CEE598 - Visual Sensing for Civil Infrastructure Eng. & Mgmt.

Section 10 - Detectors part II Descriptors

Mani Golparvar-Fard
Department of Civil and Environmental Engineering
3129D, Newmark Civil Engineering Lab
e-mail: mgolpar@illinois.edu

Outline
Detectors part II
Descriptors

- Blob detectors
- Invariance
- Descriptors

Some slides of this lectures are courtesy of prof S. Savarese, F. Li, prof S. Lazebnik, and various other lecturers

Goal:

- Identify interesting regions from the images (edges, corners, blobs…)

Descriptors e.g. SIFT

Matching / Indexing / Recognition

Characteristics

- Repeatability
  - The same feature can be found in several images despite geometric and photometric transformations
- Saliency
  - Each feature is found at an "interesting" region of the image
- Locality
  - A feature occupies a "relatively small" area of the image;

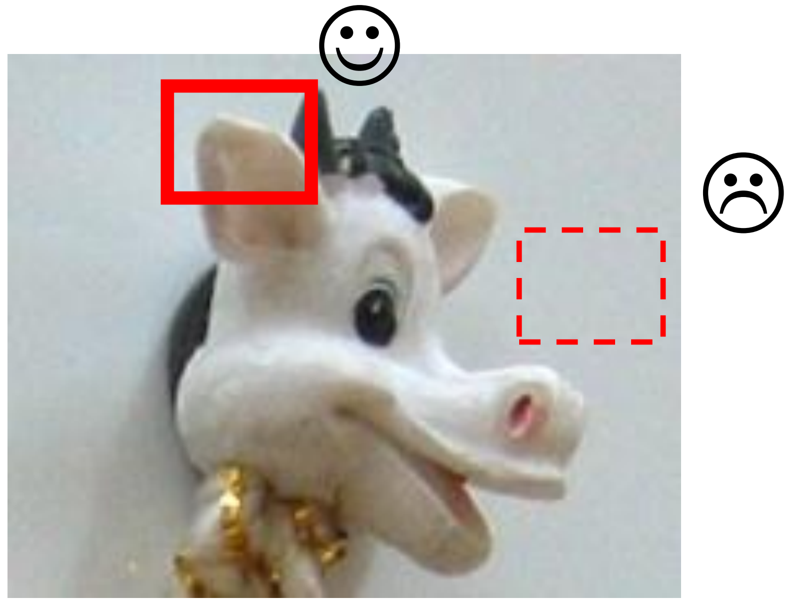
Repeatability

Illumination invariance

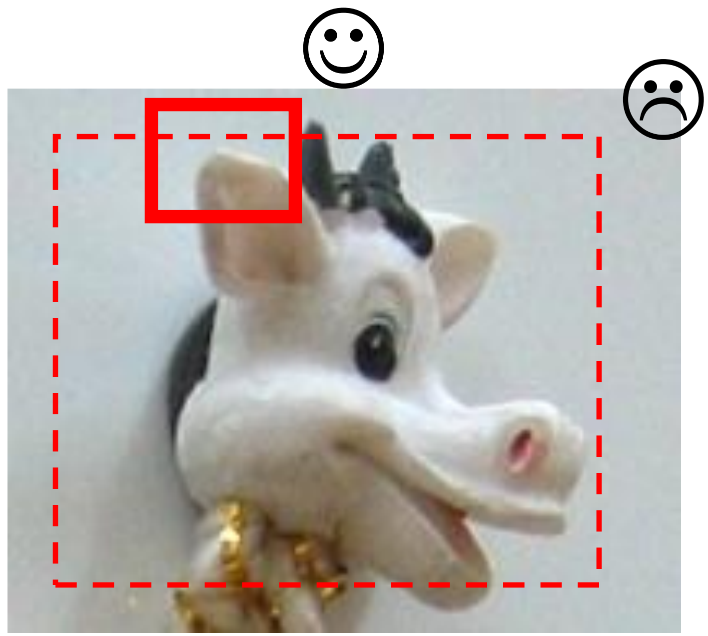
Scale invariance

Pose invariance
- Rotation
- Affine

- Saliency



- Locality

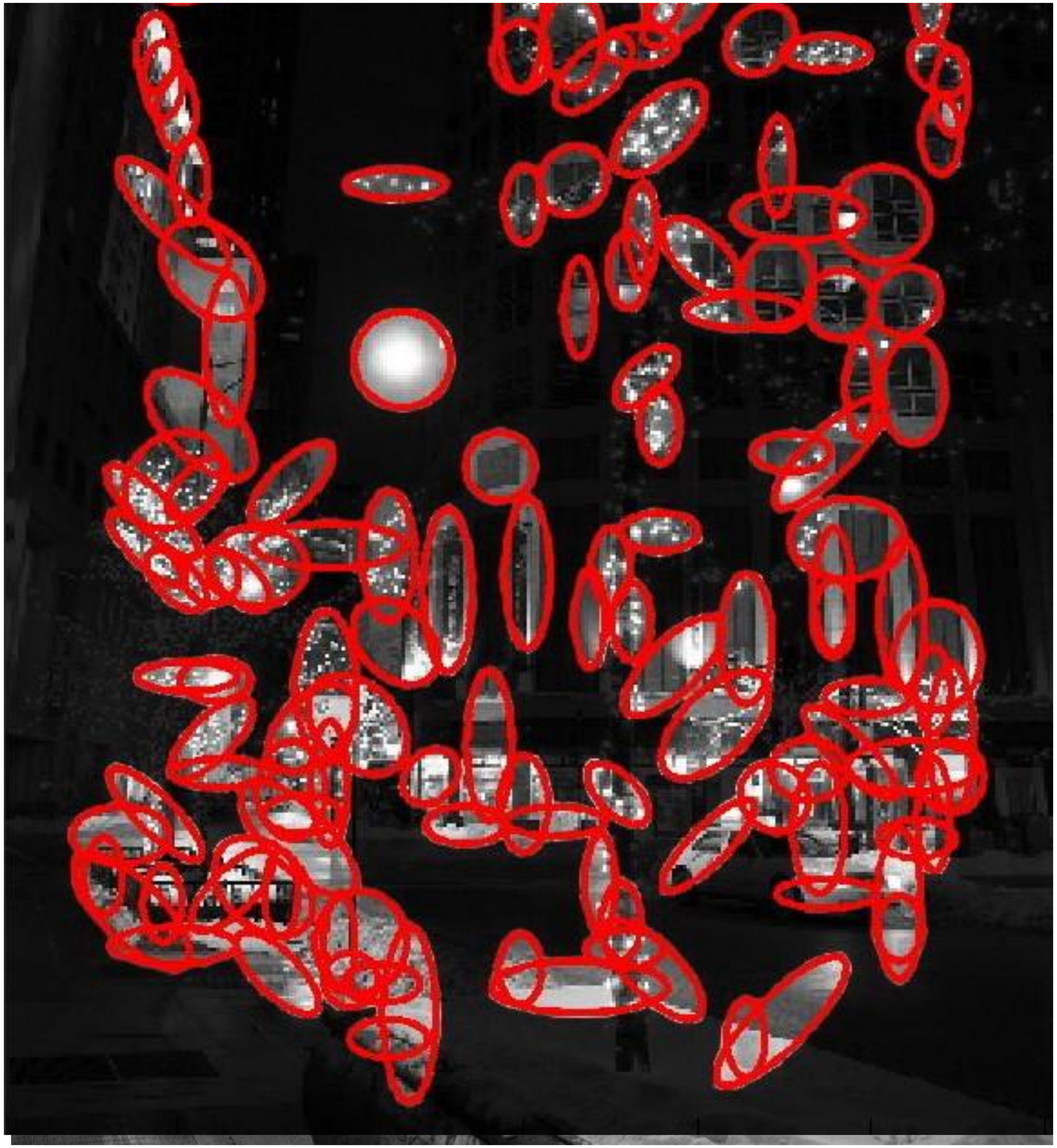


Harris Detector

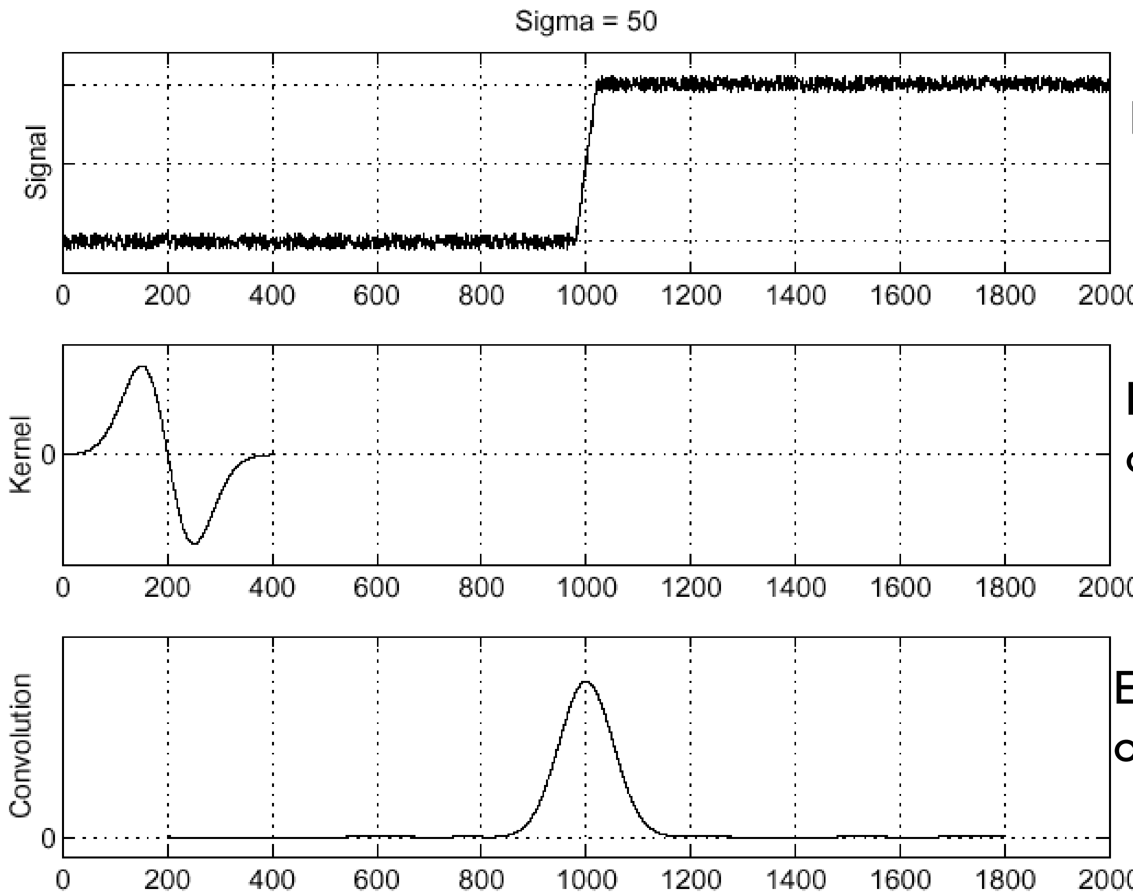
Invariance

Detector	Illumination	Rotation	Scale	View point
Harris corner	partial	Yes	No	No

Extract useful building blocks: blobs



Edge detection



f

Edge

$\frac{d}{dx} g$

Derivative
of Gaussian

$f * \frac{d}{dx} g$

Edge = maximum
of derivative

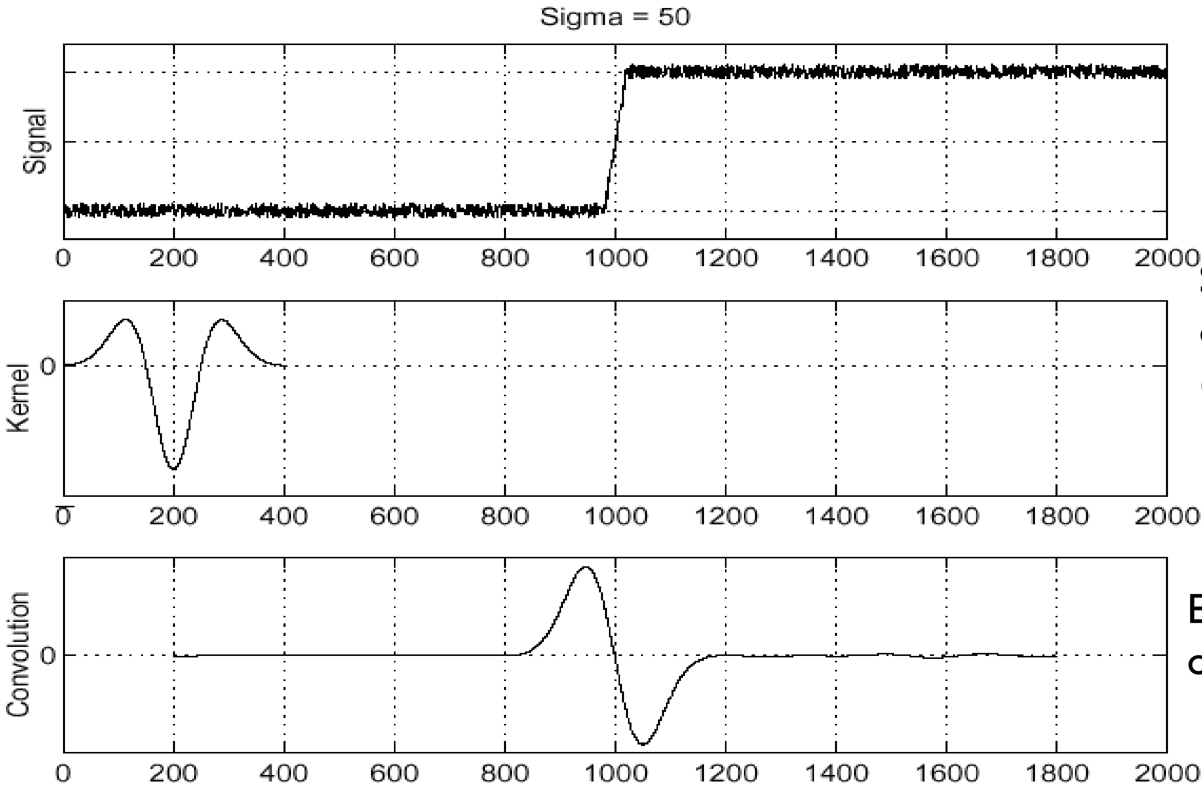
Source: S. Seitz

