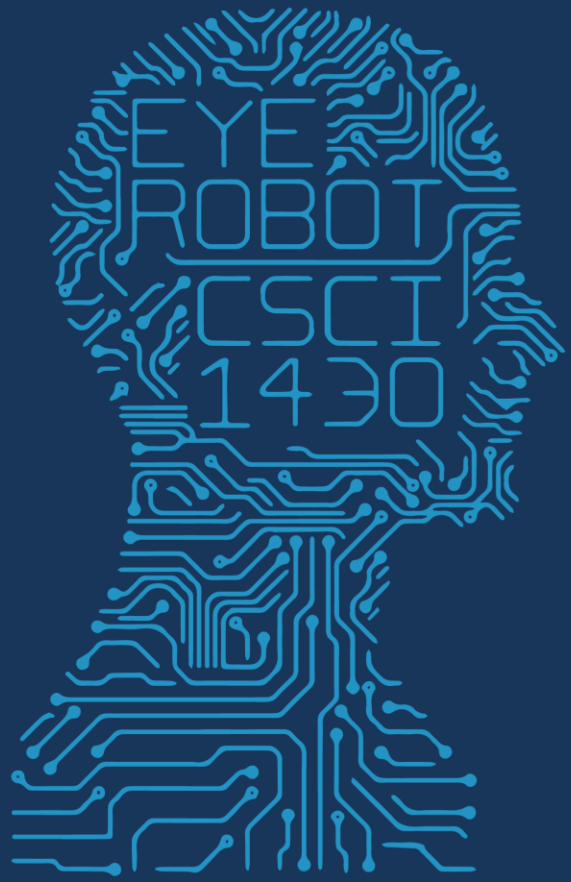
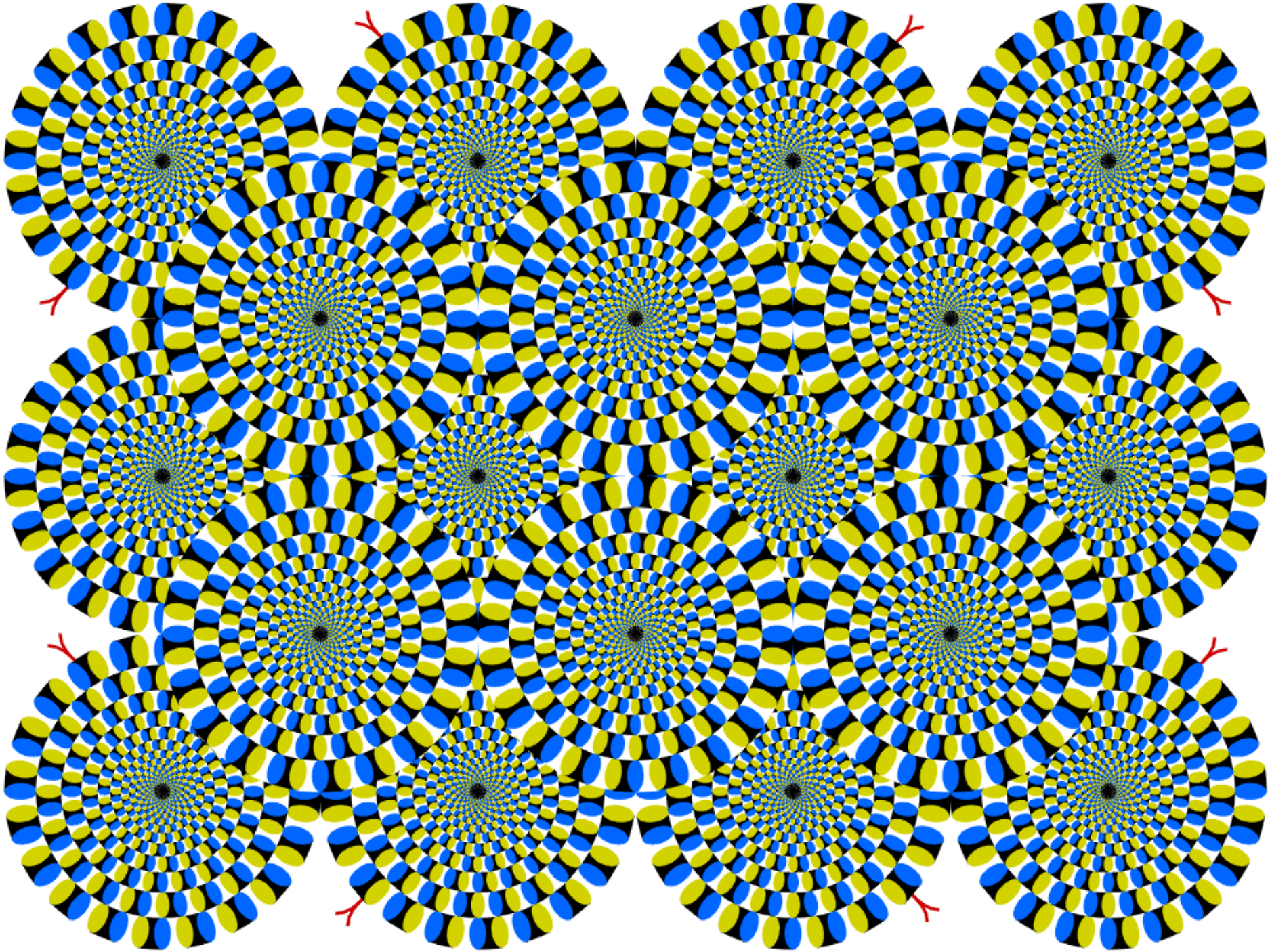
1950

