Keypoint Features II

CS 6384 Computer Vision

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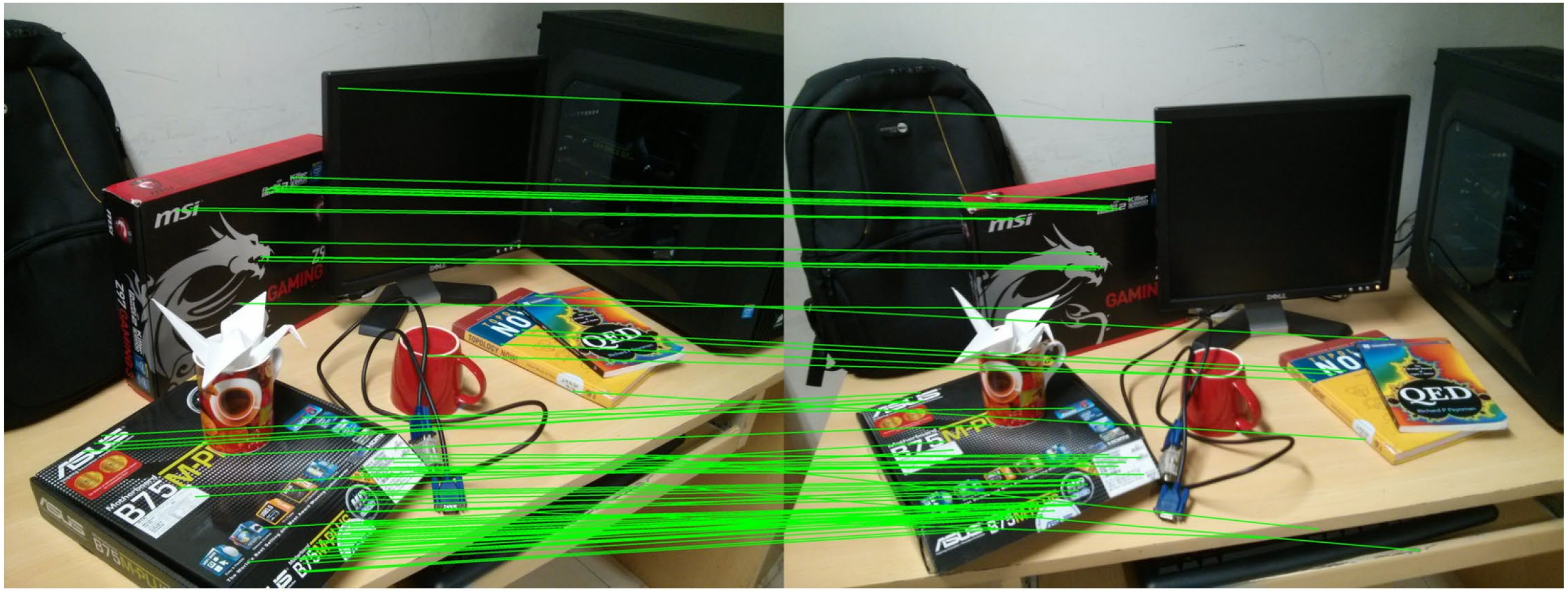
The University of Texas at Dallas

Some slides of this lecture are courtesy Kris Kitani

Feature Detection and Matching

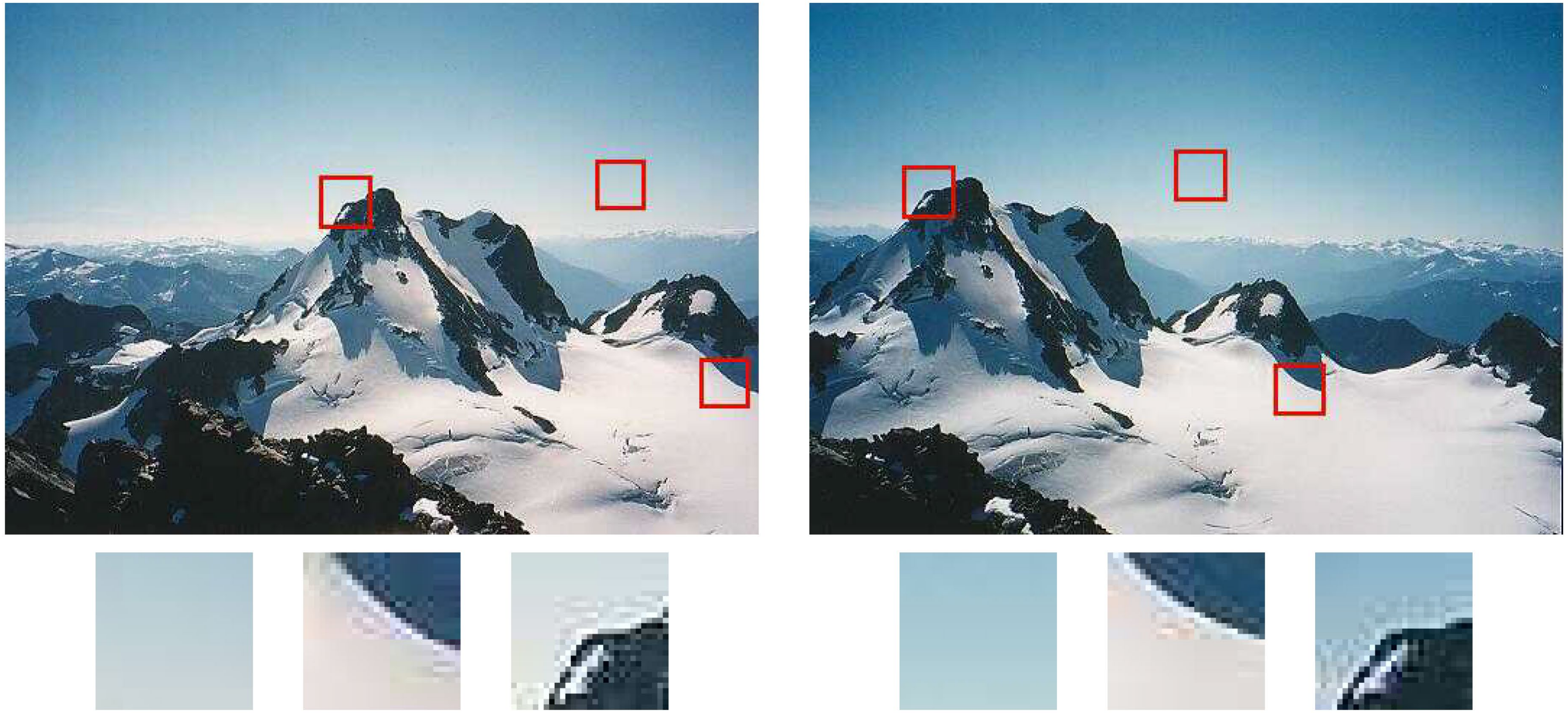


Geometry-aware Feature Matching for Structure from Motion Applications. Shah et al, WACV'15

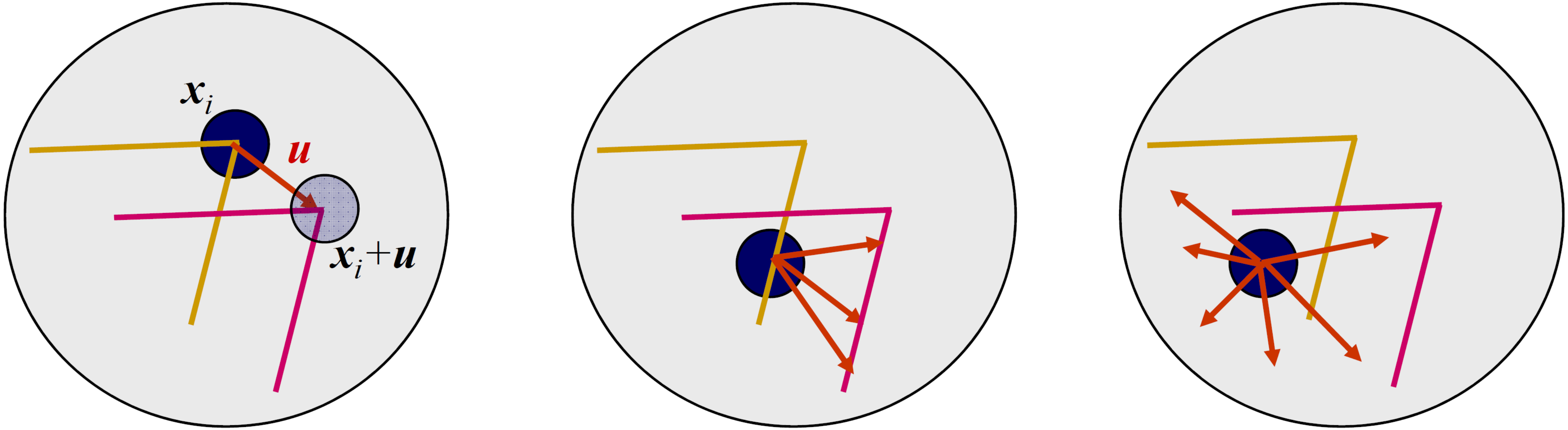
Applications: stereo matching, image stitching, 3D reconstruction, camera pose estimation, object recognition

Feature Detectors

- How to find image locations that can be reliably matched with images?



Feature Detectors



(a) Corner

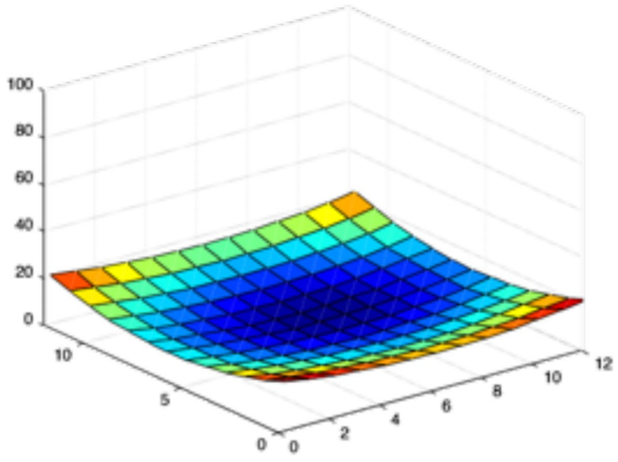
(b) Edge

(c) Textureless region

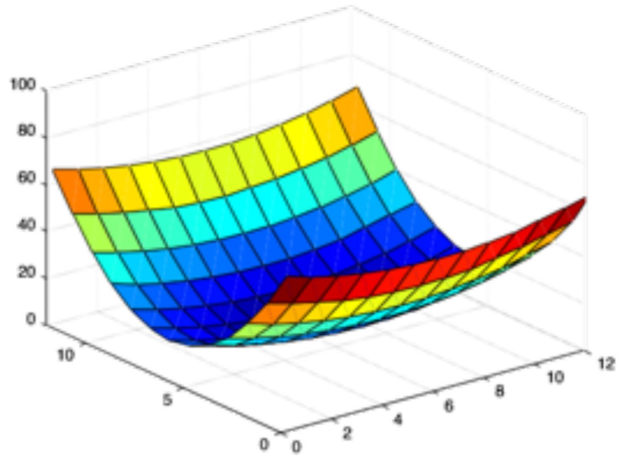
Harris Corner Detector

$$f(\Delta x, \Delta y) \approx \sum_{x,y} w(x,y)(I_x(x,y)\Delta x + I_y(x,y)\Delta y)^2$$

