Computer Vision - Lecture 5

Structure Extraction

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Course Outline

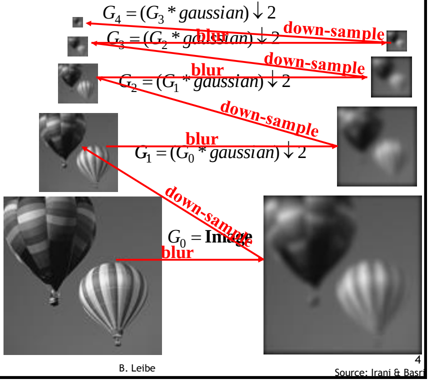
- Image Processing Basics
  - Image Formation
  - Binary Image Processing
  - Linear Filters
  - Edge & Structure Extraction
- Segmentation
- Local Features & Matching
- Object Recognition and Categorization
- 3D Reconstruction
- Motion and Tracking

Topics of This Lecture

- Recap: Edge detection
  - Image gradients
  - Canny edge detector
- Fitting as template matching
  - Distance transform
  - Chamfer matching
  - Application: traffic sign detection
- Fitting as parametric search
  - Line detection
  - Hough transform
  - Extension to circles
  - Generalized Hough transform

Recap: The Gaussian Pyramid

Low resolution



$G_4 = (G_3 * gaussian) \downarrow 2$

$G_3 = (G_2 * gaussian) \downarrow 2$

$G_2 = (G_1 * gaussian) \downarrow 2$

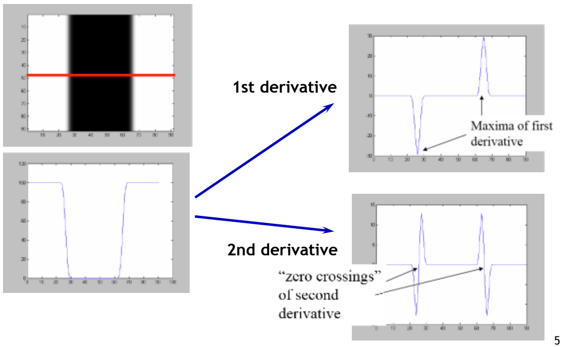
$G_1 = (G_0 * gaussian) \downarrow 2$

$G_0 = \textbf{Image}$

High resolution

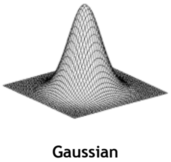
Source: Irani & Basri

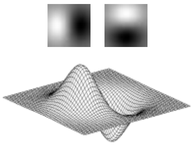
Recap: Derivatives and Edges…



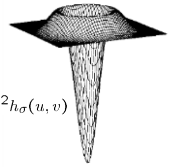
Recap: 2D Edge Detection Filters

see Exercise 2.5!





Laplacian of Gaussian



Gaussian

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

Derivative of Gaussian

$$\frac{\partial}{\partial x} h_\sigma(u,v)$$

$$\nabla^2 h_\sigma(u,v)$$

- ∇^2 is the Laplacian operator:

$$\nabla^2 f = \frac{\partial^2 f}{\partial x^2} + \frac{\partial^2 f}{\partial y^2}$$

Slide credit: Kristen Grauman

Recap: Canny Edge Detector

see Exercise 2.6!

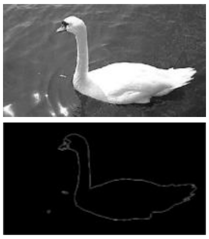
1. Filter image with derivative of Gaussian
2. Find magnitude and orientation of gradient
3. Non-maximum suppression:
   - Thin multi-pixel wide “ridges” down to single pixel width
4. Linking and thresholding (hysteresis):
   - Define two thresholds: low and high
   - Use the high threshold to start edge curves and the low threshold to continue them

- MATLAB:

```
>> edge(image,‘canny’);
>> help edge
```

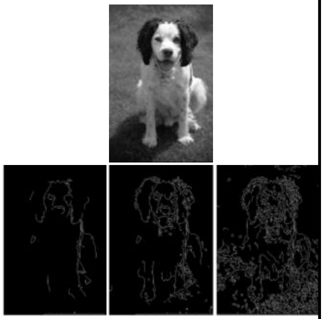
adapted from D. Lowe, L. Fei-Fei

Edges vs. Boundaries



Edges are useful signals to indicate occluding boundaries, shape.

Here the raw edge output is not so bad…

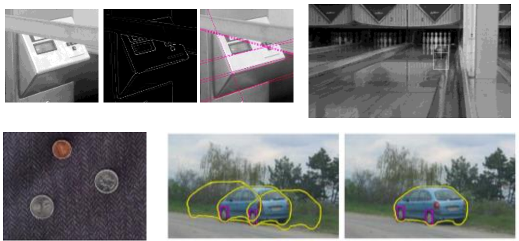


…but quite often boundaries of interest are fragmented, and we have extra “clutter” edge points.

Slide credit: Kristen Grauman

Fitting

- Want to associate a model with observed features



[Figure from Marszalek & Schmid, 2007]

For example, the model could be a line, a circle, or an arbitrary shape.

Slide credit: Kristen Grauman

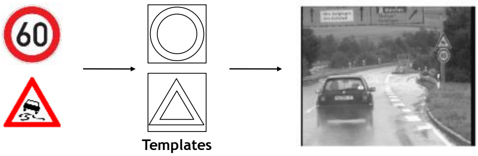
Topics of This Lecture

- Recap: Edge detection
  - Image gradients
  - Canny edge detector
- Fitting as template matching
  - Distance transform
  - Chamfer matching
  - Application: traffic sign detection
- Fitting as parametric search
  - Line detection
  - Hough transform
  - Extension to circles
  - Generalized Hough transform

Fitting as Template Matching

- We’ve already seen that correlation filtering can be used for template matching in an image.

- Let’s try this idea with “edge templates”.
  - Example: traffic sign detection in (grayvalue) video.



Templates

Edge Templates

- Correlation filtering
  - Correlation between edge pixels in template and image

$$D_{\text{corr}}(x,y) = -\sum_{u,v} T[u,v]I[x+u,y+v]$$

  - Unfortunately, this doesn’t work at all… Why?

⇒ Zero correlation score if the edge template is 1 pixel off…

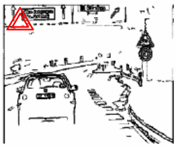
Edge Templates

- Better: Chamfer Distance
  - Average distance to nearest edge pixel

$$D_{\text{Chamfer}}(x,y) = \frac{1}{|T|}\sum_{u,v:T[u,v]=1} d_t(x+u,y+v)$$

⇒ More robust to small shifts and size variations.

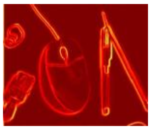
- How can we compute this efficiently?



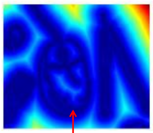
How Can This Be Made Efficient?

- Fast edge-based template matching
  - Distance transform of the edge image

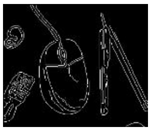
Original



Gradient



Distance transform



Edges

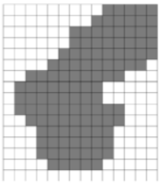
Value at (x,y) tells how far that position is from the nearest edge point (or other binary image structure)

```
>> help bwdist
```

Slide credit: Kristen Grauman

Distance Transform

- Image reflecting distance to nearest point in point set (e.g., edge pixels, or foreground pixels).



