Introduction
Color Space
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Saliency Detection

Zhu Yafei

CVBIOUC
Ocean University of China
http://vision.ouc.edu.cn/~zhenghaiyong

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What?

The eyes capture light which results in information in the order of 10^9 bits every second.

What?

What?

Bottom-Up

Top-Down

Background

- "Feature Integration Theory", Treisman & Gelade, 1980.
- "Guided Search Theory", Wolfe & Cave, 1989.
- "Integrated Competition Theory", Desimone & Duncan, 1995.

Two Waves

Salient Object Detection Model
Fixation Prediction Model
The First Wave
[1998 - 2007]
The Second Wave
[2007-Present]
IT
LC
AIM
LTD
SR
GB
AC
SUN
EDS
FT
SeR
CSM
SEG
CA
MSS
SWD
FES
HC
RC
CB
SVO
SIM
LS
GS
ULR
SF
LG
SS
SIO
HS
PCA
GC
SR
GMR
MC
DSR
DRFI
MNP
LMLC
BMS
COV
LCSP
WISO
SCRT
PDE
RBD
HDCT
LOS
SDLF
SP
1998
2000
2002
2004
2006
2008
2010
2012
2014
Year

Fixation Prediction

Fixation prediction models are constructed originally to understand human visual attention and eye movement prediction.

Representative Method

- A model of saliency-based visual attention for rapid scene analysis. PAMI 1998, Itti et al.

Architecture

Why?

The emergence of salient object detection models is driven by the requirement of saliency-based applications.

Content aware resizing

Object maniputation

Image montage

Image collage

Representative Methods

- Learning to detect a salient object. CVPR 2007, Tie Liu et al.
- Frequency-tuned salient region detection. CVPR 2009, Achanta et al.

Differences and Commons

- Differences
  - Evaluation and Datasets
  - Aims
  - Accuracy requirement
- Commons
  - Both of them generate similar saliency maps

Related Topics

- Image Segmentation
- Object Proposal Generation

Salient Object Detection

- *Block-based* vs. *Region-based analysis*
  Blocks are usually adopted by many early approaches, while regions are increasingly popular with the development of superpixel algorithms.
- *Intrinsic cues* vs. *Extrinsic cues*

Salient Object Detection

Uniqueness		
Local Contrast	Global Contrast	Multi-scale Contrast

Salient object detection is widely defined as capturing the uniqueness, distinctiveness, or rarity of a scene.

- Pixel-based
- Block-based
- Region-based

Definition

- *Color* is the visual perceptual property corresponding in humans to the categories called red, blue, yellow and others.
- *Color Space* is defined to identify colors numerically by their coordinates.

Three Elements of Color

- Hue: What we think as "color"–yellow, orange, cyan and magenta are examples of different hues
- Saturation: Saturation refers to the relative purity or the amount of white light mixed with a hue
- Intensity

Device-independent spaces

- CIE XYZ
- CIELAB
- CIELUV

Device-dependent spaces

- RGB、CMYK

Transformation

Almost all the color spaces can be transformed from RGB color space.

What are features?

An image feature is a general term but it usually means a part of an image that contains interesting details or a property of the image which we are interested in.

- Edges
- Points
- Regions

Edges

Edges are points that are at the boundary of two image regions and are detected by computing the change in brightness.

Image before and after applying edge detection

Corners/interest points

A corner is the point located at the intersection of two edges and you can think of an interest point as a small region in the image(window) for which no matter in which neighboring direction you look there is a high variations in brightness.

Blobs/regions of interest

Blobs, or regions of interest, are regions where the brightness or color of the points change very little so they can be considered in some sense to be similar to each other.

Detected largest blob highlighted in green.

feature vs *feature descriptor*

Feature detection A low-level image processing operation and it examines every pixel to see if the region around that pixel could be used as a feature.

Feature description Once the features that are interesting to us have been detected, they can be extracted. The result is known as a feature descriptor or feature vector and they characterize the region around the key point.

Feature Descriptor

- Invariance
- Distinguishability

SIFT、、

Steps

Pre-processing
(eg. grayscale,
gaussian blur)
Feature detection
(eg. corners with
Harris detector)
Feature description
(eg. SIFT descriptor)
88 82 84 88 85 83 80 93 102
88 80 78 80 80 78 73 94 100
85 79 80 78 77 74 65 91 98
38 35 40 35 39 74 77 70 63
20 25 23 28 37 69 64 60 57
22 26 22 28 40 65 64 59 34
24 28 24 30 37 60 58 56 66
21 22 23 27 38 60 67 65 67
23 22 22 25 38 59 64 67 66
Matching /
Indexing /
Recognition

What is texture?

