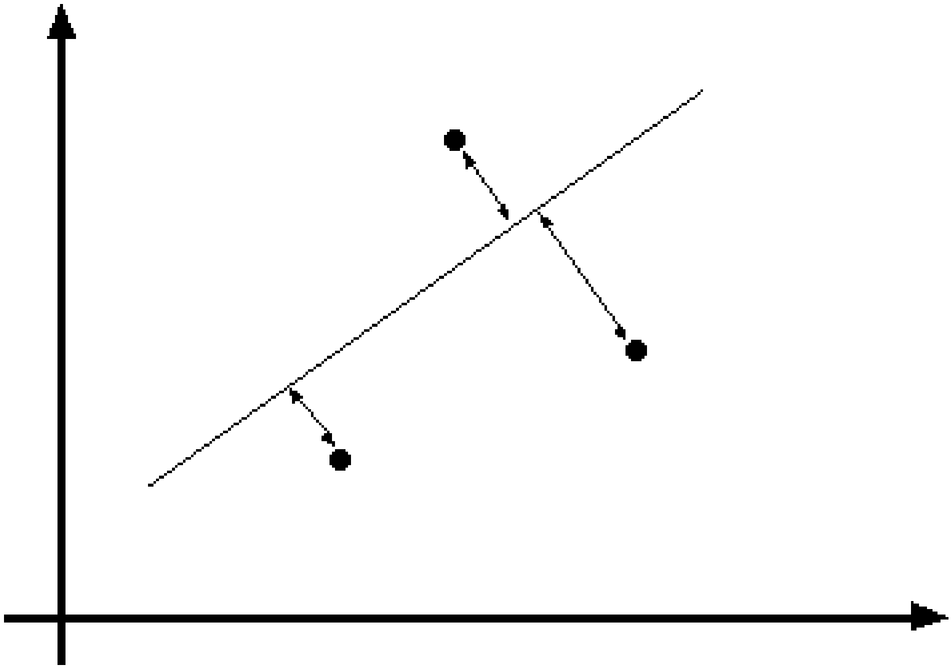
(same as the one we used in computing Minimum Moment of Inertia)

$$E = \frac{1}{N}\sum_{i}\left(\rho - x_i\cos\theta + y_i\sin\theta\right)^2$$

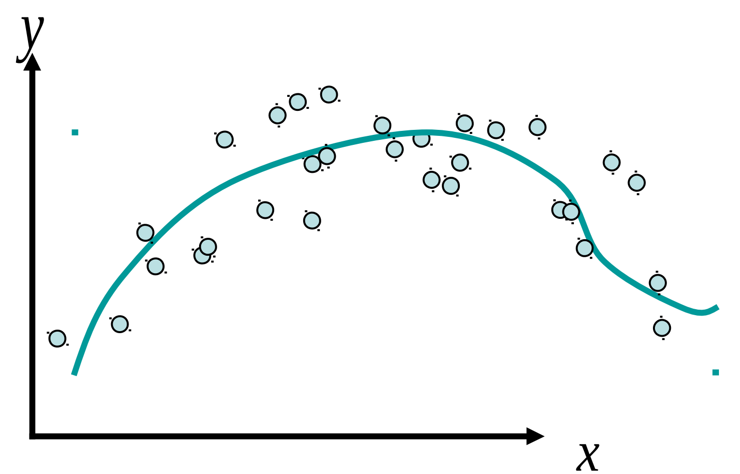
Note: Error E must be formulated carefully!



Line fitting can be max. likelihood - but choice of model is important



Curve Fitting



Find Polynomial:

$$y = f(x) = ax^3 + bx^2 + cx + d$$

that best fits the given points (x_i, y_i)

