Machine Vision

Chapter 3: Edge and Corner Detection

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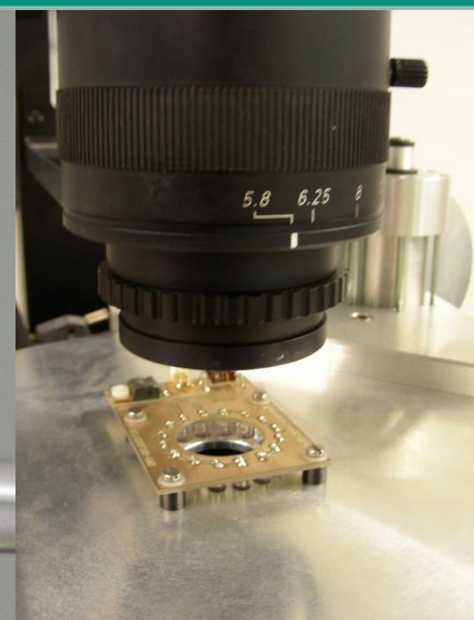
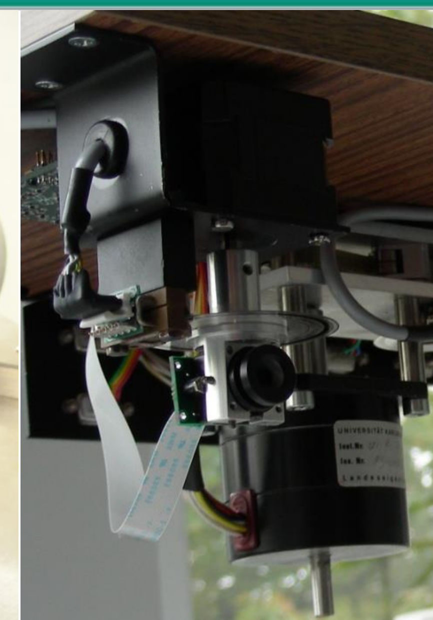
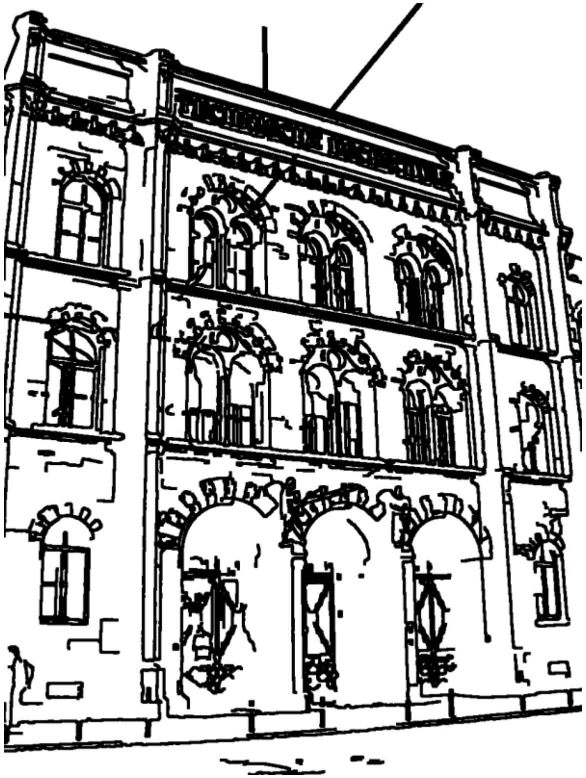




Edge Detection



-亮区和暗区之间变化剧烈的区域-
通常出现在物体边界-
出现在阴影和纹理处-
边缘与图像亮度无关-
人类视觉皮层的许多部分都在处理灰度边缘问题

grey level edges:

- areas of hard changes between bright and dark areas
- typically occur at object boundaries
- occur at shadows and texture
- edges independent of image brightness
- many parts of human visual cortex are dealing with grey level edges

Finding Edges

- edges are areas of rapidly changing grey value

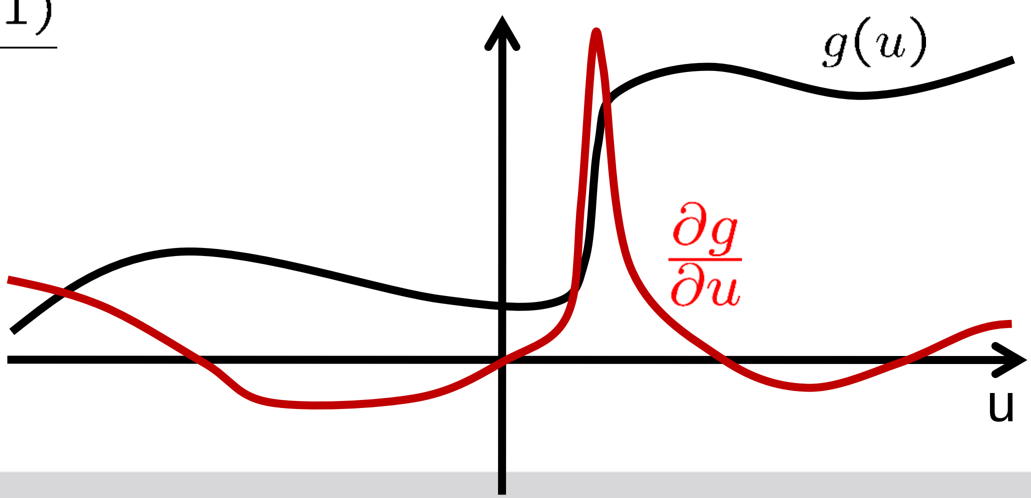
$$|g(u+\epsilon)-g(u-\epsilon)| \text{ large for small } \epsilon$$

- search areas with large derivative of g

$$\frac{\partial g}{\partial u}=\lim_{\epsilon\to 0}\frac{g(u+\epsilon)-g(u)}{\epsilon}=\lim_{\epsilon\to 0}\frac{g(u+\epsilon)-g(u-\epsilon)}{2\epsilon}$$

- approximating derivative by difference:

$$\frac{\partial g}{\partial u}\approx\frac{g(u+1)-g(u-1)}{2}$$



Finding Edges cont.

- approximating the derivative can be implemented as convolution with filter mask:

$$\frac{1}{2}\cdot \begin{array}{|c|c|c|}\hline 1 & \boxed{0} & -1 \\ \hline\end{array} \qquad \frac{\partial g}{\partial u} \approx \frac{g(u+1)-g(u-1)}{2}$$

- the 2d case:

$$\frac{1}{2}\cdot \begin{array}{|c|c|c|}\hline 1 & \boxed{0} & -1 \\ \hline\end{array} \qquad \frac{\partial g}{\partial u} \approx \frac{g(u+1,v)-g(u-1,v)}{2}$$

- analogously:

注意f*g为卷积运算，需要反向计算

$$\frac{1}{2}\cdot \begin{array}{|c|}\hline 1 \\ \hline \boxed{0} \\ \hline -1 \\ \hline\end{array} \qquad \frac{\partial g}{\partial v} \approx \frac{g(u,v+1)-g(u,v-1)}{2}$$

- noise reduction: additional averaging

Finding Edges cont.