Future Vision

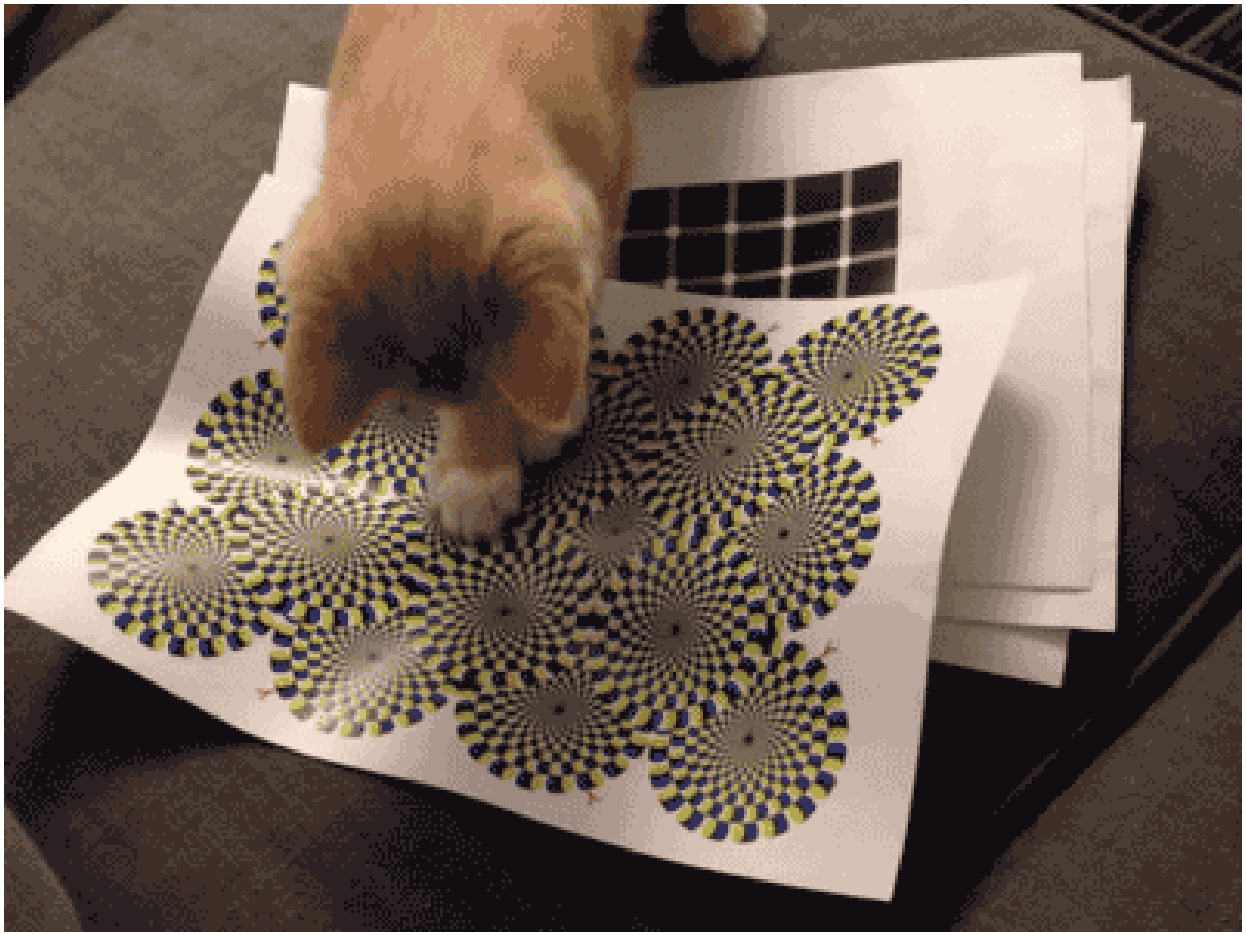


8 February 2019

Computer Vision

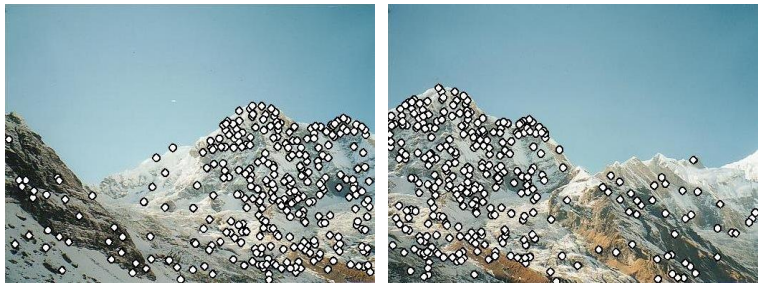


Does it work on other animals?

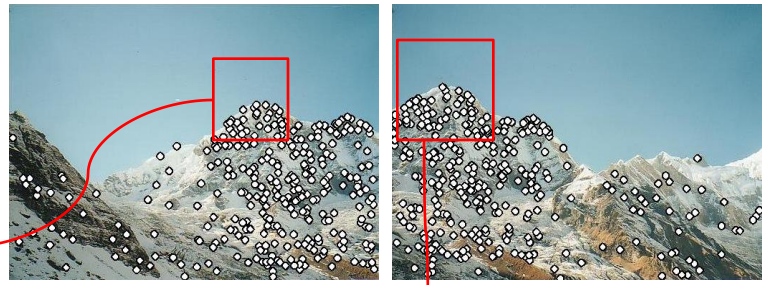


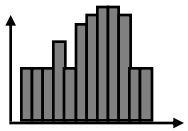
Local features: main components

1) Detection:
Find a set of distinctive key points.

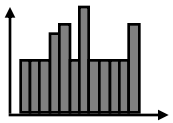


2) Description:
Extract feature descriptor around each interest point as vector.



x_1 

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

x_2 

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