Edge detection as zero crossing

f

$$\frac{d^2}{dx^2} g$$

$$f * \frac{d^2}{dx^2} g$$



Edge

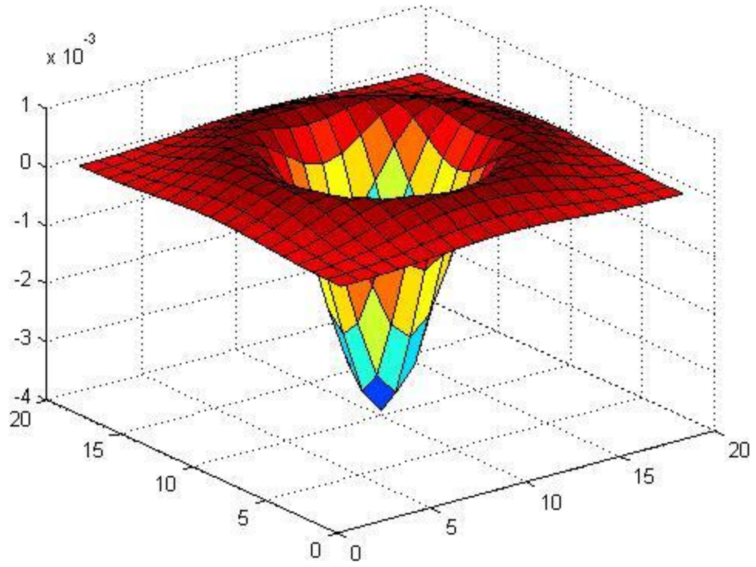
Second derivative of Gaussian (Laplacian)

Edge = zero crossing of second derivative

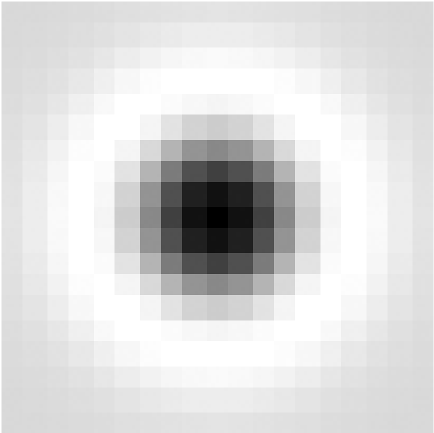
Source: S. Seitz

Blob detection in 2D

- Laplacian of Gaussian: Circularly symmetric operator for blob detection in 2D

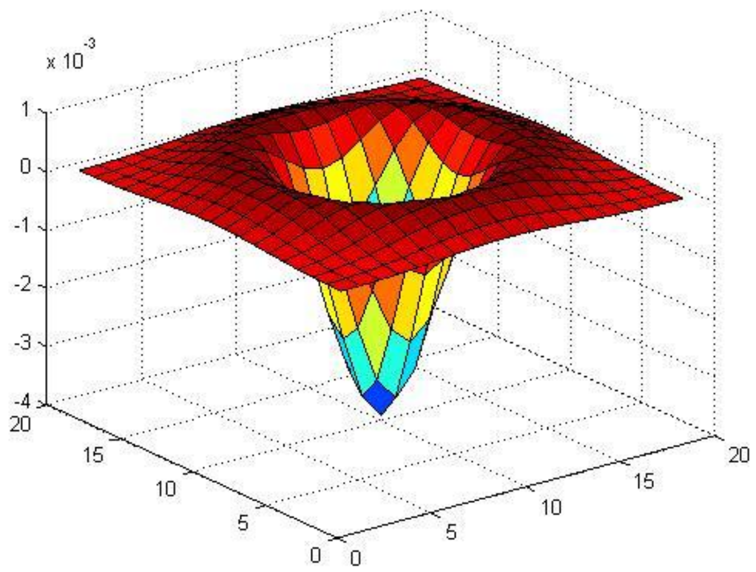


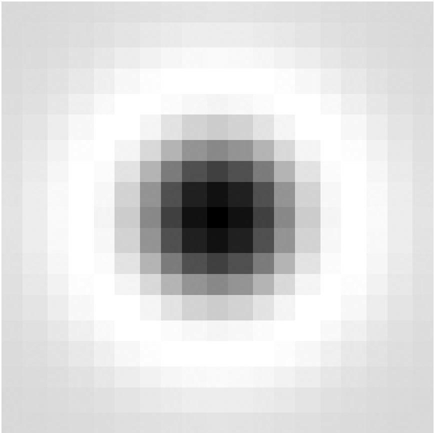
$$\nabla^2 g = \frac{\partial^2 g}{\partial x^2} + \frac{\partial^2 g}{\partial y^2}$$



Blob detection in 2D

- Laplacian of Gaussian: Circularly symmetric operator for blob detection in 2D





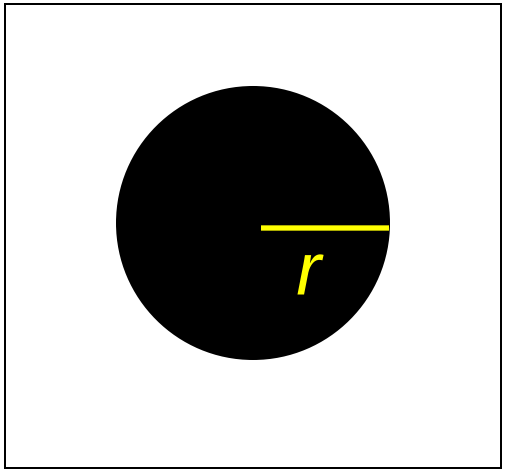
Scale-normalized: $$\nabla^2_{\text{norm}} g = \sigma^2 \left(\frac{\partial^2 g}{\partial x^2} + \frac{\partial^2 g}{\partial y^2} \right)$$

Scale selection

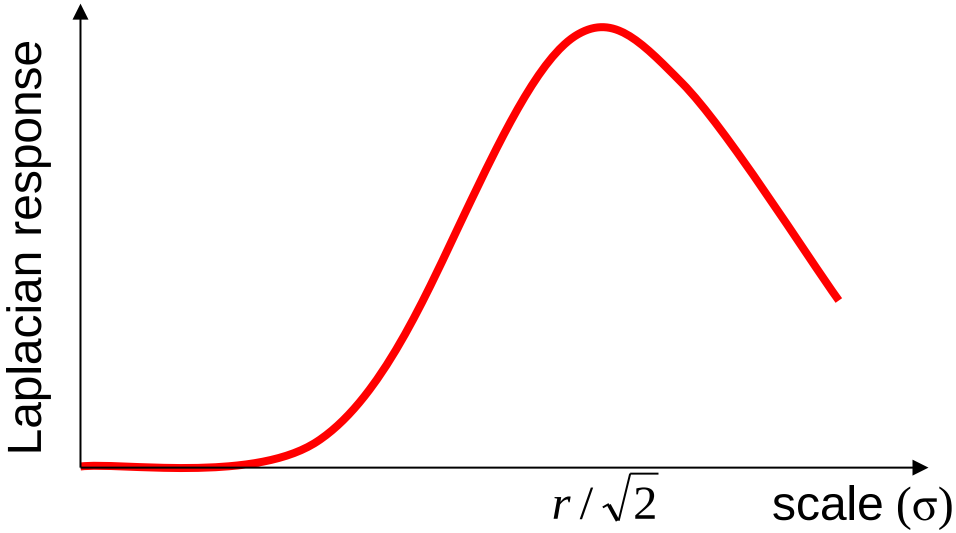
- The 2D Laplacian is given by

$$(x^2 + y^2 - 2\sigma^2)\, e^{-(x^2+y^2)/2\sigma^2} \quad \text{(up to scale)}$$

- Therefore, for a binary circle of radius r, the Laplacian achieves a maximum at

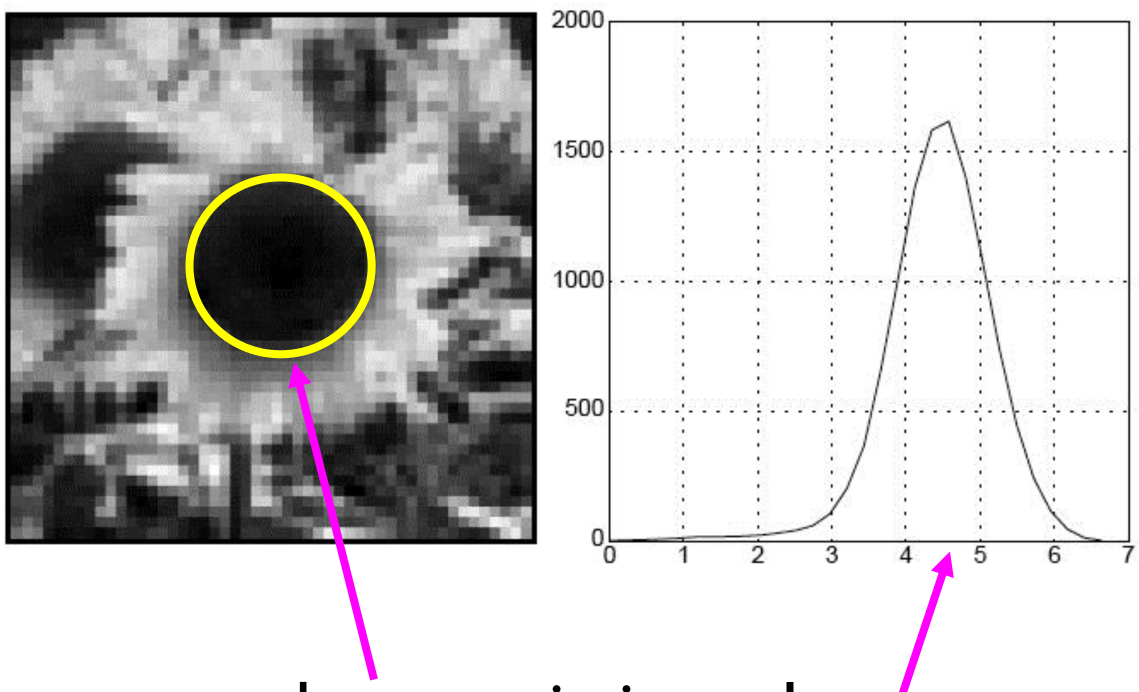


image



Characteristic scale

- We define the characteristic scale as the scale that produces peak of Laplacian response

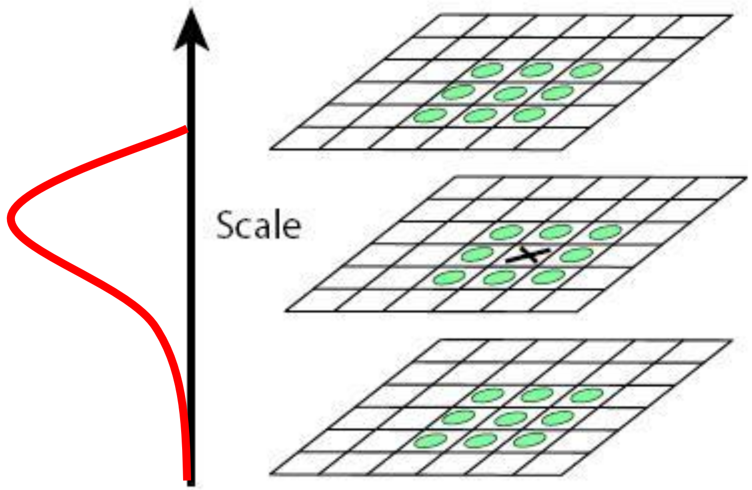


characteristic scale

T. Lindeberg (1998). "Feature detection with automatic scale selection." *International Journal of Computer Vision* **30** (2): pp 77--116.

