

Multimedia Technology

Lecture 7: Image Features

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- We already know how the image is represented in computer
- We can process image as a matrix
- We can process image as a multi-variable function
- In this lecture, focus is turned on image features
- Why image feature?
- What are they
 - Image Local Features
 - Image Global Features
- How to extract them?

Outline

1 Global Features

2 Scale Space

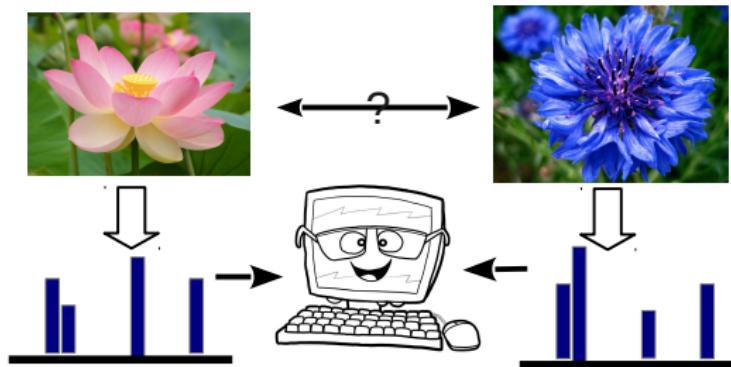
3 Local Features

4 Deep Features

5 References

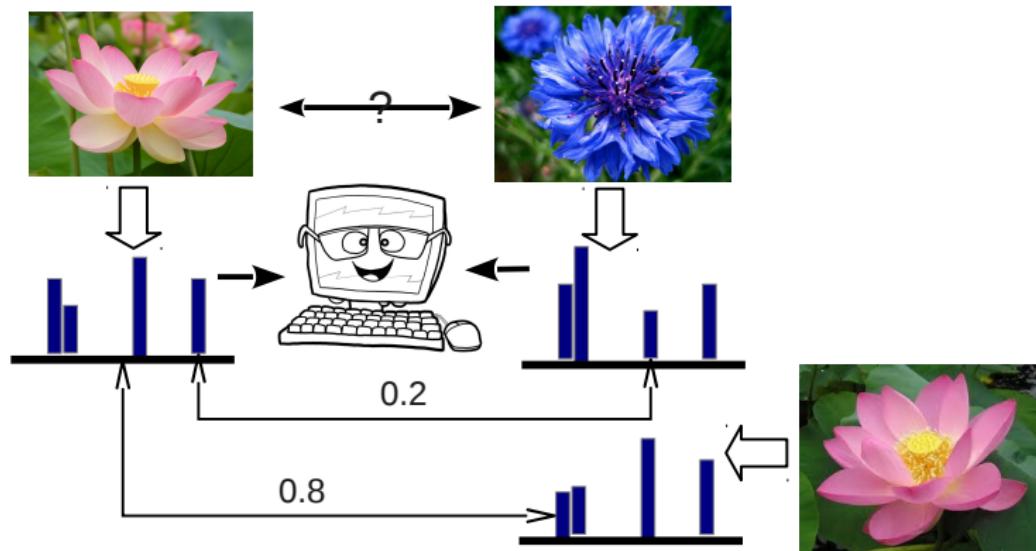
Why image features? (1)

- Images are not directly comparable by computer
- Features are the media to represent the images



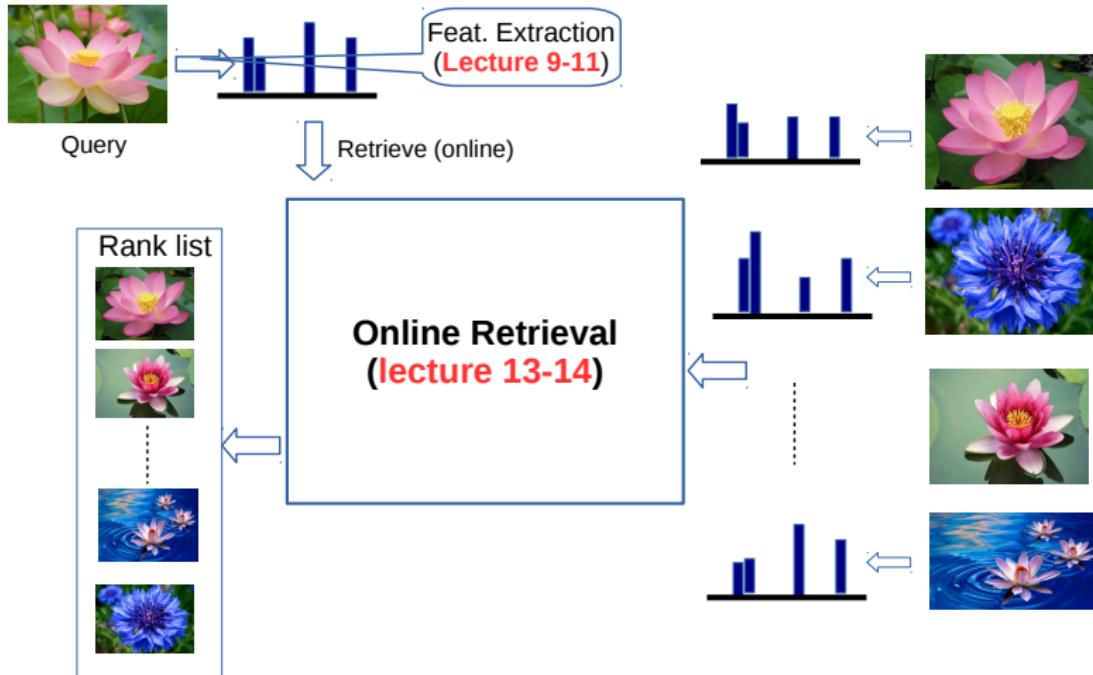
- Open issue: how the images are represented in our brain??

Why image features? (2)



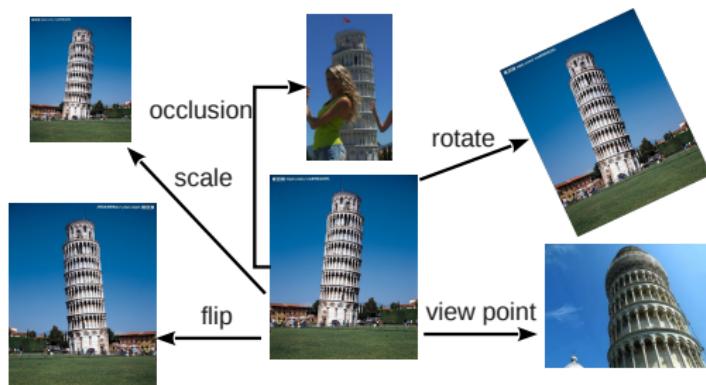
- Features should reflect the similarity as precise as possible

Framework of content based image retrieval (CBIR)



- CBIR = image features + retrieval/comparing method

Invariance properties of the features

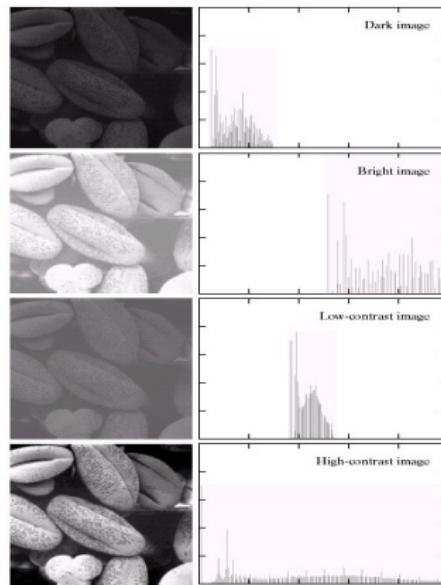
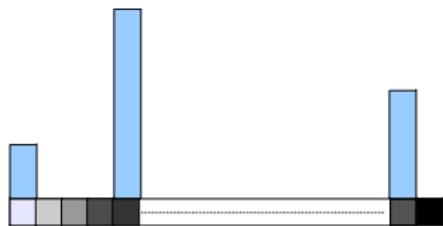


- Scale invariance is desired
- Rotation invariance is desired
- Flip invariance is desired
- Sometimes, color invariance is desired
- ...