3) Matching:
Compute distance between feature vectors to find correspondence.

$$d(\mathrm{x}_1, \mathrm{x}_2) < T$$

HOW INVARIANT ARE HARRIS CORNERS?

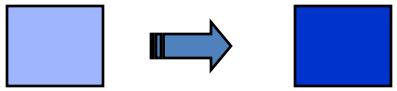
Invariance and covariance

Are locations *invariant* to photometric transformations

and *covariant* to geometric transformations?

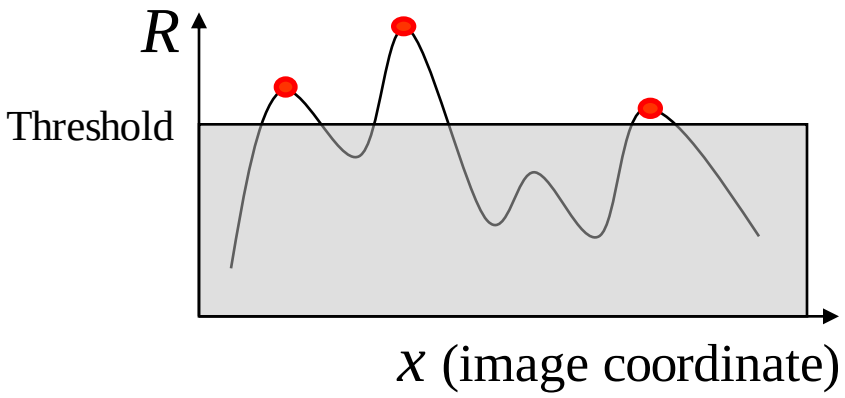
- **Invariance:** image is transformed and corner locations do not change
- **Covariance:** if we have two transformed versions of the same image, features should be detected in corresponding locations