									1	1	1	1	1
								1	2	2	2	2	1
						1	1	2	3	3	3	2	1
						1	2	3	4	4	3	2	1
					1	2	3	4	3	3	2	2	1
				1	2	3	4	3	2	2	1	1	
		1	1	2	3	4	3	2	1	1			
	1	2	2	3	4	3	2	1					
	1	2	3	4	4	3	2	1					
	1	2	3	4	5	4	3	2	1	1			
		1	2	3	4	5	4	3	2	1			
			1	2	3	4	3	2	1				
			1	2	3	3	3	2	1				
			1	2	2	2	2	2	1				
				1	1	1	1	1					

4-connected adjacency

									1	1	1	1	1
								1	1	2	2	2	1
						1	1	1	2	2	3	2	1
						1	2	2	2	3	2	2	1
					1	1	2	3	2	2	2	1	1
				1	1	2	2	2	2	1	1	1	
		1	1	1	2	2	2	1	1	1			
	1	1	2	2	2	3	2	1					
	1	2	2	3	3	3	2	1					
	1	1	2	2	3	3	2	1	1	1			
		1	1	2	3	3	2	2	1	1			
			1	2	3	3	3	2	1				
			1	2	2	3	2	2	1				
			1	1	2	2	2	1	1				
				1	1	1	1	1					

8-connected adjacency

Slide credit: Kristen Grauman

Distance Transform Algorithm (1D)

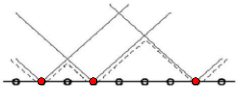
- Two-pass O(n) algorithm for 1D L_1 norm

1. Initialize: For all j
   - D[j] ← 1_P[j]   // 0 if j is in **P**, infinity otherwise
2. Forward: For j from 1 up to n-1
   - D[j] ← min(D[j], D[j-1]+1)

+1	0

3. Backward: For j from n-2 down to 0
   - D[j] ← min(D[j], D[j+1]+1)

0	+1

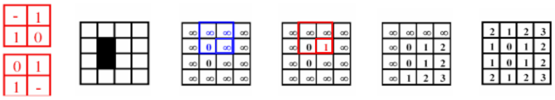


∞	0	∞	0	∞	∞	∞	0	∞
∞	0	1	0	1	2	3	0	1
1	0	1	0	1	2	1	0	1

Adapted from D. Huttenlocher

Distance Transform Algorithm (2D)

- 2D case analogous to 1D
  - Initialization
  - Forward and backward pass
    - Fwd pass finds closest above and to the left
    - Bwd pass finds closest below and to the right



-	1
1	0

0	1
1	-

∞	∞	∞	∞
∞	0	∞	∞
∞	0	∞	∞
∞	∞	∞	∞

∞	∞	∞	∞
∞	0	1	∞
∞	0	∞	∞
∞	∞	∞	∞

∞	∞	∞	∞
∞	0	1	2
∞	0	1	2
∞	1	2	3

2	1	2	3
1	0	1	2
1	0	1	2
2	1	2	3

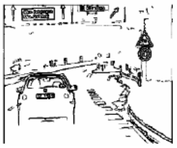
Adapted from D. Huttenlocher

Chamfer Matching

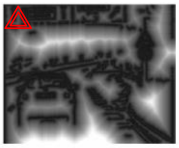
- Chamfer Distance
  - Average distance to nearest feature

$$D_{chamfer}(T,I) \equiv \frac{1}{|T|}\sum_{t\in T} d_I(t)$$

  - This can be computed efficiently by correlating the edge template with the distance-transformed image

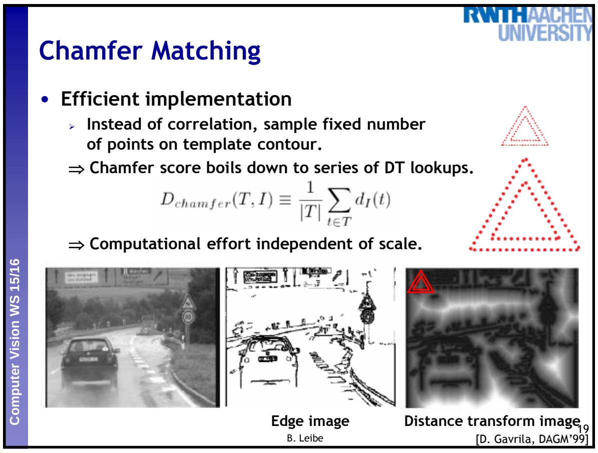


Edge image



Distance transform image

[D. Gavrila, DAGM'99]



Chamfer Matching

- Efficient implementation
  - Instead of correlation, sample fixed number of points on template contour.
  - ⇒ Chamfer score boils down to series of DT lookups.

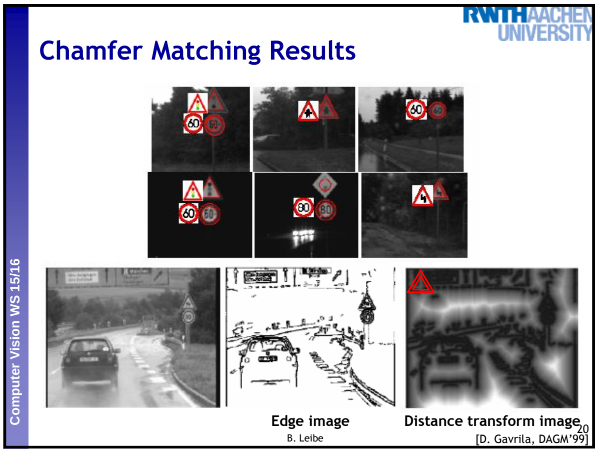
$$D_{chamfer}(T,I) \equiv \frac{1}{|T|}\sum_{t\in T} d_I(t)$$

  - ⇒ Computational effort independent of scale.

Edge image

Distance transform image

[D. Gavrila, DAGM'99]

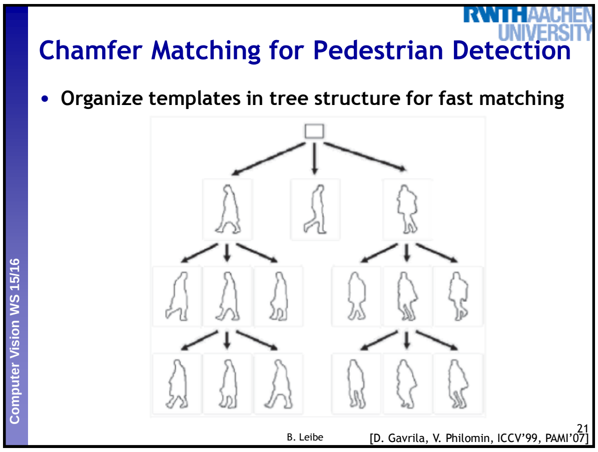


Chamfer Matching Results

Edge image

Distance transform image

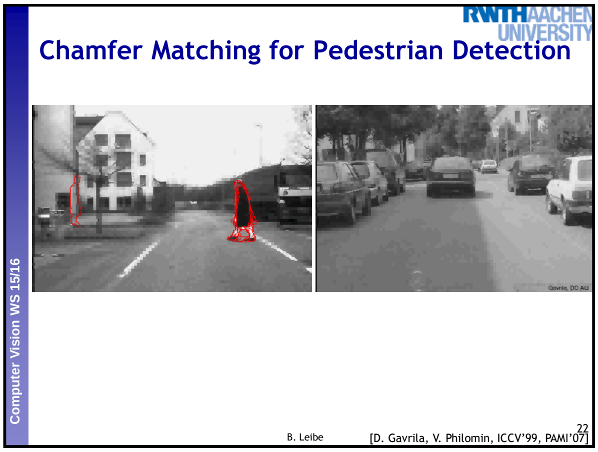
[D. Gavrila, DAGM'99]