Image global features

- They are mostly statistical variables defined on image
- Easy to compute
- Popular global features:
 - Color Histogram
 - Color Moments
 - Histogram of Oriented Gradients
 - VLAD: globalized local feature (talk later)

Color Histogram (1)

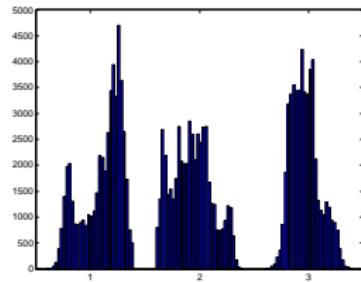


- Counting num. of pixels in each color range
- For **color** images:
 - Apply CH on each channel
 - Concatenate the vectors

Color Histogram (2)



(a) Original image



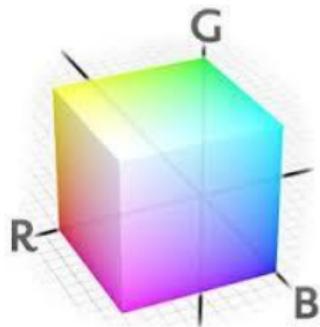
(b) Color histogram from RGB channels

Color Histogram (3)

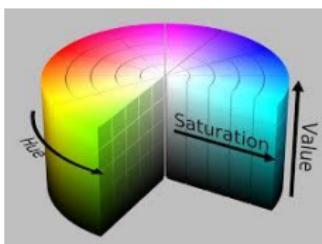
```
1 img1 = imread('lena.jpg');
2 r1 = im2double(img1(:,:,1))*256;
3 hr = hist(reshape(r1,(225*225),1),32);
4 g1 = im2double(img1(:,:,2))*256;
5 hg = hist(reshape(g1,(225*225),1),32);
6 b1 = im2double(img1(:,:,3))*256;
7 hb = hist(reshape(b1,(225*225),1),32);
8 hist = [hr;hg;hb];
9 bar(hist);
10
```

Listing 1: Code to calculate histogram of 3 channels

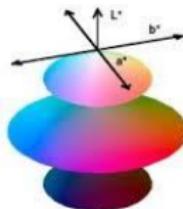
Color Spaces



(c) RGB color space



(d) HSV color space



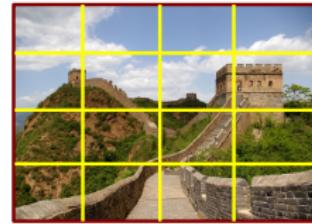
(e) Lab color space

- Image can be represented with different color spaces
- There are formulars to do the transform in between
- Color histograms on HSV and Lab are more distinctive

Color Moment

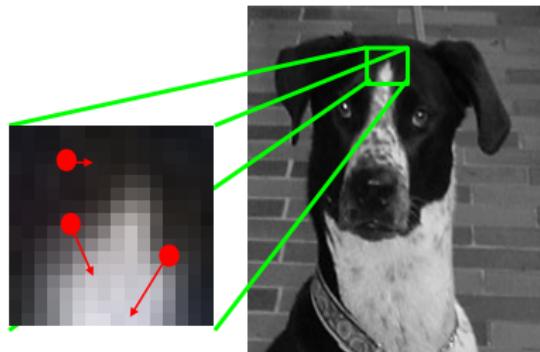
- Intensity value distribution (on one channel) is viewed as a statistical variable
- We can calculate its moments (usually referred as central moment)
- Which is given below

$$\mu_n = E[X - E[x]]^n$$



- $E[x]$ is calculated by taking the average
- n is the order
- Moments are concatenated and moments from different blocks are concatenated
- It turns out to be simple but pretty successful

HOG: Histogram of Oriented Gradients



$$\nabla I(x, y) = \left(\frac{\partial I(x, y)}{\partial x}, \frac{\partial I(x, y)}{\partial y} \right) \quad (1)$$

- π + π

- Orientation

- Magnitude

$$m = \sqrt{ \frac{\partial I(x, y)^2}{\partial x} + \frac{\partial I(x, y)^2}{\partial y} } \quad (2)$$

$$\theta = \tan^{-1} \frac{\frac{\partial I(x, y)}{\partial y}}{\frac{\partial I(x, y)}{\partial x}} \quad (3)$$

Partial Derivatives on Image

- Image is a multi-variable function $f(x, y)$
- When taking derivatives, $dx=dy=1$
- As a result

$$\frac{\partial I(x, y)}{\partial x} = I(x, y) - I(x - 1, y)$$

- The second order derivative is given as

$$\begin{aligned}\frac{\partial^2 I(x, y)}{\partial x^2} &= [I(x + 1, y) - I(x, y)] - [I(x, y) - I(x - 1, y)] \\ &= [I(x + 1, y) + I(x - 1, y)] - 2 \cdot I(x, y)\end{aligned}$$

How well are the global features?



Scaling



Rotation



Affine



Flip



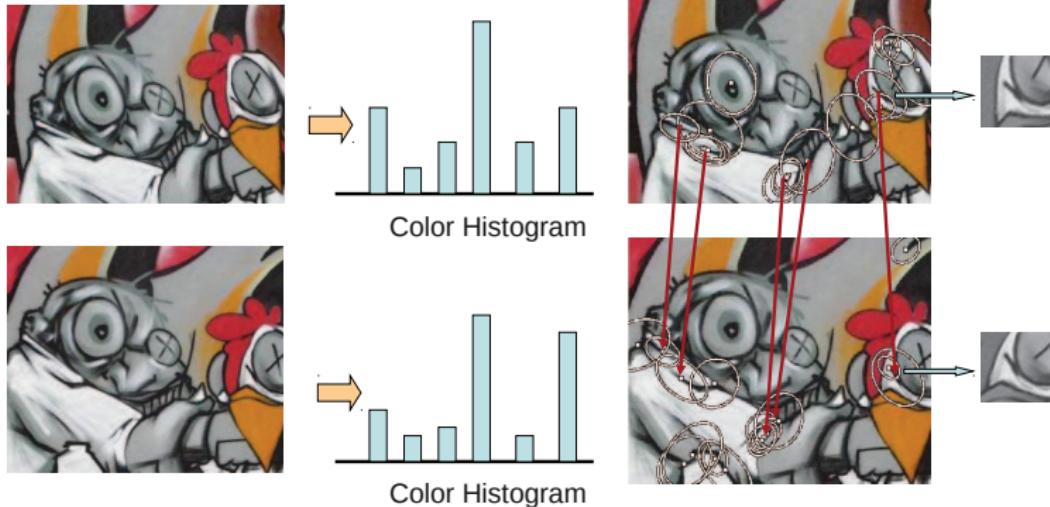
Occlusion

Transform	CH	HOG	Human vision
Scale	partially	partially	fully ¹
Rotation	fully	no	fully
Affine	partially	partially	fully
Flip	fully	no	fully
Occlusion	no	no	fully
Light/Color	vulnerable	vulnerable	fully
Blur	vulnerable	vulnerable	partially
View point	vulnerable	vulnerable	partially

- Homework:
 - Submit transformed images as query to Google image
 - See how well the system achieves invariances

¹except for extreme cases

Global Feature vs Local Interest Point Feature

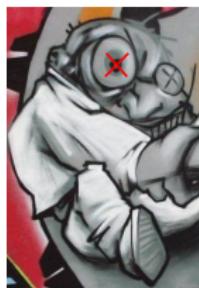


(a) Two paradigms for evaluating similarity between two images: global feature against local feature

- Images are compared in a finer granularity

Scale Invariance: the concept (1)

- We already mentioned this concept before
- We study how we can achieve this for image local feature



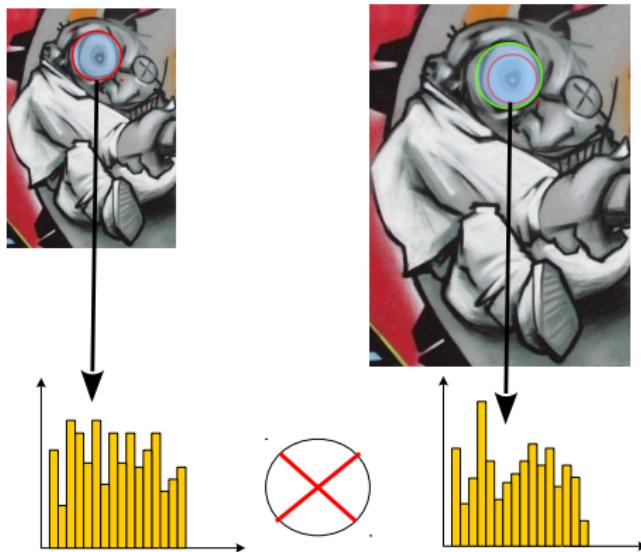
- Local feature is detected, we cannot simply compare their pixel values
- They are simply not distinctive

Scale Invariance: the concept (2)



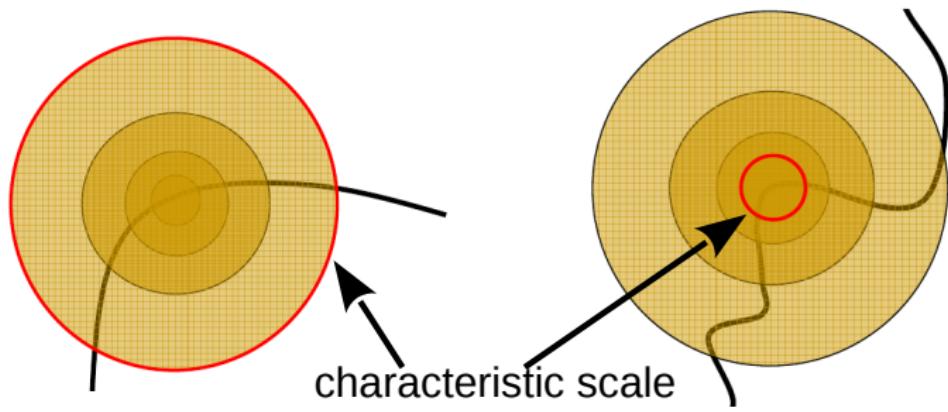
- We need to compare a local region
- But how to scope this local region?
- Fix the size for all points detected?