Scale-space blob detector

1. Convolve image with scale-normalized Laplacian at several scales
2. Find maxima of squared Laplacian response in scale-space
3. This indicate if a blob has been detected
4. And what's its intrinsic scale

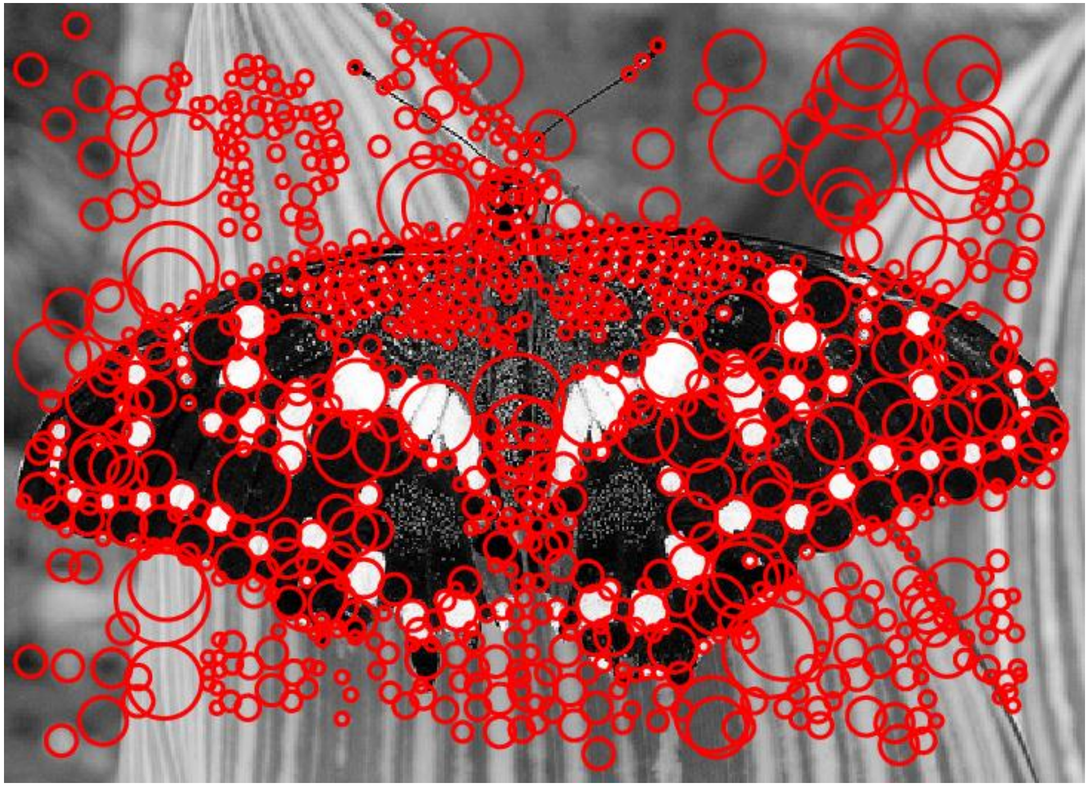


Scale-space blob detector: Example

Scale-space blob detector: Example

sigma = 11.9912

Scale-space blob detector: Example



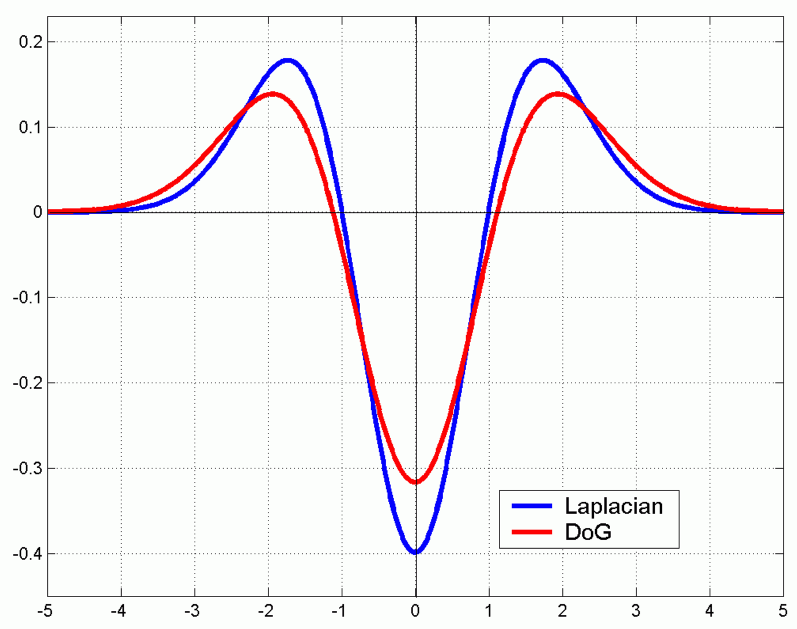
DOG

David G. Lowe. "Distinctive image features from scale-invariant keypoints." *IJCV* 60 (2), 04

- Approximating the Laplacian with a difference of Gaussians:

$$L = \sigma^2 \left(G_{xx}(x,y,\sigma) + G_{yy}(x,y,\sigma) \right)$$

(Laplacian)



$$DoG = G(x,y,k\sigma) - G(x,y,\sigma)$$

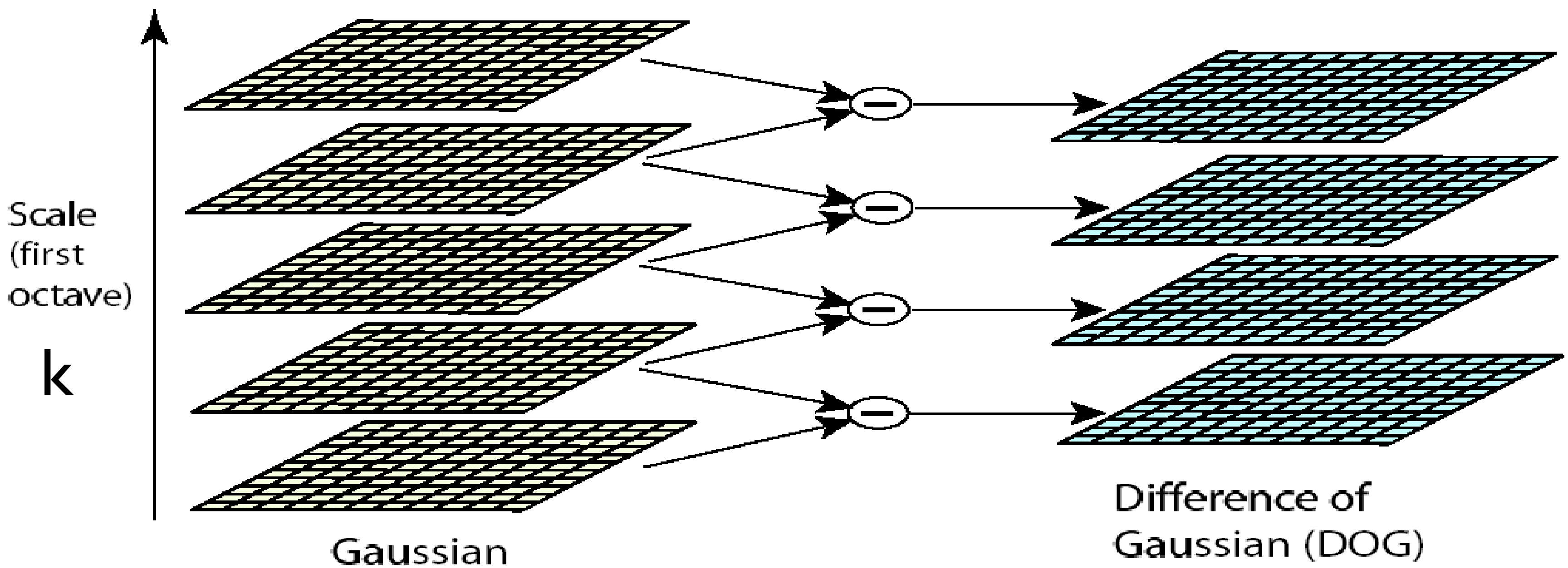
(Difference of Gaussians)

or

Difference of gaussian blurred images at scales k σ and σ

$$G(x,y,k\sigma) - G(x,y,\sigma) \approx (k-1)\sigma^2 \boldsymbol{L}$$

DOG



Output: location, scale, orientation (more later)

Example of keypoint detection

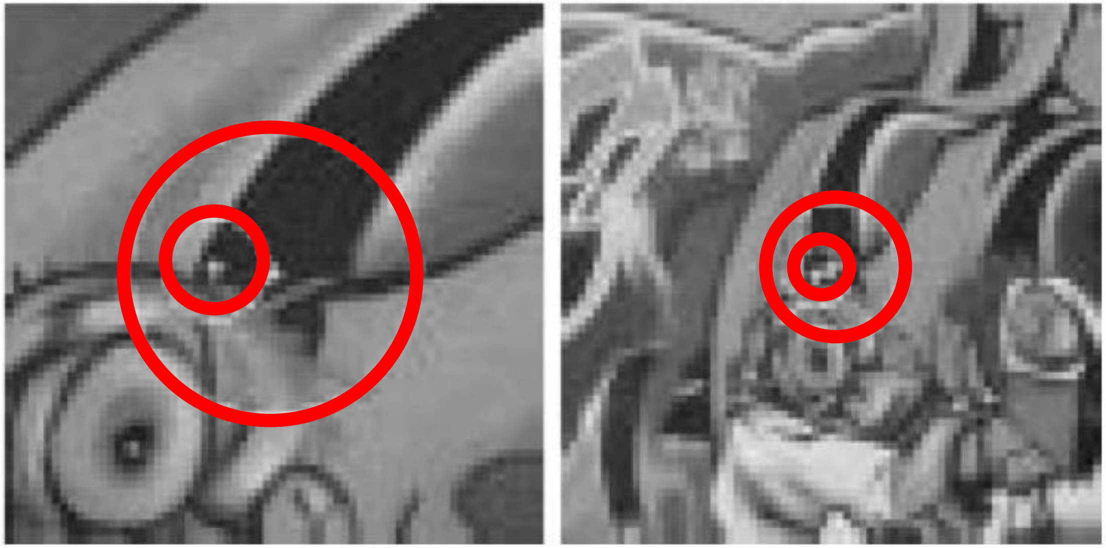
(b)

Invariance

Detector	Illumination	Rotation	Scale	View point
Harris corner	Yes	Yes	No	No
Lowe '99 (DoG)	Yes	Yes	Yes	No

Harris-Laplace
[Mikolajczyk & Schmid '01]

- Collect locations (x,y) of detected Harris features for $\sigma = \sigma_1 \ldots \sigma_2$ (the sigma is here comes from $g_{x,} g_y$)
- For each detected location (x,y) and for each σ, reject detection if Laplacian(x,y, σ) is not a local maximum



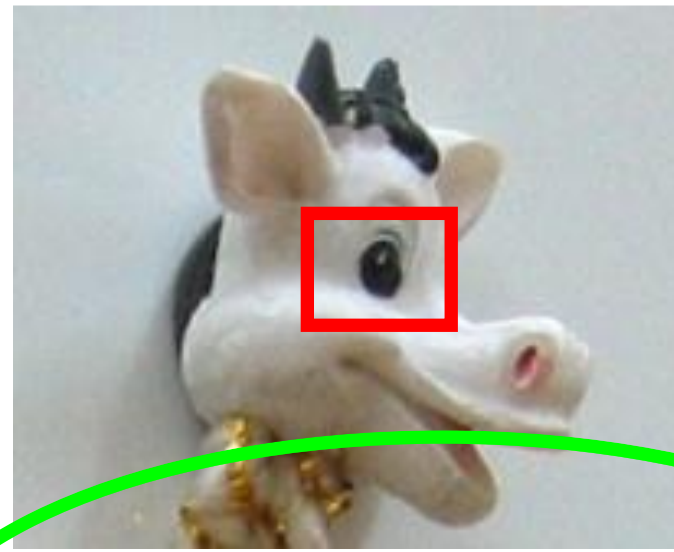
Output: location, scale

Invariance

Detector	Illumination	Rotation	Scale	View point
Harris corner	Yes	Yes	No	No
Lowe ’99 (DoG)	Yes	Yes	Yes	No
Mikolajczyk & Schmid ’01	Yes	Yes	Yes	No