Texture is actually a very nebulous concept, often attributed to human perception, as either the feel or the appearance of (woven) fabric.[1]

[1] Mark S.Nixon and Alberto S.Aguado, "Feature Extraction & Image Processing for Computer Vision"

Texture Descriptor

- Structural approaches
- Statistical approaches
- Combination approaches
- Local binary patterns

LBP(Local Binary Pattern，局部二值模式)

LBP

Regional property descriptor

- Appearance feature descriptor
- Geometric feature descriptor

Regional contrast descriptor

Priors

- Center Prior/Location Prior
- Backgroundness Prior
- Boundary Connectivity Prior
- Color Prior
- Objectness Prior
- Smoothness Prior

Center Prior/Location Prior

Objects near the image center are more attractive to people.[2]

This prior can be simply and effectively modeled as a Gaussian map.

$$S_D(\mathbf{x}) = exp\left(-\frac{||\mathbf{x}-\mathbf{c}||_2^2}{\sigma_D^2}\right) \qquad (1)$$

[2] Zhang, Lin and Gu, Zhongyi and Li, Hongyu, "SDSP: A novel saliency detection method by combining simple priors", in ICIP, 2013.

Center Prior/Location Prior

The salient object in an image is most probably placed near the center of the image.[3]

Gaussian falloff weight:

$$w_i^{(n)} = exp(-9(dx_i^{(n)})^2/w^2 - 9(dy_i^{(n)})^2/h^2 \tag{2}$$

[3] Jiang, Huaizu and Wang, Jingdong, "Automatic salient object segmentation based on context and shape prior", in BMVC, 2011

Center Prior/Location Prior

Assigning higher saliency to the image elements near the image center becomes invalid when the objects are placed far off the image center[4].

- Compute a convex hull enclosing interesting points to estimate the location of salient region.
- Use the centroid of the convex hull as the center to get the convex-hull-based center prior map.

[4] Yang, Chuan and Zhang, Lihe and Lu, Huchuan, "Graph-regularized saliency detection with convex-hull-based center prior", in Signal Processing Letters, IEEE, 2013

Backgroundness Prior

Backgroundness prior is more general than center prior because salient objects can be placed off the center, but they seldom touch the image boundary.[5]

- Assuming that a narrow border of the image is background region, regional saliency can be computer as the contrast versus "background".

[5] Wei, Yichen and Wen, Fang and Zhu, Wangjiang, "Geodesic saliency using background priors", in ECCV, 2012.

Boundary Connectivity Prior

Object regions are much less connected to image boundaries than background ones.[6]

Boundary connectivity is defined to quantify how heavily a region R is connected to the image boundaries.

$$BndCon(R) = \frac{|\{p|p \in R, p \in Bnd\}|}{\sqrt{|\{p|p \in R\}|}} \tag{3}$$

[6] Zhu, Wangjiang and Liang, Shuang, "Saliency optimization from robust background detection", in CVPR, 2014.

Color Prior

Warm colors, such as red and yellow, are more pronounced to the human visual system than cold colors, such as green and blue.[7]

$$f_{an}(\mathbf{x}) = \frac{f_a(x) - mina}{maxa - mina}, f_{bn}(\mathbf{x}) = \frac{f_b(x) - minb}{maxb - minb} \tag{4}$$

$$S_c(\mathbf{x}) = 1 - exp\left(-\frac{f_{an}^2(\mathbf{x}) + f_{bn}^2(\mathbf{x})}{\sigma_c^2}\right) \tag{5}$$

- a^*-channel represents green-red information
- b^*-channel represents blue-yellow information

[7] Zhang, Lin and Gu, Zhongyi and Li, Hongyu, "SDSP: A novel saliency detection method by combining simple priors", in ICIP, 2013.

Objectness Prior

Objectness is defined as the probability of there being a complete object in a local window centered on each pixel.[8]

- Randomly sample N windows over the image
- Assign each window w a probability score $P(w)$ to indicate its objectless
- Sum all the probability scores in windows that contains pixel x

$$O_p(x) = \sum_{w \in W \ and \ x \in w} P(W_x) \tag{6}$$

[8] Jiang, Peng and Ling, Haibin, "Salient region detection by ufo: uniqueness, focusness and objectness", in ICCV, 2013

Smoothness Prior

Smoothness constraint is often encoded by adding a pair-wise potential to the energy function which encourages neighboring pixels in the image to take the same label.[9]

$$w_{ij} = exp\left(-\frac{||c_i - c_j||}{2\sigma_w^2}\right) \tag{7}$$

$$E(S) = \sum_i (S(i) - S_i n(i))^2 + \lambda \sum_{i,j} w_{ij}(S(i) - S(j))^2 \tag{8}$$

[9] Yang, Chuan and Zhang, Lihe and Lu, Huchuan, "Graph-regularized saliency detection with convex-hull-based center prior", in Signal Processing Letters, IEEE, 2013.

SDSP[10]

[10] Zhang, Lin and Gu, Zhongyi and Li, Hongyu, "SDSP: A novel saliency detection method by combining simple priors", in ICIP, 2013.

Thanks

Yafei Zhu
Ocean University of China
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