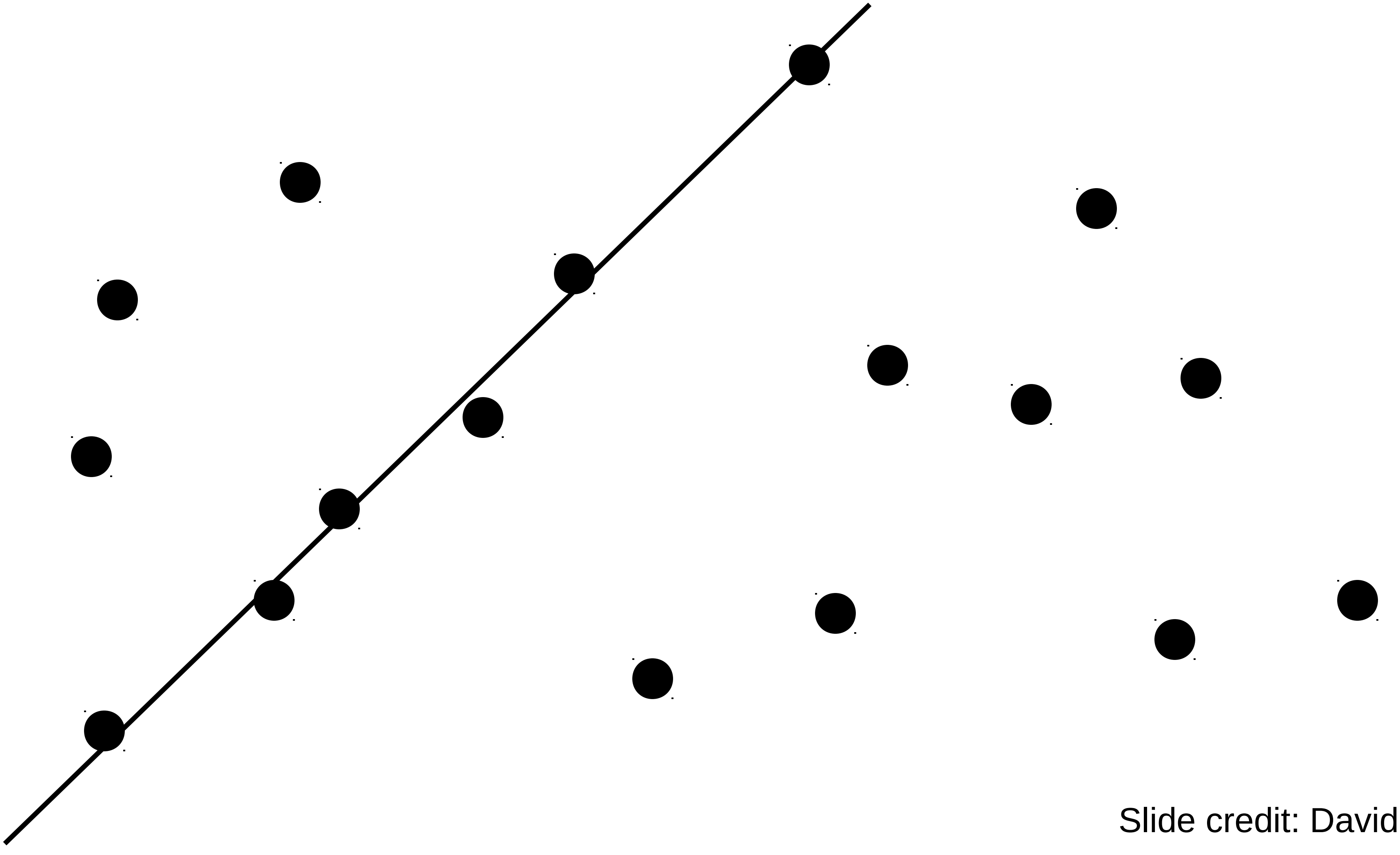
Minimize:

$$\frac{1}{N}\sum_i \left[y_i - \left(ax_i^3 + bx_i^2 + cx_i + d \right) \right]^2$$

Using: $$\frac{\partial E}{\partial a} = 0 \ , \ \frac{\partial E}{\partial b} = 0 \ , \ \frac{\partial E}{\partial c} = 0 \ , \ \frac{\partial E}{\partial d} = 0$$

Note: $f(x)$ is LINEAR in the parameters (a, b, c, d)

Line Grouping Problem



Slide credit: David Jacobs

This is difficult because of:

- Extraneous data: clutter or multiple models
  - We do not know what is part of the model?
  - Can we pull out models with a few parts from much larger amounts of background clutter?
- Missing data: only some parts of model are present
- Noise

- **Cost:**
  - It is not feasible to check all combinations of features by fitting a model to each possible subset

Hough Transform

- Elegant method for direct object recognition
    - Edges need not be connected
    - Complete object need not be visible
    - Key Idea: Edges VOTE for the possible model

Image and Parameter Spaces

Equation of Line: $y = mx + c$

Find: (m, c)

Consider point: (x_i, y_i)

$$y_i = mx_i + c \quad or \quad c = -x_i m + y_i$$

Parameter space also called Hough Space

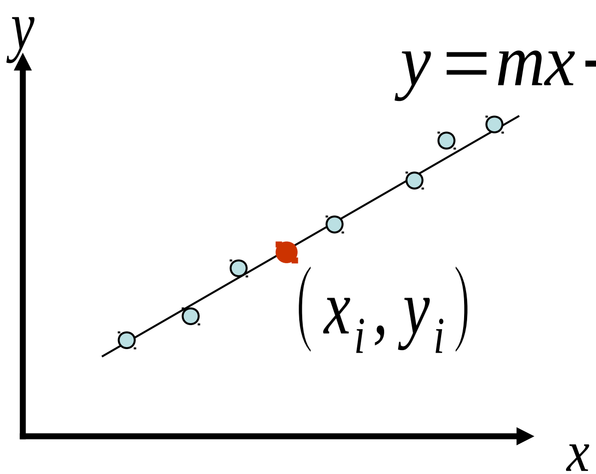
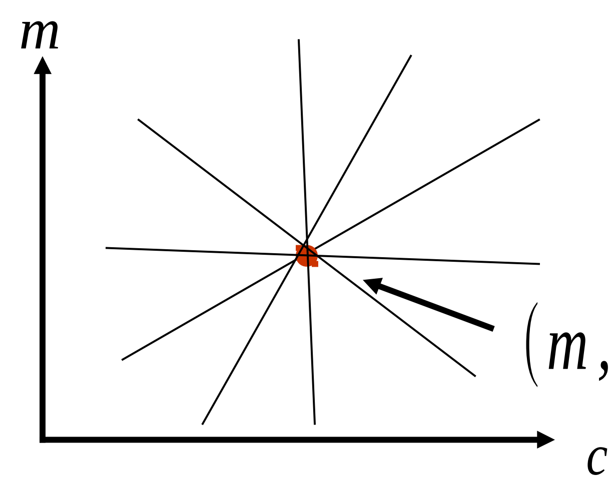