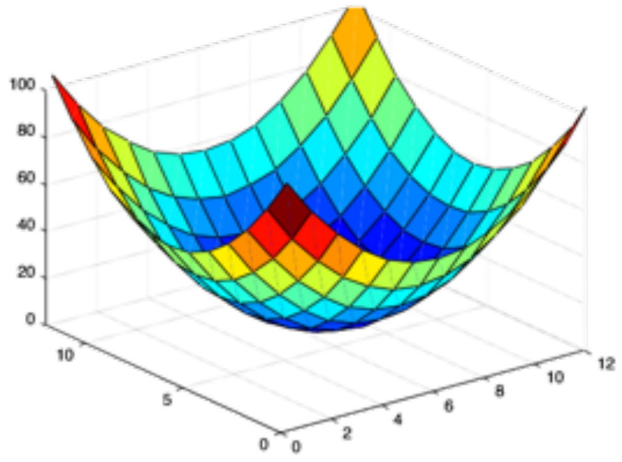
$$f(\Delta x, \Delta y) \approx (\Delta x \quad \Delta y) M \begin{pmatrix} \Delta x \\ \Delta y \end{pmatrix} \qquad M = \sum_{x,y} w(x,y) \begin{bmatrix} I_x^2 & I_x I_y \\ I_x I_y & I_y^2 \end{bmatrix} = \begin{bmatrix} \sum_{x,y} w(x,y) I_x^2 & \sum_{x,y} w(x,y) I_x I_y \\ \sum_{x,y} w(x,y) I_x I_y & \sum_{x,y} w(x,y) I_y^2 \end{bmatrix}$$



Flat



Edge



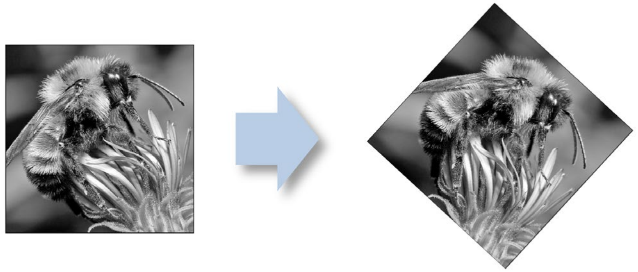
Corner

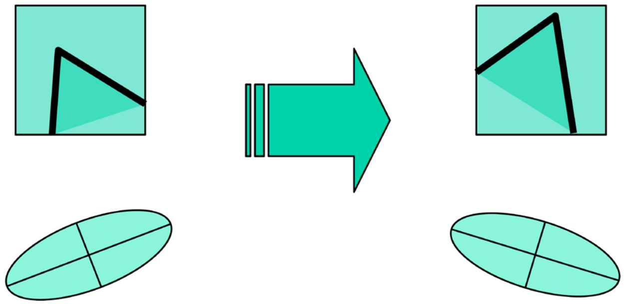
Invariance

- Can the same feature point be detected after some transformation?
  - Translation invariance

    Are Harris corners translation invariance?
  - 2D rotation invariance

    Are Harris corners rotation invariance?

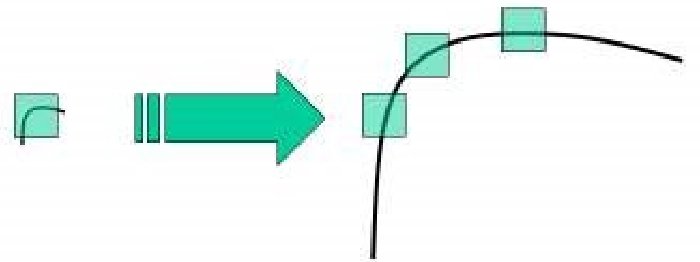


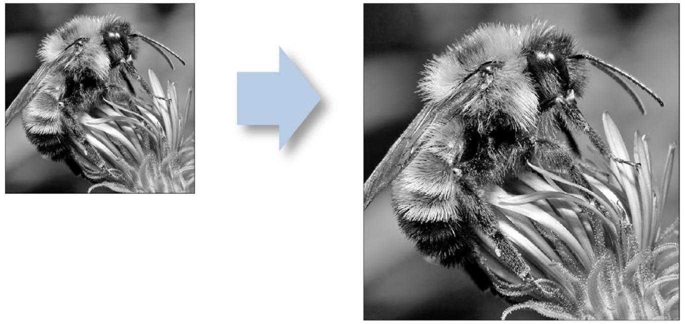


  - Scale invariance

    Are Harris corners scale invariance?

No





Scale Invariance

- Solution 1: detection features in all scales, matching features in corresponding scale (for small scale change)

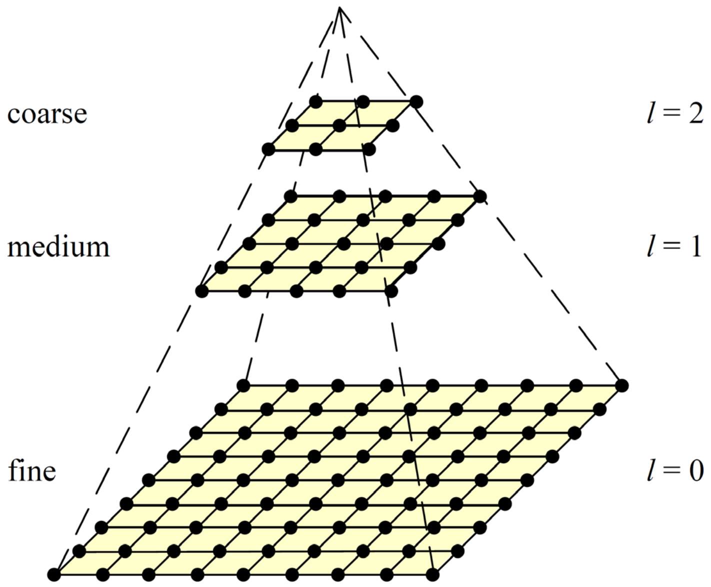
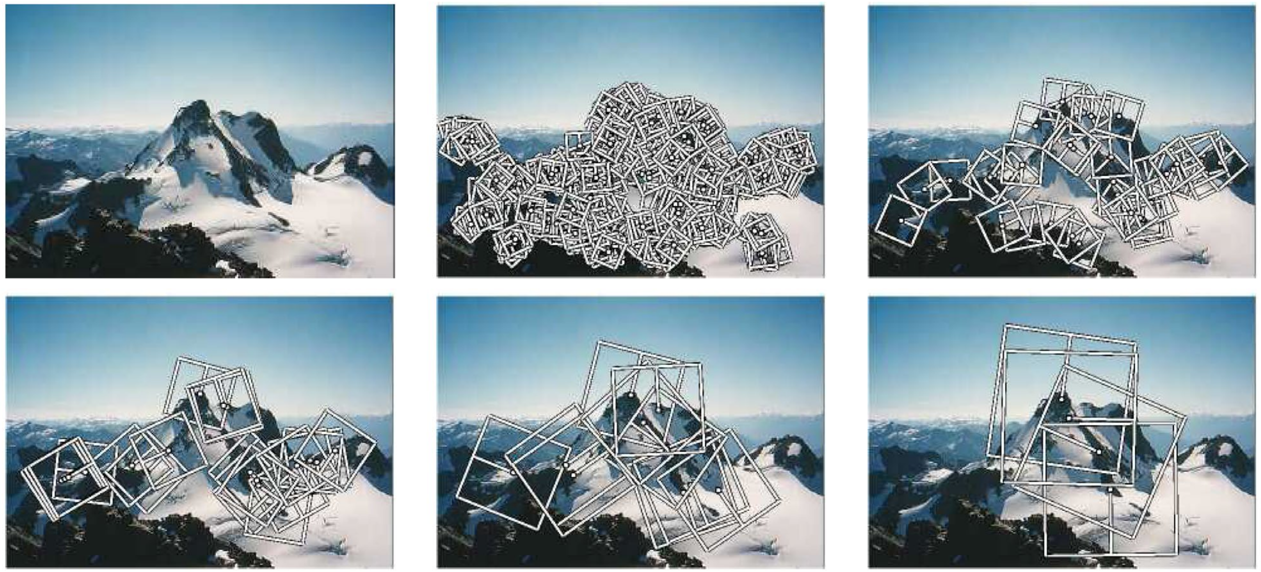


Image pyramid



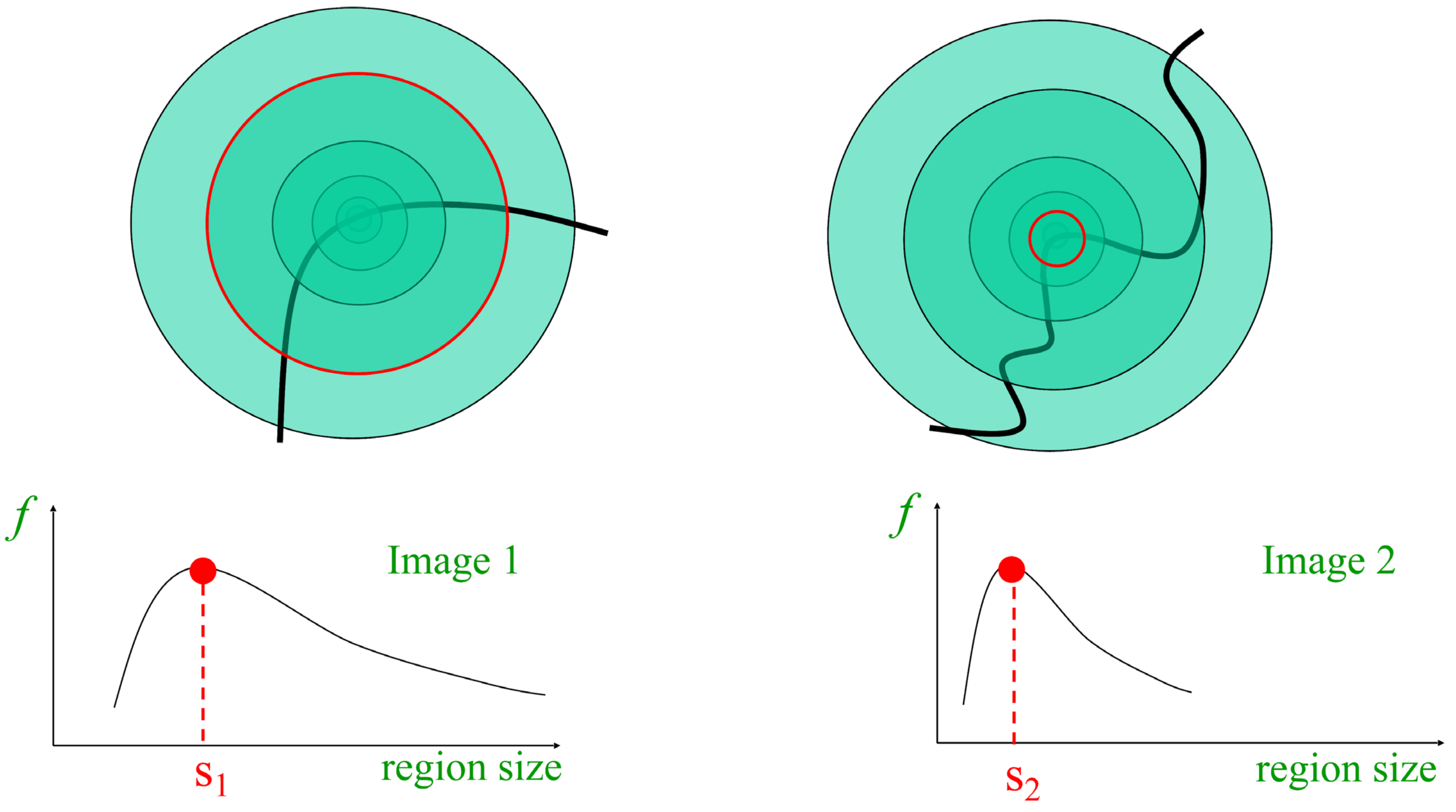
Multi-scale oriented patches (MOPS) extracted at five pyramid levels (Brown, Szeliski, and Winder 2005)

Scale Invariance

- Solution 2: detect features that are stable in both location and scale

Intuition: Find local maxima in both position and scale

What filter can we use for scale selection?