Chamfer Matching for Pedestrian Detection

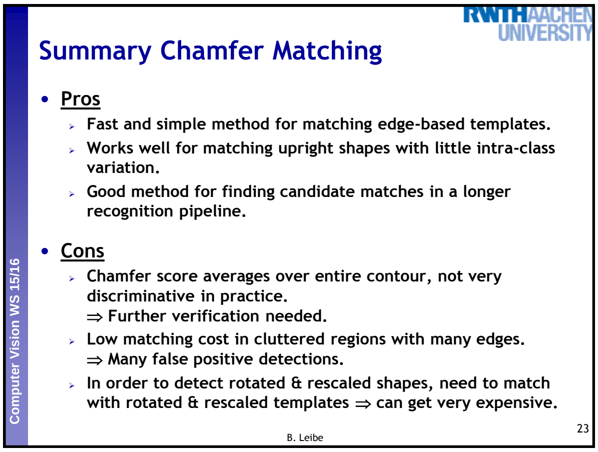
- Organize templates in tree structure for fast matching

[D. Gavrila, V. Philomin, ICCV'99, PAMI'07]



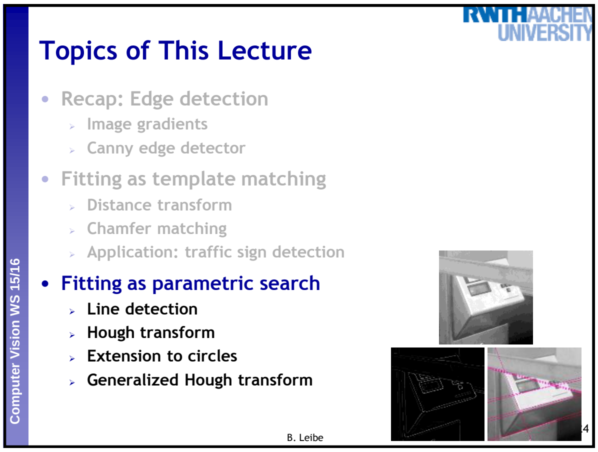
Chamfer Matching for Pedestrian Detection

[D. Gavrila, V. Philomin, ICCV'99, PAMI'07]



Summary Chamfer Matching

- Pros
  - Fast and simple method for matching edge-based templates.
  - Works well for matching upright shapes with little intra-class variation.
  - Good method for finding candidate matches in a longer recognition pipeline.
- Cons
  - Chamfer score averages over entire contour, not very discriminative in practice.
    ⇒ Further verification needed.
  - Low matching cost in cluttered regions with many edges.
    ⇒ Many false positive detections.
  - In order to detect rotated & rescaled shapes, need to match with rotated & rescaled templates ⇒ can get very expensive.



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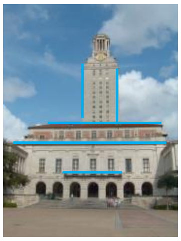
Fitting as Search in Parametric Space

- Choose a parametric model to represent a set of features
- Membership criterion is not local
  - Can't tell whether a point belongs to a given model just by looking at that point.
- Three main questions:
  - What model represents this set of features best?
  - Which of several model instances gets which feature?
  - How many model instances are there?
- Computational complexity is important
  - It is infeasible to examine every possible set of parameters and every possible combination of features

Source: L. Lazebnik

Example: Line Fitting

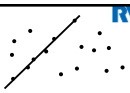
- Why fit lines?
  - Many objects are characterized by presence of straight lines

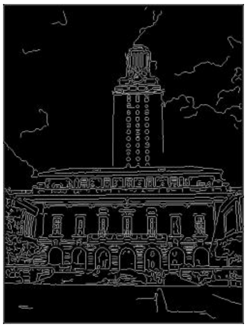


- Wait, why aren't we done just by running edge detection?

Slide credit: Kristen Grauman

Difficulty of Line Fitting





- Extra edge points (clutter), multiple models:
  - Which points go with which line, if any?
- Only some parts of each line detected, and some parts are missing:
  - How to find a line that bridges missing evidence?
- Noise in measured edge points, orientations:
  - How to detect true underlying parameters?

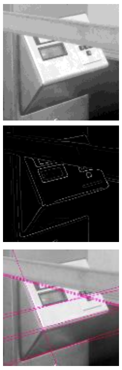
Slide credit: Kristen Grauman

Voting

- It's not feasible to check all combinations of features by fitting a model to each possible subset.
- Voting is a general technique where we let the features vote for all models that are compatible with it.
  - Cycle through features, cast votes for model parameters.
  - Look for model parameters that receive a lot of votes.
- Noise & clutter features will cast votes too, *but* typically their votes should be inconsistent with the majority of "good" features.
- Ok if some features not observed, as model can span multiple fragments.

Slide credit: Kristen Grauman

Fitting Lines

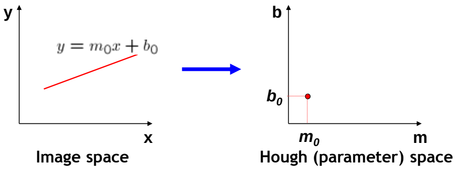


- Given points that belong to a line, what is the line?
- How many lines are there?
- Which points belong to which lines?

- The *Hough Transform* is a voting technique that can be used to answer all of these
- Main idea:
  1. Vote for all possible lines on which each edge point could lie.
  2. Look for lines that get many votes.