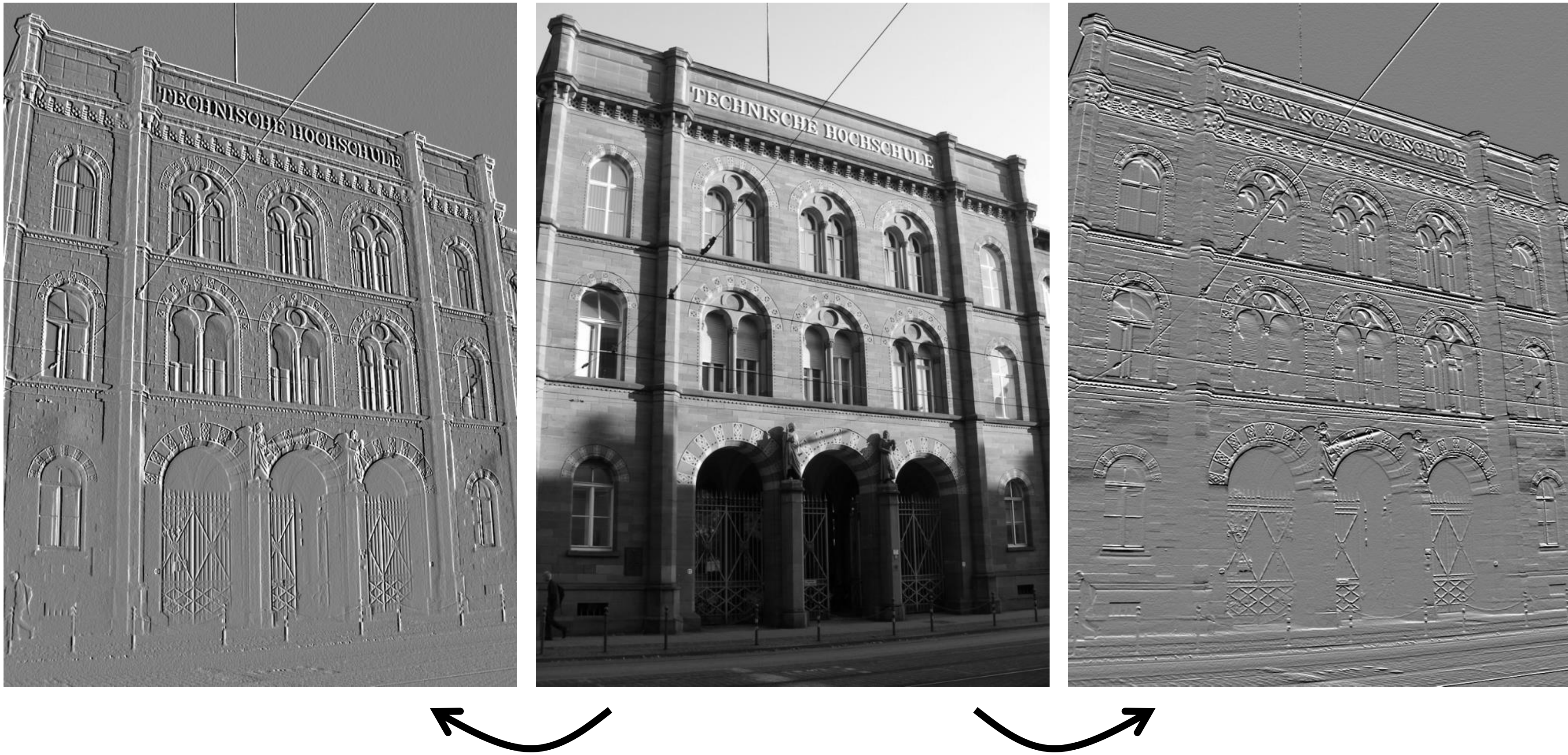
- Prewitt-operator:

$$\frac{1}{6}\cdot\begin{array}{|c|c|c|}\hline 1 & 0 & -1 \\ \hline 1 & \boxed{0} & -1 \\ \hline 1 & 0 & -1 \\ \hline\end{array} \qquad \frac{1}{6}\cdot\begin{array}{|c|c|c|}\hline 1 & 1 & 1 \\ \hline 0 & \boxed{0} & 0 \\ \hline -1 & -1 & -1 \\ \hline\end{array}$$

- Sobel-operator:

$$\frac{1}{8}\cdot\begin{array}{|c|c|c|}\hline 1 & 0 & -1 \\ \hline 2 & \boxed{0} & -2 \\ \hline 1 & 0 & -1 \\ \hline\end{array} \qquad \frac{1}{8}\cdot\begin{array}{|c|c|c|}\hline 1 & 2 & 1 \\ \hline 0 & \boxed{0} & 0 \\ \hline -1 & -2 & -1 \\ \hline\end{array}$$

Finding Edges cont.



$$\frac{\partial g}{\partial u} \qquad\qquad \frac{\partial g}{\partial v}$$

encoding derivative by gray scale for visualization:

- gray: derivative is zero
- bright: derivative is positive
- dark: derivative is negative

Finding Edges cont.

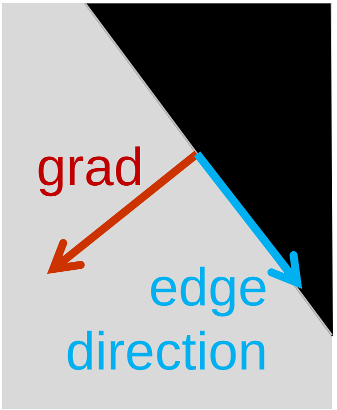
- edge orientation:

$$grad\ g = (\frac{\partial g}{\partial u}, \frac{\partial g}{\partial v})$$

  - grey level gradient points to direction of maximal grey level ascend
  - orthogonal directions exhibit no change of grey level

$$grad\ g \perp (-\frac{\partial g}{\partial v}, \frac{\partial g}{\partial u})$$

  - length of gradient is proportional to grey level change rate



Finding Edges cont.

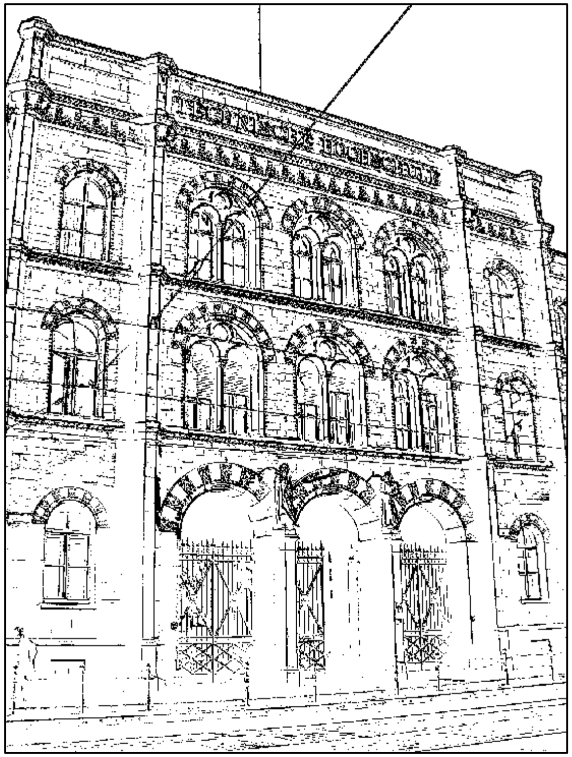
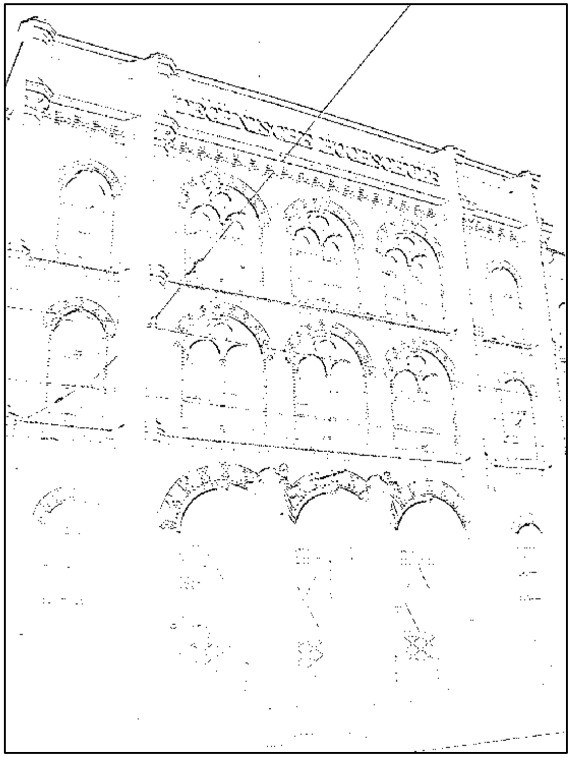
gradient plot:

- saturation: gradient length
- color: gradient direction (angle)

Finding Edges cont.