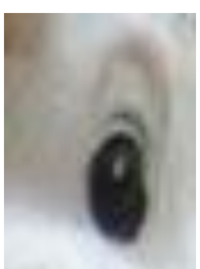
Repeatability

Illumination invariance



Scale invariance

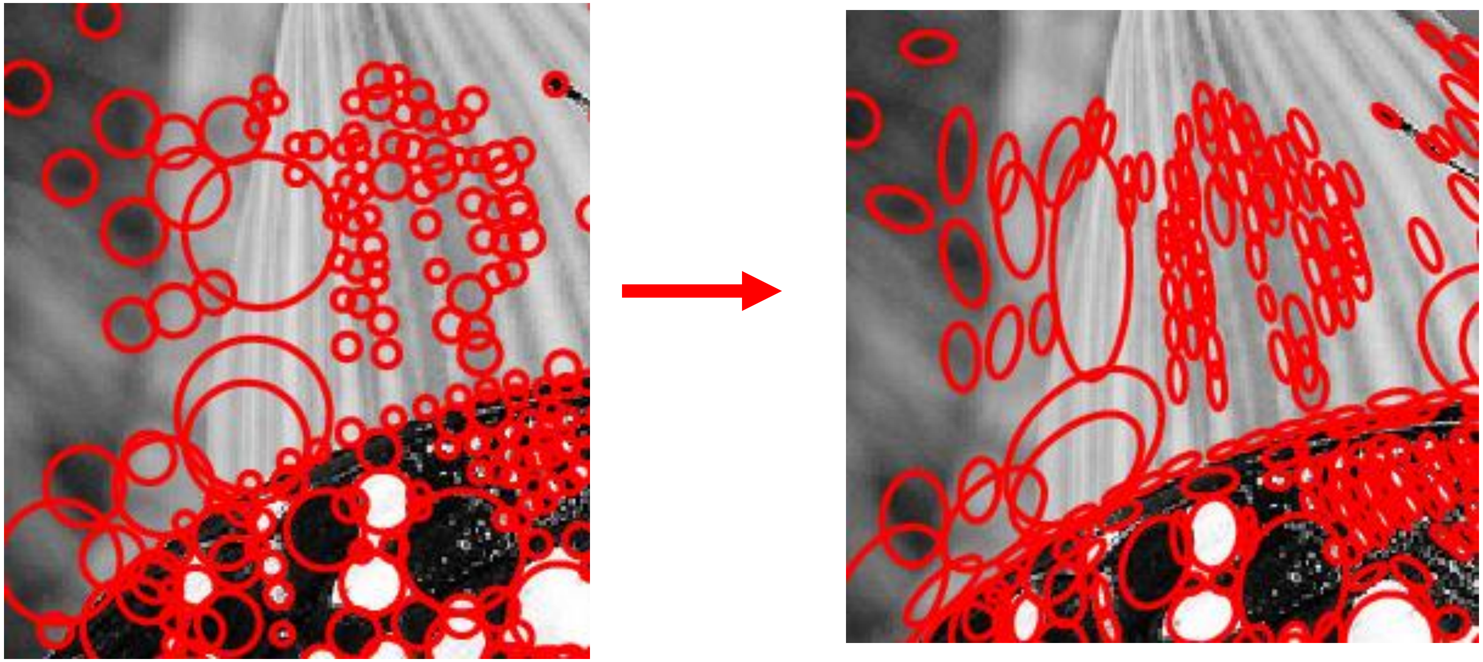
Pose invariance
- Rotation
- Affine



Affine invariance

K. Mikolajczyk and C. Schmid, Scale and Affine invariant interest point detectors, IJCV 60(1):63-86, 2004.

Similarly to characteristic scale selection, detect the characteristic shape of the local feature



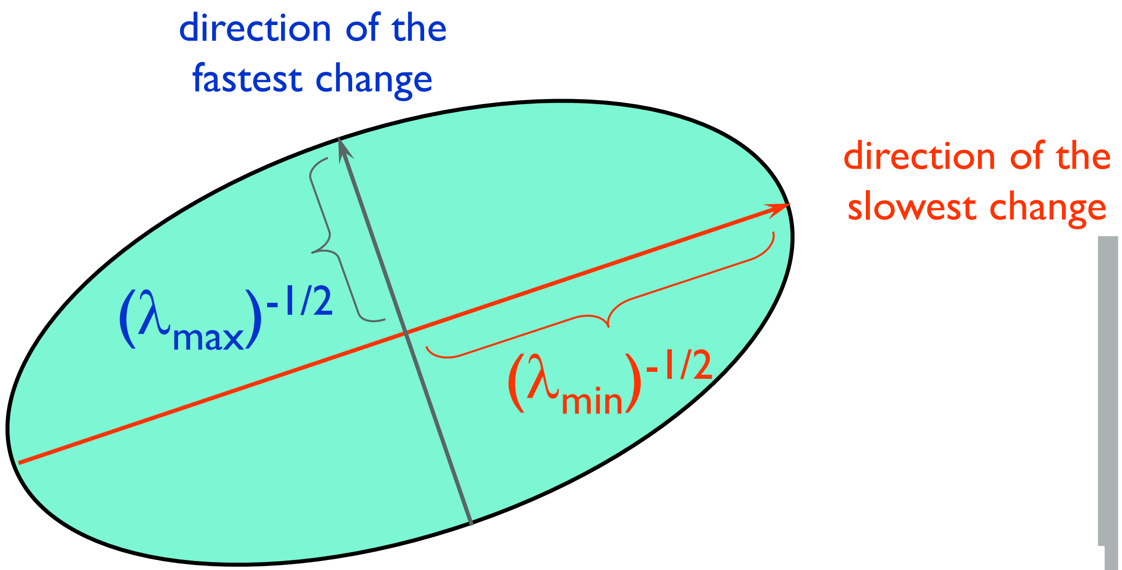
Affine adaptation

$$M = \sum_{x,y} w(x,y) \begin{bmatrix} I_x^2 & I_x I_y \\ I_x I_y & I_y^2 \end{bmatrix} = R^{-1} \begin{bmatrix} \lambda_1 & 0 \\ 0 & \lambda_2 \end{bmatrix} R$$

We can visualize *M* as an ellipse with axis lengths determined by the eigenvalues and orientation determined by *R*

Ellipse equation:

$$[u \;\; v] \; M \begin{bmatrix} u \\ v \end{bmatrix} = \text{const}$$

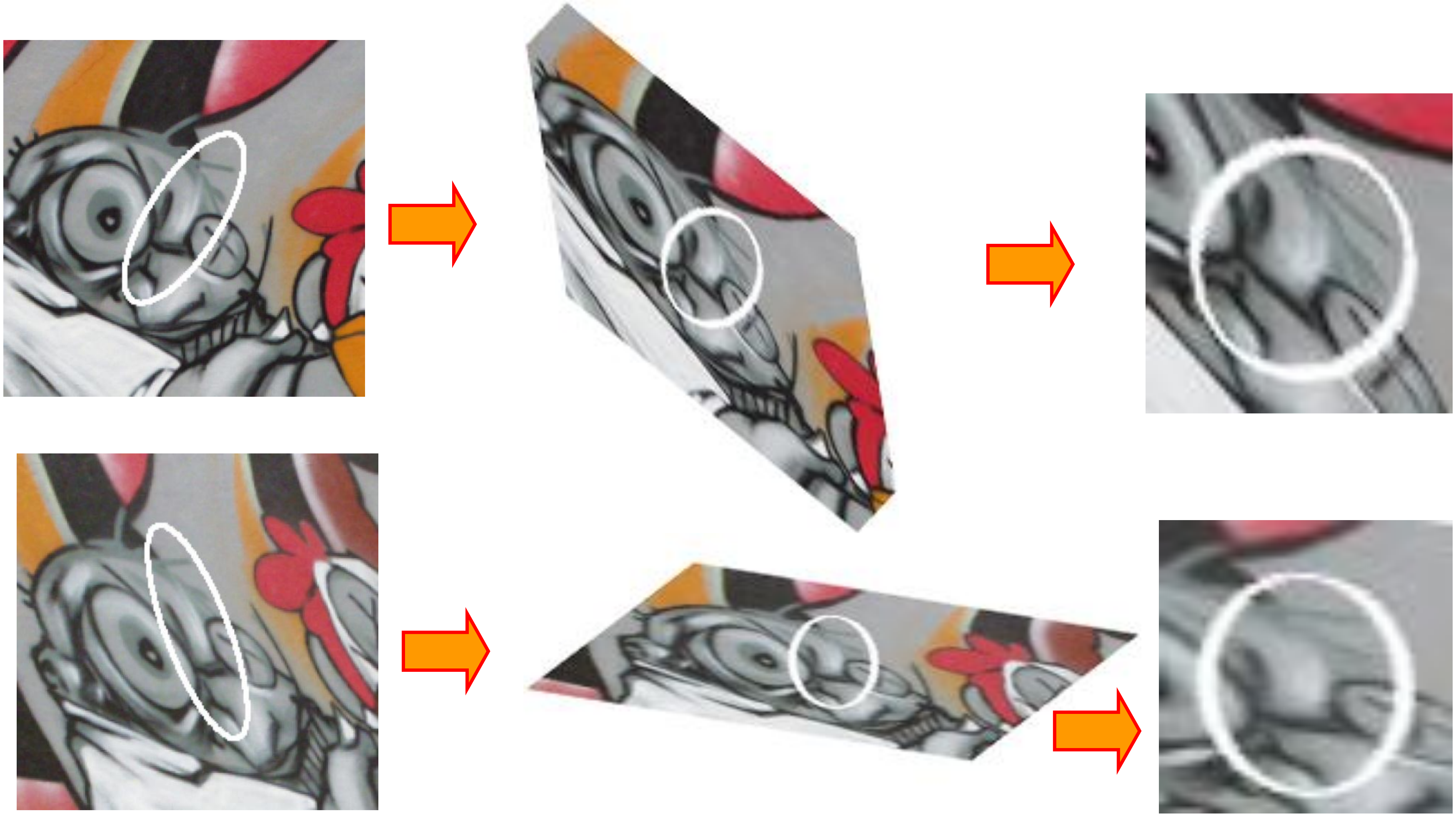


The second moment ellipse can be viewed as the "characteristic shape" of a region

Affine adaptation

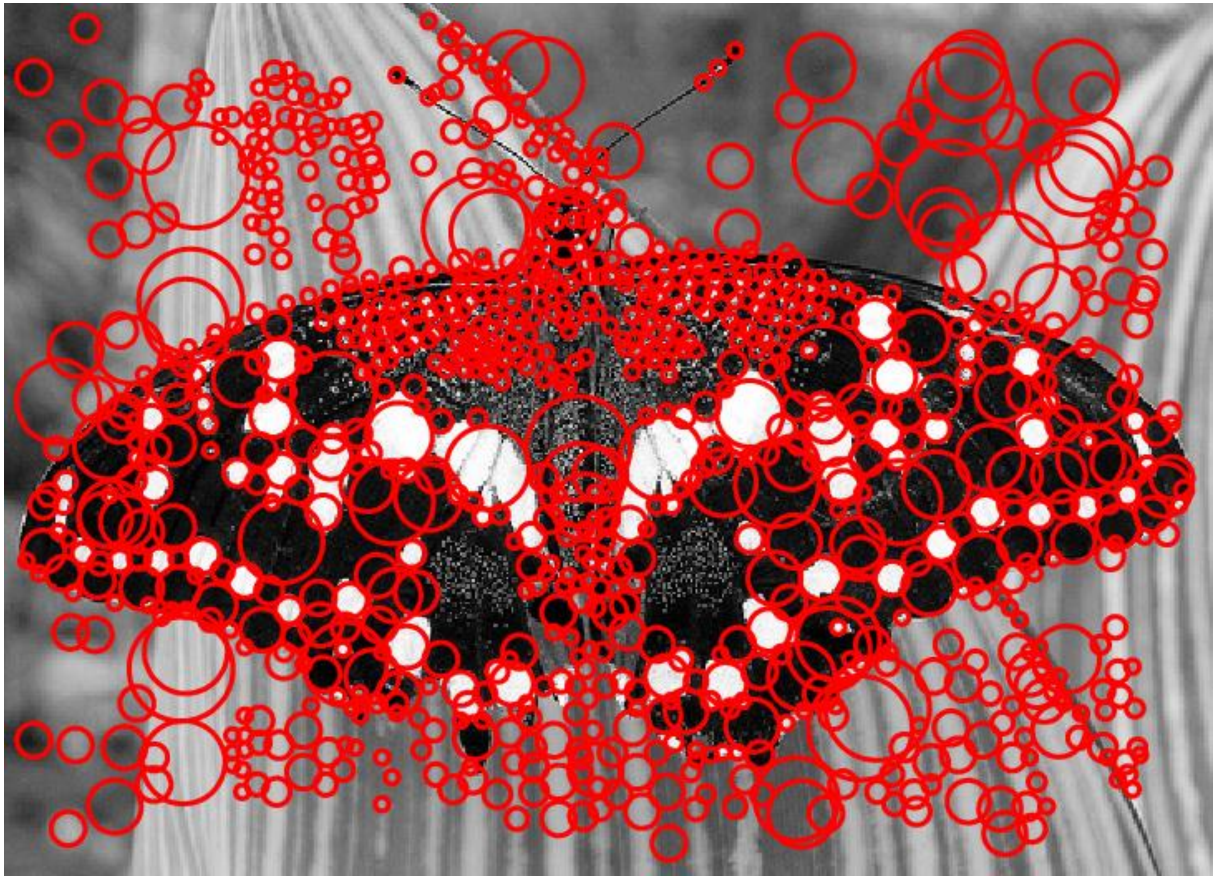
1. Detect initial region with Harris Laplace
2. Estimate affine shape with M
3. Normalize the affine region to a circular one
4. Re-detect the new location and scale in the normalized image
5. Go to step 2 if the eigenvalues of the M for the new point are not equal [detector not yet adapted to the characteristic shape]