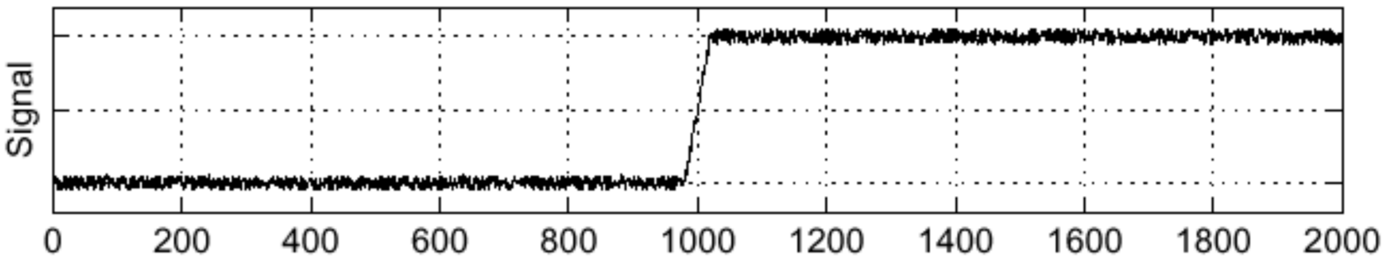
Recall Derivative Filter

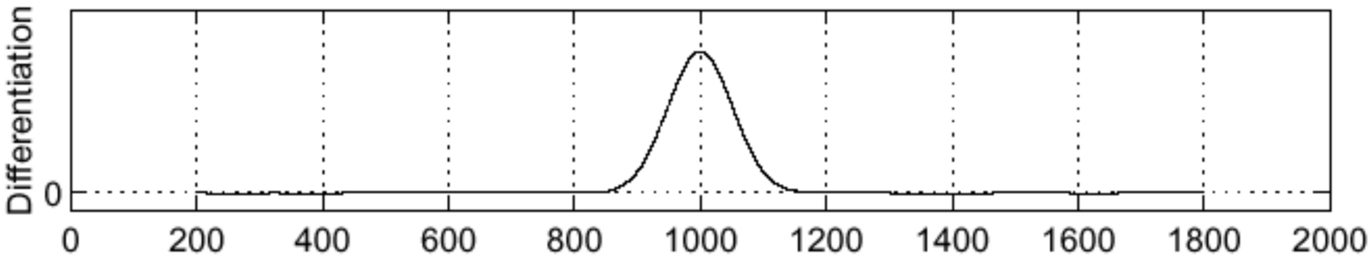
Central difference

$$f'(x) = \lim_{h \to 0} \frac{f(x + 0.5h) - f(x - 0.5h)}{h}$$

-1	0	1

X derivative

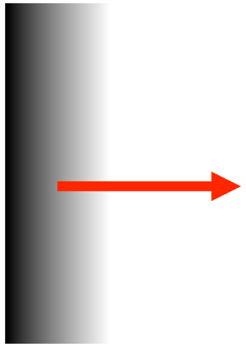




Find edge

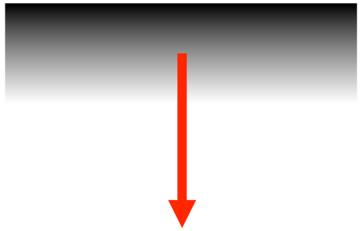
Image Gradient

Gradient in x only



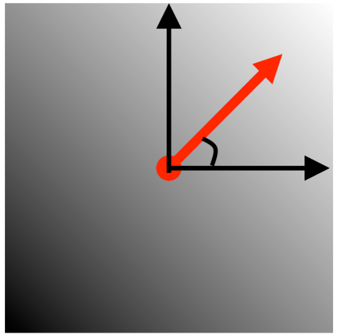
$$\nabla f = \left[\frac{\partial f}{\partial x}, 0\right]$$

Gradient in y only



$$\nabla f = \left[0, \frac{\partial f}{\partial y}\right]$$

Gradient in both x and y



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

Gradient direction

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

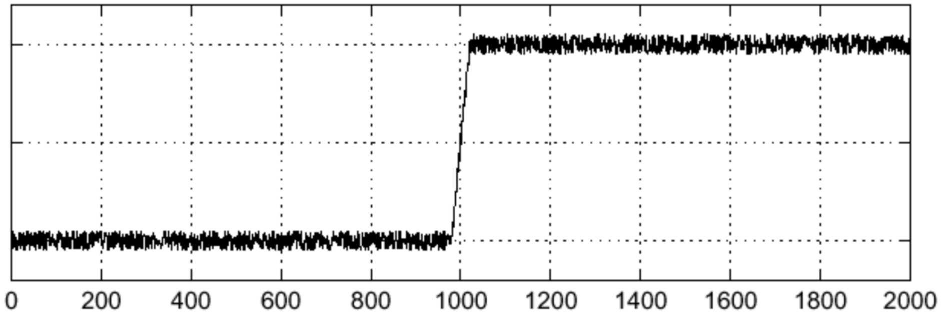
Gradient magnitude

$$||\nabla f|| = \sqrt{\left(\frac{\partial f}{\partial x}\right)^2 + \left(\frac{\partial f}{\partial y}\right)^2}$$

Signal Noises

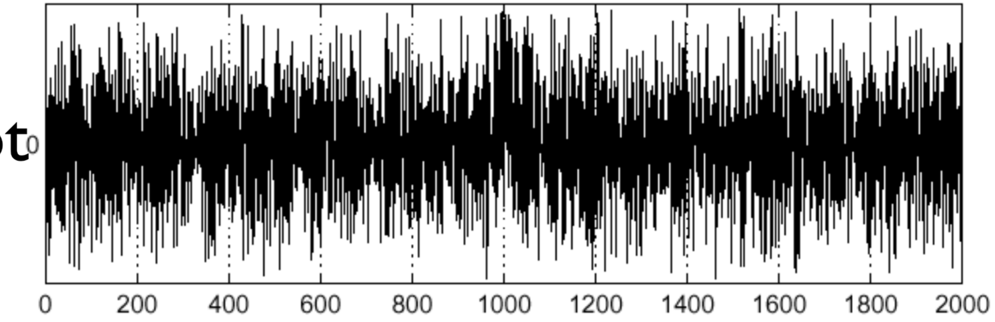
- Derivative filters are sensitive to noises

Intensity plot



How to deal with noises?

Derivative plot



Gaussian Filter

- Smoothing

1D $$g(x) = \frac{1}{\sqrt{2\pi}\sigma} e^{-\frac{x^2}{2\sigma^2}}$$

2D $$g(x, y) = \frac{1}{2\pi\sigma^2} e^{-\frac{x^2+y^2}{2\sigma^2}}$$

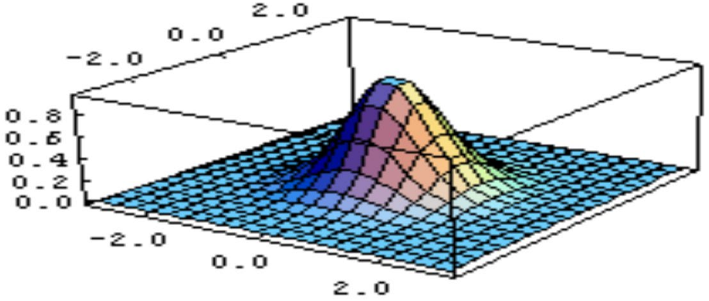
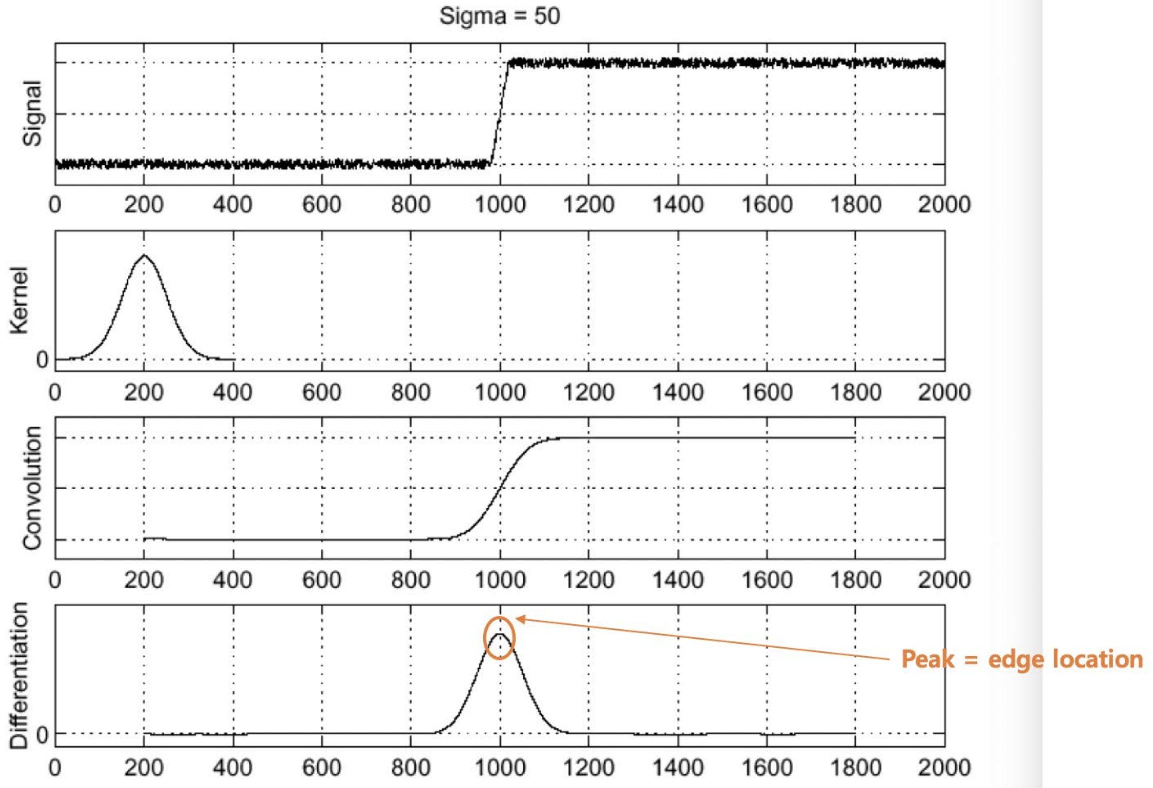


Image f

Gaussian Filter h

Convolution $h \star f$

Derivative $\frac{\partial}{\partial x}(h \star f)$



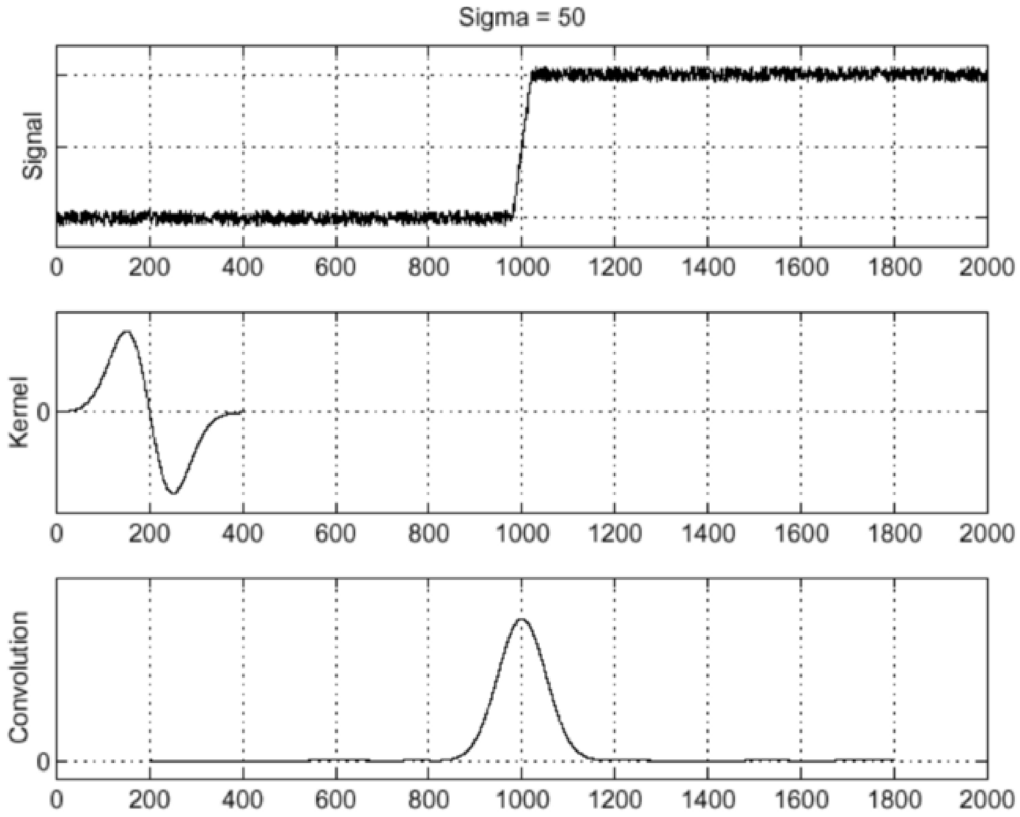
Derivative of Gaussian Filter

- Convolution is associative $\frac{\partial}{\partial x}(h \star f) = (\frac{\partial}{\partial x}h) \star f$