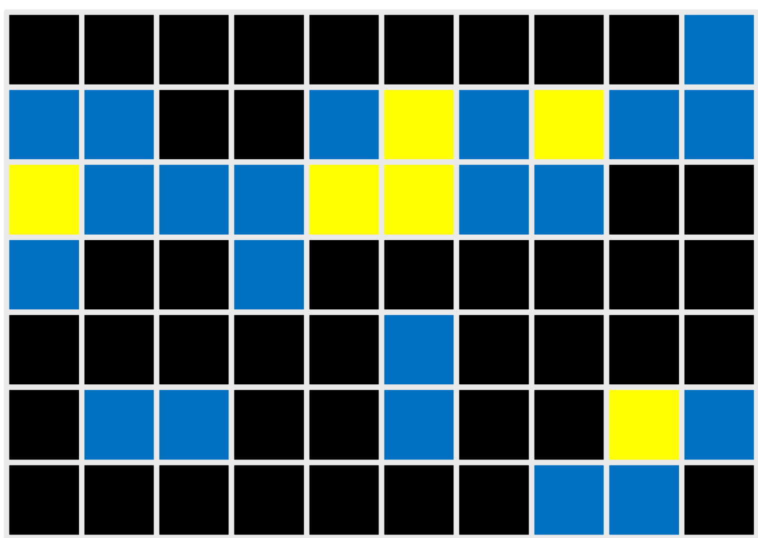
- from which gradient length on are edges relevant?
  - small threshold: too much noise remains
  - large threshold: contours not connected
  - idea: double thresholding

Threshold的大小的影响

Finding Edges cont.

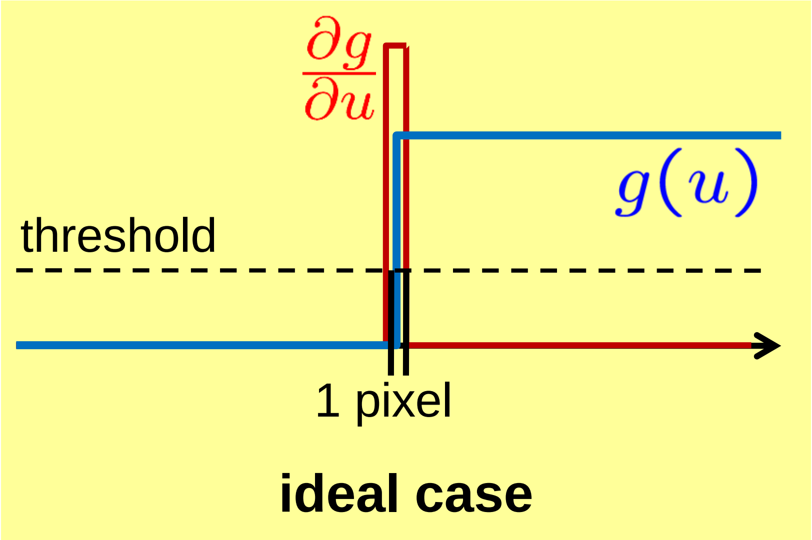
- double thresholding:
  - two thresholds: $\theta_L,\ \theta_U,\ \theta_L < \theta_U$
  - pixels are classified according to gradient length $||\vec{g}||$:
    - $||\vec{g}|| \leq \theta_L$ pixel is not edge element
    - $||\vec{g}|| \geq \theta_U$ pixel is edge element
    - $\theta_L < ||\vec{g}|| < \theta_U$ pixel is edge element if a neighboring pixel is edge element

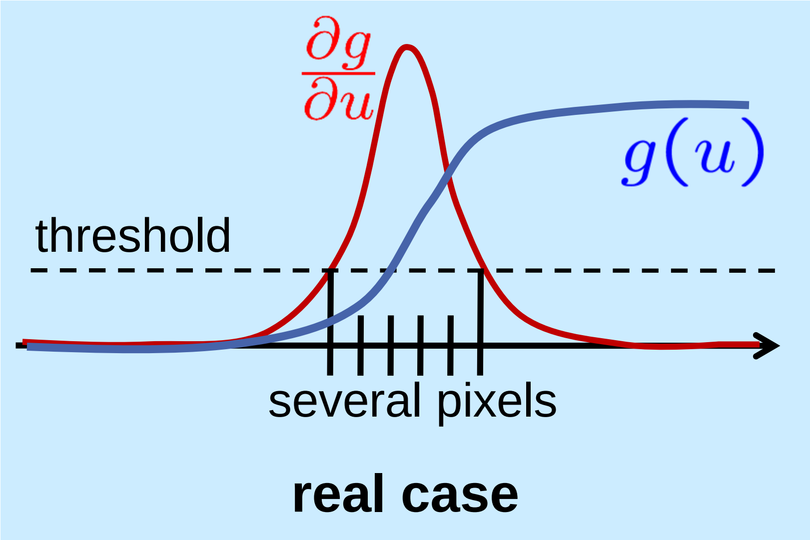


- black: $||\vec{g}|| \leq \theta_L$
- blue: $\theta_L < ||\vec{g}|| < \theta_U$
- yellow: $||\vec{g}|| \geq \theta_U$

Finding Edges cont.

- problem: thick lines

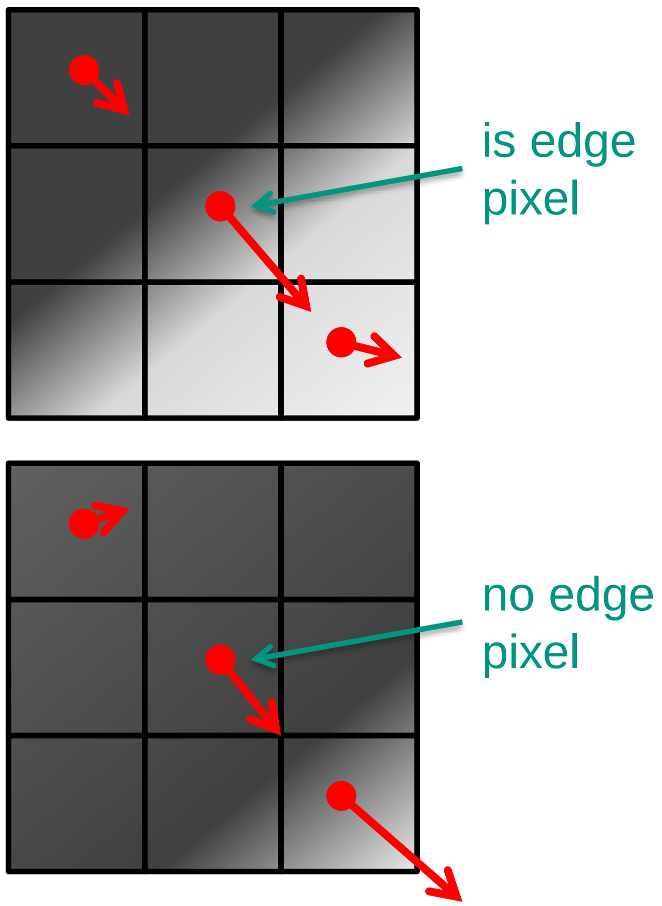




- non-maxima suppression
  - idea: among neighboring pixels, consider only the one with maximal gradient length
  - 2D case: take into account edge direction

Finding Edges cont.