Affine adaptation



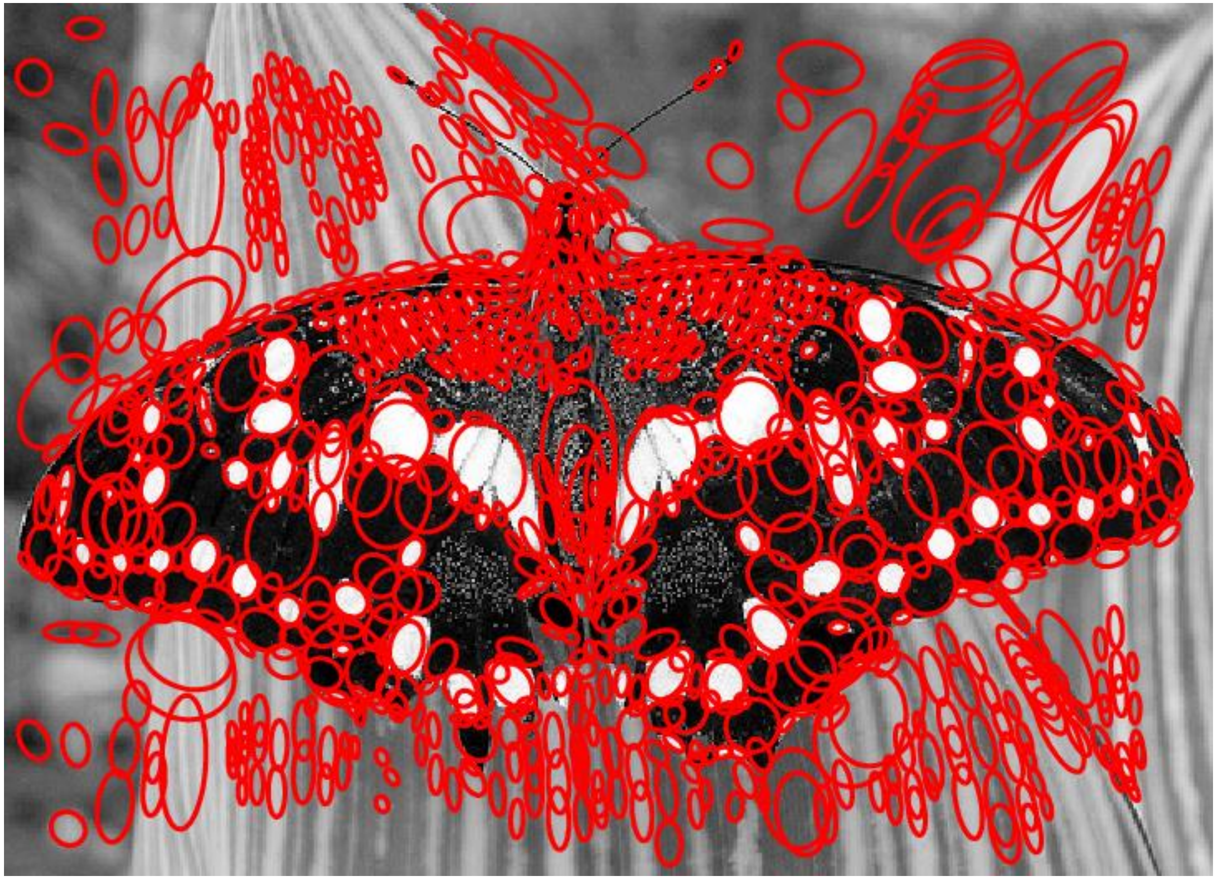
Output: location, scale, affine shape, rotation (more later)

Affine adaptation example



Scale-invariant regions (blobs)

Affine adaptation example



Affine-adapted blobs

Invariance

Detector	Illumination	Rotation	Scale	View point
Harris corner	Yes	Yes	No	No
Lowe '99 (DoG)	Yes	Yes	Yes	No
Mikolajczyk & Schmid '01	Yes	Yes	Yes	No
Mikolajczyk & Schmid '02	Yes	Yes	Yes	Yes

Detector	Illumination	Rotation	Scale	View point
Harris corner	Yes	Yes	No	No
Lowe ’99 (DoG)	Yes	Yes	Yes	Yes
Mikolajczyk & Schmid ’01, ‘02	Yes	Yes	Yes	Yes
Tuytelaars, ‘00	Yes	Yes	No (Yes ’04)	Yes
Kadir & Brady, 01	Yes	Yes	Yes	no
Matas, ’02	Yes	Yes	Yes	no

- Blob detectors
- Invariance
- Descriptors

Goal:

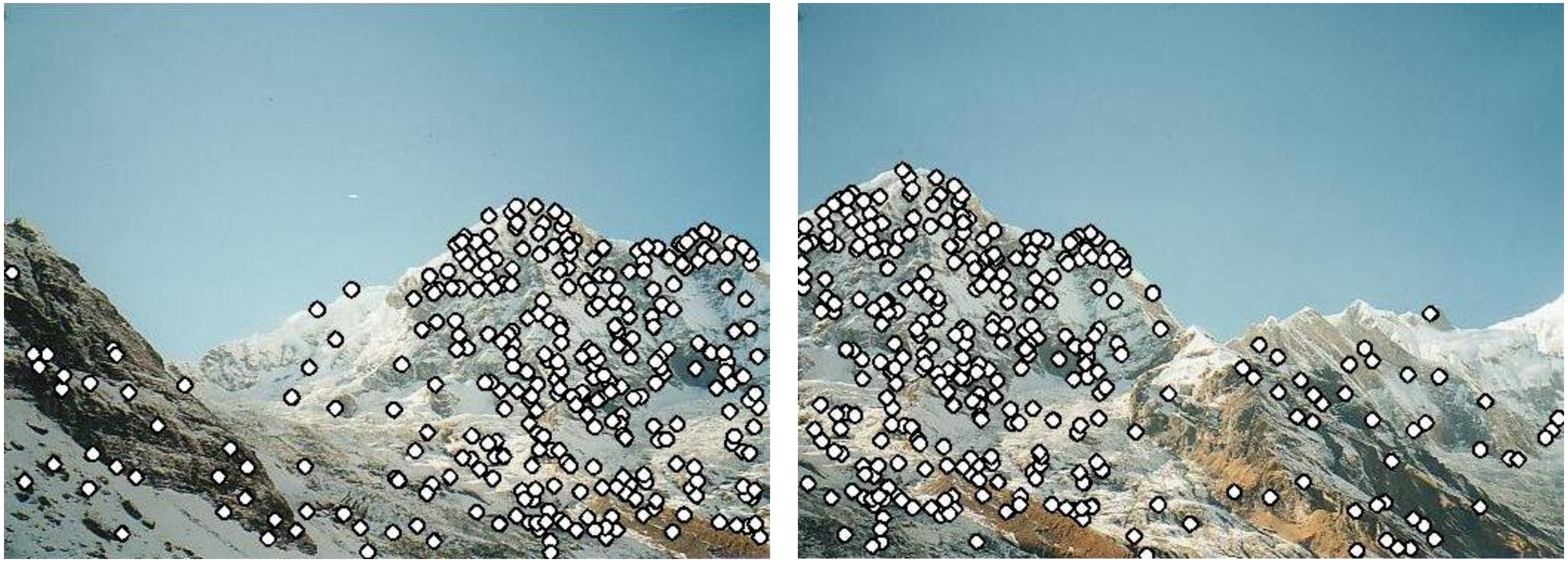
- Identify interesting regions from the images (edges, corners, blobs…)

Descriptors e.g. SIFT

Matching / Indexing / Recognition

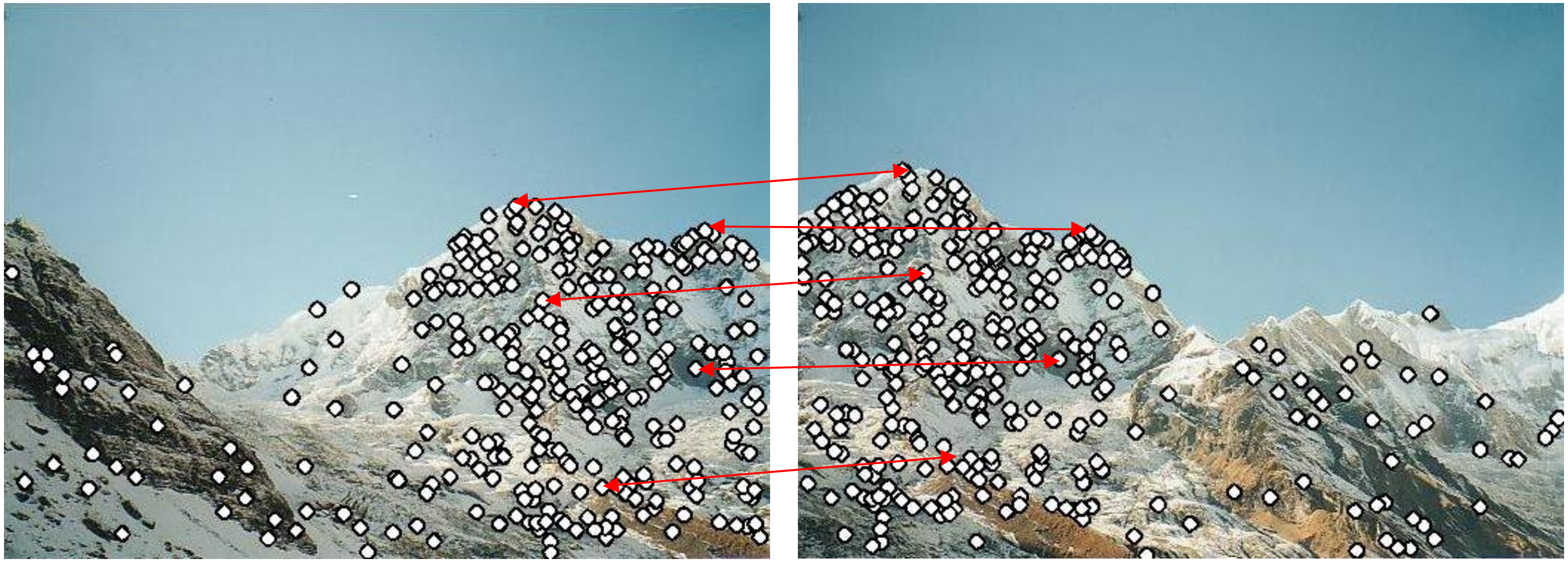
Matching Features
(stitching images)

- Detect feature points in both images



Matching Features
(stitching images)

- Detect feature points in both images
- Find corresponding pairs

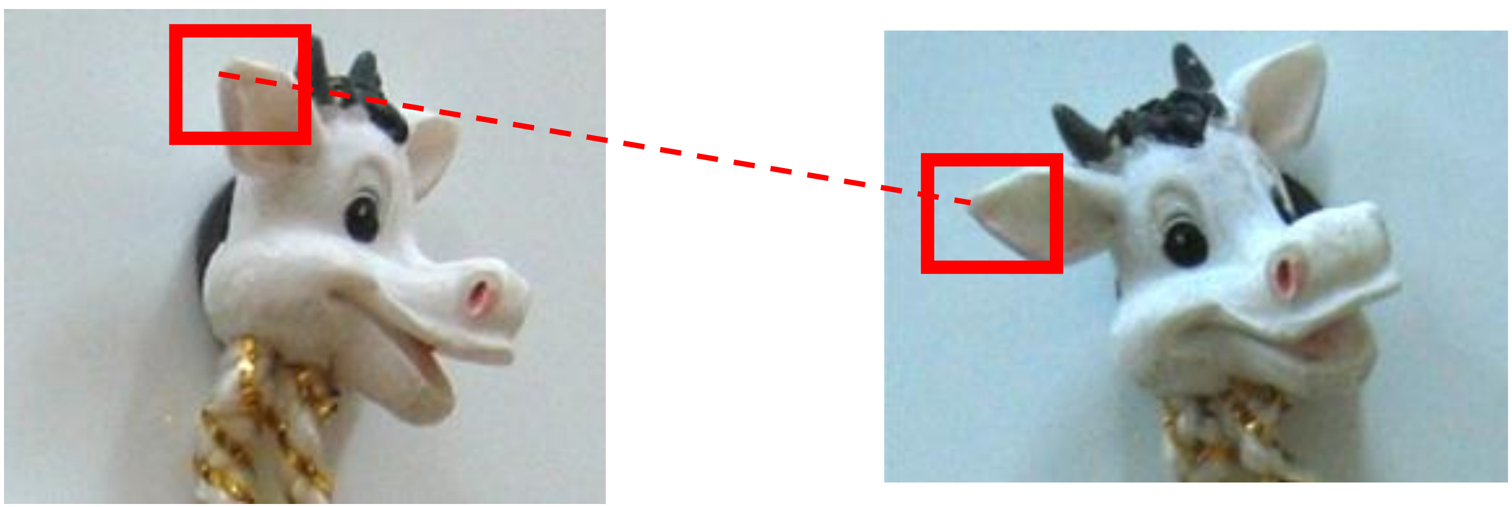


Matching Features
(stitching images)

- Detect feature points in both images
- Find corresponding pairs
- Use these pairs to align images

Matching Features
(estimating F)

- Detect feature points in both images
- Find corresponding pairs
- Use these pairs to estimate F