Image Space



Parameter Space

Line Detection by Hough Transform

Algorithm:

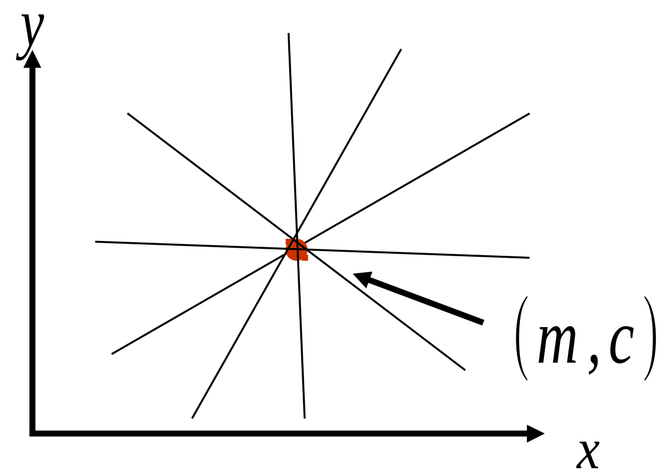
- Quantize Parameter Space (m, c)
- Create Accumulator Array $A(m, c)$
- Set $A(m, c) = 0 \quad \forall m, c$
- For each image edge (x_i, y_i) increment:

$$A(m, c) = A(m, c) + 1$$

- If (m, c) lies on the line:

$$c = -x_i m + y_i$$

- Find local maxima in $A(m, c)$



Parameter Space

$A(m, c)$

	1						1		
		1				1			
			1		1				
				2					
			1		1				
		1				1			
	1						1		

Better Parameterization

NOTE: $-\infty \leq m \leq \infty$

Large Accumulator

More memory and computations

Improvement: (Finite Accumulator Array Size)

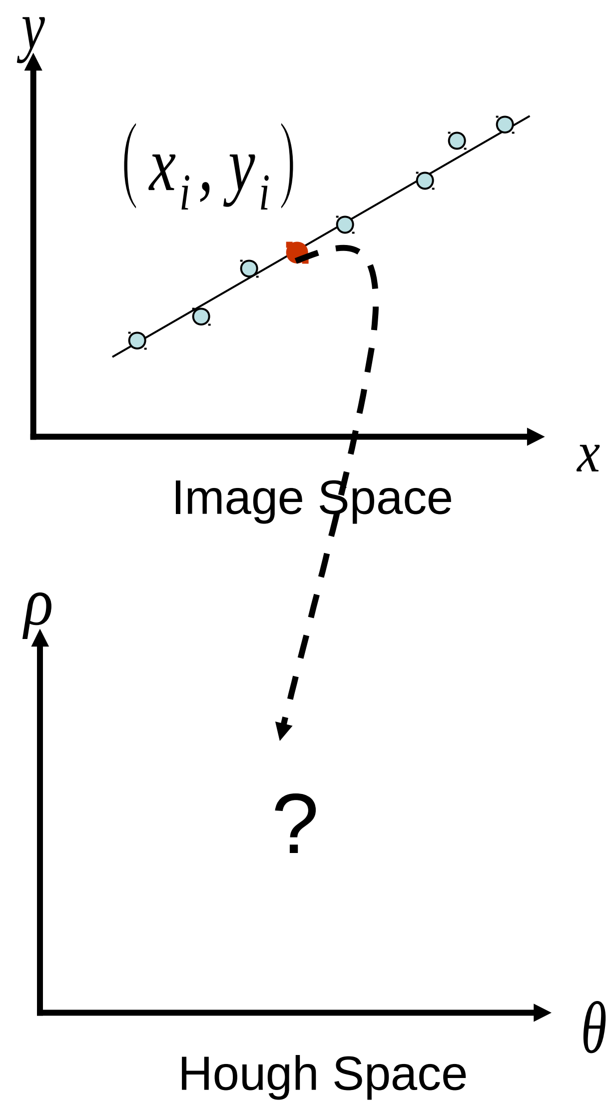
Line equation: $\rho = -x\cos\theta + y\sin\theta$