- Non-maxima suppression

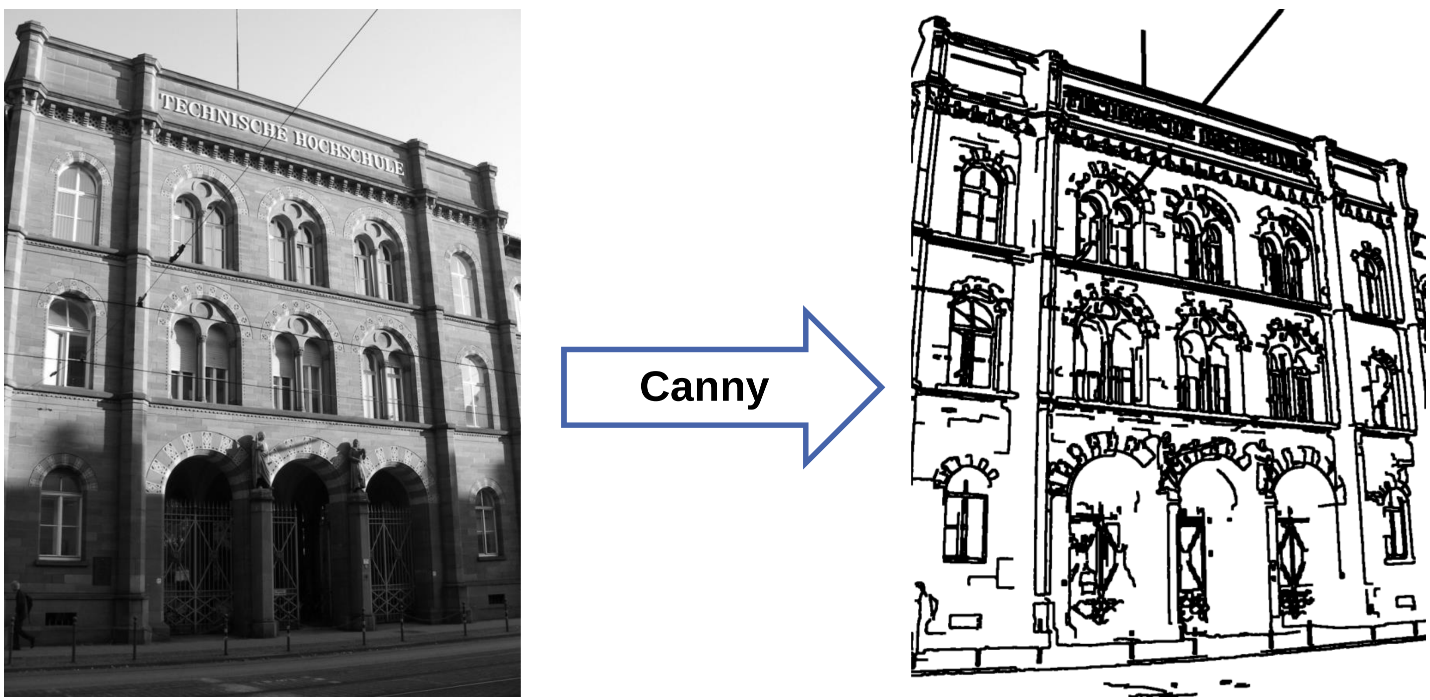


- check gradient direction
- select neighboring pixel in gradient direction and opposite gradient direction
- pixel is edge pixel if gradient length is larger than in those two neighboring pixels

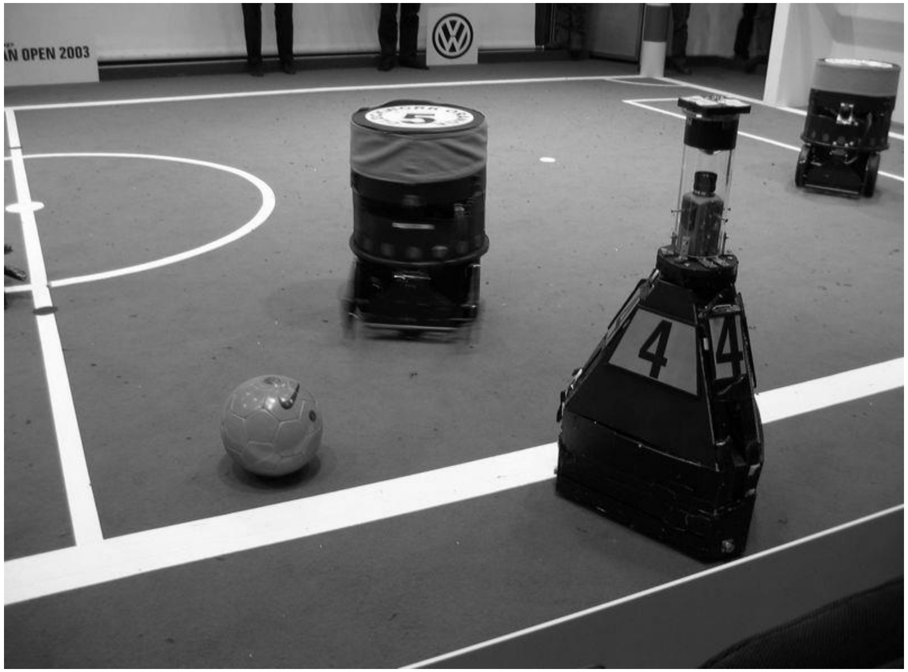
Canny Edge Detector

Canny edge detector combines the following techniques:

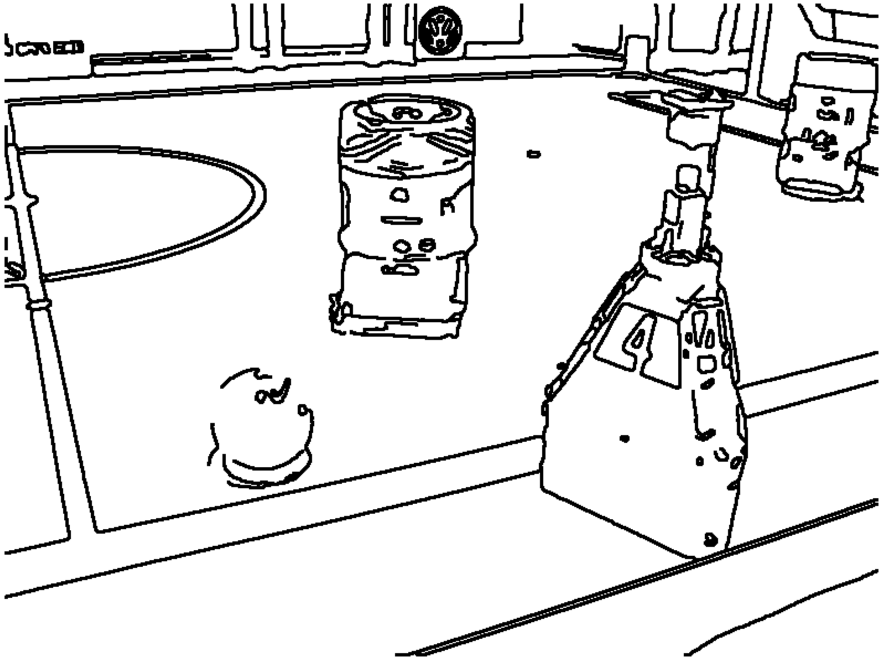
1. smooth image with Gaussian filter
2. compute grey level gradient with Sobel/Prewitt masks
3. apply non-maxima suppression
4. apply double thresholding