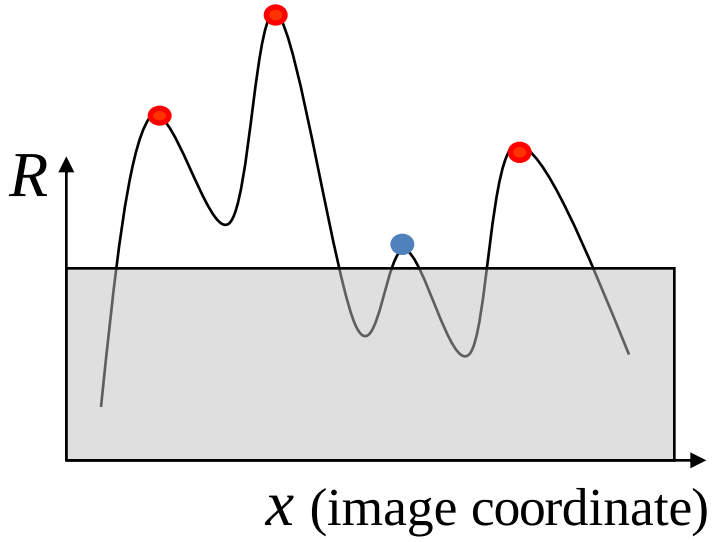
Affine intensity change



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

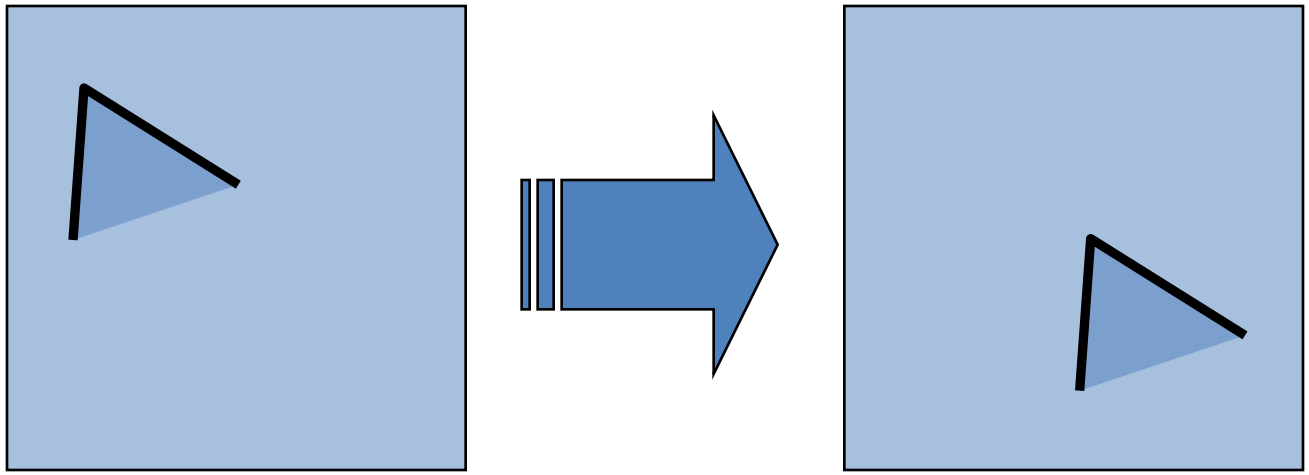
- Only derivatives are used => invariance to intensity shift $I \rightarrow I + b$
- Intensity scaling: $I \rightarrow a\,I$