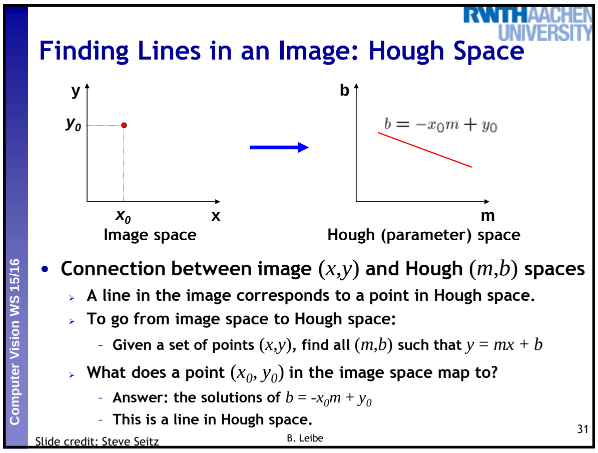
Slide credit: Kristen Grauman

Finding Lines in an Image: Hough Space



- Connection between image (x,y) and Hough (m,b) spaces
  - A line in the image corresponds to a point in Hough space.
  - To go from image space to Hough space:
    - Given a set of points (x,y), find all (m,b) such that $y = mx + b$

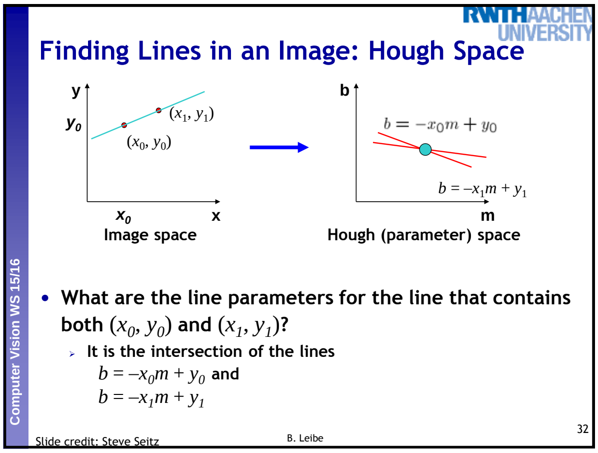
Slide credit: Steve Seitz



Finding Lines in an Image: Hough Space

- Connection between image (x,y) and Hough (m,b) spaces
  - A line in the image corresponds to a point in Hough space.
  - To go from image space to Hough space:
    - Given a set of points (x,y), find all (m,b) such that $y = mx + b$
  - What does a point (x_0, y_0) in the image space map to?
    - Answer: the solutions of $b = -x_0 m + y_0$
    - This is a line in Hough space.

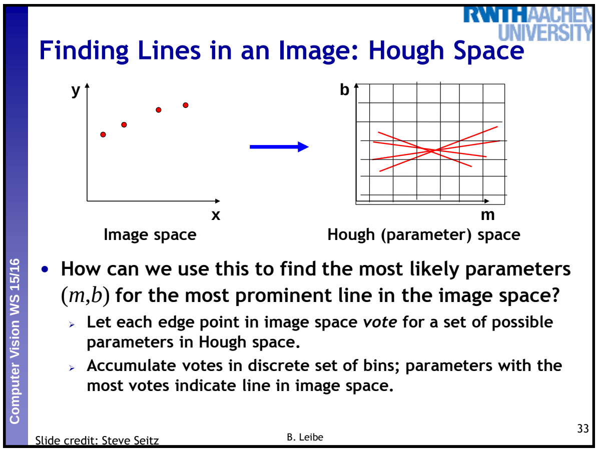
Slide credit: Steve Seitz



Finding Lines in an Image: Hough Space

- What are the line parameters for the line that contains both (x_0, y_0) and (x_1, y_1)?
  - It is the intersection of the lines
    $b = -x_0 m + y_0$ and
    $b = -x_1 m + y_1$

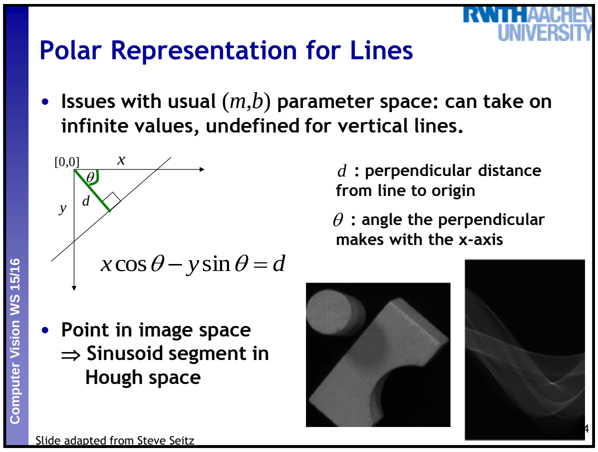
Slide credit: Steve Seitz



Finding Lines in an Image: Hough Space

- How can we use this to find the most likely parameters (m,b) for the most prominent line in the image space?
  - Let each edge point in image space *vote* for a set of possible parameters in Hough space.
  - Accumulate votes in discrete set of bins; parameters with the most votes indicate line in image space.

Slide credit: Steve Seitz



Polar Representation for Lines

- Issues with usual (m,b) parameter space: can take on infinite values, undefined for vertical lines.

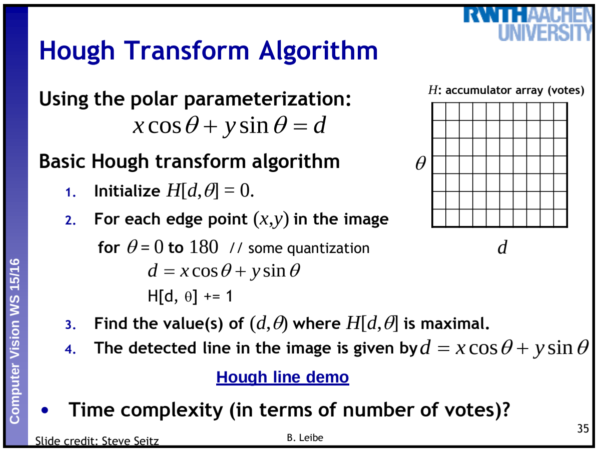
$$x\cos\theta - y\sin\theta = d$$

d : perpendicular distance from line to origin

θ : angle the perpendicular makes with the x-axis

- Point in image space
  ⇒ Sinusoid segment in Hough space

Slide adapted from Steve Seitz



Hough Transform Algorithm

Using the polar parameterization:

$$x\cos\theta + y\sin\theta = d$$

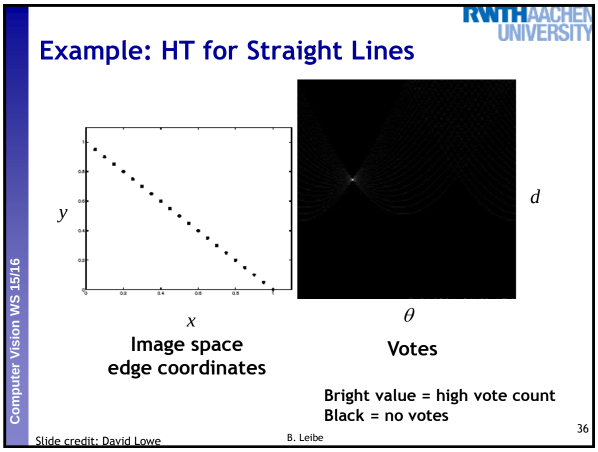
Basic Hough transform algorithm

```
1. Initialize $H[d,\theta] = 0$.
2. For each edge point $(x,y)$ in the image
     for $\theta = 0$ to $180$   // some quantization
         $d = x\cos\theta + y\sin\theta$
         H[d, θ] += 1
3. Find the value(s) of $(d,\theta)$ where $H[d,\theta]$ is maximal.
4. The detected line in the image is given by $d = x\cos\theta + y\sin\theta$
```

Hough line demo

- Time complexity (in terms of number of votes)?