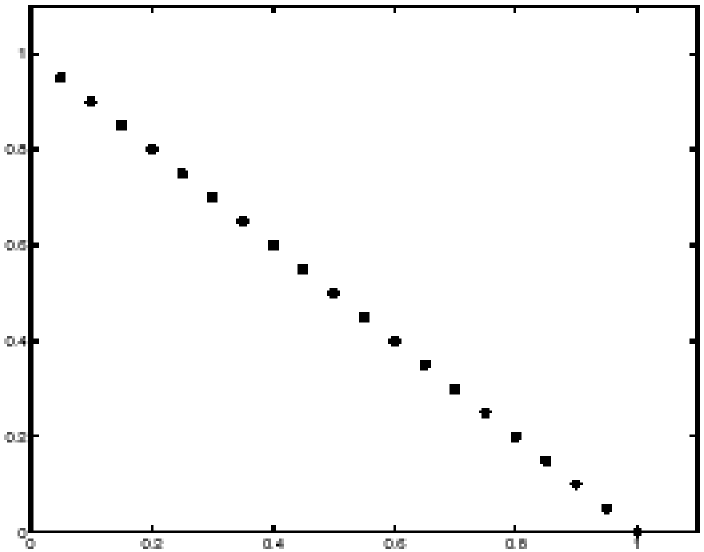
Here $0 \leq \theta \leq 2\pi$

$0 \leq \rho \leq \rho_{\max}$

Given points (x_i, y_i) find (ρ, θ)

Hough Space Sinusoid





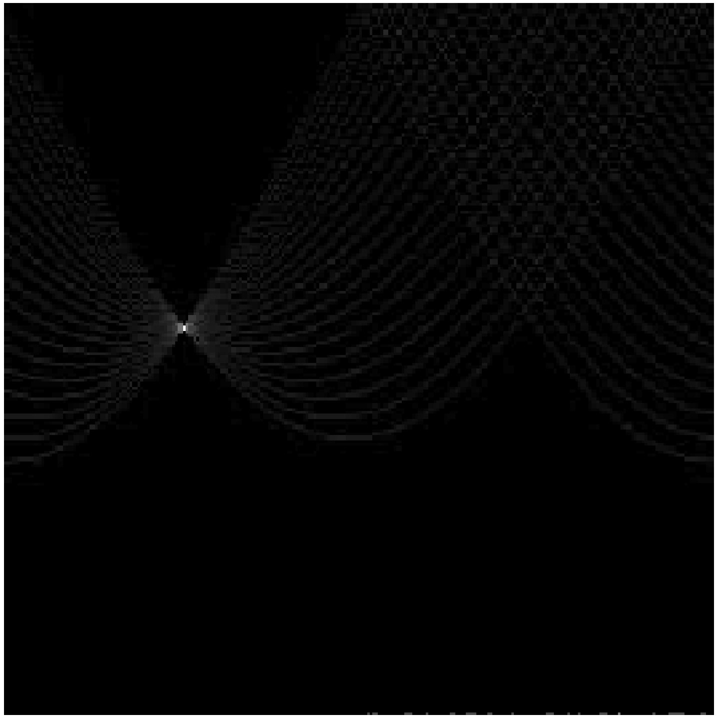
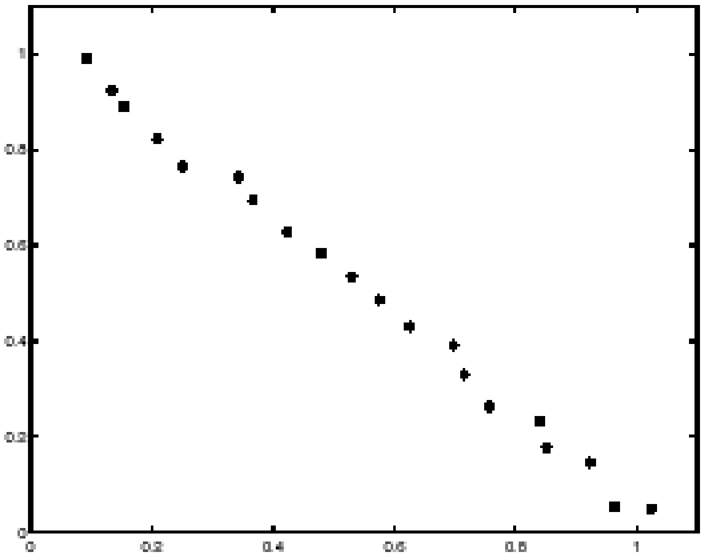


Image space

Votes

Horizontal axis is θ, vertical is rho.



