Overview: A 3D Surface Tracking Algorithm

Yao Ming

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1 Introduction

This algorithm constructs a surface model from edge voxels. A voxel is identified as being on the surface if its second derivative is negative and changes sign for neighbors in the gradient direction. By this definition, there can only exist one layer of surface voxels, and the tracking algorithm is simply a breadth-first search. Moreover, the definition of surface voxels is not sensitive to gradient directions, thus this approach is robust against noise. The test results on real data are also reported. Section 2 discusses the surface voxel identification method. Section 3 introduces the surface tracking algorithm.

2 Surface Identification

The section presents a 3D surface identification method based on the Laplacian of Gaussian Filter, which means the condition for an edge voxel being on a surface is that the second derivative is negative and changes sign for neighbors in the gradient direction. With this approach, we have to find the zero-crossings of the second derivative.

2.1 Surface Points in Continuous Space

Suppose there is a step intensity change across an object surface. Let $I(x, y, z)$ be the intensity function, $(x, y, z) \in R^3$, where R is the set of real numbers. Without loss of generality, suppose the intensity change occurs at the origin and in the x direction. It will be shown in the following that a zero-crossing occurs at the origin; thus the origin is the desired surface point.

For a bright object surrounded by a darker background, the intensity around the surface can be modeled as a one-dimensional step change, $I(x, y, z) = c(\pi/2 - \arctan(kx))$ for a sufficiently large constant $k > 0$. The constant c describes the magnitude change and k describes the intensity change rate.

To use the Laplacian of Gaussian Filter, we use the smoothing filter $G(x, y, z)$, a Gaussian filter with variance σ. Let $w(x, y, z)$ be the secon derivative in the x-direction of the smoothed function $I(x, y, z)$,

$$w(x,y,z) = \frac{\partial^2}{\partial x^2}[G(x,y,z) * I(x,y,z)], \tag{1}$$

that is,

$$w(x) = \frac{1}{\sqrt{2\pi}\sigma}\int_{-\infty}^{\infty} e^{-x'^2/2\sigma^2}\frac{2ck^3(x-x')}{(1+k^2(x-x')^2)^2}dx', \tag{2}$$

which is a function of x. At $x = 0$,$w(0) = 0$ and

$$w'(0) = \frac{2ck^3}{\sqrt{2\pi}\sigma^3}\int_{-\infty}^{\infty}\frac{x'^2 e^{-x'^2/2\sigma^2}}{1+k^2x'^2}dx' > 0 \tag{3}$$

Hence $w(x)$ is monotonically increasing in the neighborhood of $x = 0$. In other words, $w(x)$ changes sign from negative to positive as it crosses zero at $x = 0$. $x = 0$ is therefore called a zero-crossing.

Let $v = (x, y, z) \in R^3$ and l be a directed line at v pointing outside of the surface. Writing the above equations in terms of v and l, if v is on the surface, it must satisfy the following conditions:

$$\begin{aligned} w(v) &= 0 \\ w(v - \delta l) &< 0 \\ w(v + \delta l) &> 0. \end{aligned} \tag{4}$$

Besides, it's worthwhile to point out that, obviously, the location of zero-crossings is not sensitive to the direction of the second derivative of an intensity change. So it's desirable to take the second derivative in a direction that has a maximum rate of change. Because of the fact that the gradient direction is the one in which the second derivative of the intensity function has the maximum change rate, it is a good choice to use the direction g, the gradient direction at v, as direction l in equation (4). Then, equation (1) becomes like this:

$$w(v) = G''_g(v) * I(v), \tag{5}$$

and equation (4) would be like this:

$$\begin{aligned} w(v) &= 0 \\ w(v - \delta g) &< 0 \\ w(v + \delta g) &> 0. \end{aligned} \tag{6}$$

2.2 Surface Voxels in Discrete Space

In discrete space, we would first introduce the concept of the positive layer and the negative layer of voxels, and then define surface voxels in a discrete space.