Partially invariant to affine intensity change

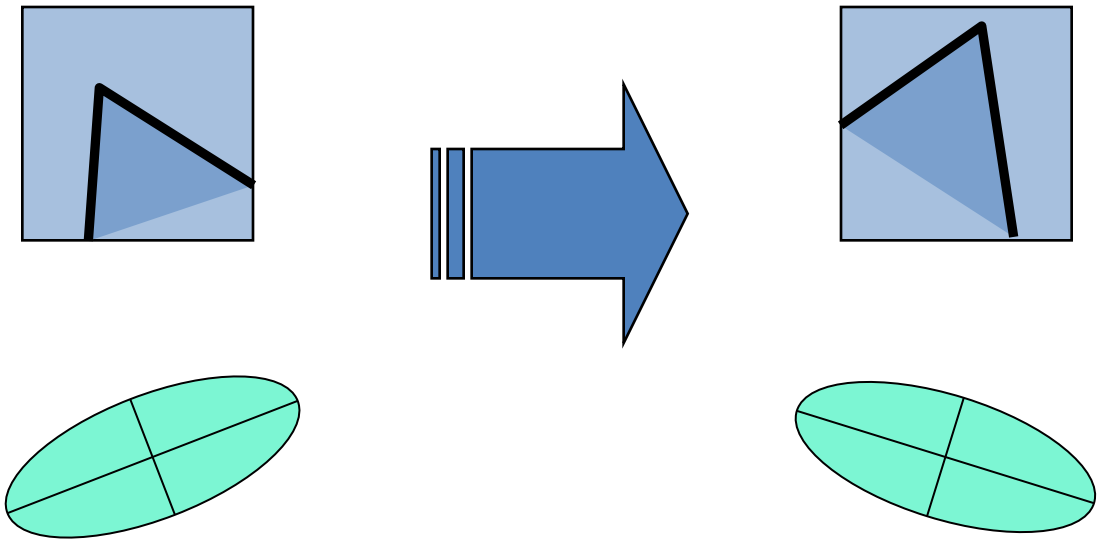
Image translation



- Derivatives and window function are shift-invariant.

Corner location is covariant w.r.t. translation

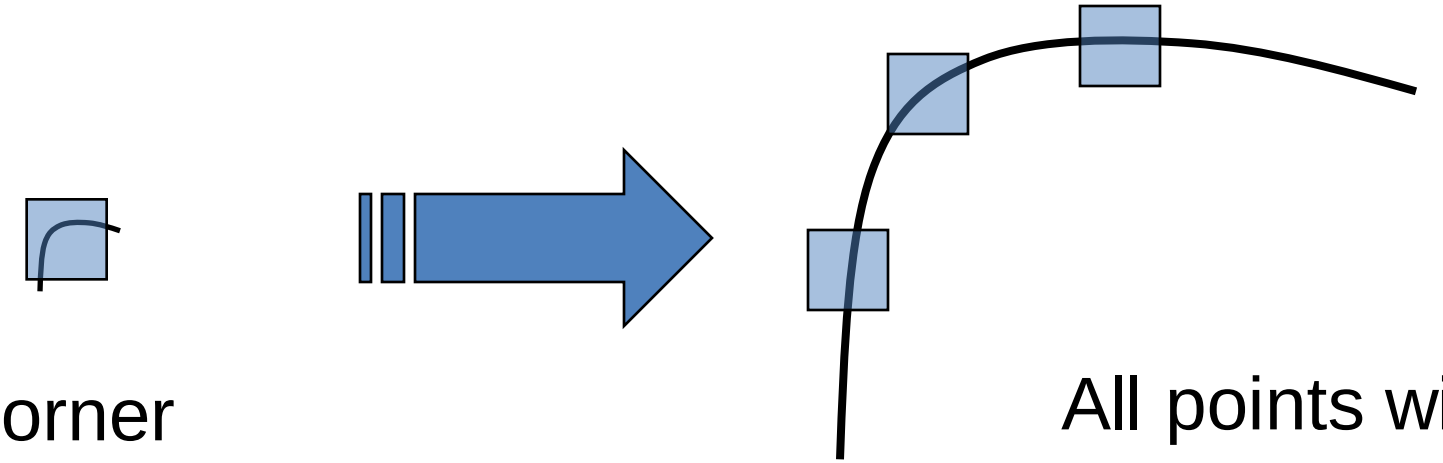
Image rotation



Second moment ellipse rotates but its shape (i.e., eigenvalues) remains the same.