f

Smoothing and derivative $\frac{\partial}{\partial x}h$

$(\frac{\partial}{\partial x}h) \star f$

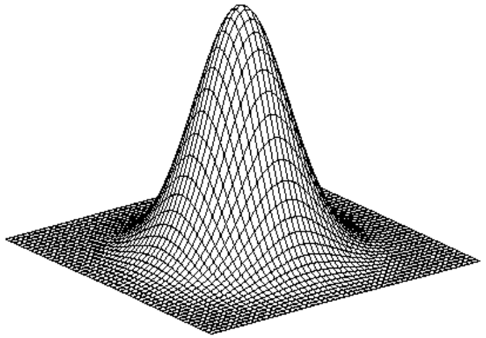


Derivative of Gaussian Filter

- Convolution is associative $\frac{\partial}{\partial x}(h \star f) = (\frac{\partial}{\partial x}h) \star f$

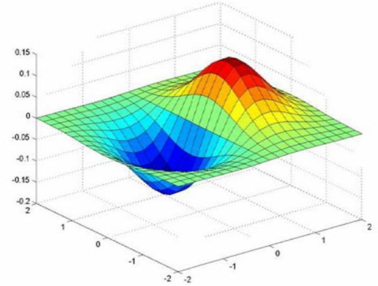
$$g_x(x,y) = \frac{\partial g(x,y)}{\partial x} = \frac{-x}{2\pi\sigma^4} e^{-\frac{x^2+y^2}{2\sigma^2}}$$

$$g_y(x,y) = \frac{\partial g(x,y)}{\partial y} = \frac{-y}{2\pi\sigma^4} e^{-\frac{x^2+y^2}{2\sigma^2}}$$

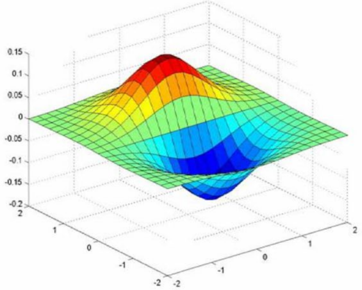


Gaussian

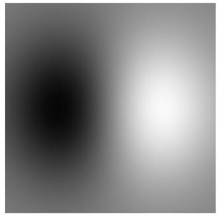
$$g(x,y) = \frac{1}{2\pi\sigma^2} e^{-\frac{x^2+y^2}{2\sigma^2}}$$

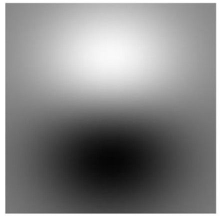


x-direction



y-direction





Laplace Filter

first-order
finite difference

$$f'(x) = \lim_{h\to 0} \frac{f(x+0.5h) - f(x-0.5h)}{h}$$

Derivative filter

-1	0	1

second-order
finite difference

$$f''(x) \approx \frac{\delta_h^2[f](x)}{h^2} = \frac{\frac{f(x+h)-f(x)}{h} - \frac{f(x)-f(x-h)}{h}}{h} = \frac{f(x+h) - 2f(x) + f(x-h)}{h^2}$$

Laplace filter

1	-2	1

Laplace Filter

- 2D $$\nabla^2 \mathbf{I} = \frac{\partial^2 \mathbf{I}}{\partial x^2} + \frac{\partial^2 \mathbf{I}}{\partial y^2}$$

1	-2	1

1D Laplace filter

0	1	0
1	-4	1
0	1	0

2D Laplace filter

Laplacian of Gaussian Filter

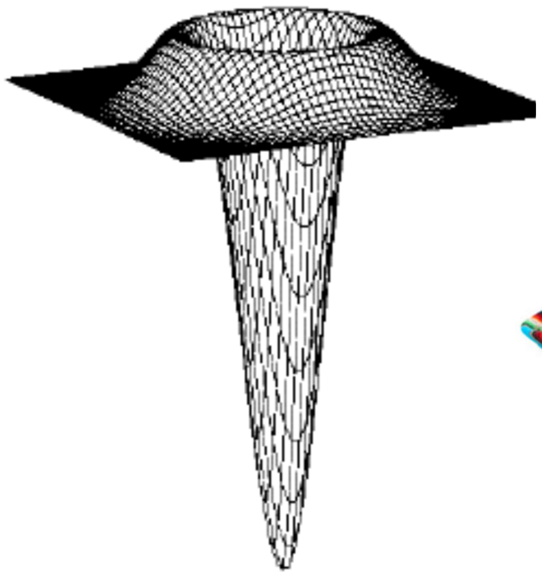
$$\nabla^2 \mathbf{I} = \frac{\partial^2 \mathbf{I}}{\partial x^2} + \frac{\partial^2 \mathbf{I}}{\partial y^2}$$