Let $I(v) \in N, N = \{0, 1, 2, ...\}$ be an intensity function defined on a discrete domain, $v = (x, y, z) \in Z^3, Z = \{0, \pm 1, \pm 2, ...\}$. For simplicity, v is called a voxel. Let $G''_g(x, y, z)$ be a finite scale discrete Gaussian filter, resulting from sampling G''_g in (5) in a finite interval $(-3\sigma, 3\sigma)$, and let $w(x, y, z)$ be the discrete convolution of $G''_g(x, y, z)$ with $I(x, y, z)$,

$$w(x, y, z) = G''_g(x, y, z) * I(x, y, z). \tag{7}$$

If $v = (x, y, z)$ is a surface voxel, $w(x, y, z) = 0$.

In discrete space, not many voxels have $w(x, y, z) = 0$. Condition (6) however, implies that for a bright object surrounded by a darker background and for those voxels close to a surface, $w(x, y, z)$ is negative inside the object and positive outside. There can only exist one layer of voxels on which $w(x, y, z)$

is negative and changes sign for neighbors in the gradient direction. This layer is called the negative layer. Similarly, there exists exactly one positive layer of voxels. It is possible to define either the negative layer or the positive layer as the surface. Since the negative layer is part of the object, the surface is defined as the negative layer of voxels. Zero-crossing voxels can be treated as either positive or negative and are also included in the surface set. The first condition of (6) therefore becomes $w(x, y, z) \leq 0$.

As another two conditions in (6), we have to test every possible nonzero situation of the gradient of $I(v)$ at v and get the corresponding conditons in discrete space.

To summarize, for a bright object surrounded by a darker background, if $v(x, y, z)$ is a surface voxel, it must simultaneously satisfy the following inequalities:

$$\begin{aligned} w(x, y, z) &\leq 0, \\ w(x+1, y, z)w(x-1, y, z) &< 0, if \nabla_x \neq 0, \\ w(x, y+1, z)w(x, y-1, z) &< 0, if \nabla_y \neq 0, \\ w(x, y, z+1)w(x, y, z-1) &< 0, if \nabla_z \neq 0, \end{aligned} \tag{8}$$

The inequalities (8) is the condition to identify surface voxels in a discrete space. Obviously, there is only one layer of voxels that will satisfy the condition. This makes subsequent surface tracking much easier.

3 The Surface Tracking Algorithm

In this section, we can discuss the tracking algorithms based on the definition of the surface voxel. This algorithms extracts a single layer of surface using inequalities (8) and converts surface voxels to graphical primitives to construct a surface model. We would introduce the definition of graphics primitives first, which is based on the extended cuberille model.

3.1 The Extended Cuberille Model

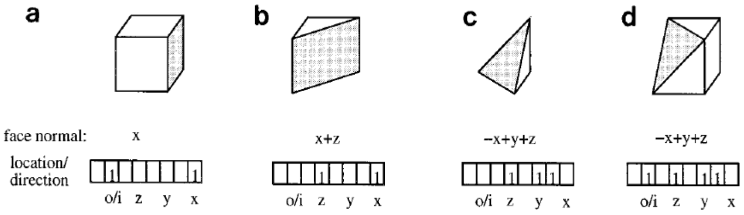

FIG.1. The location/direction codes for the four volume primitives

```
SURFACE_TRACKING($Q\_CELL * current\_voxel$)
unsigned char index;      //the table index
$get\_start\_face()$;      //start voxel coordinates
$span\_start\_face()$;      //span the start voxel
while $current\_voxel == remove\_q\_head()$
        do
            $x, y, z = current\_voxel- > x, y, z$;
            $index = grad\_loc\_dir[x][y][z] \quad \& \quad \sim MARK$;
            $Neighbor\_face(index)$;      //search for surface voxels
            $add\_to\_display\_table(x, y, z, index)$      //add to display table
```