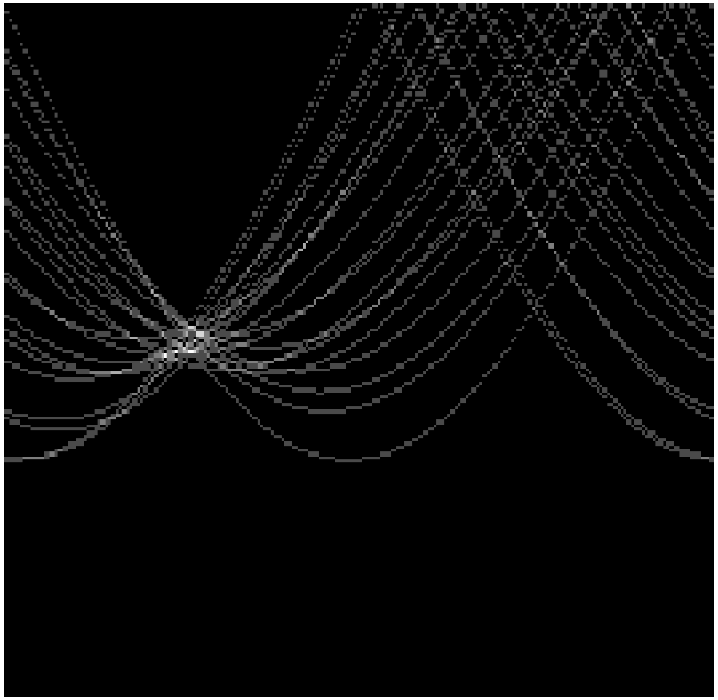
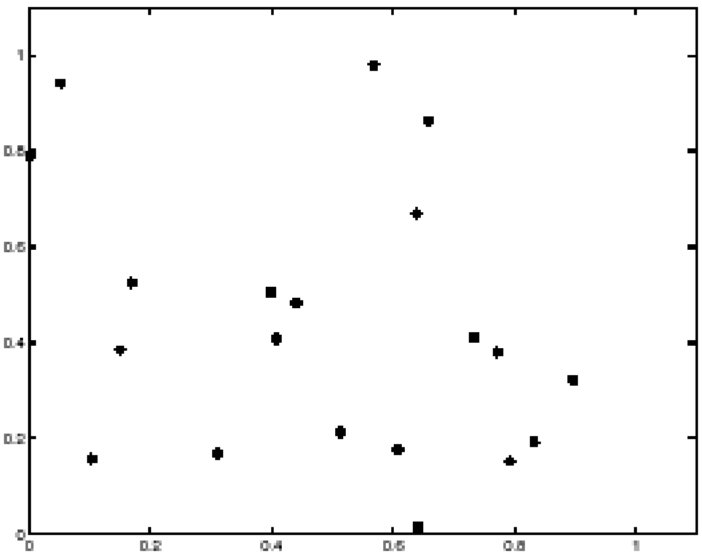
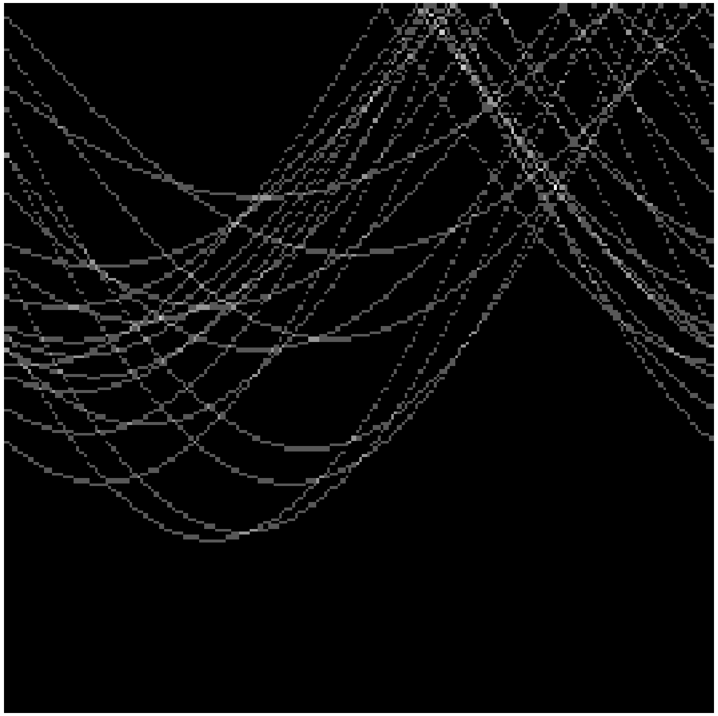