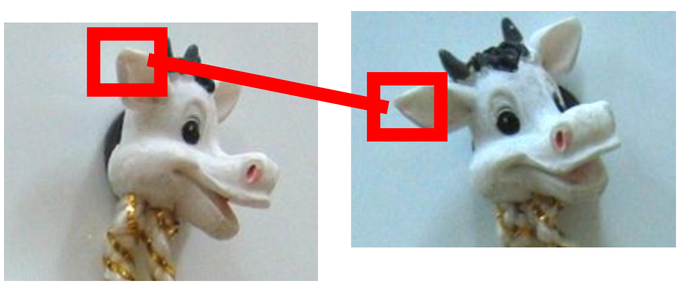
Matching Features
(recognizing objects)

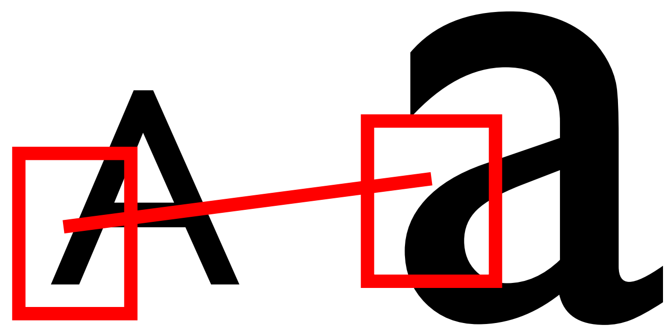
- Detect feature points in both images
- Find corresponding pairs
- Use these pairs to match different object instances

Challenges

Depending on the application a descriptor must incorporate information that is:

- Invariant w.r.t:
  - Illumination
  - Pose
  - Scale
  - Intraclass variability



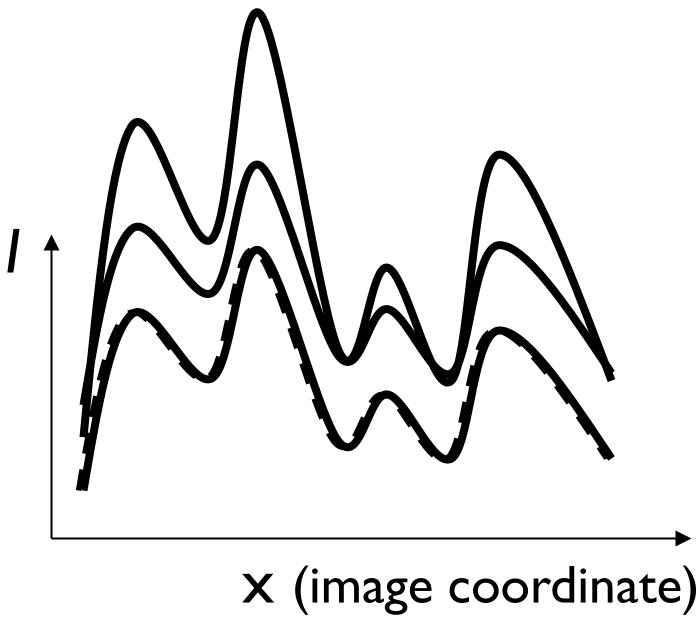


- **Highly distinctive** (allows a single feature to find its correct match with good probability in a large database of features)

Illumination normalization

- *Affine intensity* change:

$$I \rightarrow I + b$$
$$\rightarrow a\,I + b$$



•Make each patch zero mean:

$$\mu = \frac{1}{N}\sum_{x,y} I(x,y)$$

$$Z(x,y) = I(x,y) - \mu$$

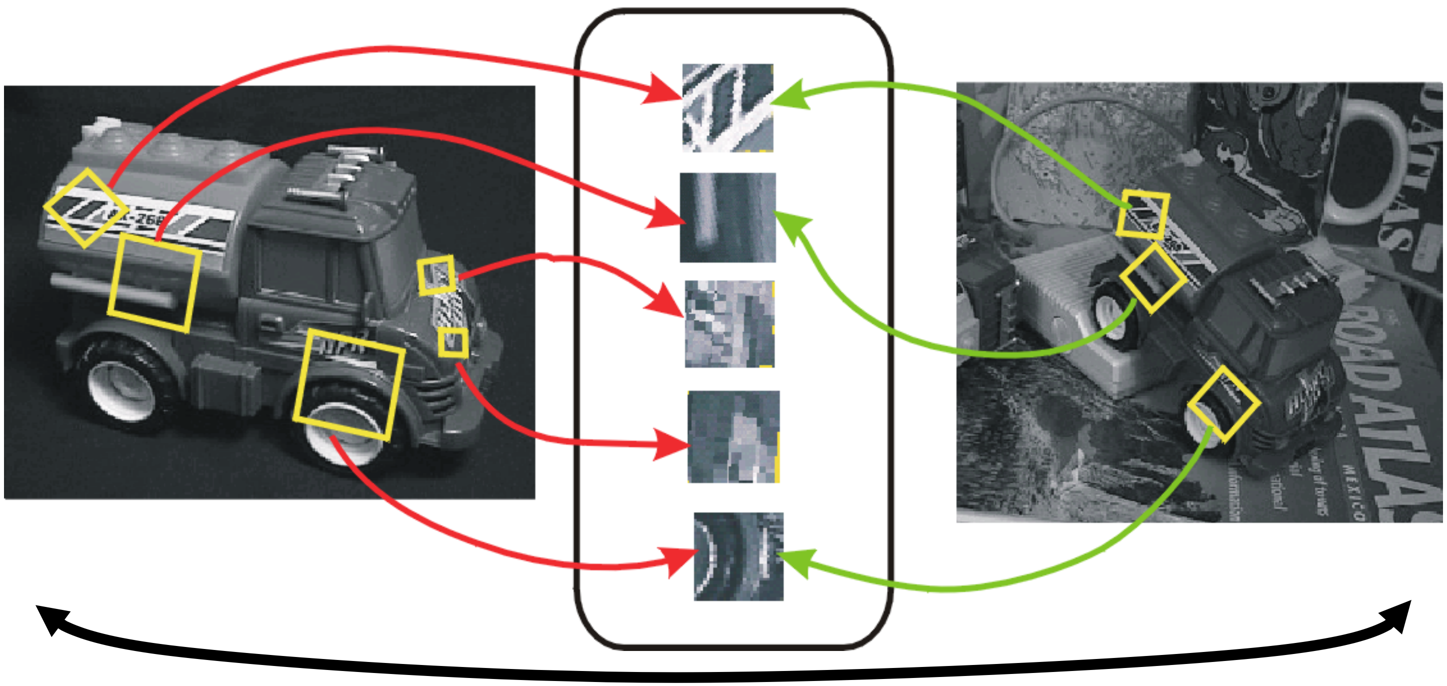
•Then make unit variance:

$$\sigma^2 = \frac{1}{N}\sum_{x,y} Z(x,y)^2$$

$$ZN(x,y) = \frac{Z(x,y)}{\sigma}$$

Pose normalization

- Keypoints are transformed in order to be invariant to translation, rotation, scale, and other geometrical parameters

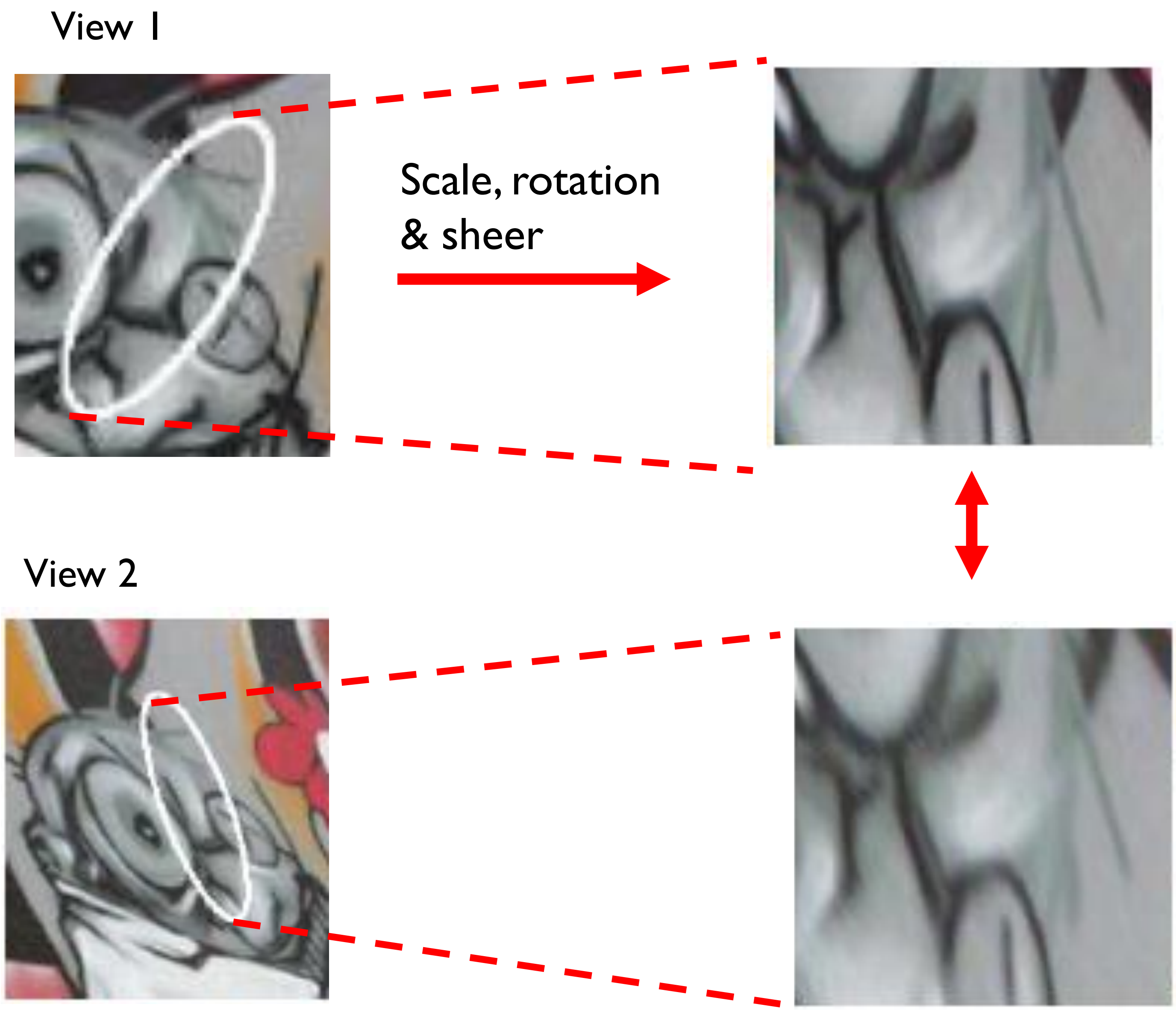


Courtesy of D. Lowe

Change of scale, pose, illumination…

Pose normalization

NOTE: location, scale, rotation & affine pose are given by the detector or calculated within the detected regions



The simplest descriptor

1 x NM vector of pixel intensities

w= [ … ]

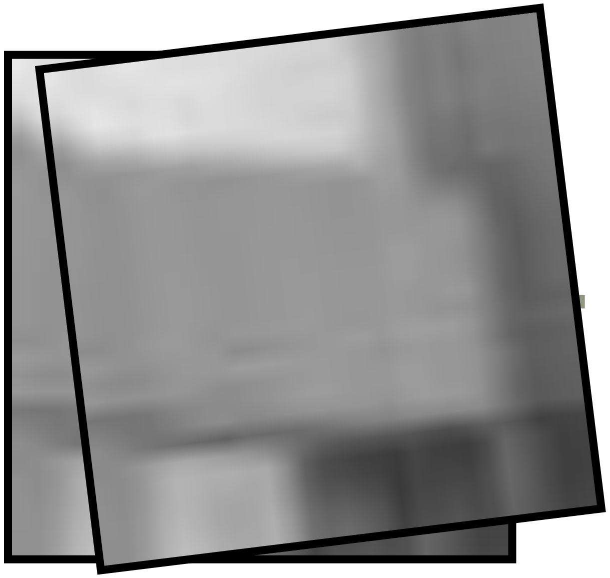
$$w_n = \frac{(w - \overline{w})}{\left\|(w - \overline{w})\right\|}$$

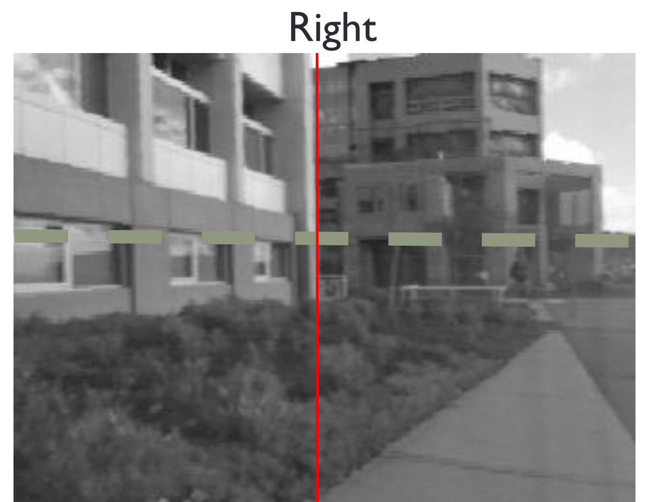
Makes the descriptor invariant with respect to affine transformation of the illumination condition

Why can’t we just use this?