Corner location is covariant w.r.t. rotation

Scaling



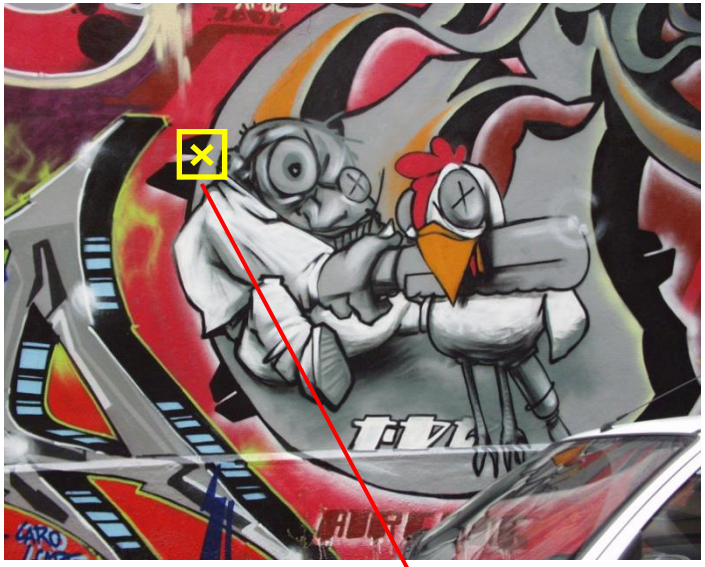
Corner

All points will be incorrectly classified as edges

Corner location is not covariant to scaling!

WHAT IS THE ‘SCALE’ OF A FEATURE POINT?

Automatic Scale Selection



$$f(I_{i_1 \ldots i_m}(x,\sigma)) \quad = \quad f(I_{i_1 \ldots i_m}(x',\sigma'))$$

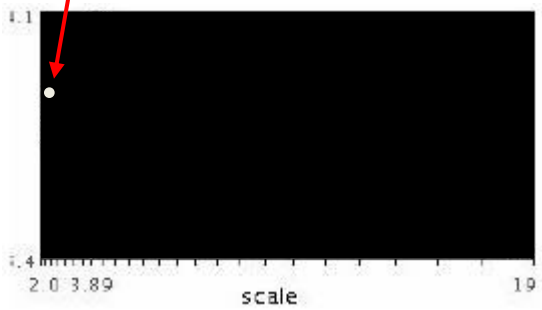
How to find patch sizes at which *f* response is equal?

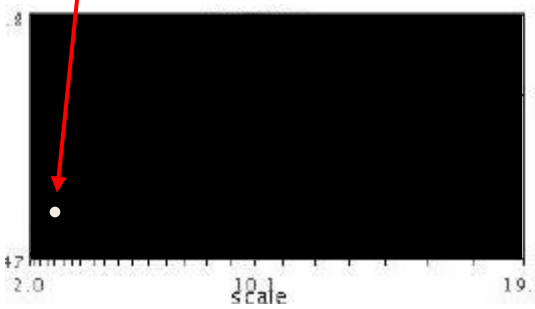
What is a good *f* ?

Automatic Scale Selection

- Function responses for increasing scale (scale signature)

Response of some function *f*





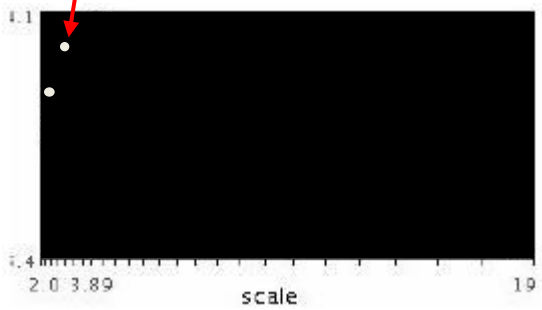
$f(I_{i_1 \ldots i_m}(x,\sigma))$

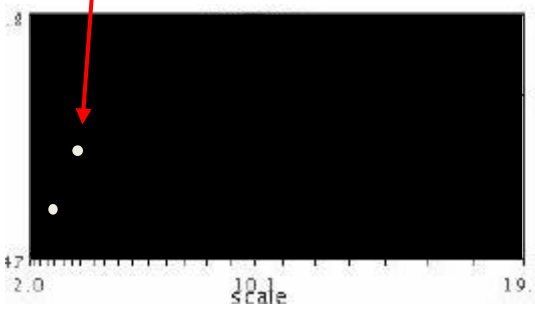
$f(I_{i_1 \ldots i_m}(x',\sigma'))$

Automatic Scale Selection

- Function responses for increasing scale (scale signature)