Slide credit: Steve Seitz



Example: HT for Straight Lines

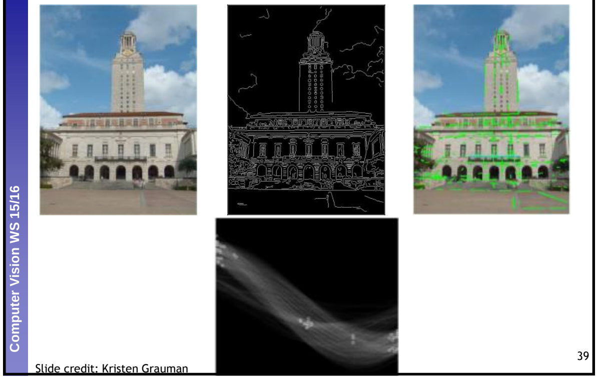
Image space edge coordinates

Votes

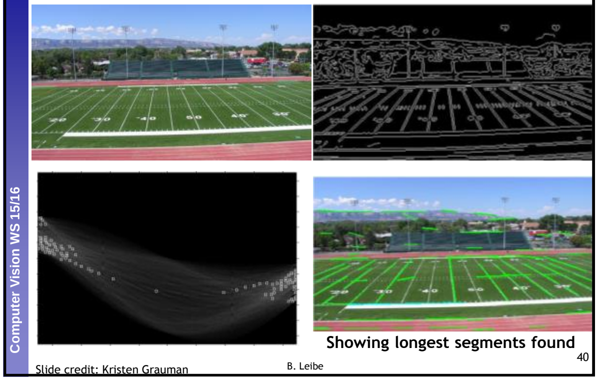
Bright value = high vote count
Black = no votes

Slide credit: David Lowe

Real-World Examples



Slide credit: Kristen Grauman



Showing longest segments found

Slide credit: Kristen Grauman

Impact of Noise on Hough Transform

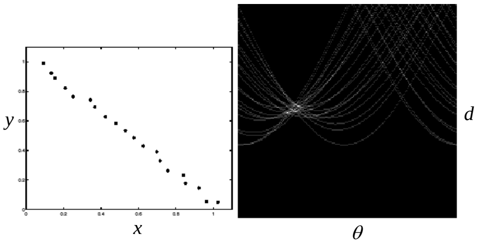


Image space
edge coordinates

Votes

What difficulty does this present for an implementation?

Slide credit: David Lowe

Impact of Noise on Hough Transform

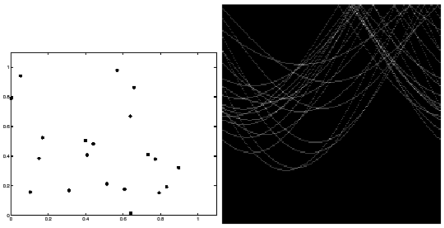


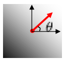
Image space
edge coordinates

Votes

Here, everything appears to be “noise”, or random edge points, but we still see peaks in the vote space.

Slide credit: David Lowe

Extensions



$\nabla f = \left[\frac{\partial f}{\partial x}, \frac{\partial f}{\partial y}\right]$

$\theta = \tan^{-1}\left(\frac{\partial f}{\partial y} / \frac{\partial f}{\partial x}\right)$

Extension 1: Use the image gradient

1. same
2. for each edge point I[x,y] in the image
   θ = gradient at (x,y)
   $d = x\cos\theta - y\sin\theta$
   H[d,θ] += 1
3. same
4. same

(Reduces degrees of freedom)

Slide credit: Kristen Grauman

Extensions

Extension 1: Use the image gradient

1. same
2. for each edge point I[x,y] in the image
   compute unique (d,θ) based on image gradient at (x,y)
   H[d,θ] += 1
3. same
4. same

(Reduces degrees of freedom)

Extension 2

- Give more votes for stronger edges (use magnitude of gradient)

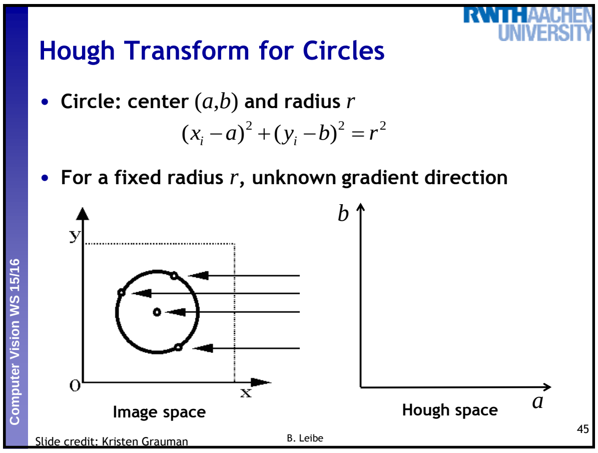
Extension 3

- Change the sampling of (d,θ) to give more/less resolution

Extension 4

- The same procedure can be used with circles, squares, or any other shape…

Slide credit: Kristen Grauman



Hough Transform for Circles

- Circle: center (a,b) and radius r

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

- For a fixed radius r, unknown gradient direction

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Slide credit: Kristen Grauman

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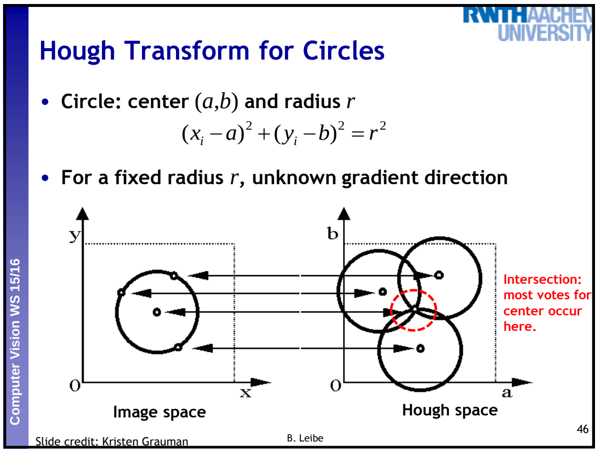
45



Hough Transform for Circles

- Circle: center (a,b) and radius r

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

- For a fixed radius r, unknown gradient direction

Intersection: most votes for center occur here.