$$\nabla^2 \mathbf{I} \circ g = \nabla^2 g \circ \mathbf{I}$$

$$\nabla^2 g = \frac{x^2 + y^2 - 2\sigma^2}{\sigma^4} g(x, y)$$

Smoothing and second derivative

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



Laplacian of Gaussian

Mexican Hat Function

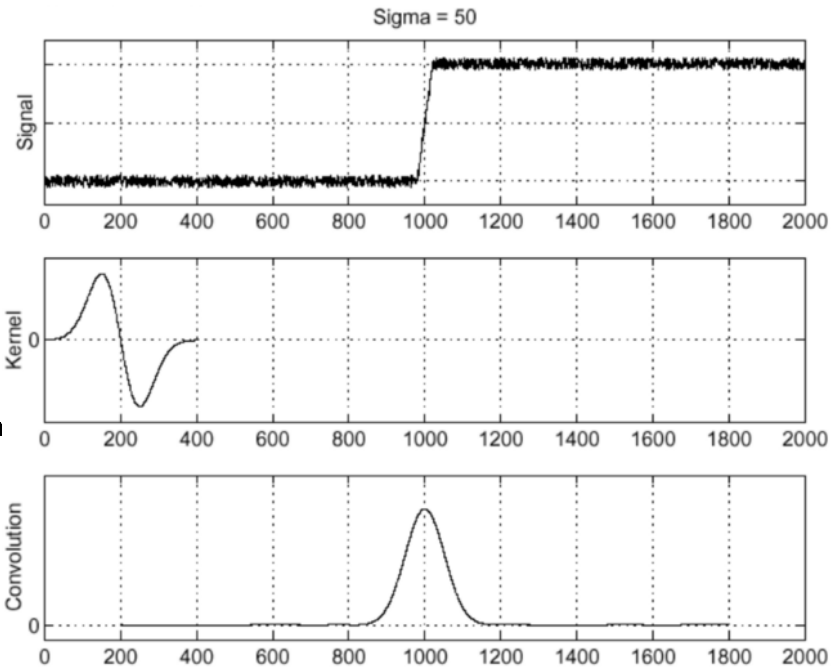
Laplacian of Gaussian Filter

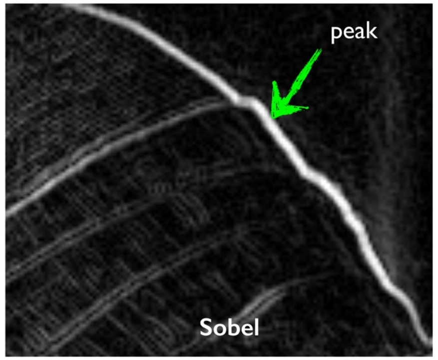
f

$\frac{\partial}{\partial x}h$

Derivative of Gaussian

$(\frac{\partial}{\partial x}h) \star f$



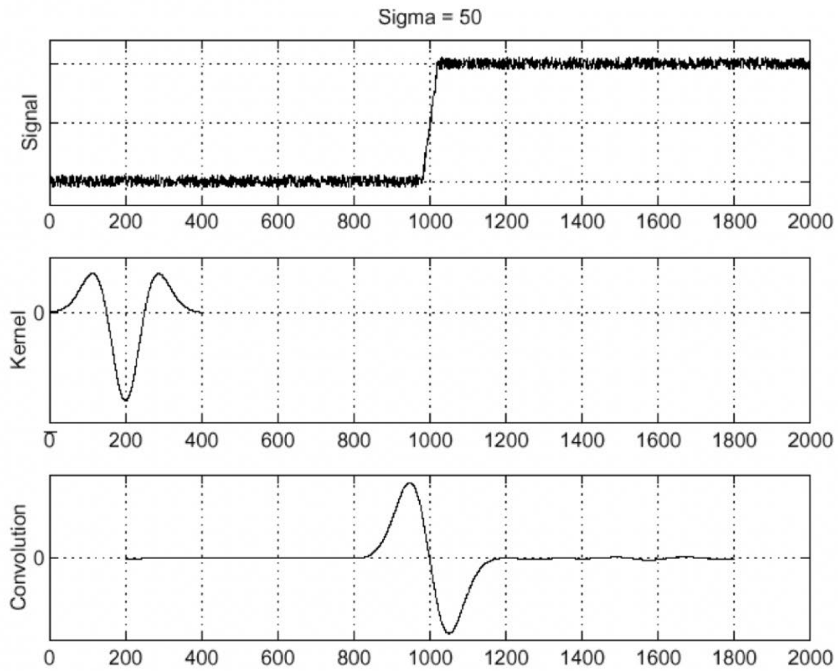


f

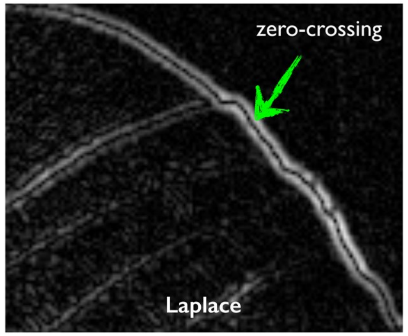
$\frac{\partial^2}{\partial x^2}h$

Laplacian of Gaussian

$(\frac{\partial^2}{\partial x^2}h) \star f$

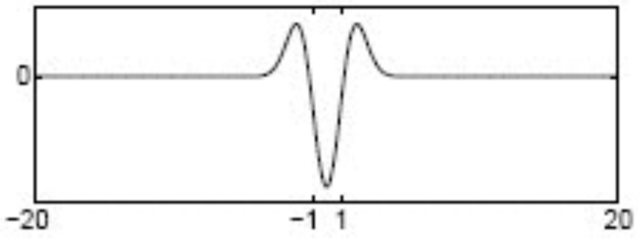


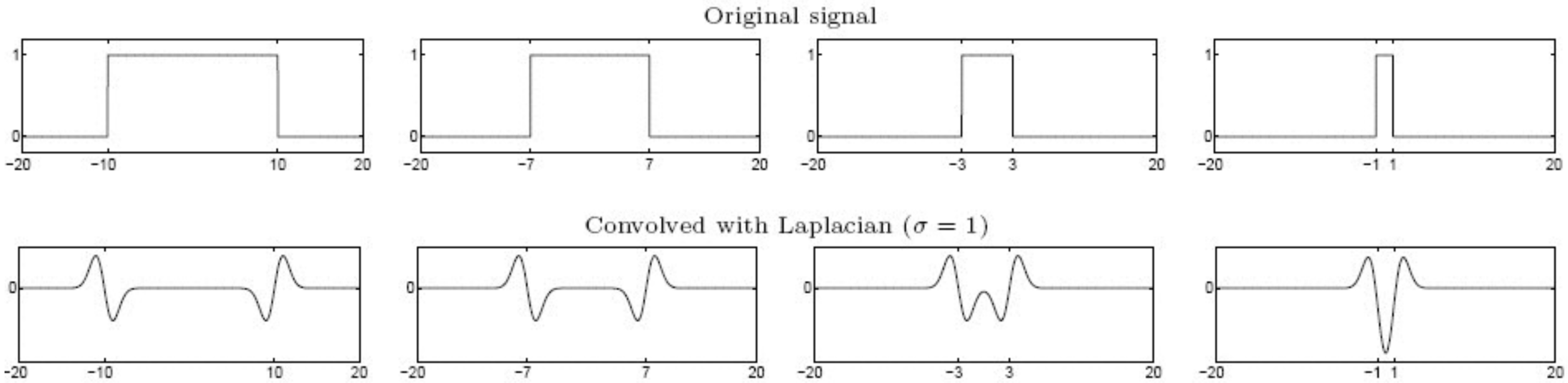
Zero crossings



Laplacian of Gaussian for Scale Selection

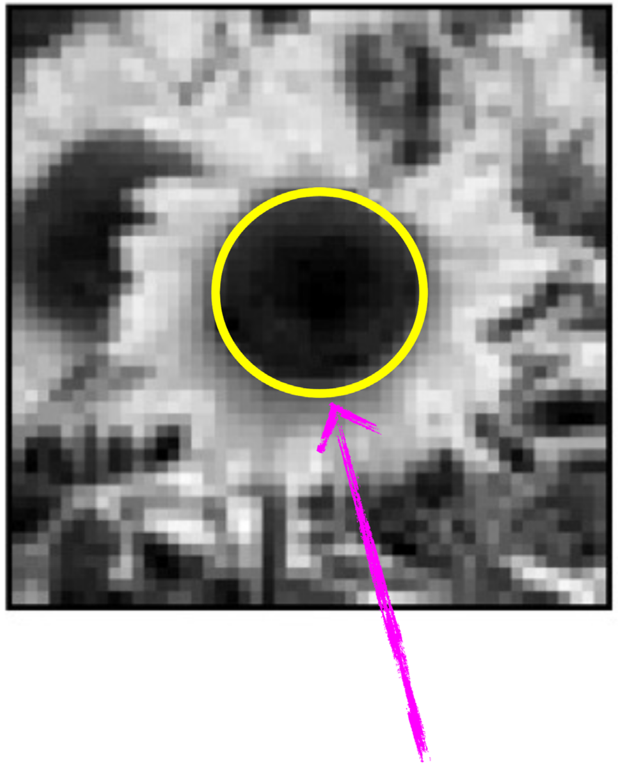
Laplacian filter

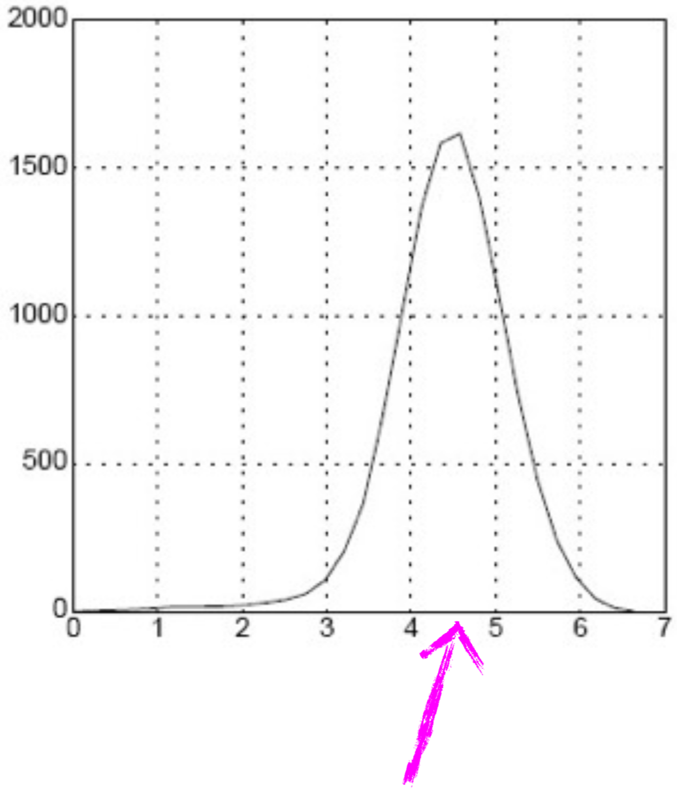


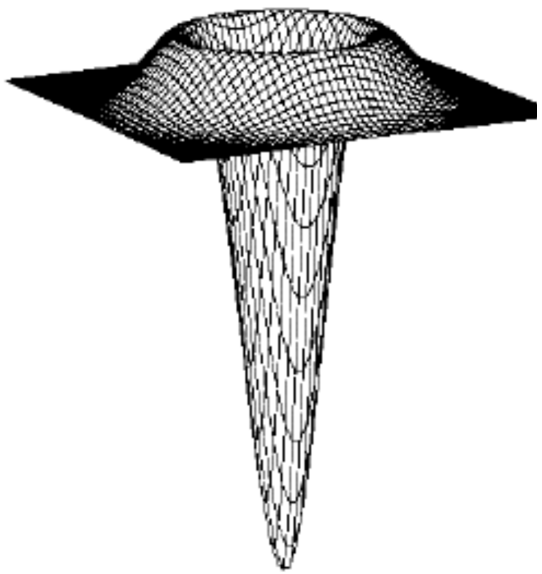


Highest response when the signal has the same **characteristic scale** as the filter

Laplacian of Gaussian for Scale Selection







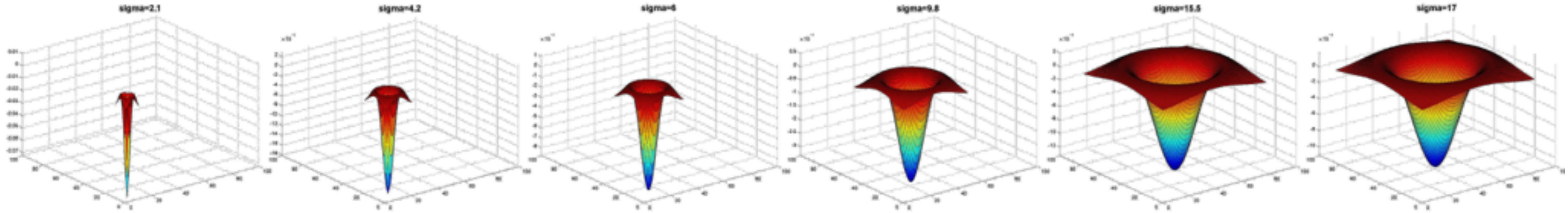
$\nabla^2 h_\sigma(u, v)$

Laplacian of Gaussian

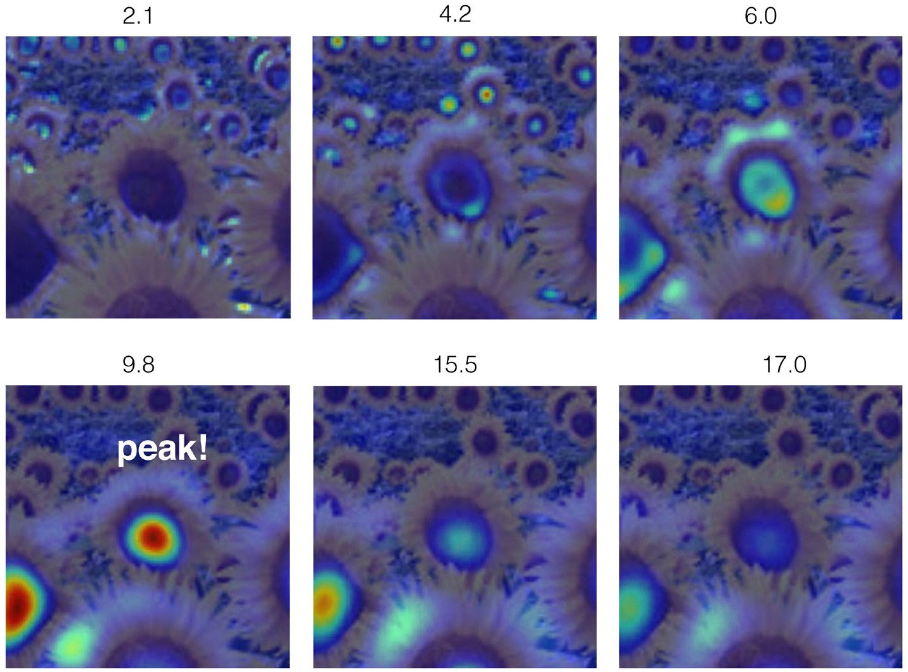
characteristic scale

Search over different scales σ

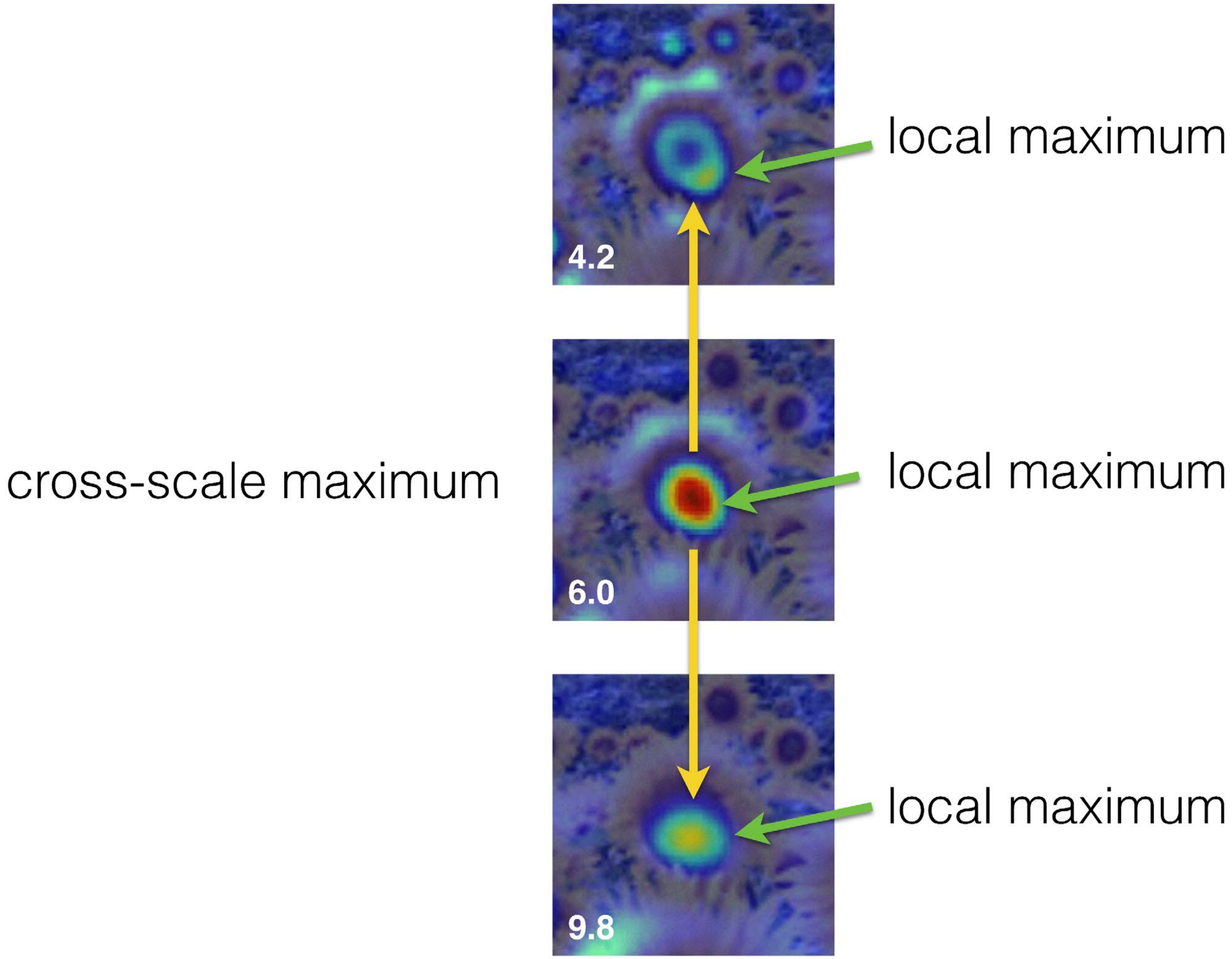
Laplacian of Gaussian for Scale Selection