Scale Invariance: the concept (3)



- It is not working!!
- Fixed size does not cover the same region in two different images
- What we expect is the region scoped by green circle

Scale Invariance: the concept (4)



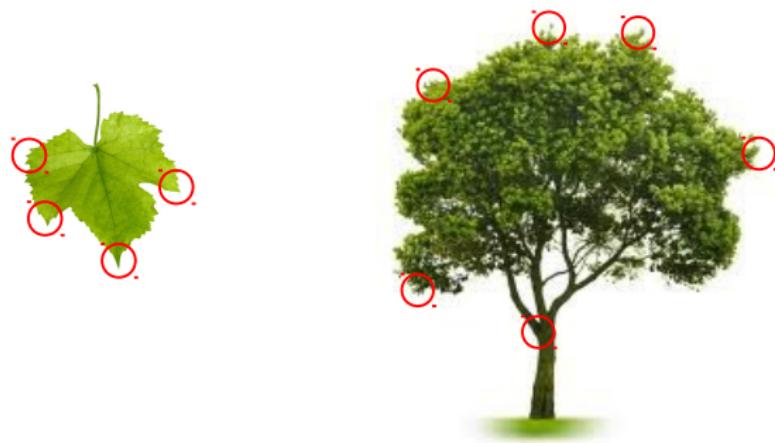
- We are looking for something like this
- The selected scale in two images cover the same local structure
- Notice that we detect corners from each image independently

Scale Invariance: scale space (1)



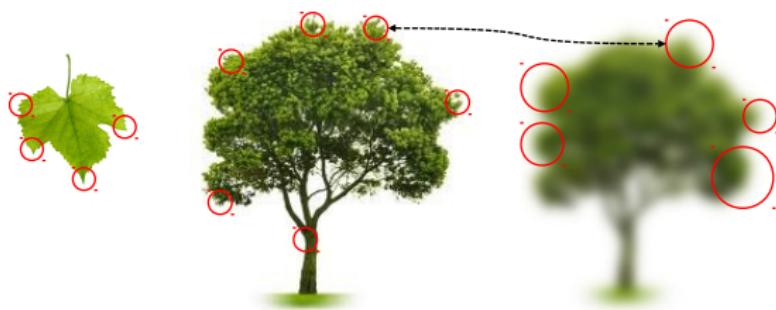
- In order to achieve scale invariance, let's look at scale space first
- What you can see you stand under tree?
- What you can see you stand 50 meters away from the tree?

Scale Invariance: scale space (2)



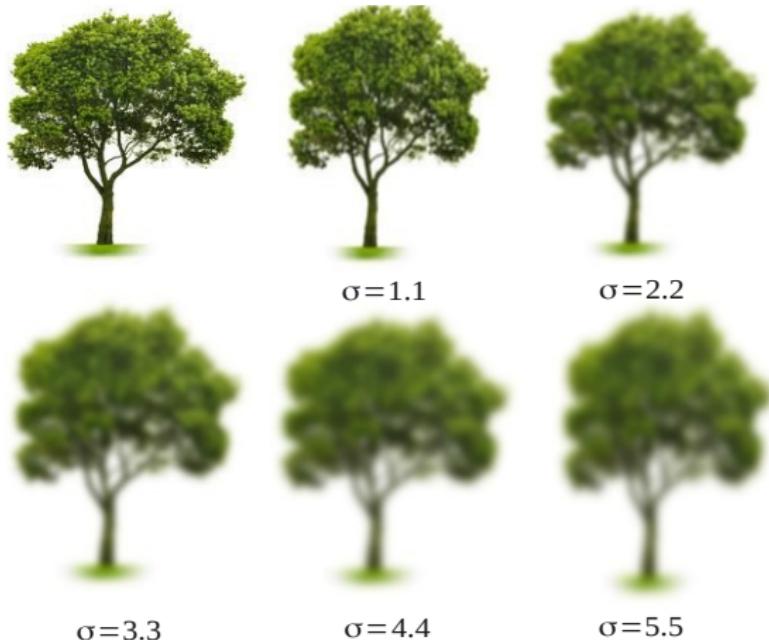
- Now you are asked to finger out corners from the leaf and from the tree
- Are you convinced?
- Can you still see the corners in one leaf when you stand 50 meters away?

Scale Invariance: scale space (3)



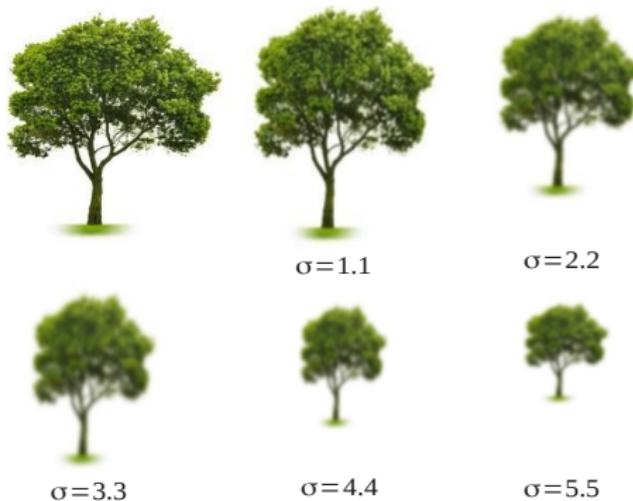
- Now let's move to 200 meters away from the tree
- What you can see??
- Conclusion: **certain corners only appear/survive in certain range of scales/watching distances**

Scale Invariance: scale space (4)



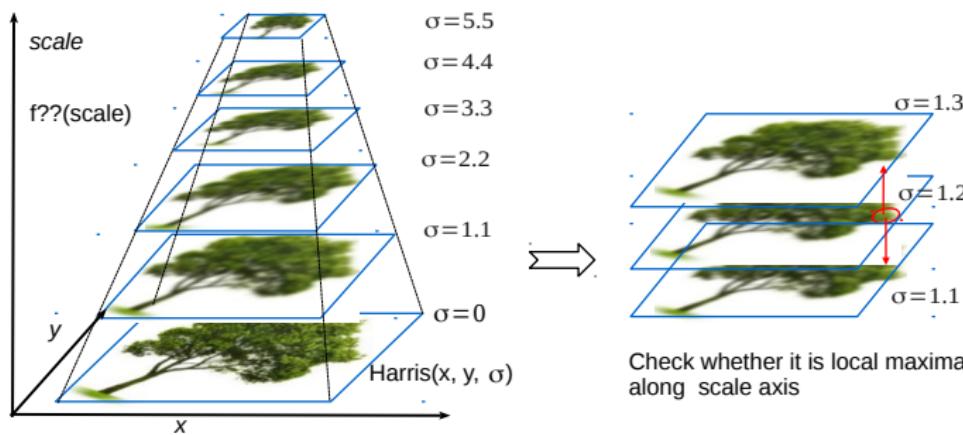
- Once the photo is taken, the distance between the tree and our watch position is fixed
- We simulate this by convolution with different σ s

Scale Invariance: scale space (5)

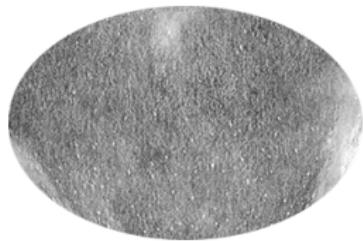


- When the image is blurred heavily, it is no need to keep its original size
- So finally we have above blurred image series
- As mentioned before, in different distances, you see different corners
- We want to find these stable points, which are visible within certain distance range

Scale Invariance: scale space (6)

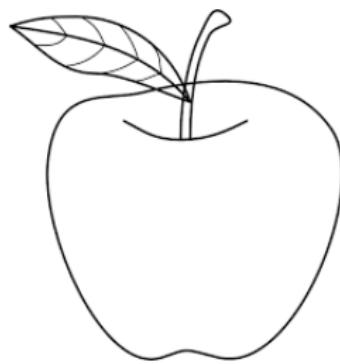


- If we stack up this series of blurred images
- We have this pyramid
- Stable points are those which attain local maximum in scale space
- Local maximum means it is '**salient**' within certain distance range





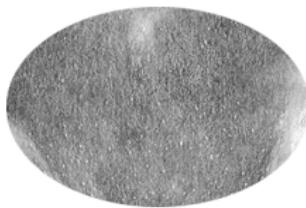
Why edges (2)