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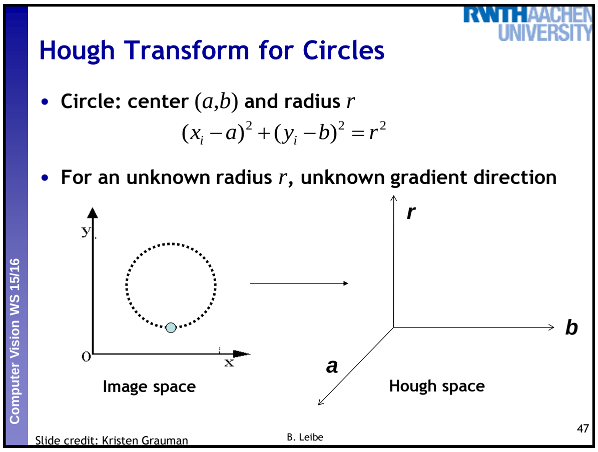
46



Hough Transform for Circles

- Circle: center (a,b) and radius r

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

- For an unknown radius r, unknown gradient direction

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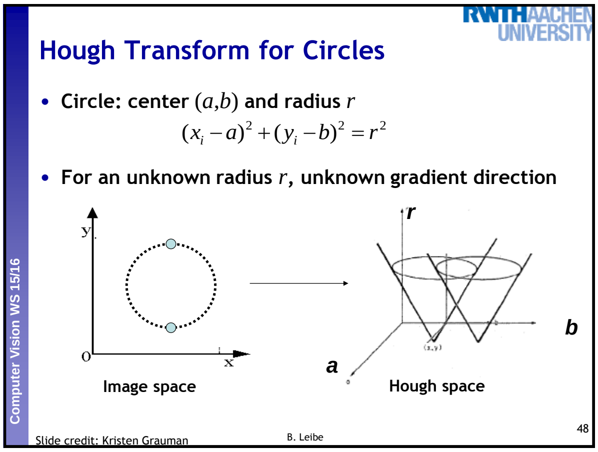
47



Hough Transform for Circles

- Circle: center (a,b) and radius r

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

- For an unknown radius r, unknown gradient direction

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Slide credit: Kristen Grauman

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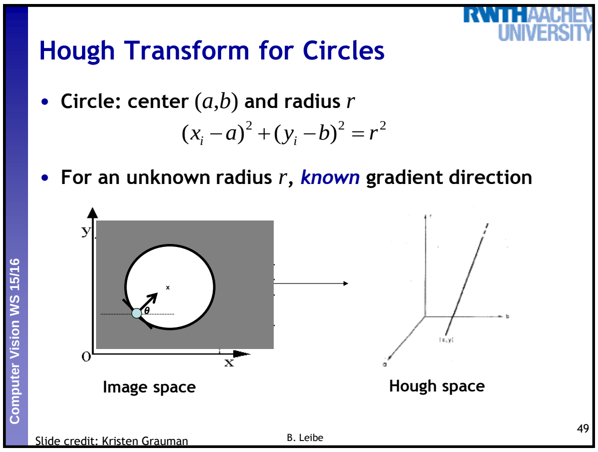
48



Hough Transform for Circles

- Circle: center (a,b) and radius r

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

- For an unknown radius r, ***known*** gradient direction

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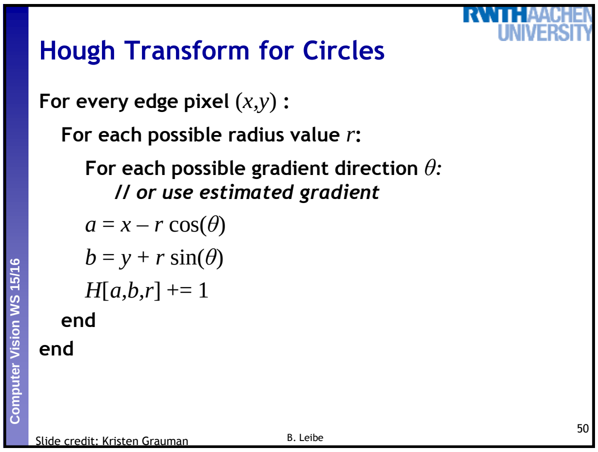
49



Hough Transform for Circles

```
For every edge pixel $(x,y)$ :
   For each possible radius value $r$:
      For each possible gradient direction $\theta$:
         // or use estimated gradient
      $a = x - r\cos(\theta)$
      $b = y + r\sin(\theta)$
      $H[a,b,r] += 1$
   end
end
```

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Slide credit: Kristen Grauman

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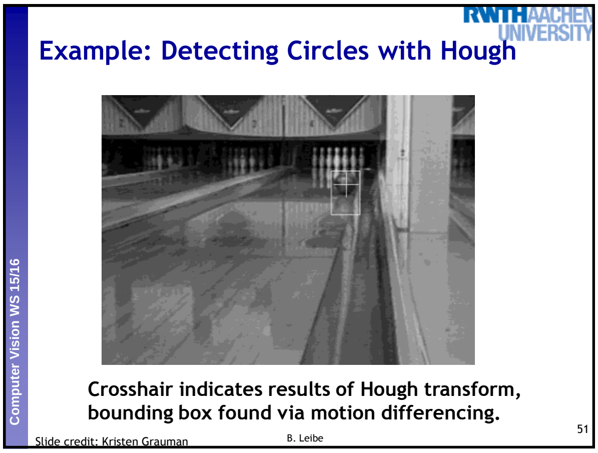
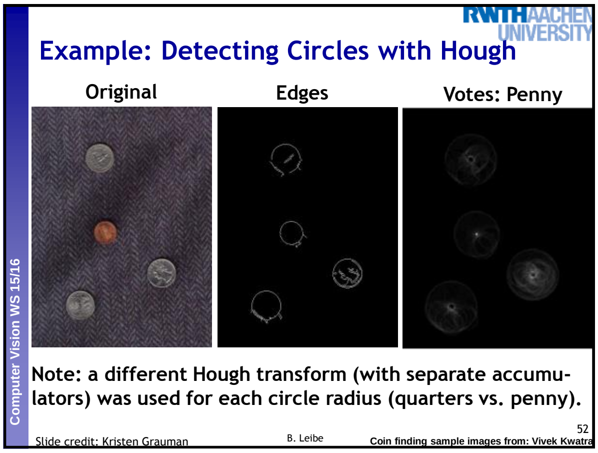
50



Example: Detecting Circles with Hough

Crosshair indicates results of Hough transform, bounding box found via motion differencing.

Slide credit: Kristen Grauman

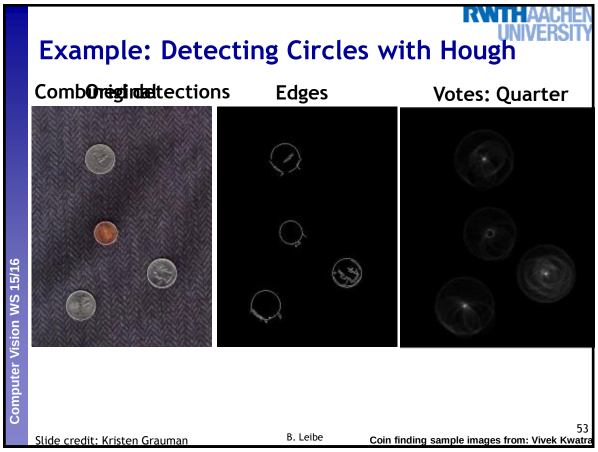


Example: Detecting Circles with Hough

Note: a different Hough transform (with separate accumulators) was used for each circle radius (quarters vs. penny).