Multi-scale
2D Blob detection

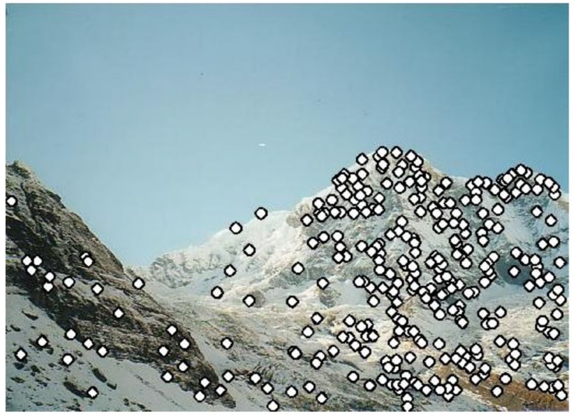


Laplacian of Gaussian for Scale Selection



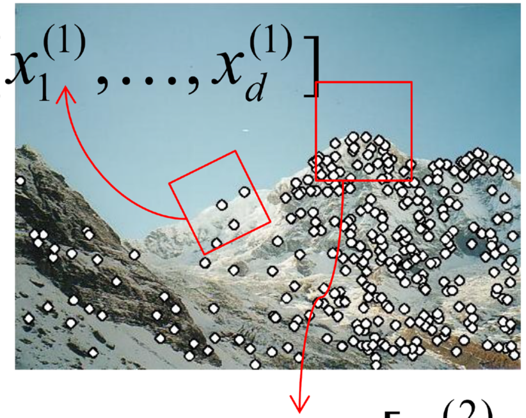
Scale Invariance Feature Transform (SIFT)

- Keypoint detection



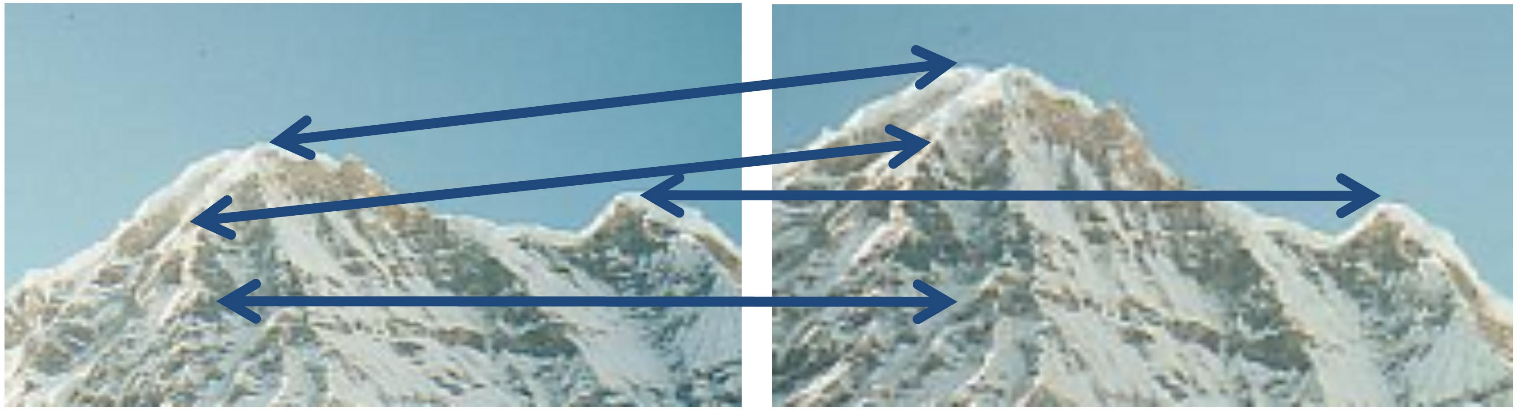
- Compute descriptors

$$\mathbf{x}_1 = [x_1^{(1)}, \ldots, x_d^{(1)}]$$



$$\mathbf{x}_2 = [x_1^{(2)}, \ldots, x_d^{(2)}]$$

- Matching descriptors



David Lowe, Distinctive Image Features from Scale-Invariant Keypoints. IJCV, 2004

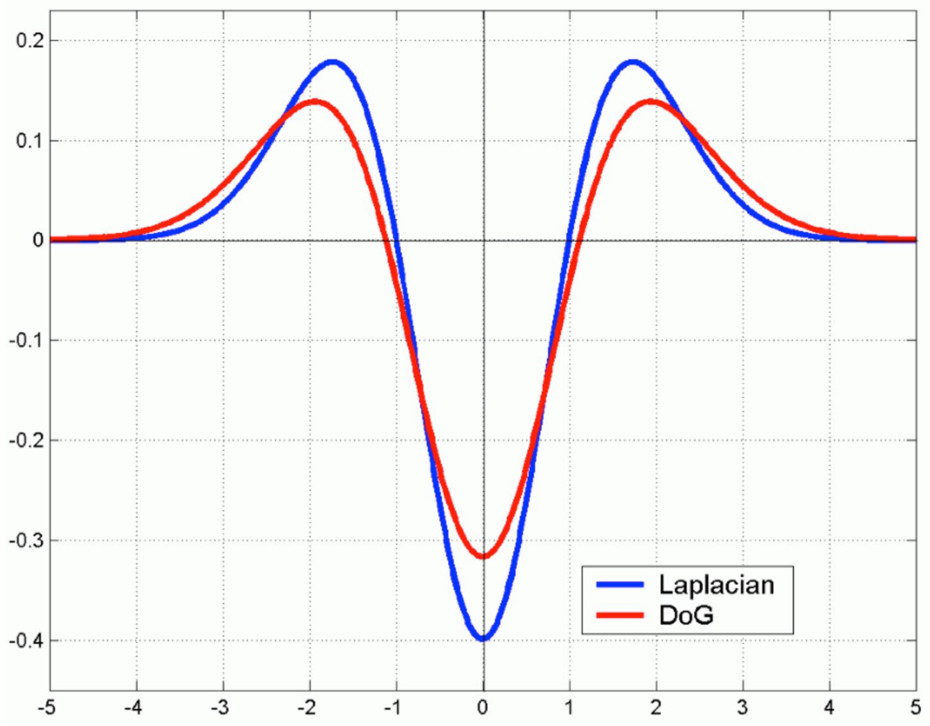
SIFT: Scale-space Extrema Detection

- Difference of Gaussian (DoG)

$$G(x, y, \sigma) = \frac{1}{2\pi\sigma^2} e^{-(x^2+y^2)/2\sigma^2}$$

$$L(x, y, \sigma) = G(x, y, \sigma) * I(x, y)$$

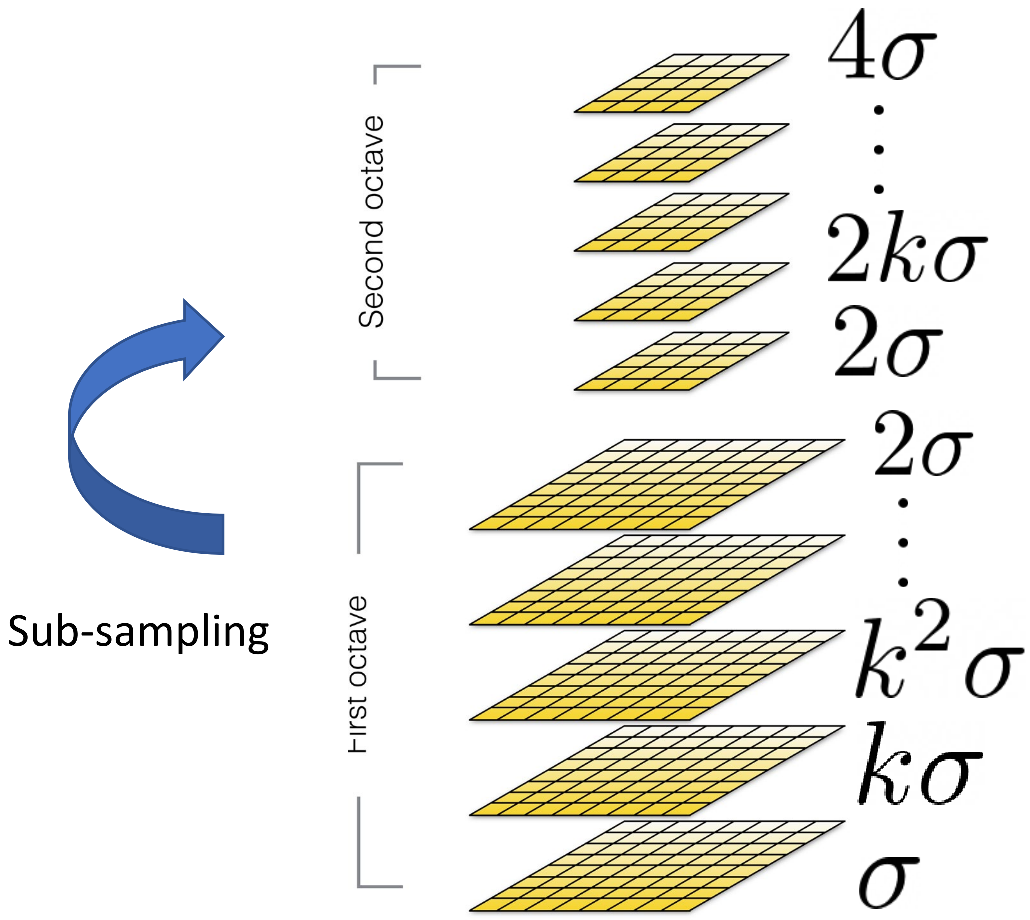
$$\begin{aligned} D(x, y, \sigma) &= (G(x, y, k\sigma) - G(x, y, \sigma)) * I(x, y) \\ &= L(x, y, k\sigma) - L(x, y, \sigma). \end{aligned}$$



Approximate of Laplacian of Gaussian
(efficient to compute)