Why edges (3)



(a)



(b)



(c)

- Edges use less number of pixels than color blocks (Fig. (b)-(c)), however turn out to be more informative

Why edges (4)



(a)



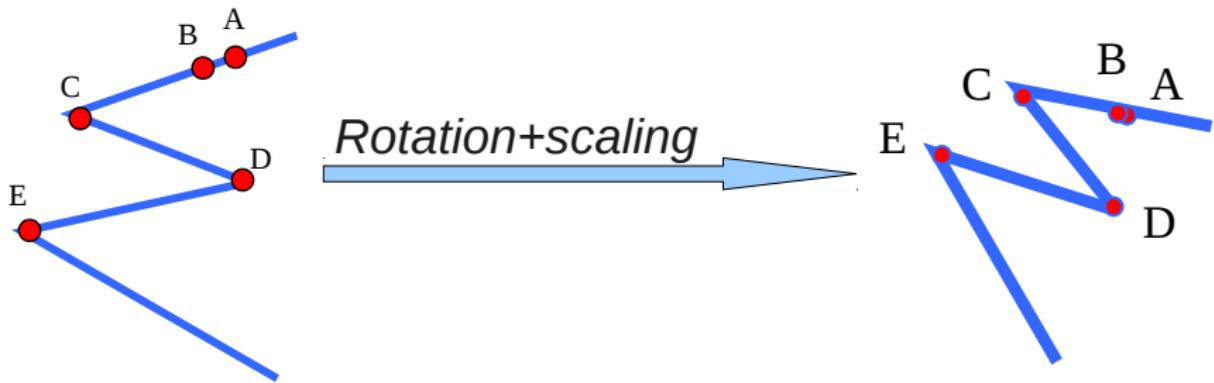
(b)



(c)

- Edges already carry most of the information to outline an object

Why corners instead of edges (1)



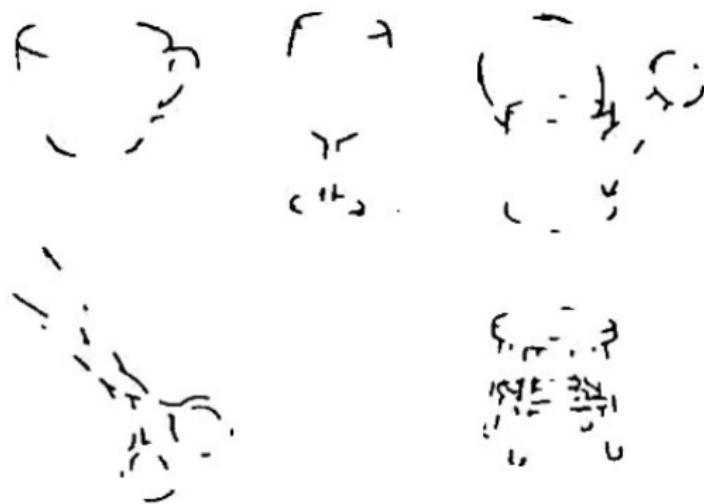
- Points (A, B) along the edges merged to each other
- The same for points in the flat region
- Corners (C, D, E) survive through scaling and rotation
- Different regions have different degree of robustness
- Corners are preferred

Why corners instead of edges (2)



- Guess what are the objects with edges only (corners are largely removed)

Why corners instead of edges (3)



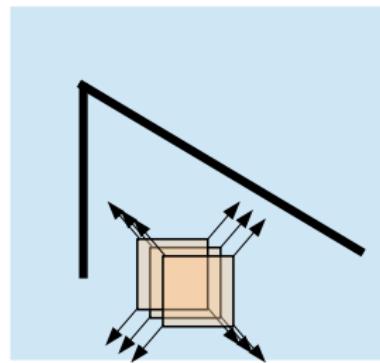
- Guess what are the objects with corners only

Why corners instead of edges (4)

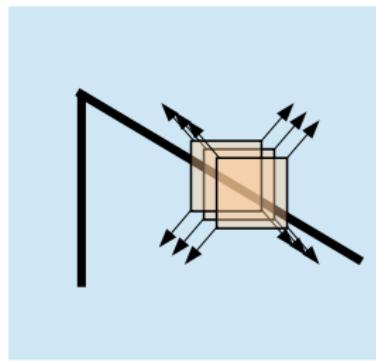


- Check your answer

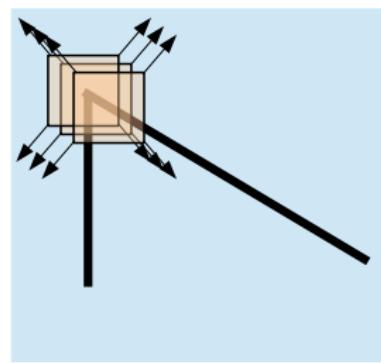
How to detect the corners



(a)



(b)



(c)

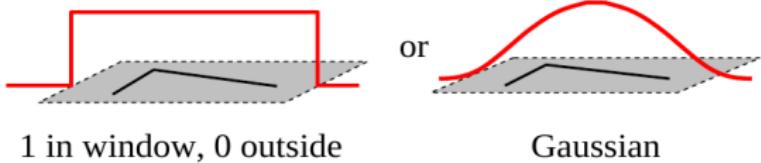
- Take an observing window, and move around
- No change in (a)
- Change happens along one direction in (b)
- Strong responses in two directions in (c)

Formularize the probing procedure (1)

$$E(u, v) = \sum_{x, y} w(x, y) \cdot [I(x+u, y+v) - I(x, y)]^2$$

Window function
 Shifted intensity
 Intensity

Window function $w(x, y) =$



- Measuring the energy changes
- w is the probing window
- u and v are the shifts in x and y directions

Formularize the probing procedure (2)

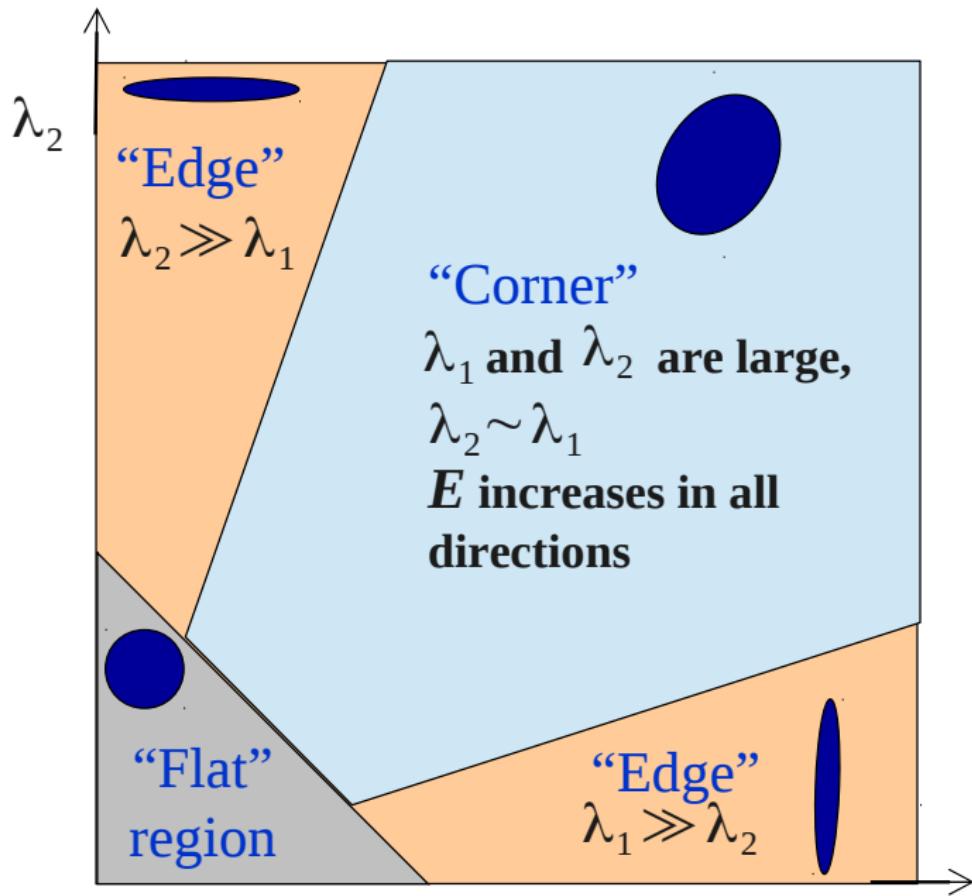
$$I(x+u, y+v) \approx I(x, y) + u \cdot I_x(x, y) + v \cdot I_y(x, y)$$

$$\begin{aligned} E(u, v) &= \sum_{x,y} w(x, y)[I(x + u, y + v) - I(x, y)]^2 \\ &= \sum_{x,y} w(x, y)[I(x, y) + uI_x(x, y) + vI_y(x, y) - I(x, y)]^2 \\ &= \sum_{x,y} w(x, y)[uI_x(x, y) + vI_y(x, y)]^2 \\ &= [u, v] \left(\sum_{x,y} w(x, y) \begin{bmatrix} I_x^2 & I_x I_y \\ I_x I_y & I_y^2 \end{bmatrix} \right) \begin{bmatrix} u \\ v \end{bmatrix} \end{aligned} \tag{4}$$