Slide credit: Kristen Grauman

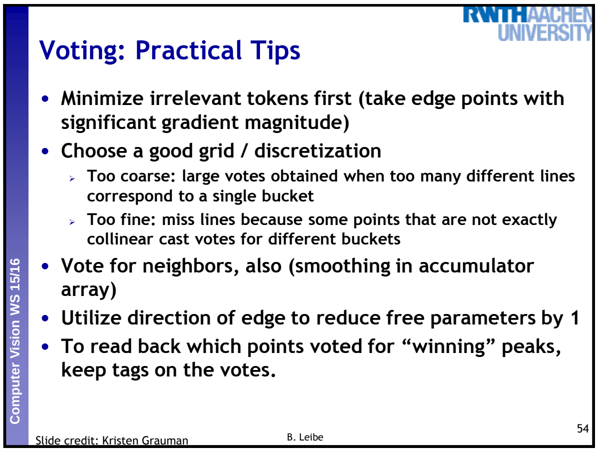
Coin finding sample images from: Vivek Kwatra



Example: Detecting Circles with Hough

Slide credit: Kristen Grauman

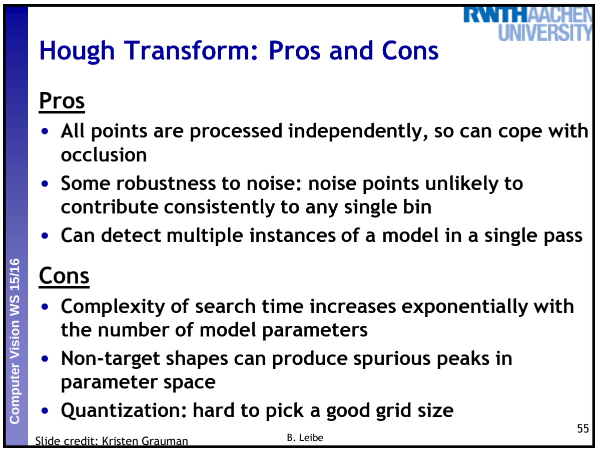
Coin finding sample images from: Vivek Kwatra



Voting: Practical Tips

- Minimize irrelevant tokens first (take edge points with significant gradient magnitude)
- Choose a good grid / discretization
  - Too coarse: large votes obtained when too many different lines correspond to a single bucket
  - Too fine: miss lines because some points that are not exactly collinear cast votes for different buckets
- Vote for neighbors, also (smoothing in accumulator array)
- Utilize direction of edge to reduce free parameters by 1
- To read back which points voted for “winning” peaks, keep tags on the votes.

Slide credit: Kristen Grauman



Hough Transform: Pros and Cons

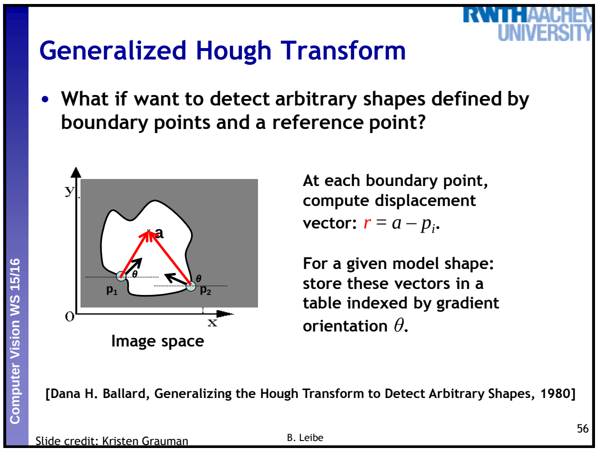
Pros

- All points are processed independently, so can cope with occlusion
- Some robustness to noise: noise points unlikely to contribute consistently to any single bin
- Can detect multiple instances of a model in a single pass

Cons

- Complexity of search time increases exponentially with the number of model parameters
- Non-target shapes can produce spurious peaks in parameter space
- Quantization: hard to pick a good grid size

Slide credit: Kristen Grauman



Generalized Hough Transform

- What if want to detect arbitrary shapes defined by boundary points and a reference point?

Image space

At each boundary point, compute displacement vector: $r = a - p_i$.

For a given model shape: store these vectors in a table indexed by gradient orientation θ.

[Dana H. Ballard, Generalizing the Hough Transform to Detect Arbitrary Shapes, 1980]

Slide credit: Kristen Grauman

Generalized Hough Transform

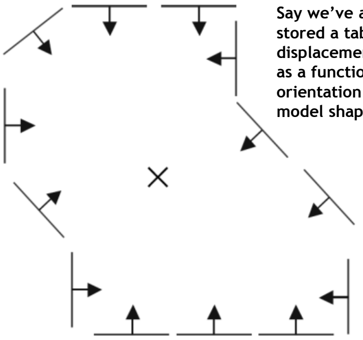
To *detect* the model shape in a new image:

- For each edge point
  - Index into table with its gradient orientation θ
  - Use retrieved r vectors to vote for position of reference point
- Peak in this Hough space is reference point with most supporting edges

Assuming translation is the only transformation here, i.e., orientation and scale are fixed.

Slide credit: Kristen Grauman

Example: Generalized Hough Transform

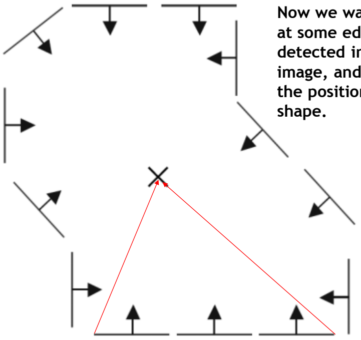


Say we've already stored a table of displacement vectors as a function of edge orientation for this model shape.

Model shape

Slide credit: Svetlana Lazebnik

Example: Generalized Hough Transform

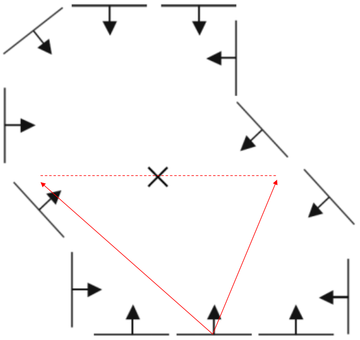


Now we want to look at some edge points detected in a *new* image, and vote on the position of that shape.