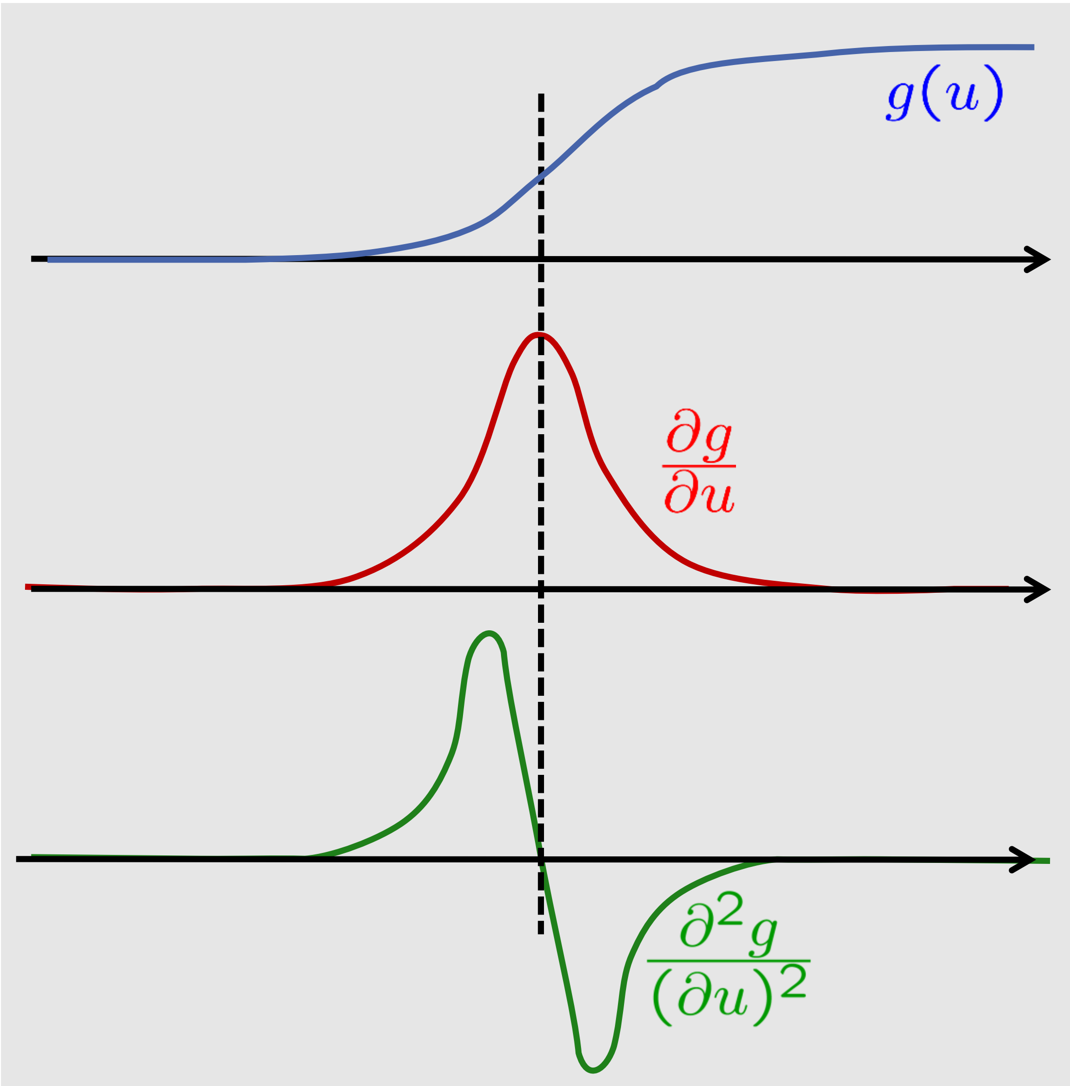
Canny Edge Detector



Canny



Finding Edges cont.



grey level edge:

- g rapidly changing
- maximum of $\frac{\partial g}{\partial u}$
- zero crossing of $\frac{\partial^2 g}{(\partial u)^2}$

- 2D analogon to 2nd order derivative is Laplace operator:

$$\nabla^2 g = \frac{\partial^2 g}{(\partial u)^2} + \frac{\partial^2 g}{(\partial v)^2}$$
$$= trace(H)$$

(H Hessian)

Laplace Operator

- Approximation to Laplace operator:

$$\frac{\partial g}{\partial u}(u,v) \approx g(u+1,v) - g(u,v)$$

$$\begin{aligned}\frac{\partial^2 g}{(\partial u)^2}(u,v) &\approx \frac{\partial g}{\partial u}(u,v) - \frac{\partial g}{\partial u}(u-1,v)\\ &\approx g(u+1,v) - 2g(u,v) + g(u-1,v)\end{aligned}$$

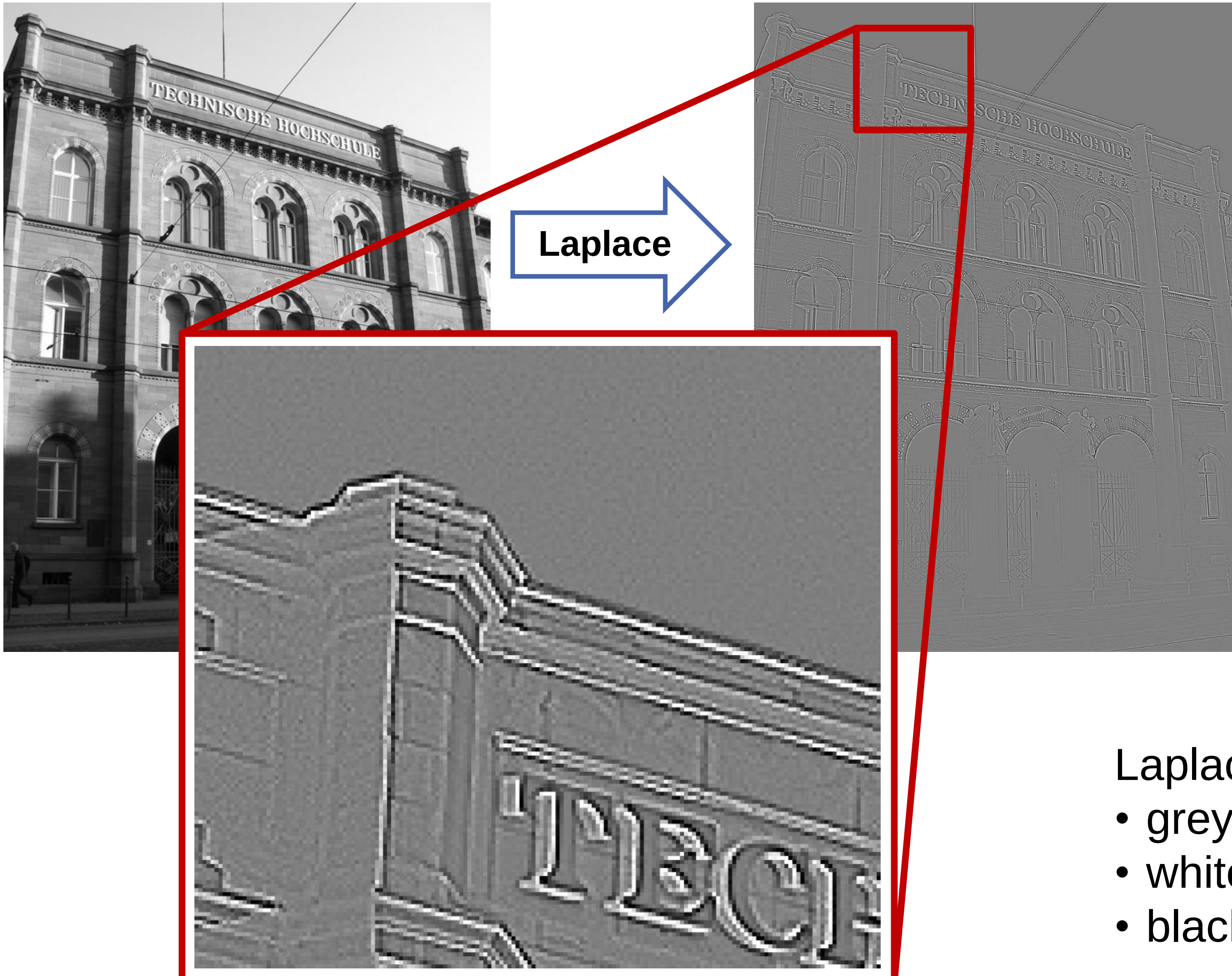
$$\frac{\partial^2 g}{(\partial v)^2}(u,v) \approx g(u,v+1) - 2g(u,v) + g(u,v-1)$$

$$\nabla^2 g \approx g(u+1,v) + g(u-1,v) + g(u,v+1) + g(u,v-1) - 4g(u,v)$$

- implementation as filter mask:

$$\begin{array}{|c|c|c|}\hline 0 & 1 & 0 \\ \hline 1 & \boxed{-4} & 1 \\ \hline 0 & 1 & 0 \\ \hline\end{array} \qquad \frac{1}{6}\cdot\begin{array}{|c|c|c|}\hline 1 & 4 & 1 \\ \hline 4 & \boxed{-20} & 4 \\ \hline 1 & 4 & 1 \\ \hline\end{array}$$

Laplace Operator cont.



Laplace operator
- grey: zero
- white: positive
- black: negative

Laplace Operator cont.