SIFT: Scale-space Extrema Detection

- Gaussian pyramid



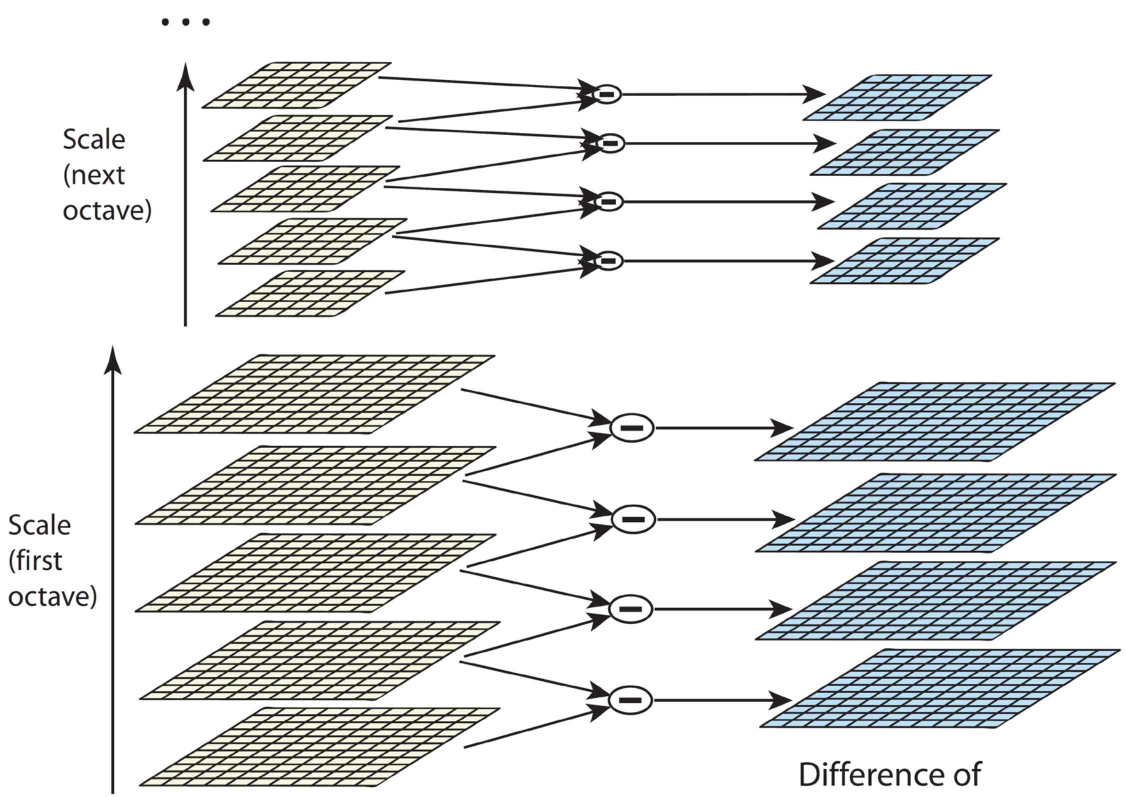
- Gaussian filters

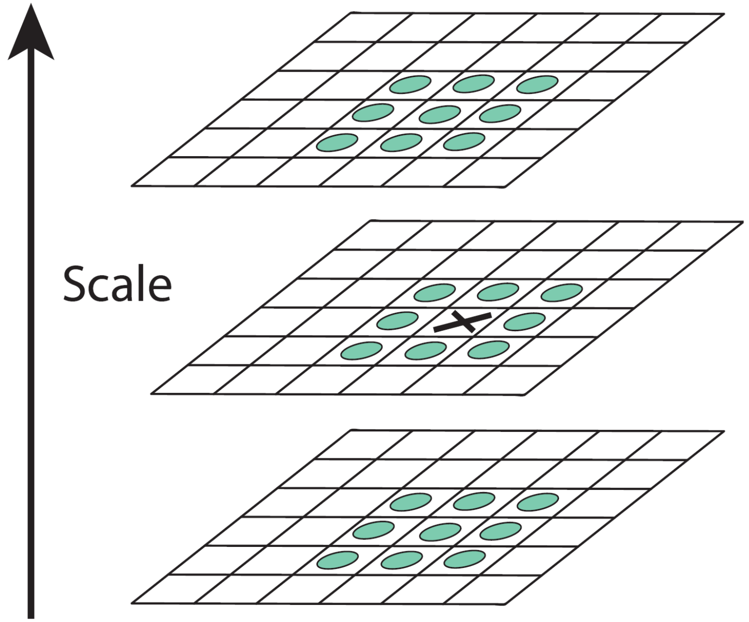
$$L(x, y, \sigma) = G(x, y, \sigma) * I(x, y)$$

$$G_{\sigma_1} * G_{\sigma_2} = G_{\sigma} \quad \sigma^2 = \sigma_1^2 + \sigma_2^2$$

- Sub-sampling by a factor of 2
  - Multiple the Gaussian kernel deviation by 2

SIFT: Scale-space Extrema Detection





Maxima and minima of DoG images

$$L(x, y, \sigma) = G(x, y, \sigma) * I(x, y)$$

$$G(x, y, \sigma) = \frac{1}{2\pi\sigma^2} e^{-(x^2+y^2)/2\sigma^2}$$

$$\begin{aligned} D(x, y, \sigma) &= (G(x, y, k\sigma) - G(x, y, \sigma)) * I(x, y) \\ &= L(x, y, k\sigma) - L(x, y, \sigma). \end{aligned}$$

SIFT Descriptor

- Image gradient magnitude and orientation

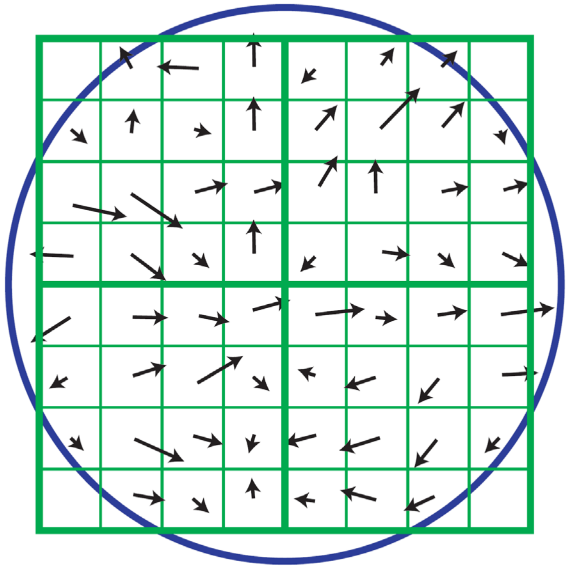


Image gradients

$$L(x, y, \sigma) = G(x, y, \sigma) * I(x, y)$$

$$m(x, y) = \sqrt{(L(x+1, y) - L(x-1, y))^2 + (L(x, y+1) - L(x, y-1))^2}$$

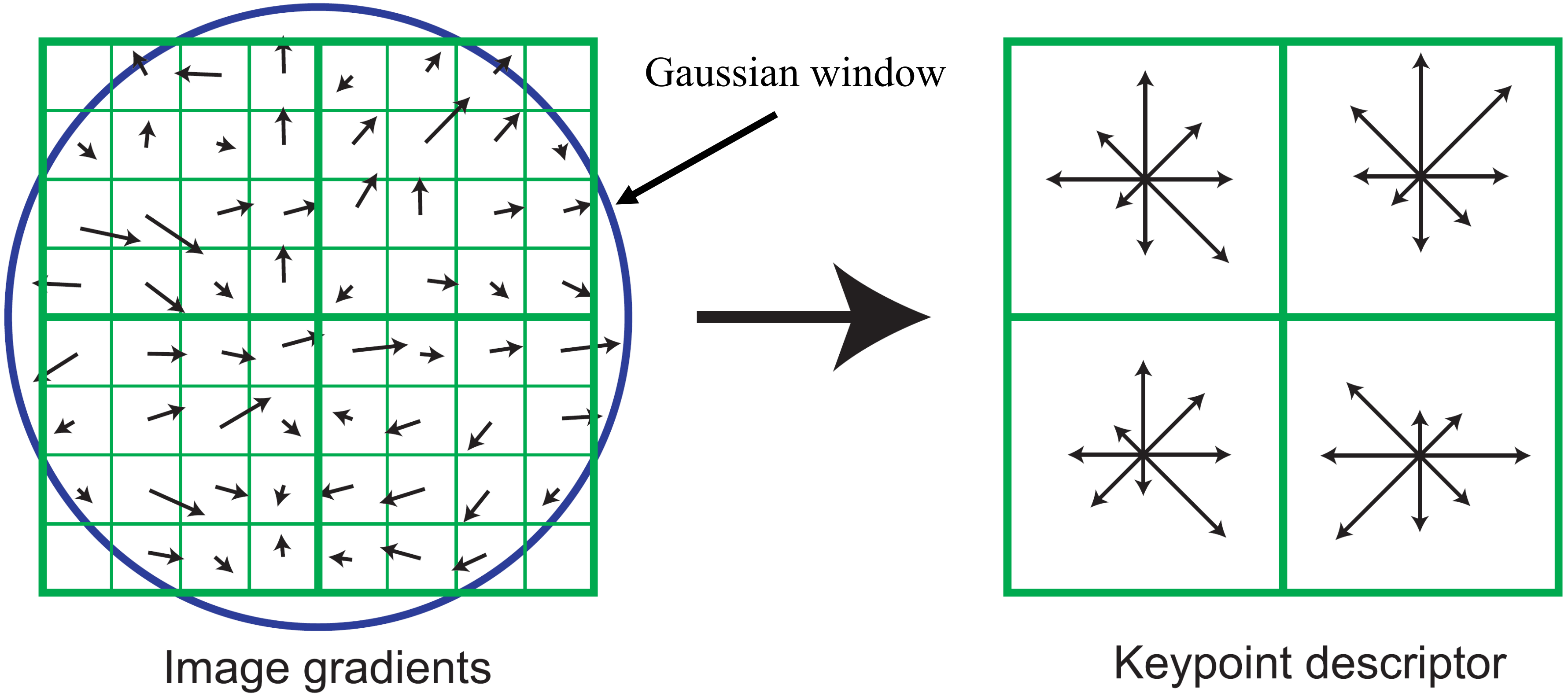
X-derivative Y-derivative

$$\theta(x, y) = \tan^{-1}((L(x, y+1) - L(x, y-1))/(L(x+1, y) - L(x-1, y)))$$

SIFT Descriptor

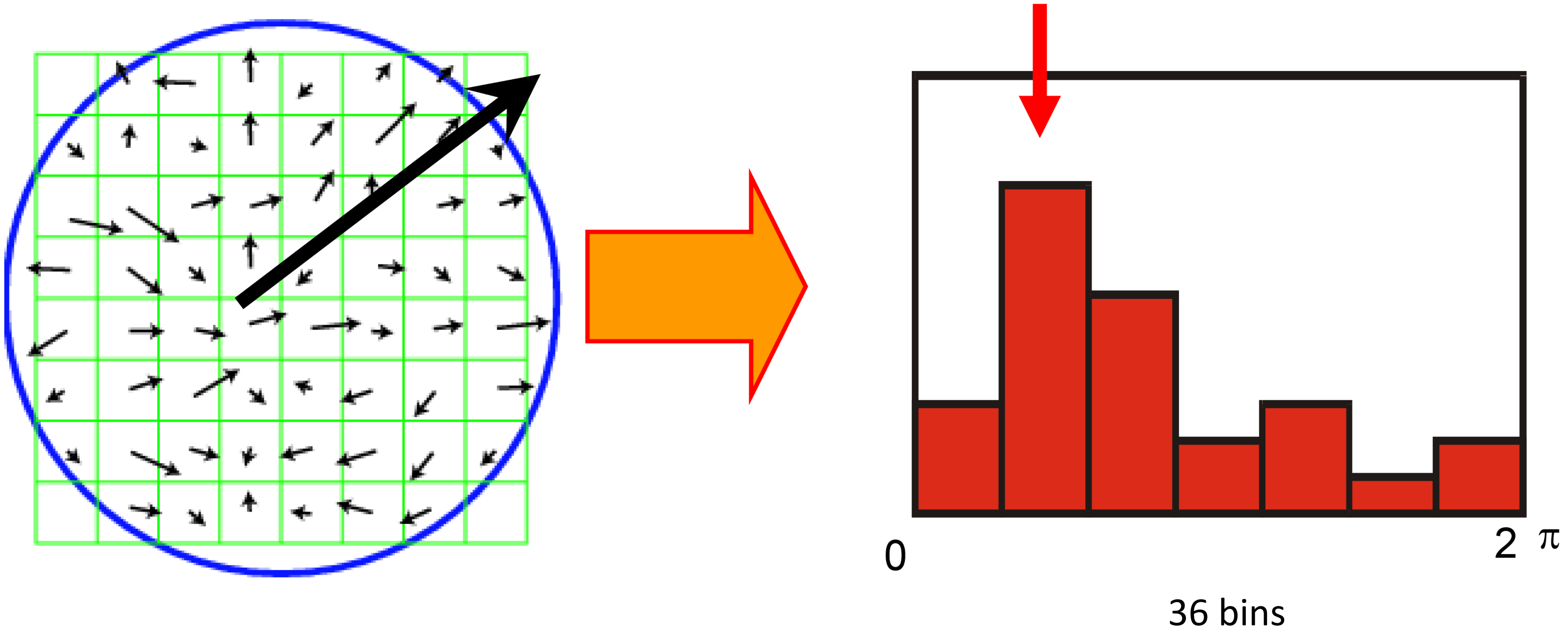
- Divide the 16x16 window into a 4x4 grid of cells (2x2 case shown below)
- Compute an orientation histogram for each cell
- 16 cells * 8 orientations = 128 dimensional descriptor