- Sensitive to small variation of:
  - location
  - Pose
  - Scale
  - intra-class variability
- Poorly distinctive

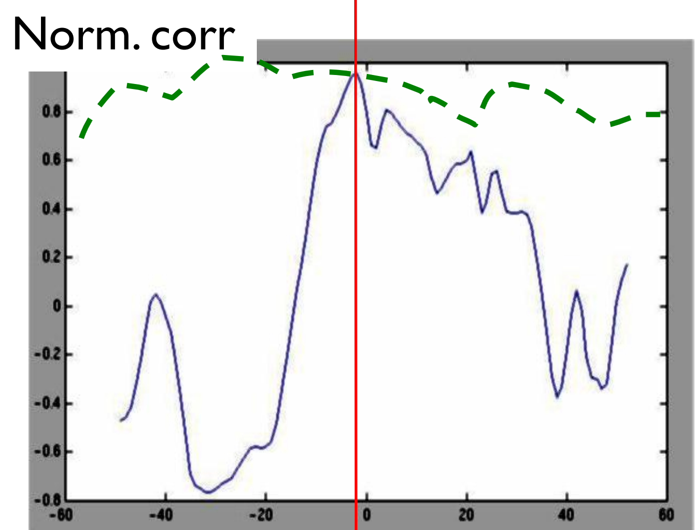
Stereo systems





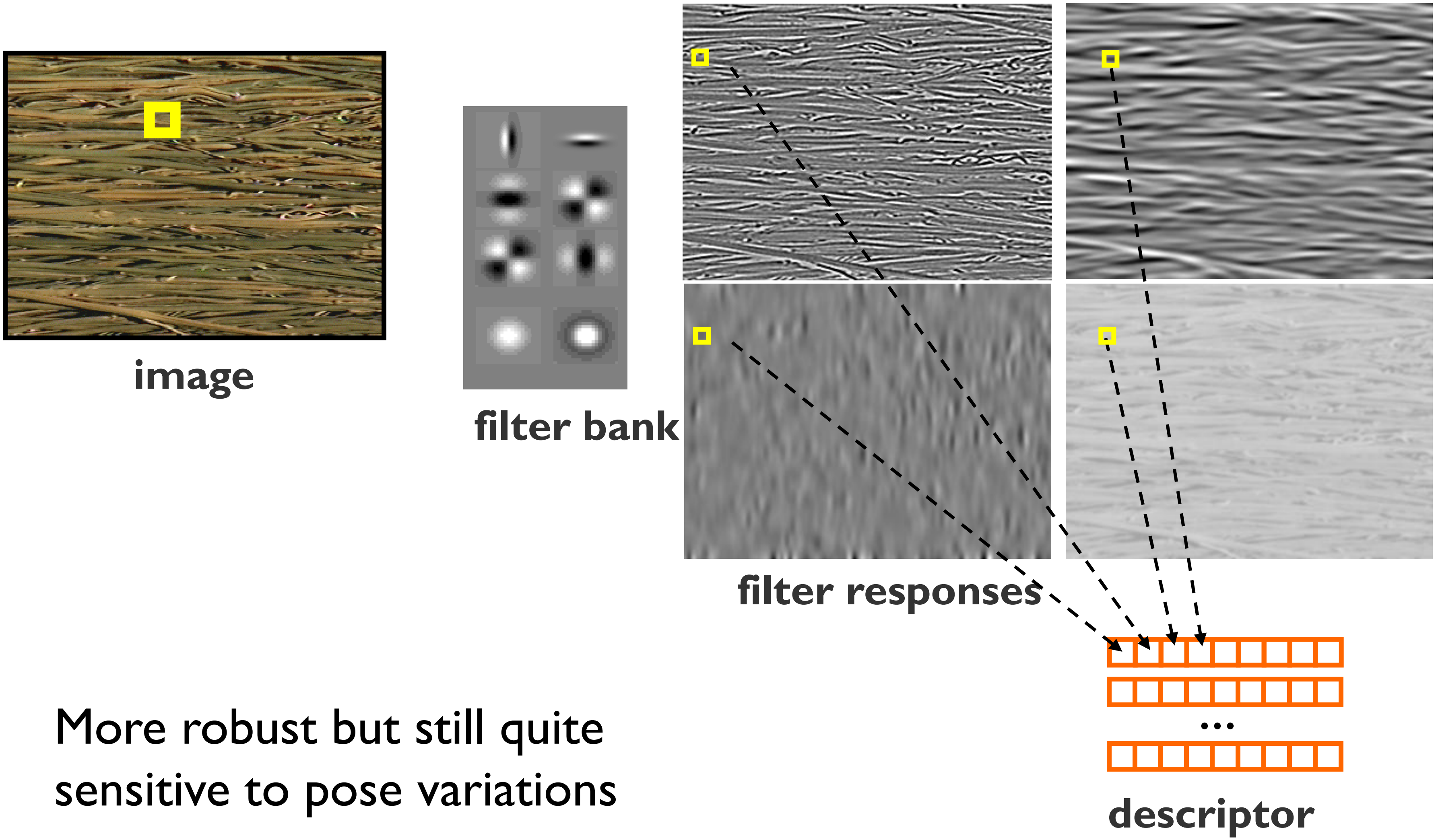
Normalized Correlation:

$$w_n \cdot w'_n = \frac{(w - \overline{w})(w' - \overline{w}')}{\left\| (w - \overline{w})(w' - \overline{w}') \right\|}$$



Detector	Illumination	Pose	Intra-class variab.
PATCH	***	*	*

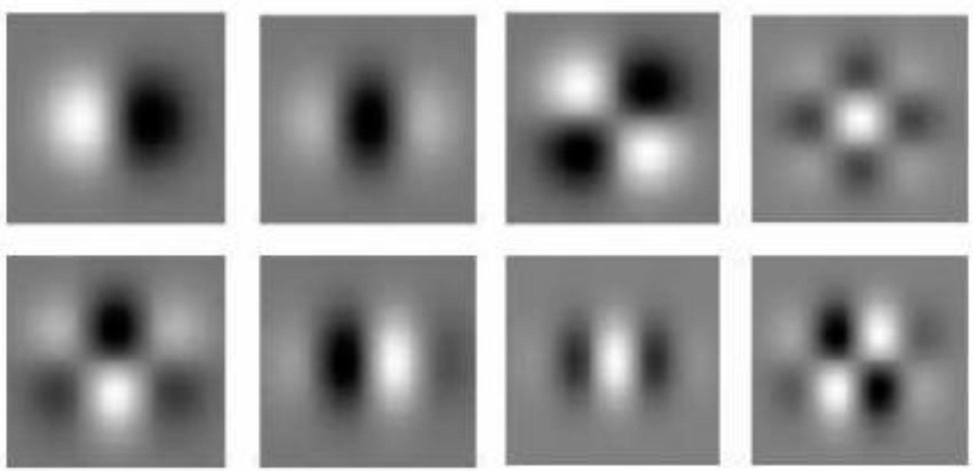
Bank of filters



More robust but still quite sensitive to pose variations

Bank of filters - Steerable filters

Gaussian derivatives up to 4^{th} order. The remaining derivatives can be computed by rotation of 90 degrees.



Detector	Illumination	Pose	Intra-class variab.
PATCH	***	*	*
FILTERS	***	**	**

SIFT descriptor

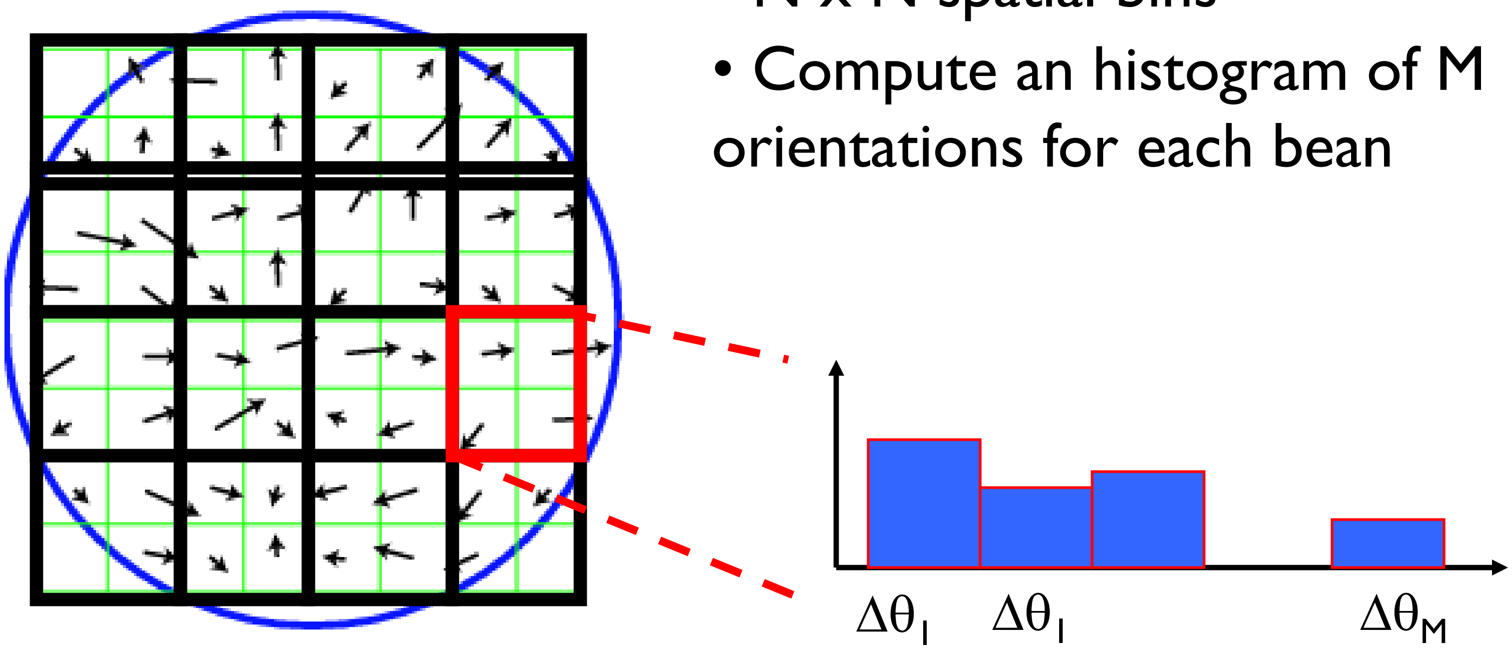
David G. Lowe. **"Distinctive image features from scale-invariant keypoints."** *IJCV* 60 (2), 04

- Alternative representation for image patches
- Location and characteristic scale s given by DoG detector

SIFT descriptor

David G. Lowe. **"Distinctive image features from scale-invariant keypoints."** *IJCV* 60 (2), 04

- Alternative representation for image patches
- Location and characteristic scale s given by DoG detector



- Compute gradient at each pixel
- N x N spatial bins
- Compute an histogram of M orientations for each bean

SIFT descriptor

David G. Lowe. **"Distinctive image features from scale-invariant keypoints."** *IJCV* 60 (2), 04

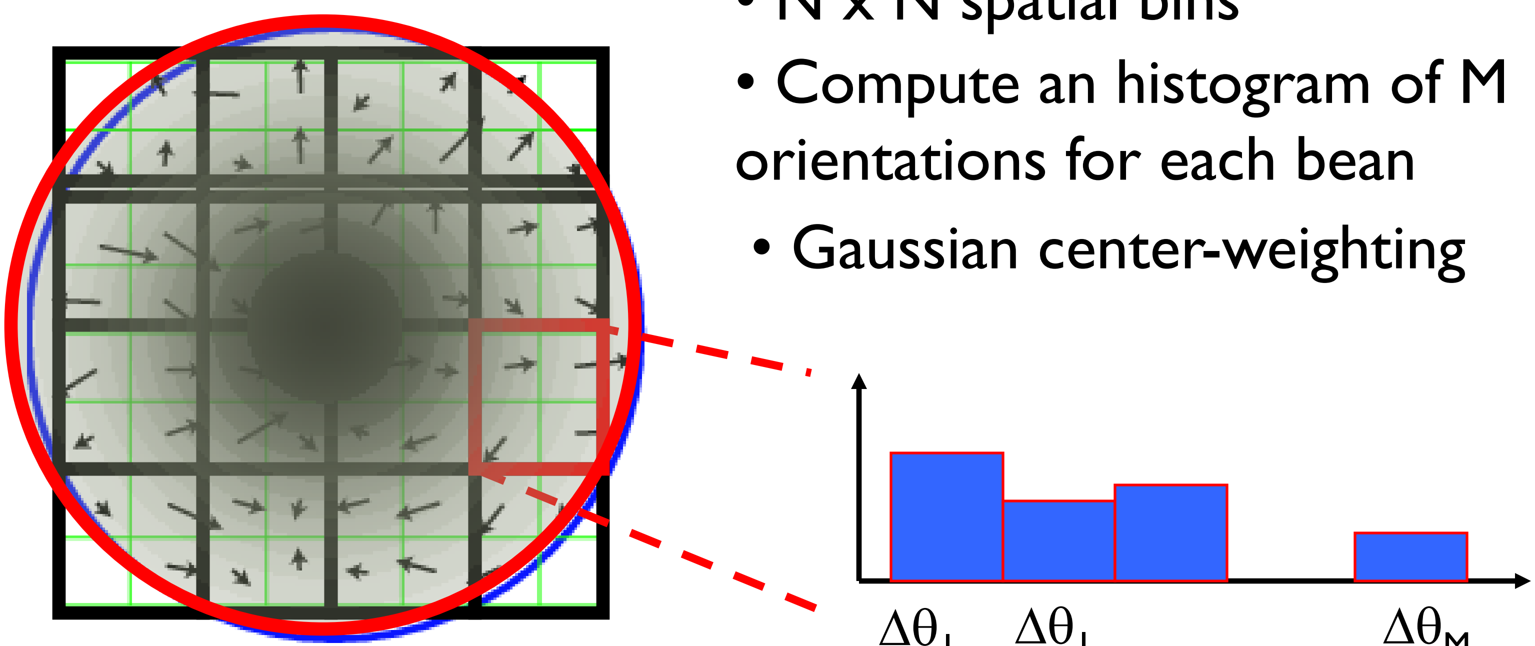
- Alternative representation for image patches
- Location and characteristic scale s given by DoG detector