- 2nd order derivative is very noisy
- combine Laplacian with Gaussian smoothing

$$\nabla^2(G * g) = (\nabla^2 G) * g$$

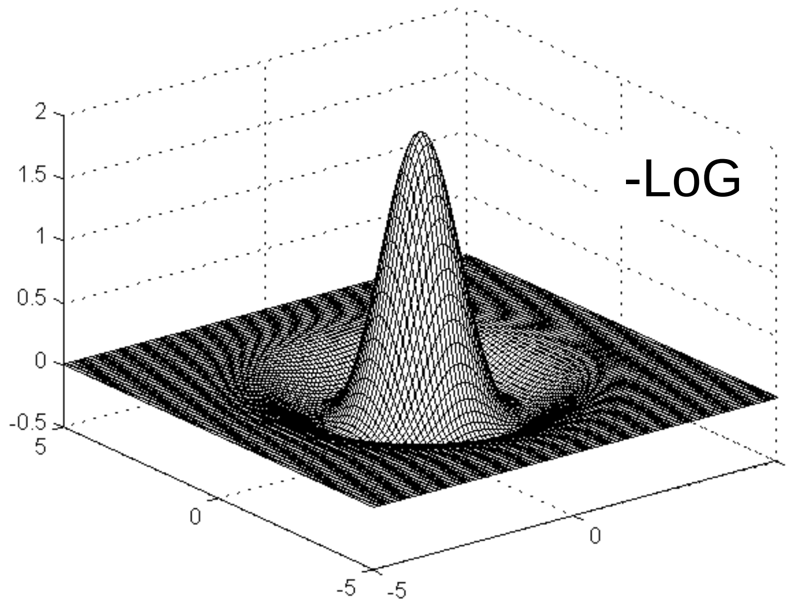
(G Gaussian)

$$G(u,v) = \frac{1}{2\pi\sigma^2} e^{-\frac{1}{2\sigma^2}(u^2+v^2)}$$

$$\frac{\partial G}{\partial u} = \frac{1}{2\pi\sigma^2}\left(-\frac{1}{2\sigma^2}\right) 2u e^{-\frac{1}{2\sigma^2}(u^2+v^2)}$$
$$= -\frac{u}{\sigma^2} G(u,v)$$

$$\frac{\partial^2 G}{(\partial u)^2} = -\frac{1}{\sigma^2} G(u,v) - \frac{u}{\sigma^2}\left(-\frac{u}{\sigma^2} G(u,v)\right)$$
$$= \frac{u^2 - \sigma^2}{\sigma^4} G(u,v)$$

$$\nabla^2 G = \frac{u^2 + v^2 - 2\sigma^2}{\sigma^4} G(u,v)$$



“Laplacian of Gaussian” (LoG)

“mexican hat”

Laplace Operator cont.

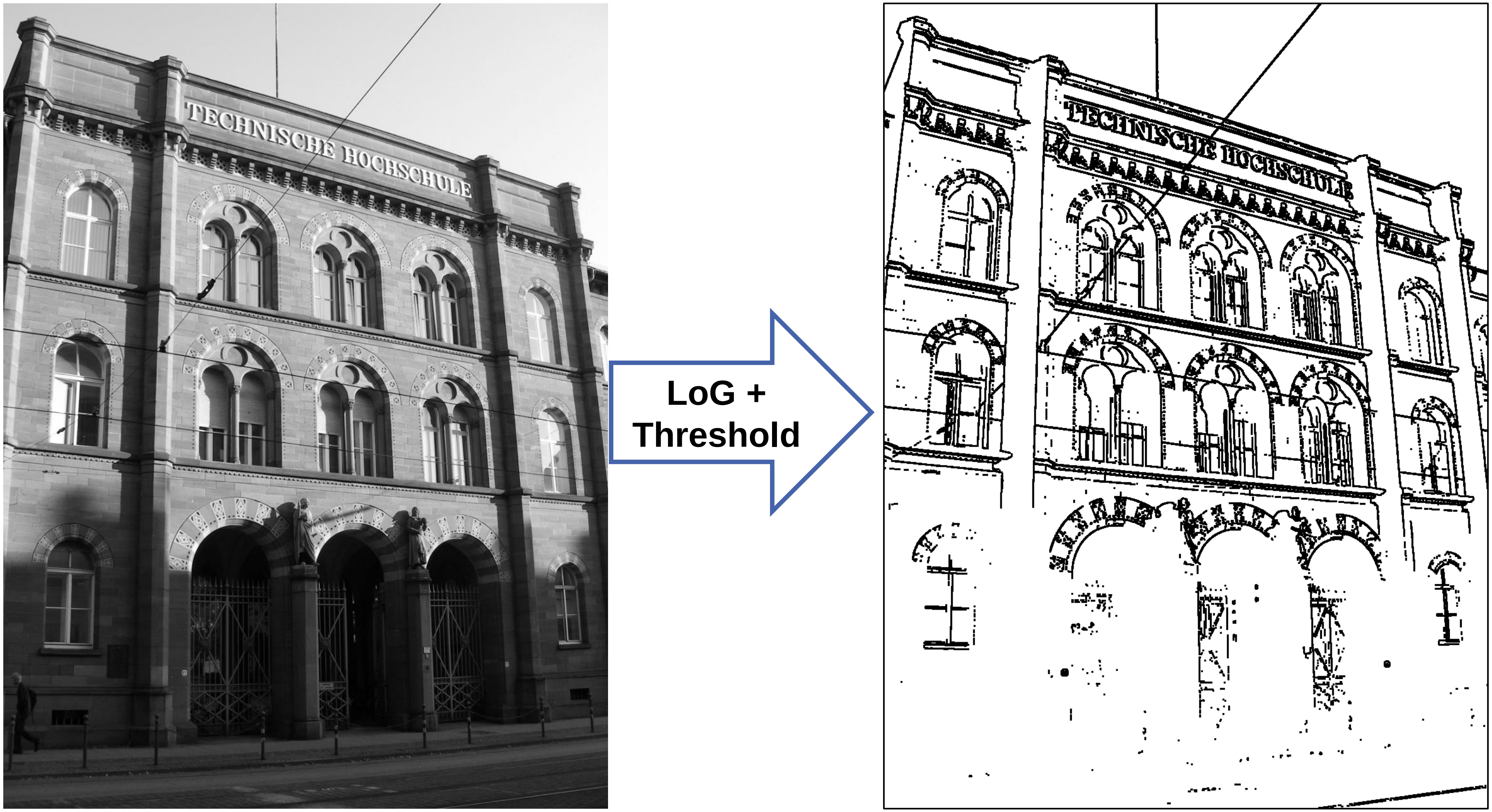
- filter masks for LoG:

0	0	1	0	0
0	1	2	1	0
1	2	-16	2	1
0	1	2	1	0
0	0	1	0	0

- LoG can be approximated by DoG “Difference of Gaussian”

$$DoG(u,v) = G_{\sigma_1}(u,v) - G_{\sigma_2}(u,v)$$

Laplace Operator cont.



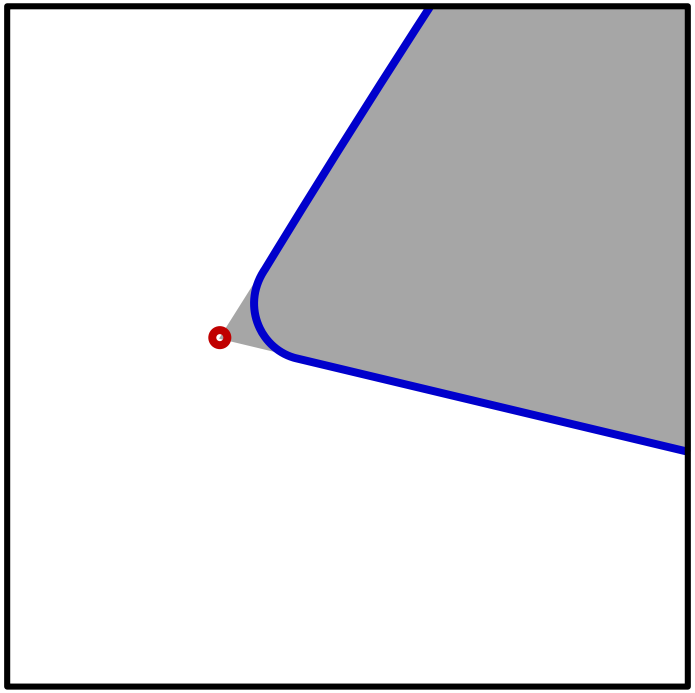
- edge detection approach according to Marr/Hildreth