Formularize the probing procedure (3)

$$\begin{aligned}
 E(u, v) &= \sum_{x,y} w(x, y)[I(x + u, y + v) - I(x, y)]^2 \\
 &= \sum_{x,y} w(x, y)[I(x, y) + uI_x(x, y) + vI_y(x, y) - I(x, y)]^2 \\
 &= \sum_{x,y} w(x, y)[uI_x(x, y) + vI_y(x, y)]^2 \\
 &= [u, v] \left(\sum_{x,y} w(x, y) \begin{bmatrix} I_x^2 & I_x I_y \\ I_x I_y & I_y^2 \end{bmatrix} \right) \begin{bmatrix} u \\ v \end{bmatrix}
 \end{aligned} \tag{5}$$

$$E(u, v) = [u, v] \cdot M \cdot \begin{bmatrix} u \\ v \end{bmatrix} \tag{6}$$



Harris Detector: the results

- Steps:
 - ① Compute $\text{Harris}(x, y)$ for each pixel
 - ② Select the points that attain local maximum (**Non-maximum suppression**)
 - ③ Consider points whose $\text{Harris}(x, y) > t_0$



- How to make use of these detected points?
- How the circle comes?

Hessian Detector

- In practice, Hessian function is also a good option

$$H(x, y, \sigma) = \begin{bmatrix} \frac{\partial^2 I(x, y, \sigma)}{\partial x^2} & \frac{\partial^2 I(x, y, \sigma)}{\partial x \partial y} \\ \frac{\partial^2 I(x, y, \sigma)}{\partial y \partial x} & \frac{\partial^2 I(x, y, \sigma)}{\partial y^2} \end{bmatrix}$$

$$\text{Hessian}(x, y, \sigma) = \text{Det}(H(x, y, \sigma)) * \sigma^2$$

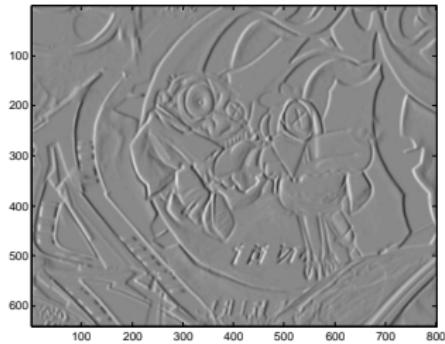
Hessian Detector: steps

- ① Convert input color image into gray level image (optional)
- ② Design D_{xx} , D_{xy} , D_{yy} Gaussian templates
- ③ Apply D_{xx} , D_{xy} , D_{yy} template on the gray level image
- ④ Calculate Hessian function based on following Equation

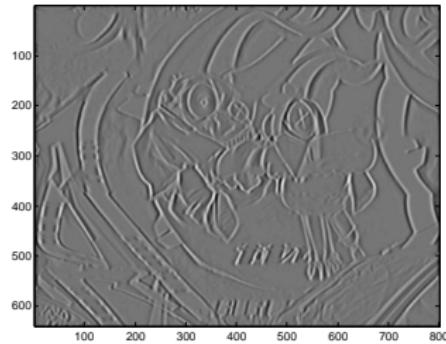
$$H(x, y, \sigma) = \sigma^4 * (D_{xx} * D_{yy} - D_{xy}^2)$$

- ⑤ Apply non-maximum suppression on Hessian function image
- ⑥ Display points higher than a threshold

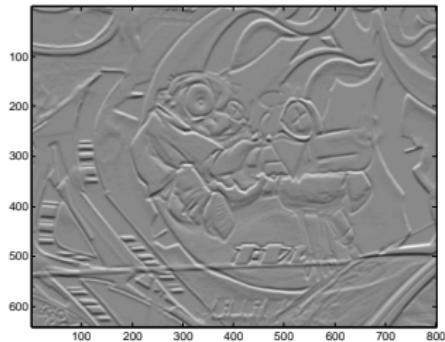
Hessian Detector: the derivatives



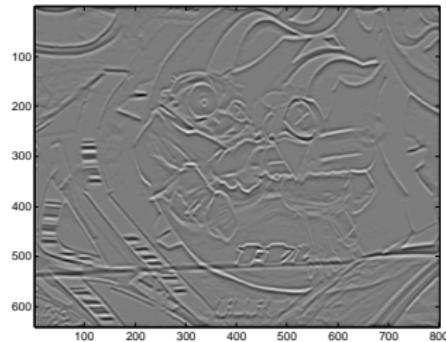
(d) imgDx



(e) imgDxx

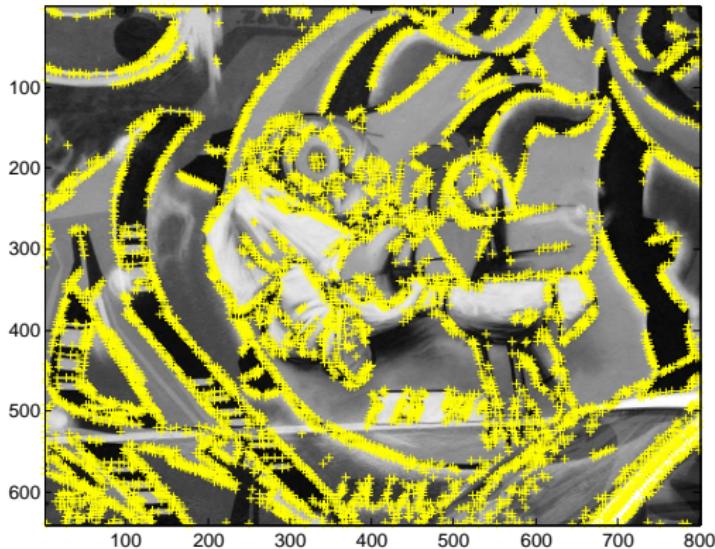


(f) imgDy



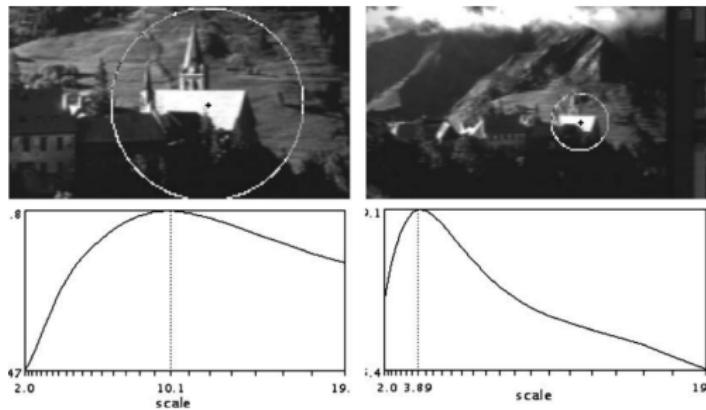
(g) imgDyy

Hessian Detector: the derivatives



Scale Invariance by Hessian Detector

- Calculate Hessian with a series of $\sigma_1, \sigma_2, \dots$

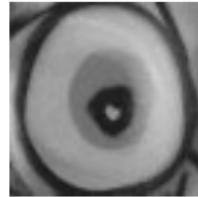
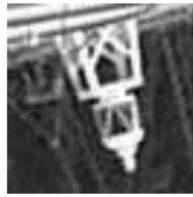


- Take the σ where $H(x, y, \sigma)$ achieves local maxima as the **characteristic scale**

$$H(x, y, \sigma) = \sigma^4 * (D_{xx} * D_{yy} - D_{xy}^2)$$

SIFT descriptor: the motivation

- Up to now, we are able to extract local point as a local patch
- To check whether two local patches are similar or not
- We need a feature representation for this local patch
- There are dozens of options: CH, CM or Gabor (wavelet feature)
- SIFT turns out to be the most successful one

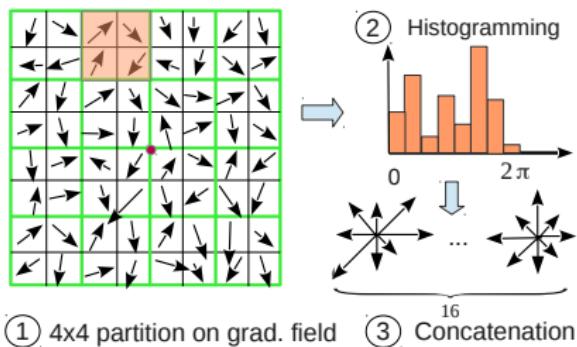


Overview about SIFT descriptor

- It is known the best local interest point (keypoint) descriptor
- Num. Of citations: 31,039 (up to 14th, Aug., 2015)
- It is distinctive, but still tolerant to small errors (displacement, lighting changes, deformation) in the local patch
- When people talk about image local features, people talk on the basis of SIFT