•Compute gradient at each pixel

• N x N spatial bins

• Compute an histogram of M orientations for each bean

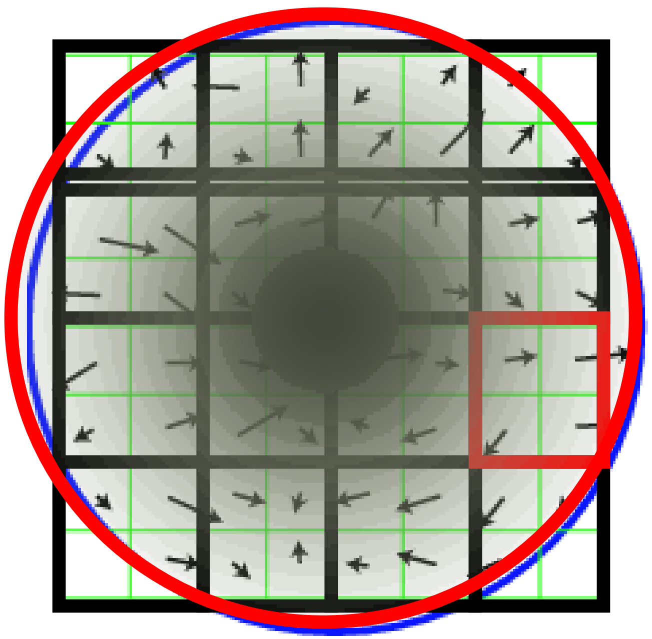
• Gaussian center-weighting



SIFT descriptor

David G. Lowe. "Distinctive image features from scale-invariant keypoints." *IJCV* 60 (2), 04

- Alternative representation for image patches
- Location and characteristic scale s given by DoG detector



- Compute gradient at each pixel
- N x N spatial bins
- Compute an histogram of M orientations for each bean
  - Gaussian center-weighting
  - Normalized unit norm

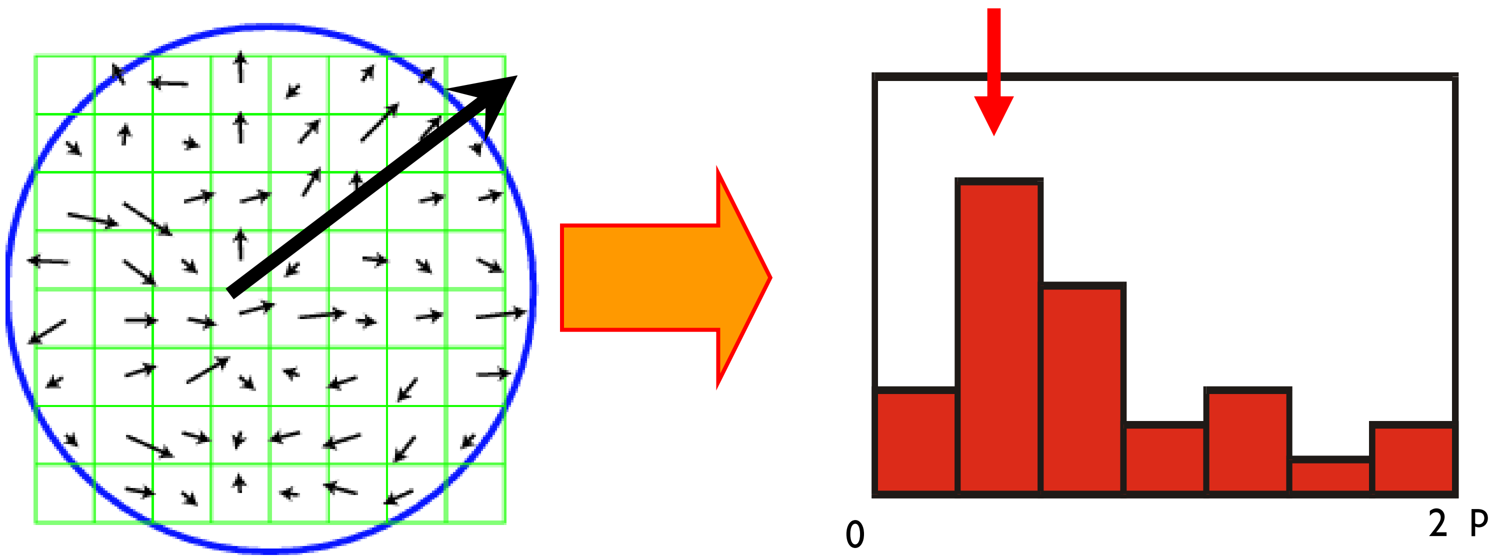
Typically M = 8; N= 4, 4x4
1 x 128 descriptor

SIFT descriptor

- Robust w.r.t. small variation in:
  - Illumination (thanks to gradient & normalization)
  - Pose (small affine variation thanks to orientation histogram)
  - Scale (scale is fixed by DOG)
  - Intra-class variability (small variations thanks to histograms)

Rotational invariance

- Find dominant orientation by building smoothed orientation histogram
- Rotate all orientations by the dominant orientation

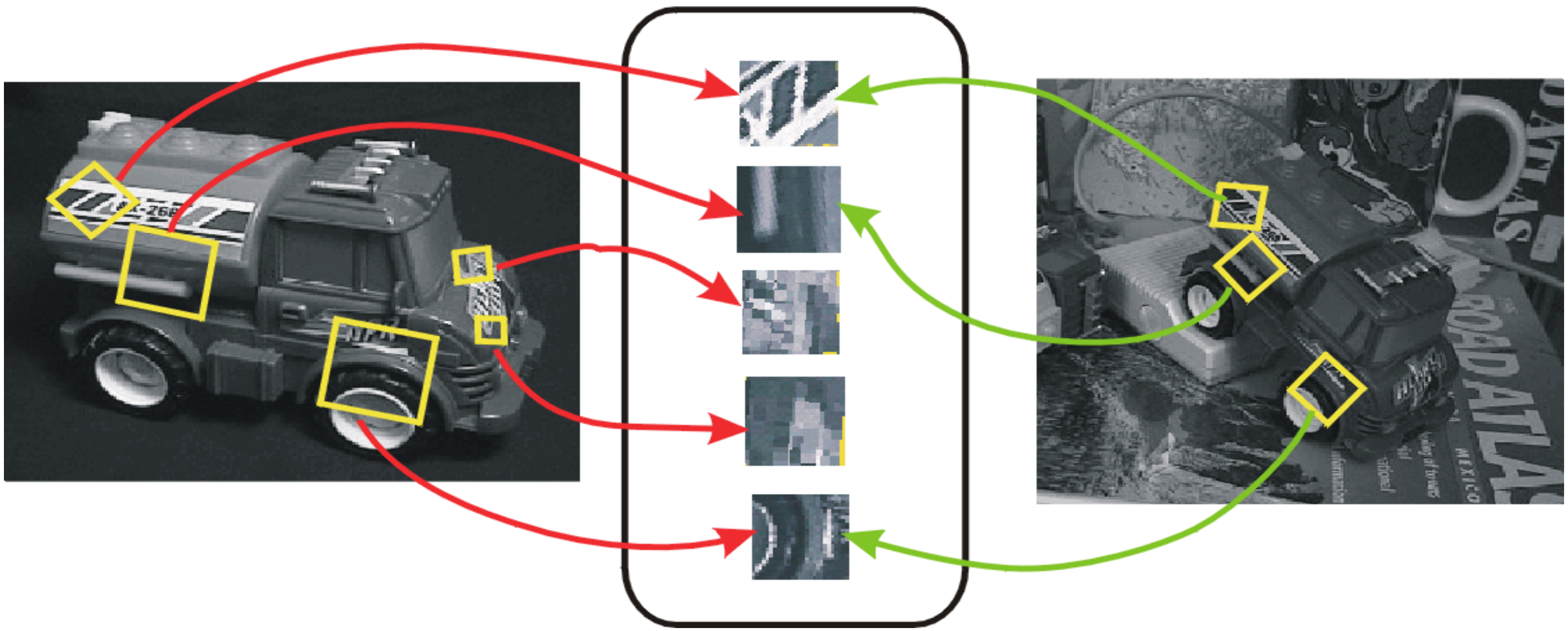


This makes the SIFT descriptor rotational invariant

Rotational invariance

(b)

Rotational invariance

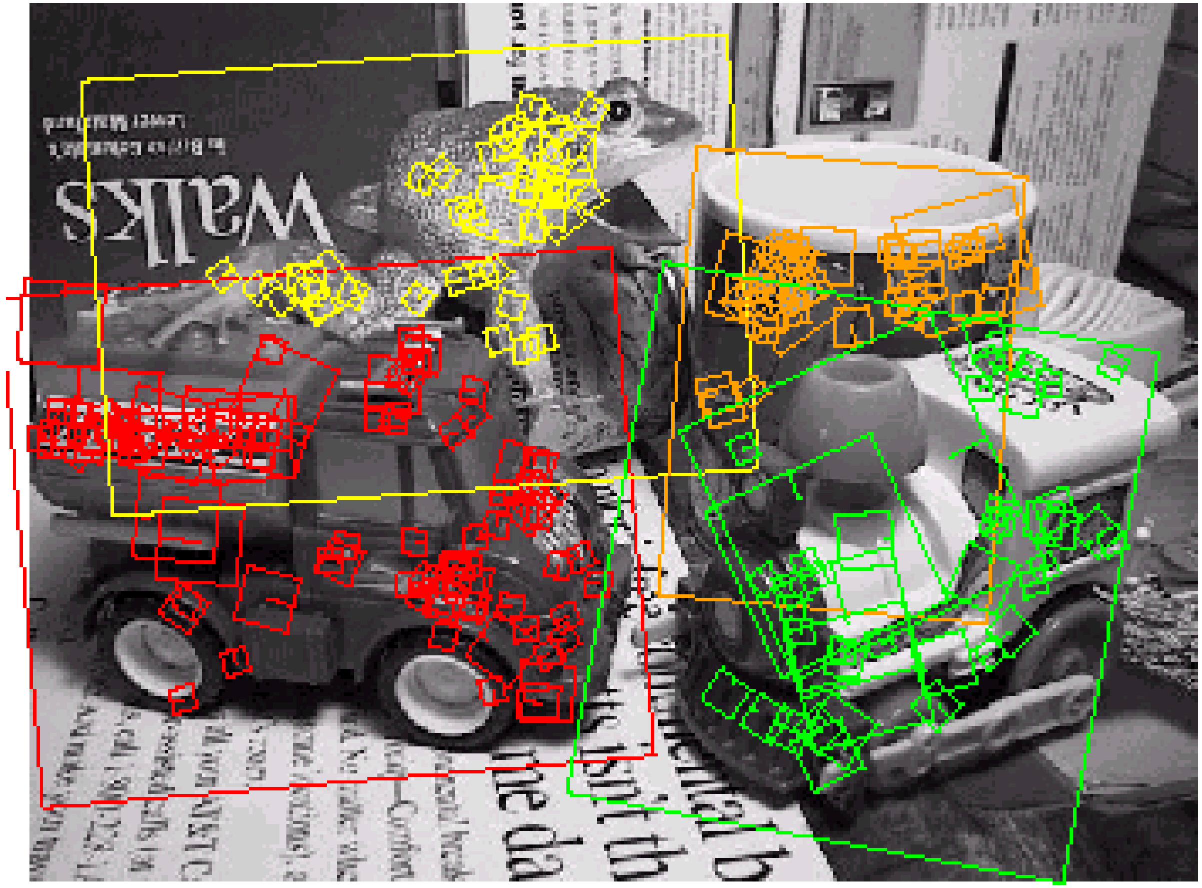


Matching using SIFT

David G. Lowe. **"Distinctive image features from scale-invariant keypoints."** *IJCV* 60 (2), 04

Matching using SIFT

David G. Lowe. **"Distinctive image features from scale-invariant keypoints."** *IJCV* 60 (2), 04



Detector	Illumination	Pose	Intra-class variab.
PATCH	***	*	*
FILTERS	***	**	**
SIFT	***	***	***