CORNER DETECTION

Corner Detection

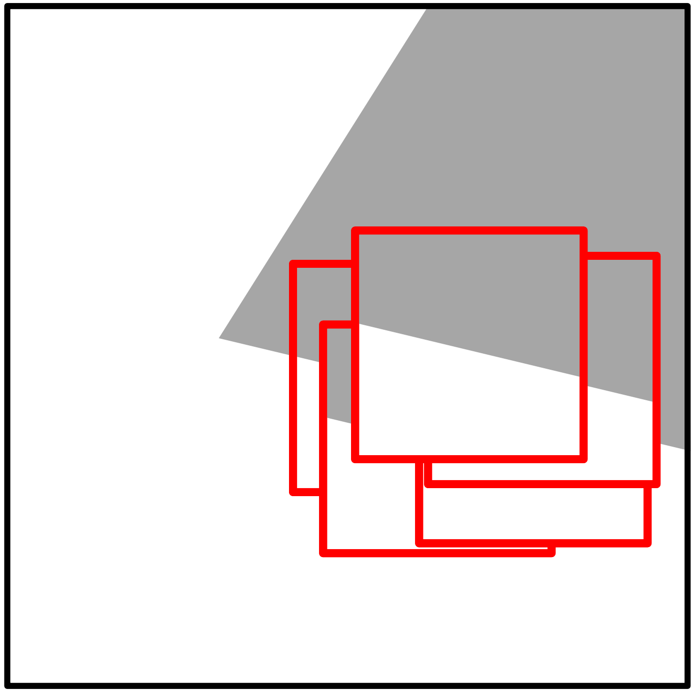
- graylevel corners important due to:
  - good features to find again in another image
  - corners as feature points, e.g. for calibration
  - edge detector usually round off corners

→ special filter to detect corners

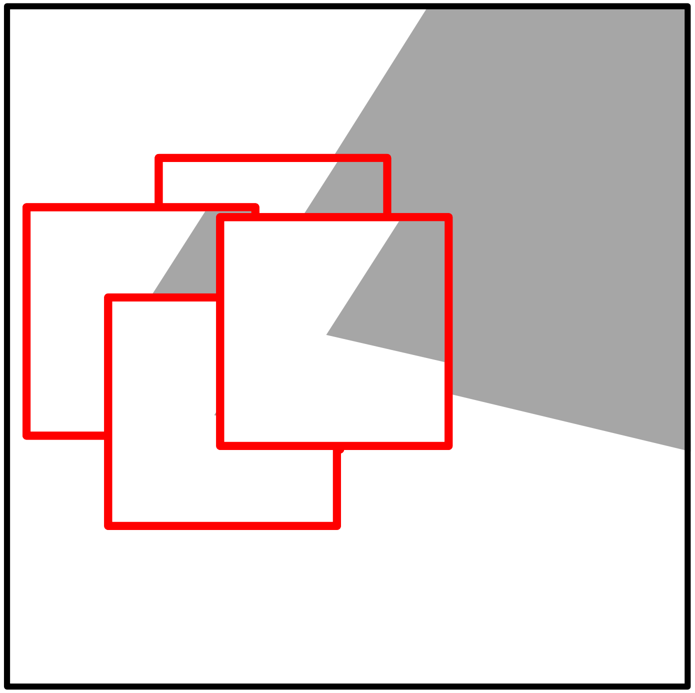


Corner Detection cont.

- Idea: find patches of maximal dissimilarity for local moves



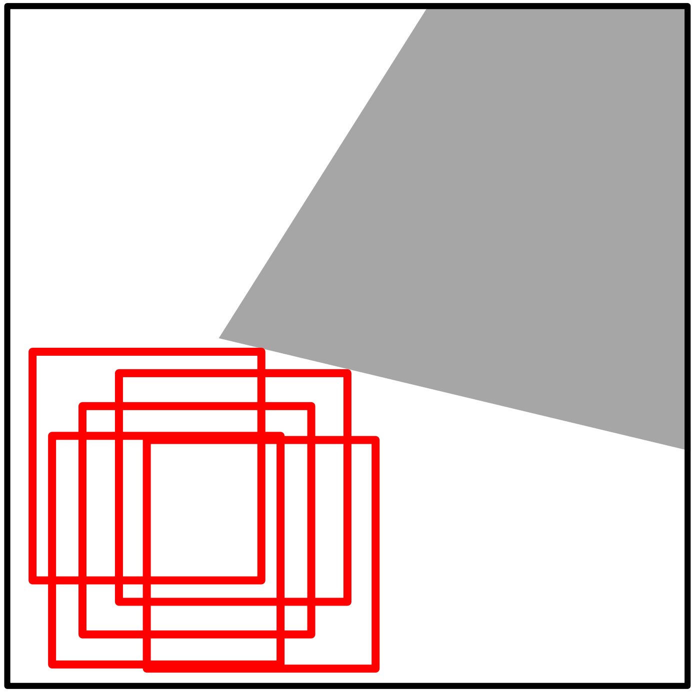
edge: similar when moving along edge, dissimilar when moving orthogonal



corner: dissimilar in all direction

Corner Detection cont.

- Idea: find patches of maximal dissimilarity for local moves



homogeneous areas:
similar in all directions

dissimilarity measure:

$$\sum_{(u,v)\in rectangle} (g(u+\Delta u, v+\Delta v) - g(u,v))^2$$

$$\approx \sum_{(u,v)\in rectangle} (g(u,v) + \Delta u \frac{\partial g}{\partial u} + \Delta v \frac{\partial g}{\partial v} - g(u,v))^2$$

$$= \sum_{(u,v)\in rectangle} ((\Delta u \frac{\partial g}{\partial u})^2 + 2\Delta u \frac{\partial g}{\partial u} \Delta v \frac{\partial g}{\partial v} + (\Delta v \frac{\partial g}{\partial v})^2)$$

$$= \begin{pmatrix} \Delta u \\ \Delta v \end{pmatrix}^T \underbrace{\begin{pmatrix} \sum(\frac{\partial g}{\partial u})^2 & \sum \frac{\partial g}{\partial u}\frac{\partial g}{\partial v} \\ \sum \frac{\partial g}{\partial u}\frac{\partial g}{\partial v} & \sum(\frac{\partial g}{\partial v})^2 \end{pmatrix}}_{=:S} \begin{pmatrix} \Delta u \\ \Delta v \end{pmatrix}$$

Corner Detection cont.

- Dissimilarity measure:

$$d := \begin{pmatrix}\Delta u \\ \Delta v\end{pmatrix}^T \underbrace{\begin{pmatrix}\sum(\frac{\partial g}{\partial u})^2 & \sum \frac{\partial g}{\partial u}\frac{\partial g}{\partial v} \\ \sum \frac{\partial g}{\partial u}\frac{\partial g}{\partial v} & \sum(\frac{\partial g}{\partial v})^2\end{pmatrix}}_{=:S} \begin{pmatrix}\Delta u \\ \Delta v\end{pmatrix}$$

  – dissimilarity should be large for all unit vectors $(\Delta u, \Delta v)$

  – for special choice of coordinate system S becomes a diagonal matrix (Eigenvector coordinate system)

$$d := \begin{pmatrix}\Delta u \\ \Delta v\end{pmatrix}^T \underbrace{\begin{pmatrix}\lambda_1 & 0 \\ 0 & \lambda_2\end{pmatrix}}_{=S} \begin{pmatrix}\Delta u \\ \Delta v\end{pmatrix} = \lambda_1(\Delta u)^2 + \lambda_2(\Delta v)^2$$

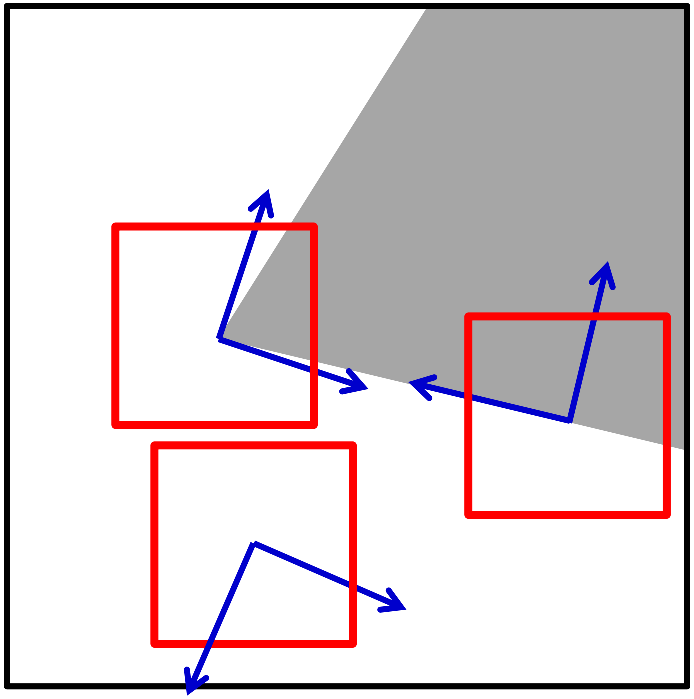
w.l.o.g. $\lambda_1 \geq \lambda_2 \geq 0$