Image space

votes

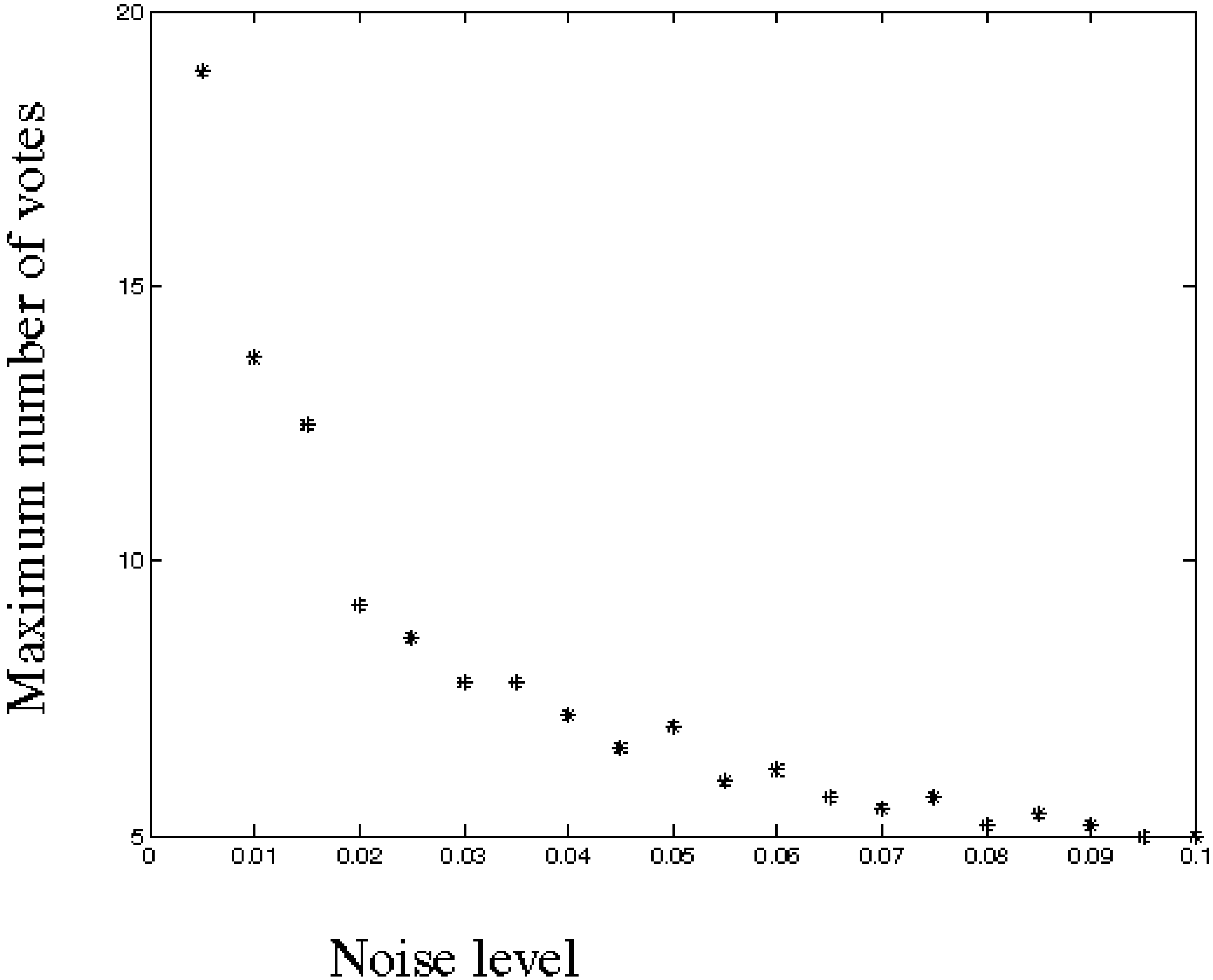


1
0.8
0.6
0.4
0.2
0
0
0.2
0.4
0.6
0.8
1

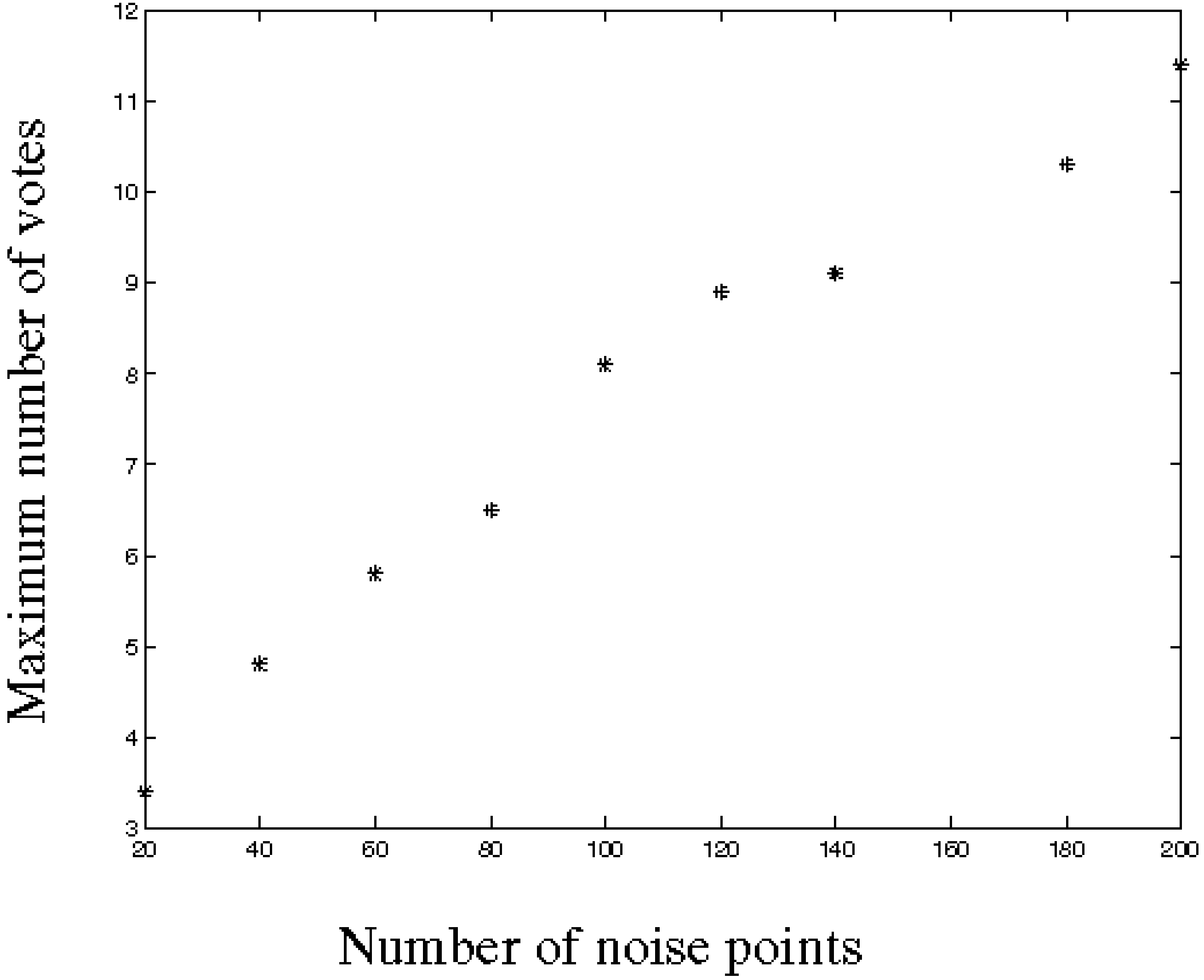


Mechanics of the Hough transform

- Difficulties
  - how big should the cells be? (too big, and we merge quite different lines; too small, and noise causes lines to be missed)
- How many lines?
  - Count the peaks in the Hough array