Response of some function *f*





$f(I_{i_1 \ldots i_m}(x,\sigma))$

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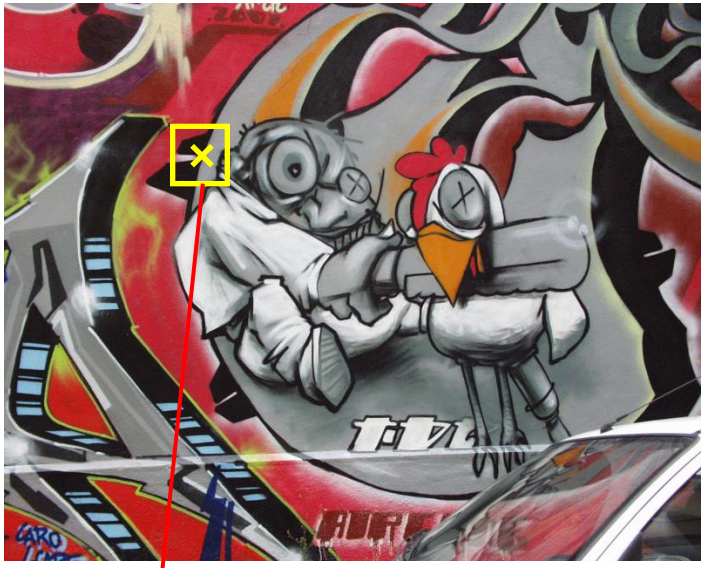
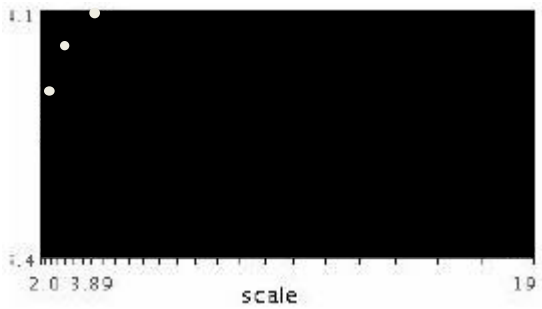
Automatic Scale Selection

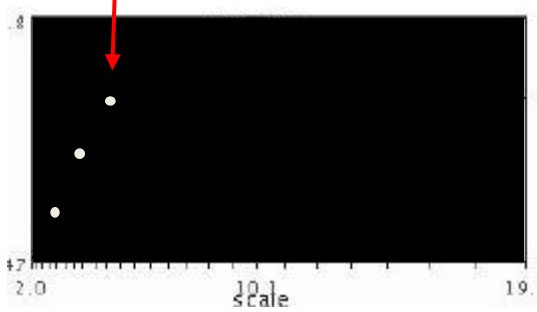
- Function responses for increasing scale (scale signature)