Corner Detection cont.

$$d := \begin{pmatrix}\Delta u\\ \Delta v\end{pmatrix}^T \underbrace{\begin{pmatrix}\lambda_1 & 0\\ 0 & \lambda_2\end{pmatrix}}_{=S} \begin{pmatrix}\Delta u\\ \Delta v\end{pmatrix} = \lambda_1(\Delta u)^2 + \lambda_2(\Delta v)^2$$

w.l.o.g. $\lambda_1 \geq \lambda_2 \geq 0$

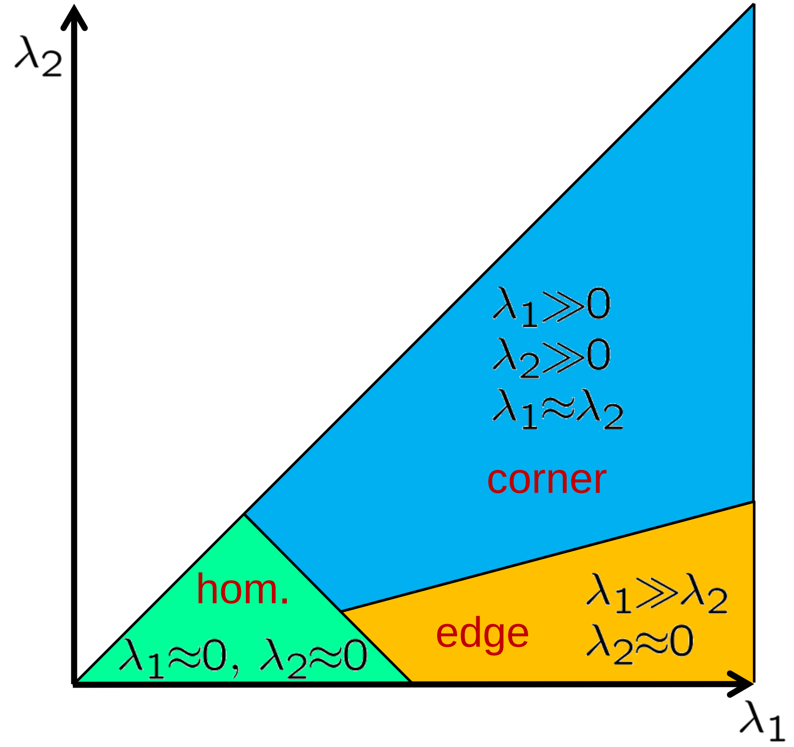
- typical cases:



	λ_1	λ_2
edge	large	small
corner	large	large
homogeneous area	small	small

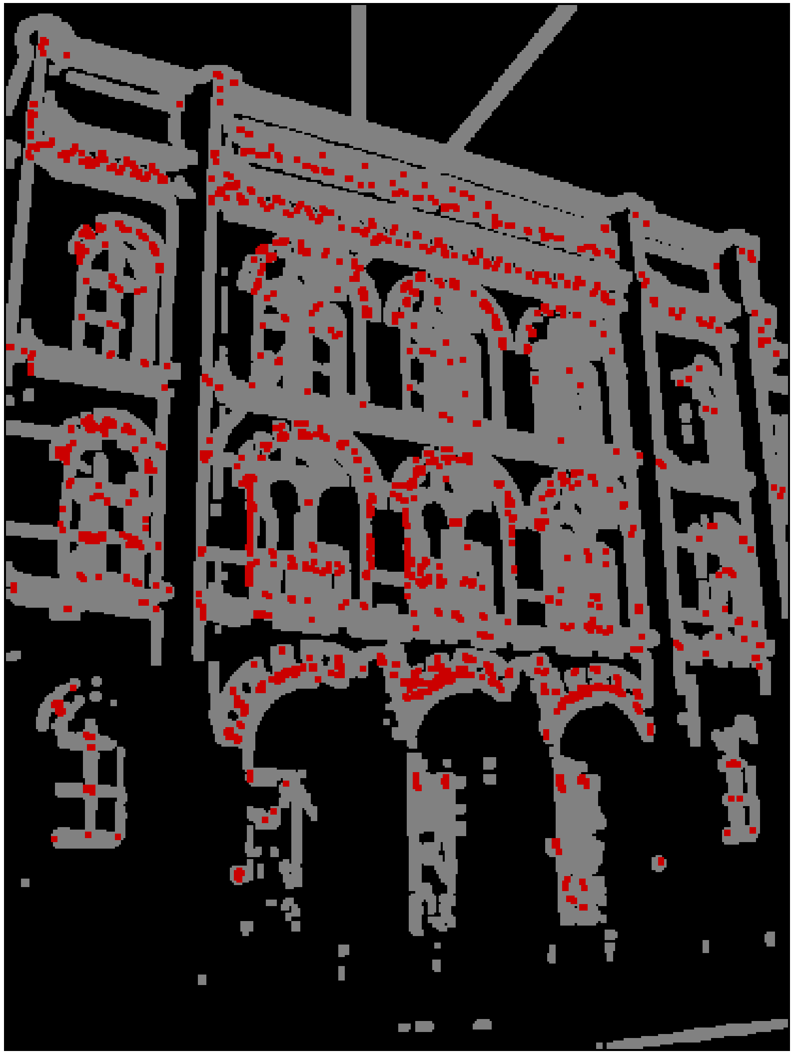
Corner Detection cont.

- decision rule
  - pixel is in homogeneous area if
    $$trace(S) = \lambda_1 + \lambda_2 < \theta$$
  - otherwise, pixel is corner if
    $$\lambda_2 > \alpha\lambda_1$$
    $$\Leftrightarrow det(S) - \frac{\alpha}{(1+\alpha)^2}(trace(S))^2 > 0$$
  - otherwise, pixel is edge
- parameters θ and α have to be tuned manually



Harris corner detector

Corner Detection cont.



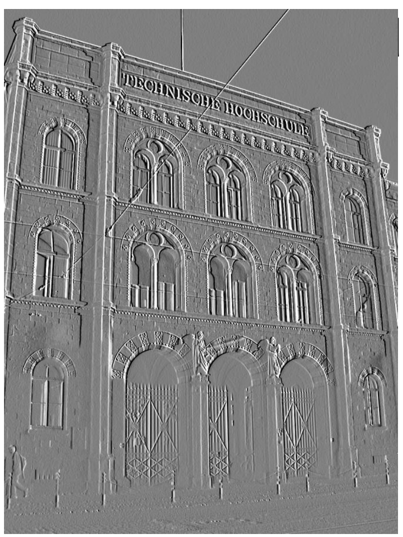
SUMMARY:
EDGE AND CORNER DETECTION

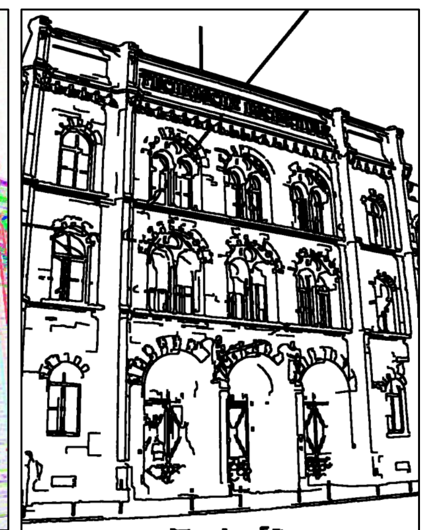
Summary

- **edge detection**
  - gradient: Sobel, Prewitt
  - thresholding, double thresholding
  - non-maxima suppression
  - Canny operator
  - Laplace operator, Marr/Hildreth approach

1	0	-1
2	0	-2
1	0	-1

1	4	1
4	-20	4
1	4	1



Summary cont.

- **edge detection**
- **corner detection**
  - Harris corner detector