Displacement vectors for model points

Slide credit: Svetlana Lazebnik

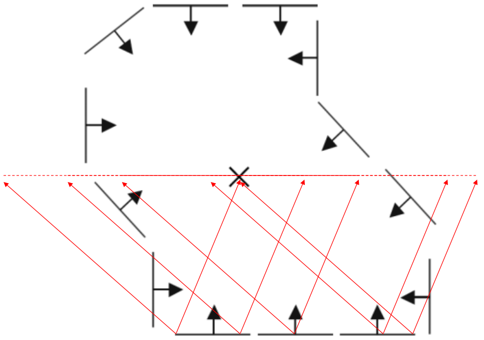
Example: Generalized Hough Transform



Range of voting locations for test point

Slide credit: Svetlana Lazebnik

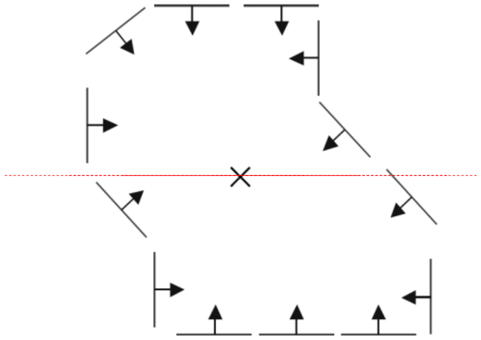
Example: Generalized Hough Transform



Range of voting locations for test point

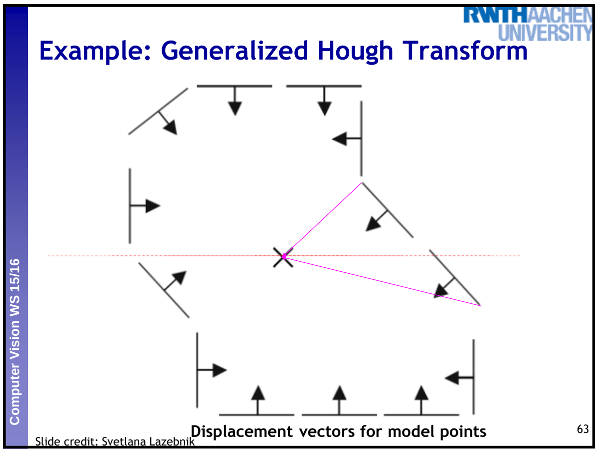
Slide credit: Svetlana Lazebnik

Example: Generalized Hough Transform



Votes for points with $\theta = \uparrow$

Slide credit: Svetlana Lazebnik



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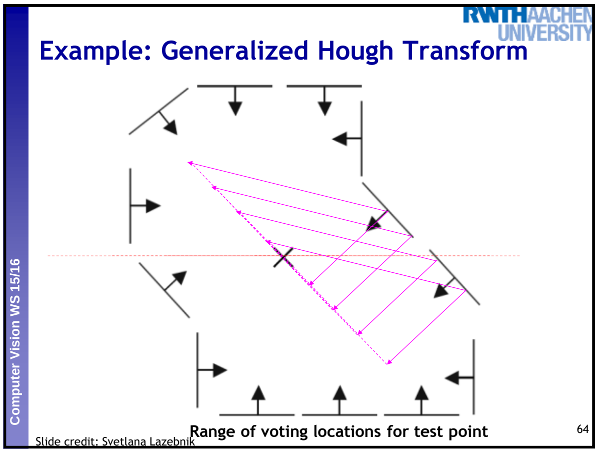
Example: Generalized Hough Transform

Displacement vectors for model points

Slide credit: Svetlana Lazebnik

63



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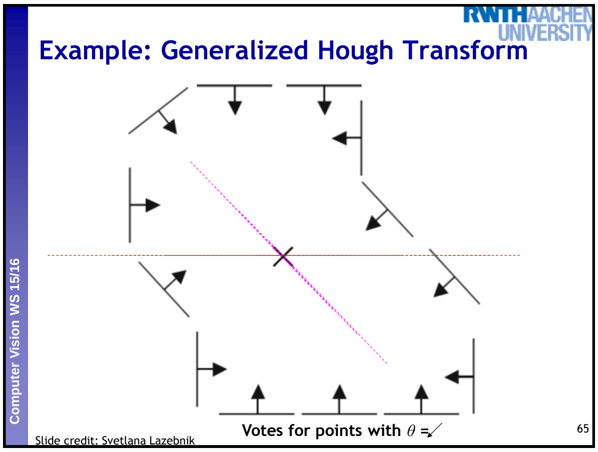
Example: Generalized Hough Transform

Range of voting locations for test point

Slide credit: Svetlana Lazebnik

64



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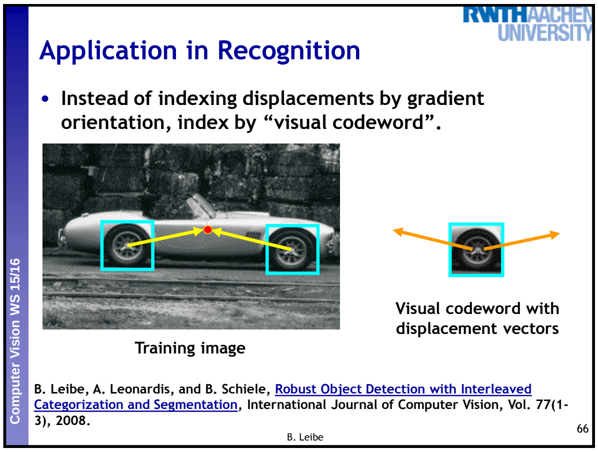
Example: Generalized Hough Transform

Votes for points with θ = ↙

Slide credit: Svetlana Lazebnik

65



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Application in Recognition

- Instead of indexing displacements by gradient orientation, index by “visual codeword”.

Training image

Visual codeword with displacement vectors

B. Leibe, A. Leonardis, and B. Schiele, Robust Object Detection with Interleaved Categorization and Segmentation, International Journal of Computer Vision, Vol. 77(1-3), 2008.

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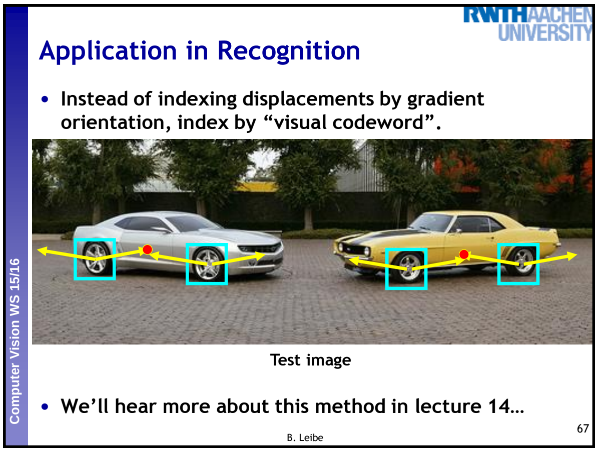
66



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Application in Recognition

- Instead of indexing displacements by gradient orientation, index by “visual codeword”.

Test image

- We’ll hear more about this method in lecture 14…

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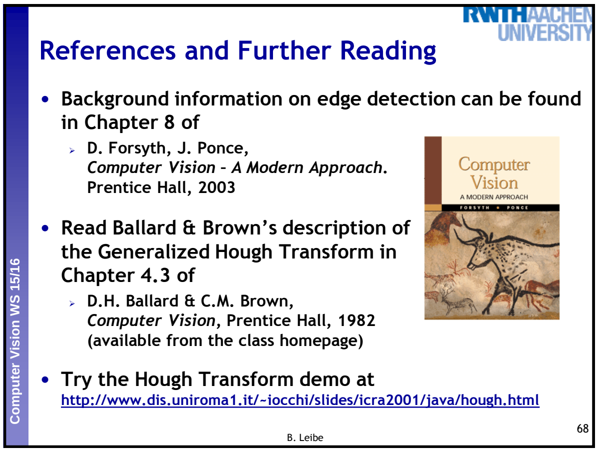
67



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References and Further Reading

- Background information on edge detection can be found in Chapter 8 of
  - D. Forsyth, J. Ponce, *Computer Vision – A Modern Approach*. Prentice Hall, 2003
- Read Ballard & Brown’s description of the Generalized Hough Transform in Chapter 4.3 of
  - D.H. Ballard & C.M. Brown, *Computer Vision*, Prentice Hall, 1982 (available from the class homepage)
- Try the Hough Transform demo at http://www.dis.uniroma1.it/~iocchi/slides/icra2001/java/hough.html

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68