  - Treat adjacent peaks as a single peak
- Which points belong to each line?
  - Search for points close to the line
  - Solve again for line and iterate



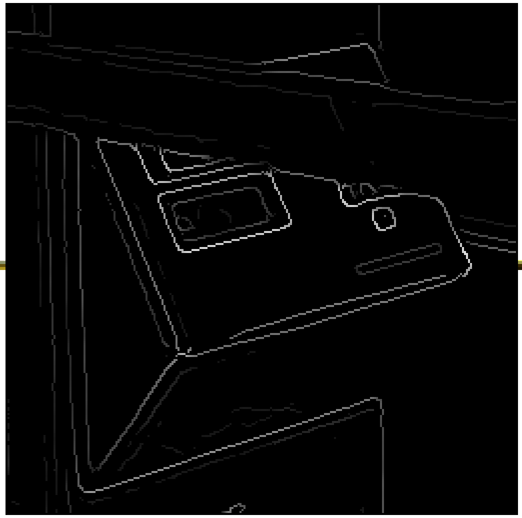
Fewer votes land in a single bin when noise increases.



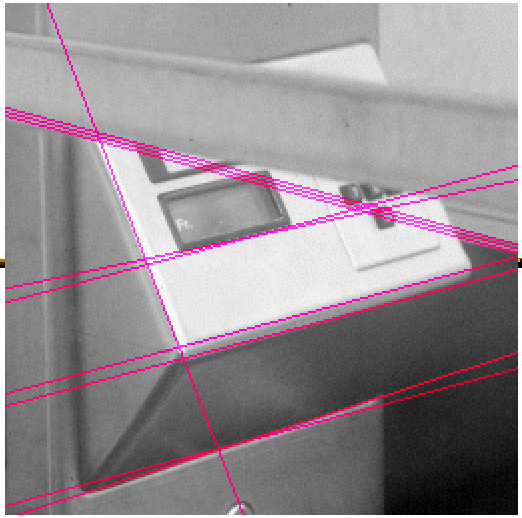
Adding more clutter increases number of bins with false peaks.