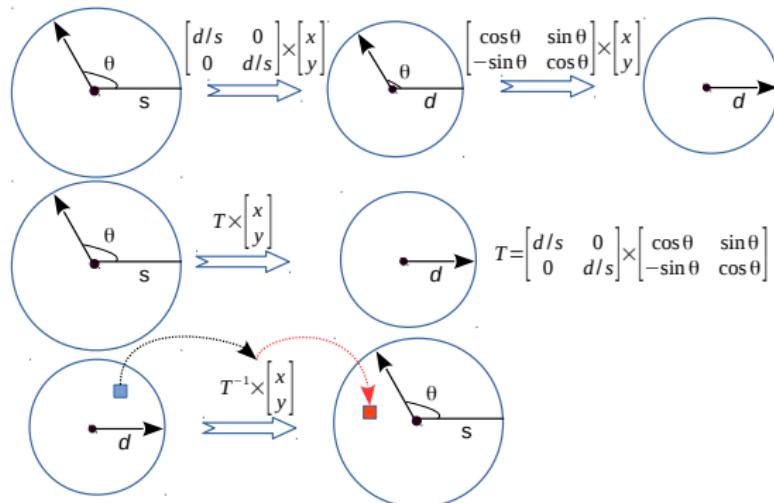
- Refer to: David G. Lowe, Distinctive Image Features from Scale-Invariant Keypoints, IJCV'04, pp. 91-110.

SIFT descriptor: the procedure



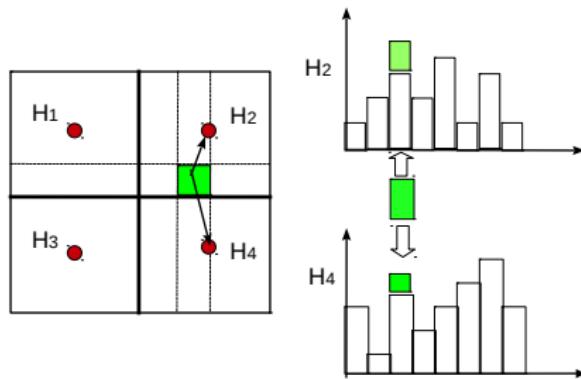
- Pre-processing steps:
- Normalize the patch to $2d \times 2d$
- Calculate gradient field
- SIFT generation:
 - ① Partition gradient into 4×4 grid
 - ② Compute gradient histogram on each block
 - ③ Concatenate 16 histograms as the final feature

Three tricks in SIFT Implementation: (1)

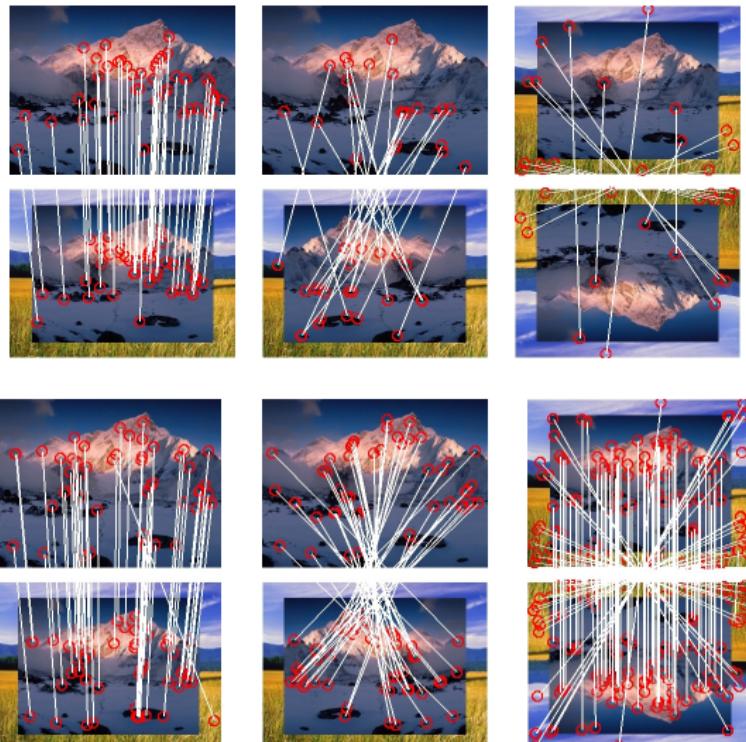


- ① Extracting hole-less Normalized Patch
- ② 2D interpolation
- ③ Removal of abnormal peaks

Three tricks in SIFT Implementation (2)



- ① Extracting hole-less Normalized Patch
- ② 2D interpolation
- ③ Removal of abnormal peaks



(a) Scale

(b) Scale+flip

(c) Rotate+flip

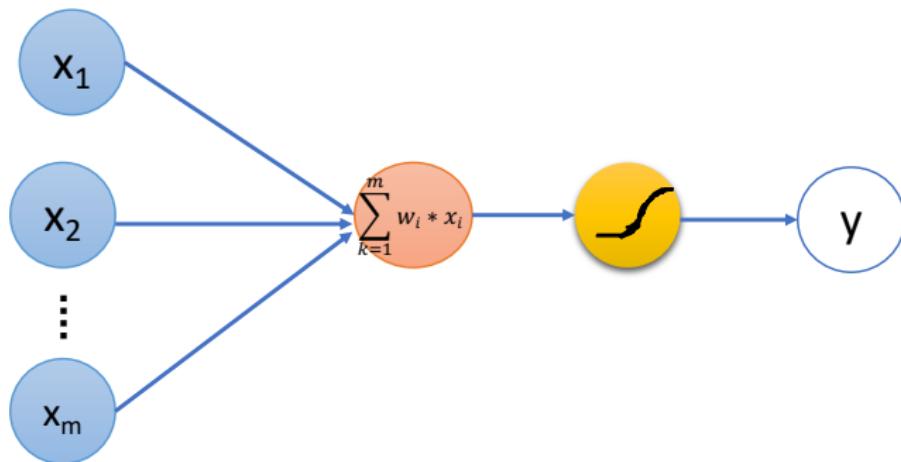
Summary over Geometric Invariances

- Based on different schemes, we can achieve
 - ① **Scale invariance** by detecting points in scale-space
 - ② **Rotation invariance** by estimating the dominant orientation
 - ③ **Affine invariance** by adapting to local structure
 - ④ **Flip invariance** by estimating the dominant angular moment

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- 2 Scale Space
- 3 Local Features
- 4 Deep Features
- 5 References

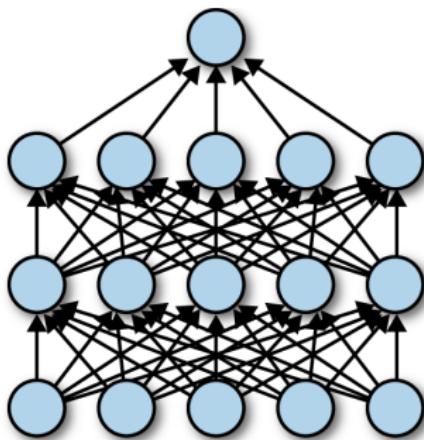
Perceptron: a Review



$$N(x) = \eta\left(\sum_{i=1}^m w_i \cdot x_i + b\right) \quad (7)$$

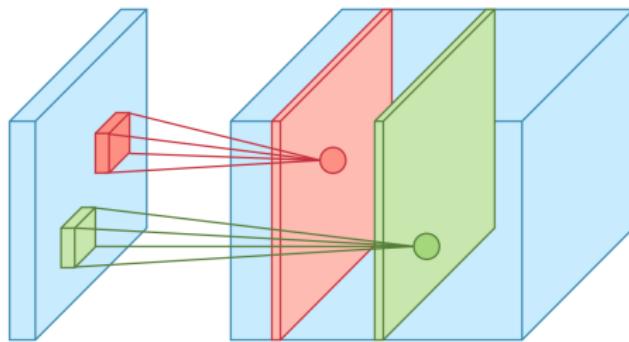
- The basic element for a neural Network is neuron
- It consists of a linear mapping with a non-linear activation