Using the scale of the keypoint to select the level of Gaussian blur for the image



SIFT: Rotation Invariance

- Rotate all orientations by the dominant orientation



SIFT: Rotation Invariance

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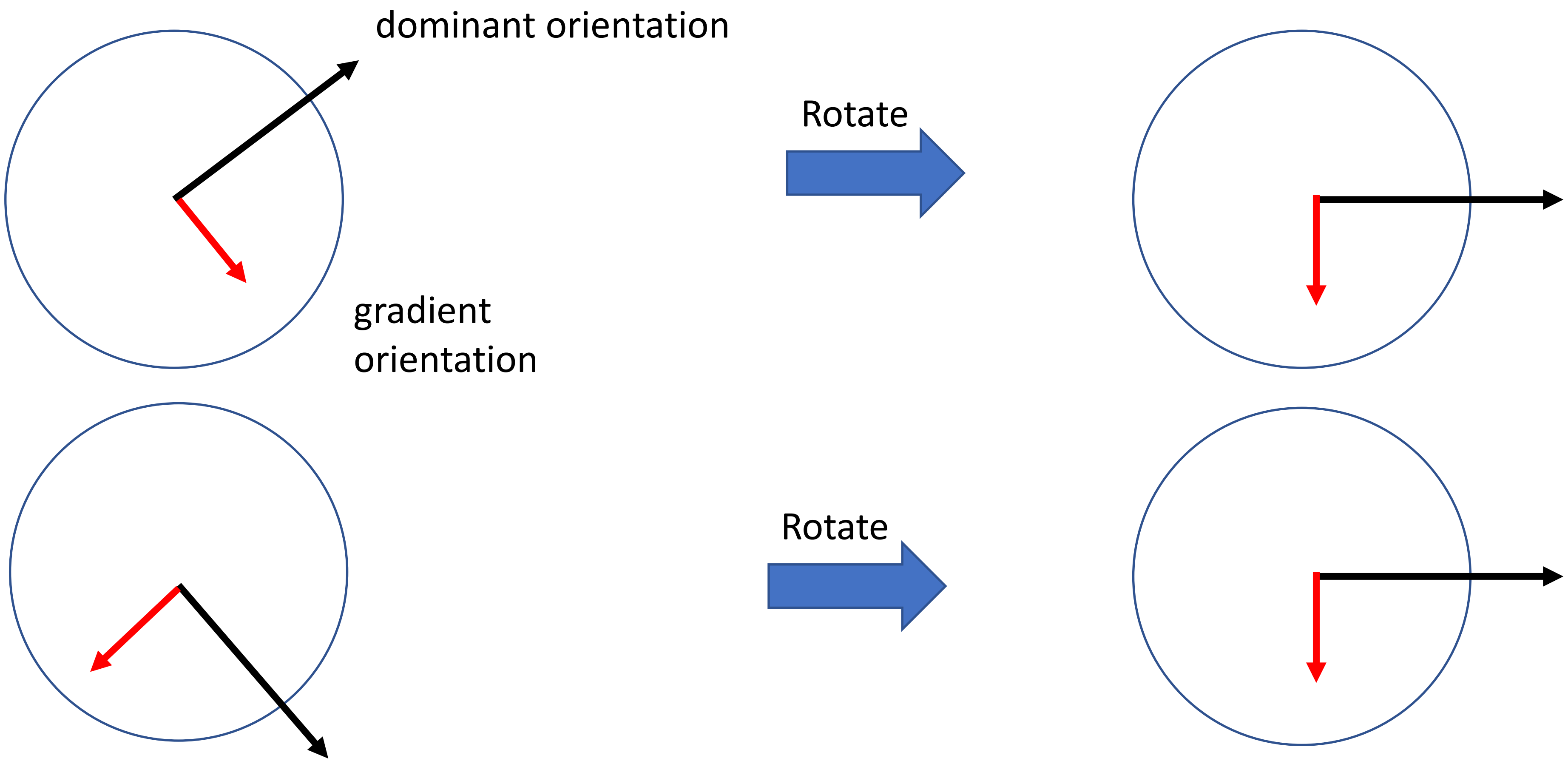


SIFT Properties

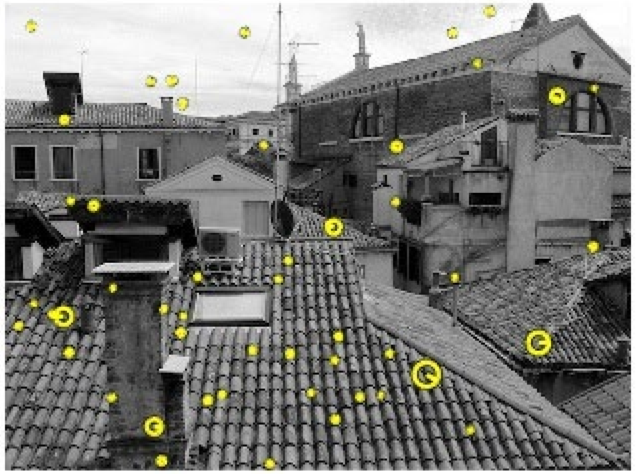
- Can handle change in viewpoint (up to about 60 degree out of plane rotation)

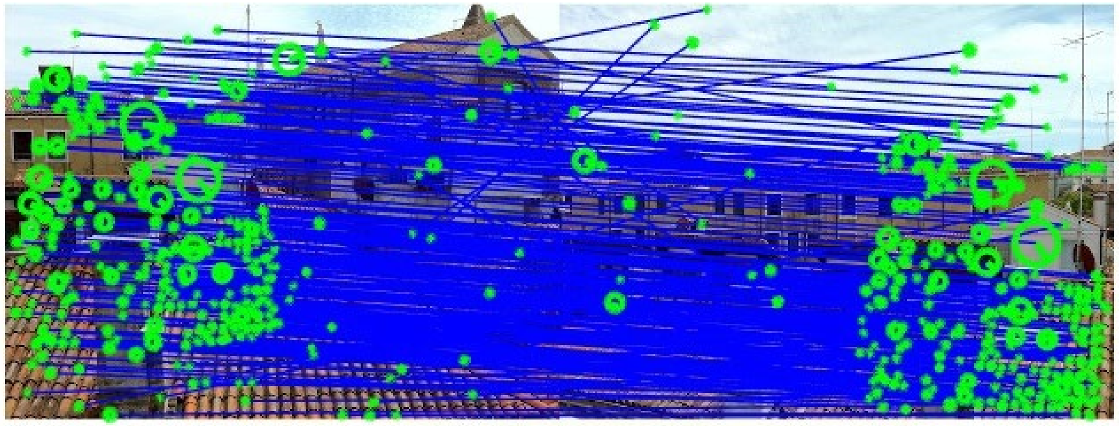
- Can handle significant change in illumination

- Relatively fast < 1s for moderate image sizes

- Lots of code available
  - E.g., https://www.vlfeat.org/overview/sift.html

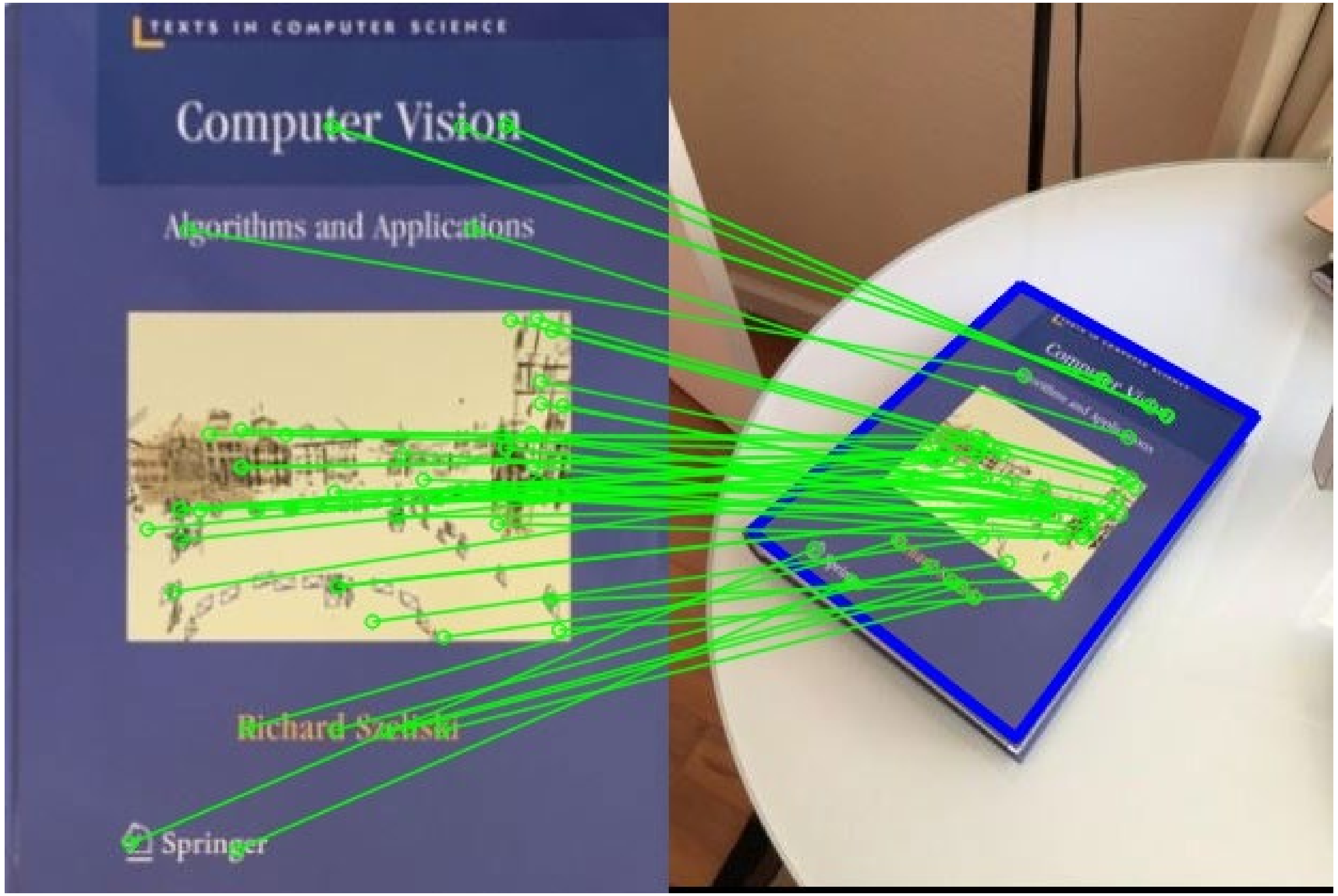
SIFT Matching Example





https://www.vlfeat.org/overview/sift.html

SIFT Matching Example



Further Reading

- Section 7.1, Computer Vision, Richard Szeliski

- David Lowe, Distinctive Image Features from Scale-Invariant Keypoints. IJCV, 2004

- ORB: An efficient alternative to SIFT or SURF. Rublee et al., ICCV, 2011