Real World Example

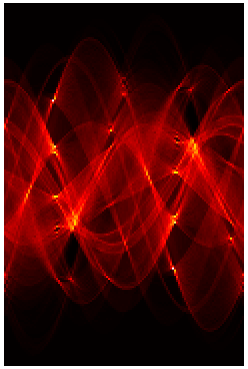
Original



Edge Detection



Found Lines



Parameter Space

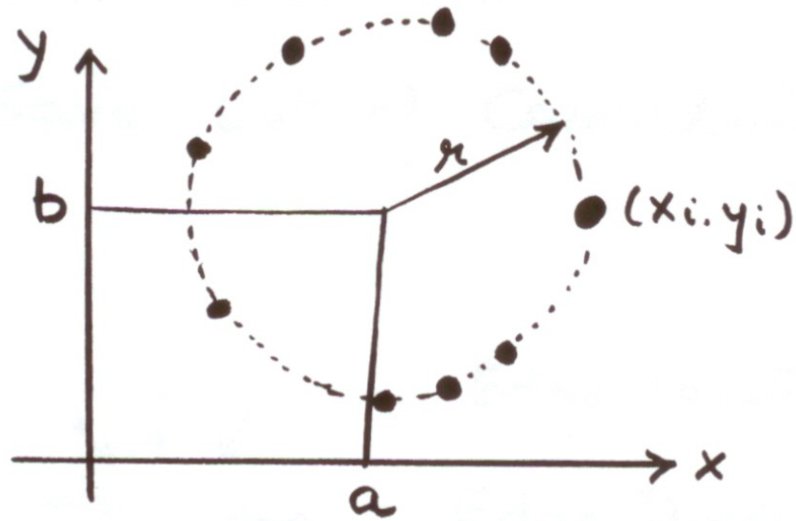
Finding Circles by Hough Transform

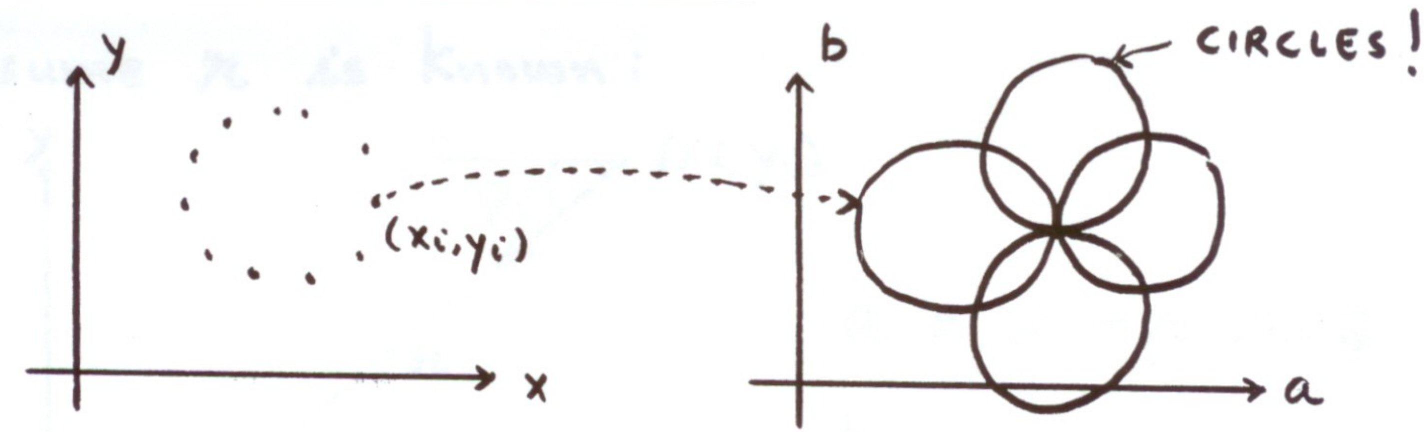
Equation of Circle:

$$(x_i - a)^2 + (y_i - b)^2 = r^2$$

If radius is known: (2D Hough Space)

Accumulator Array $A(a,b)$





Finding Circles by Hough Transform

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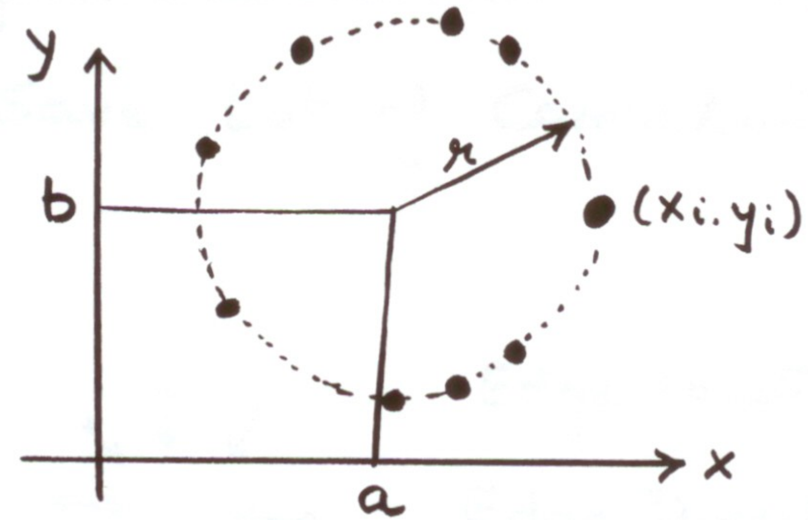

If radius is not known: 3D Hough Space!

Use Accumulator array $A\left(a, b, r\right)$

What is the surface in the hough space?

Notes

- https://tinyurl.com/yd5mj45n