Dense Network: a Review



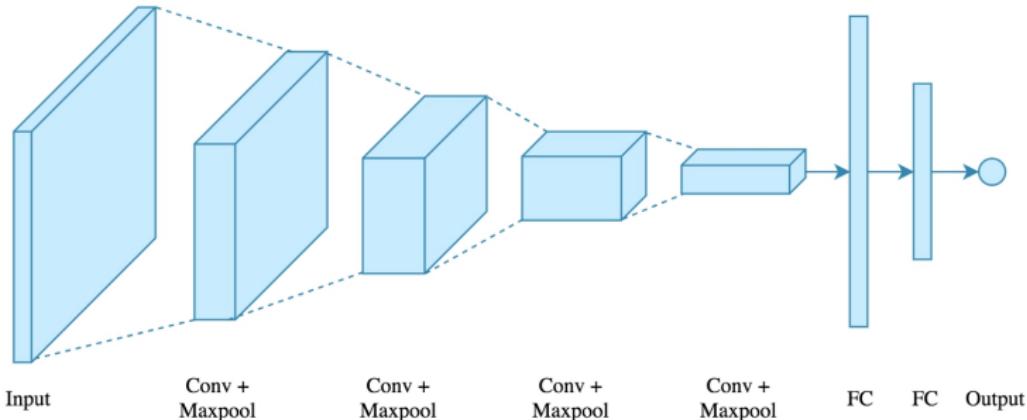
- Dense Network

Convolution Neural Network (1)



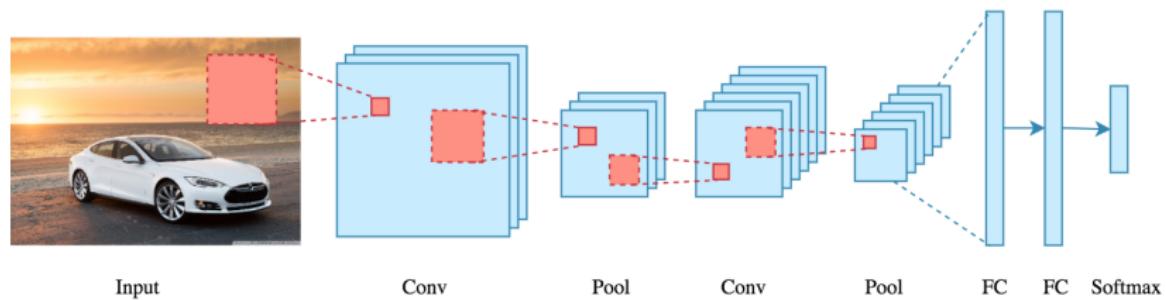
- One filter convolves over the whole image
- The resulting image is called a feature map
- One filter is trained to pick certain pattern from the image

Convolution Neural Network (2)



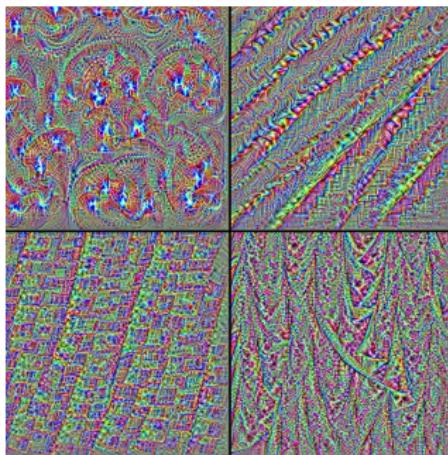
- A complete CNN is a stack-up of several CNN layers

Convolution Neural Network (3)



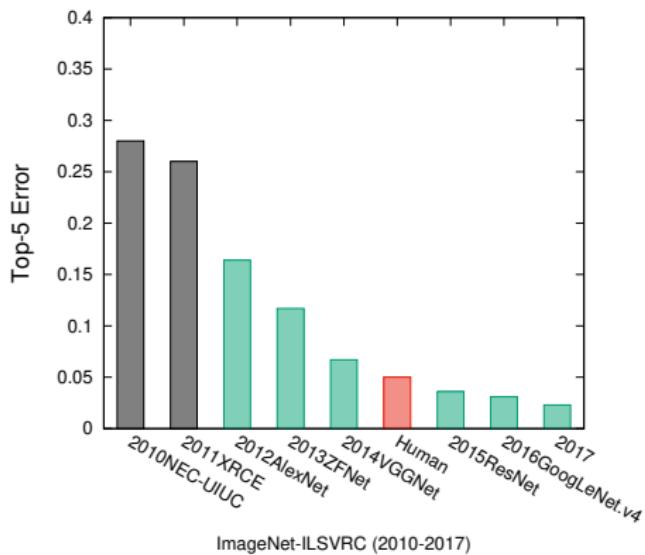
- CNN is first found to be powerful for image classification task
- The filter maintains the relative location pixels

Convolution Neural Network (4)



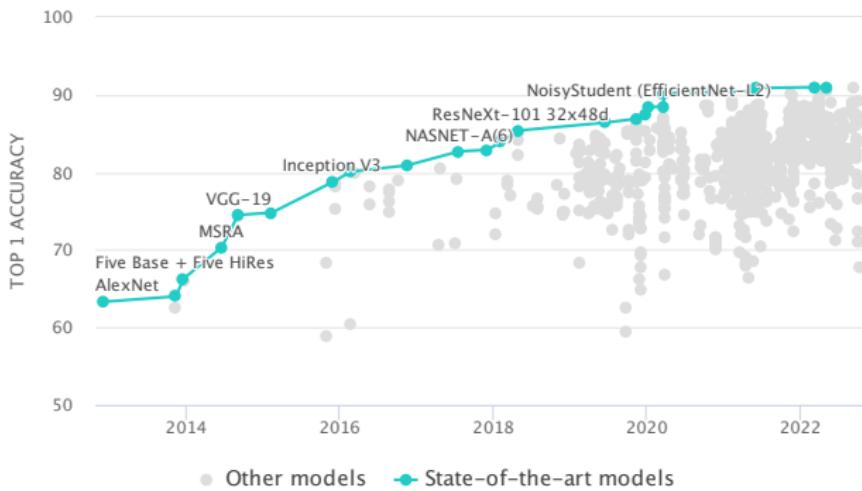
- A visualization of VGG-Block5 filters
- One filter picks a specific pattern from the feature maps of the previous layer

CNN for Classification (1)



- Year 2012 is the starting year of deep learning
- Supervised image classification is no longer a problem

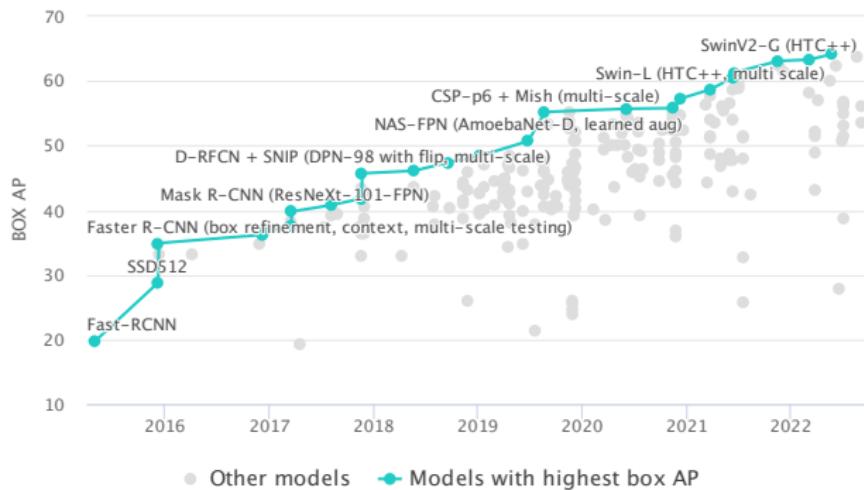
CNN for Classification (2)



- Supervised image classification is no longer a problem²
- It becomes a platform to verify the power of a deep model

²<https://paperswithcode.com/sota/>

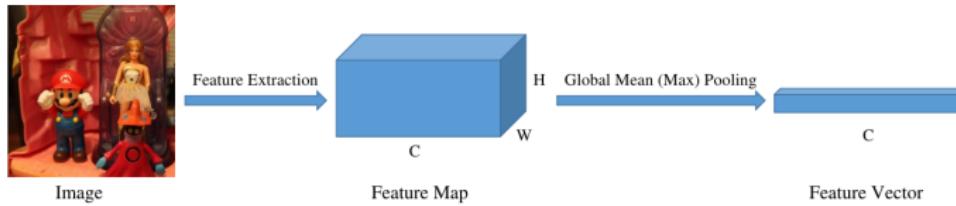
CNN for Object Detection



- The performance of Supervised Object Detection is also saturated³
- Online/semi-supervised/unsupervised Object detection are open issues

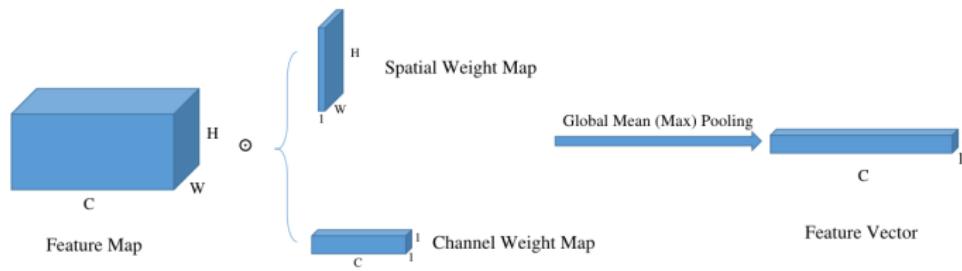
³<https://paperswithcode.com/sota/>

Global Max Pooling



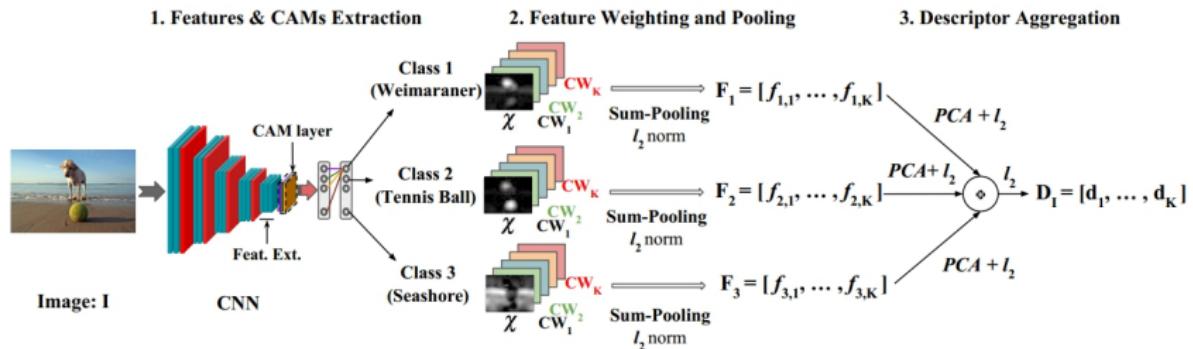
- One feature vector is produced for one image
- Max pooling is applied on one feature map
- Pooling results are concatenated into a fixed length vector

Global Weighted Max Pooling

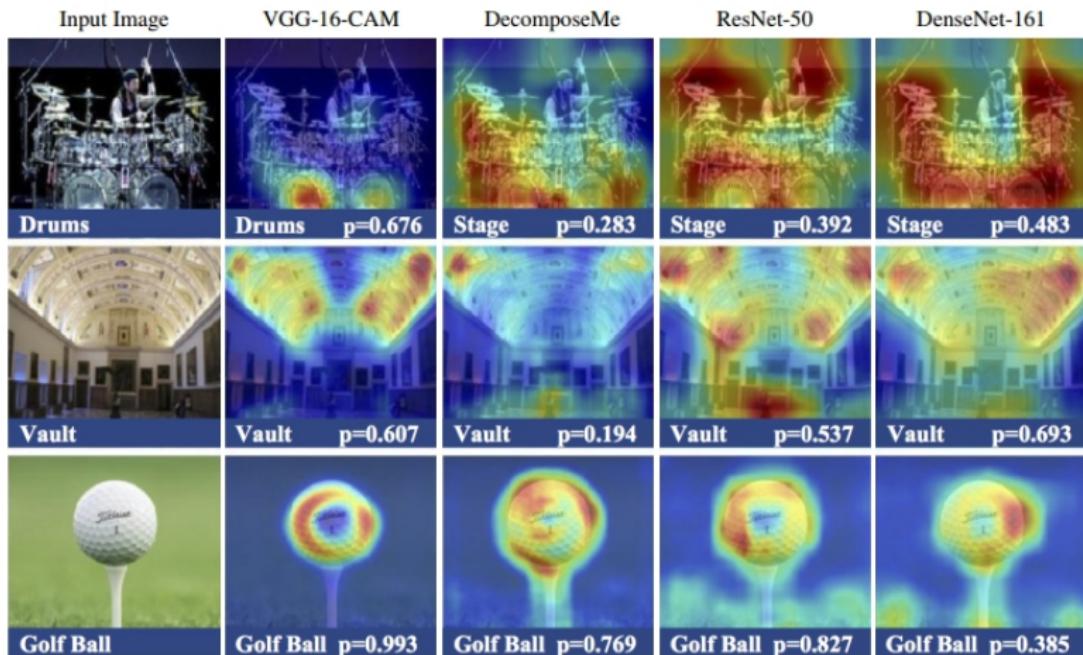


- As a variant, you can assign a weight according to the importance

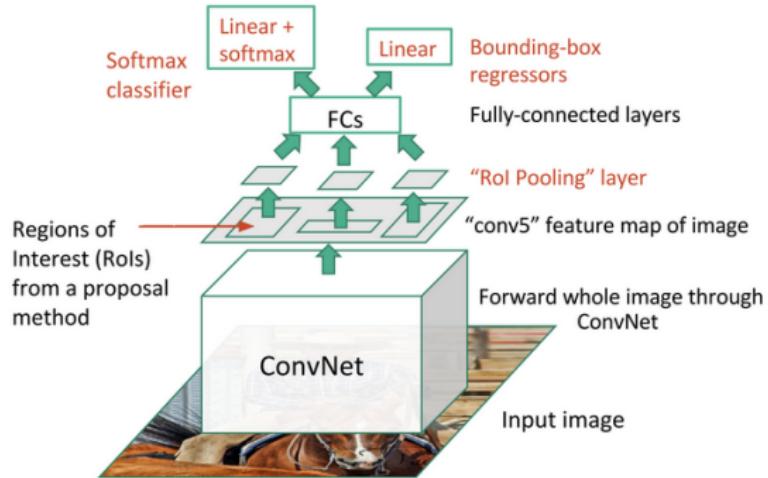
Global Max Pooling Example (1)



Global Max Pooling Example (2)



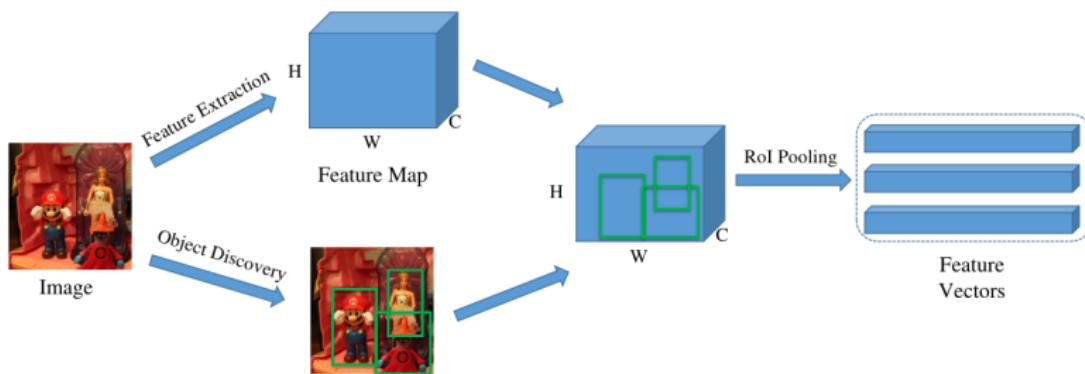
ROI Pooling (1)



- It was first proposed in Faster R-CNN paper⁴
- Different sizes of proposals are converted into the feature maps in the same size

⁴S. Ren, K. He, R. Girshick, J. Sun: Faster R-CNN: Towards Real-Time Object Detection with Region Proposal Networks.

ROI Pooling (2)



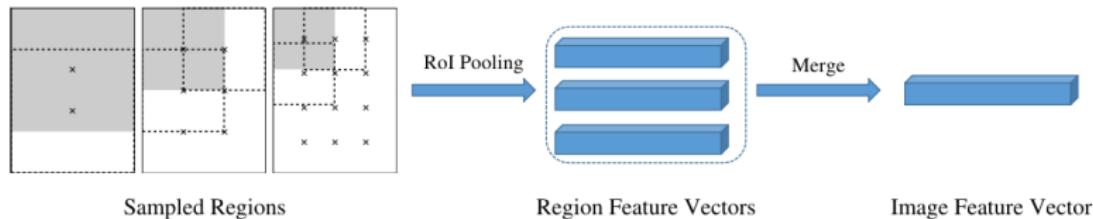
- Given we want to build feature from a local region
- Maxpooling/average pooling is applied on a local

ROI pooling in animation

- Divide the proposals into fixed number of blocks⁵
- Take the maximum/average on each block

⁵View animation with Acrobat Reader

ROI Pooling Example



- R-MAC extracts local features from feature maps

References

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- ③ Flip invariant SIFT for Video Copy and Object Detection, Wan-Lei Zhao and et al. *TIP'13*
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- ⑥ Local Invariant Feature Detectors: A Survey, T. Tuytelaars and K. Mikolajczyk, NoW Publisher Inc. 2008
- ⑦ Class-weighted convolutional features for visual instance search, Jimenez A, Alvarez J M, Giro-i-Nieto X., 2017
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- ⑨ S. Ren, K. He, R. Girshick, J. Sun: Faster R-CNN: Towards Real-Time Object Detection with Region Proposal Networks. ICCV, 2015
- ⑩ Particular object retrieval with integral max-pooling of CNN activations, Tolias G, Sicre R, Jégou H., 2015

Q & A

Thanks for your attention!