Response of some function *f*



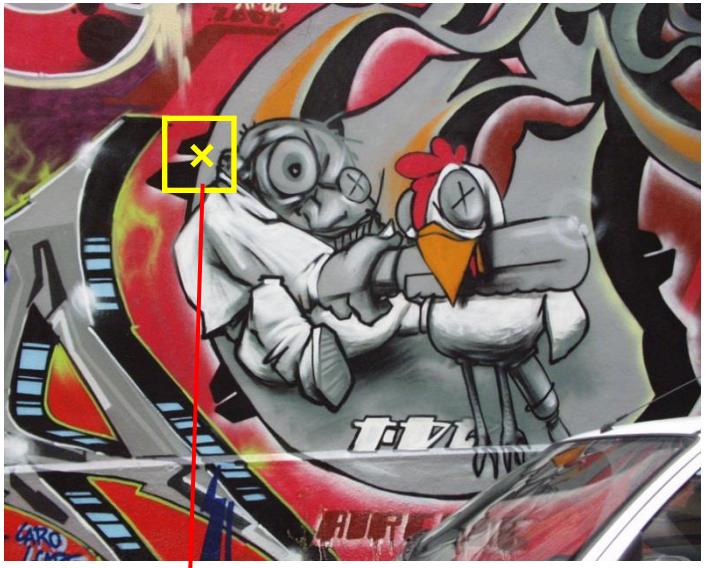
$f(I_{i_1 \ldots i_m}(x,\sigma))$



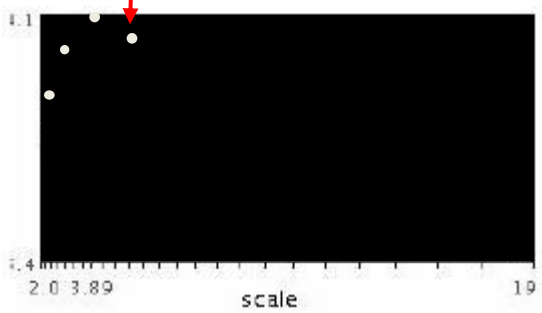
$f(I_{i_1 \ldots i_m}(x',\sigma'))$

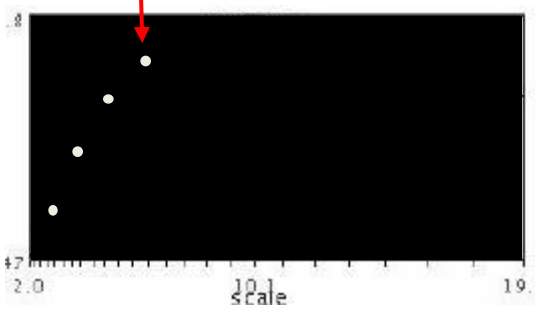
Automatic Scale Selection

- Function responses for increasing scale (scale signature)



Response of some function *f*





$f(I_{i_1 \ldots i_m}(x,\sigma))$

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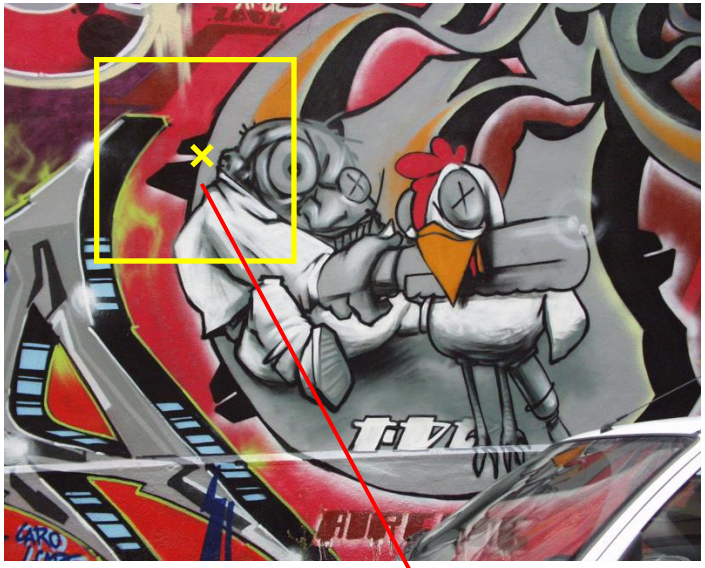
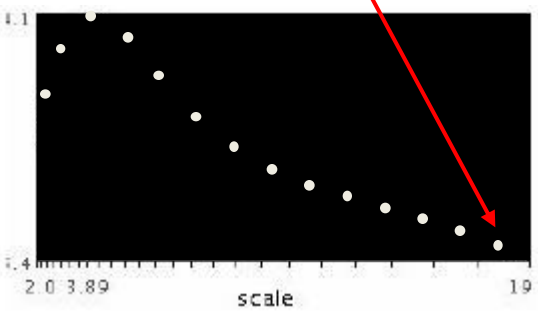
Automatic Scale Selection

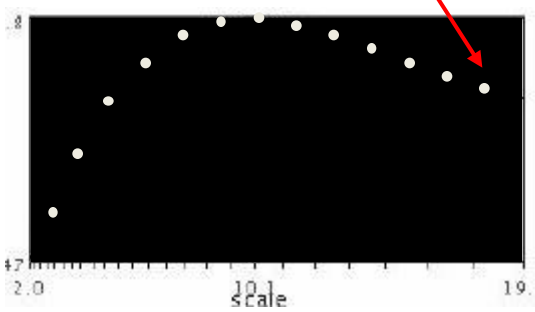
- Function responses for increasing scale (scale signature)



Response of some function *f*



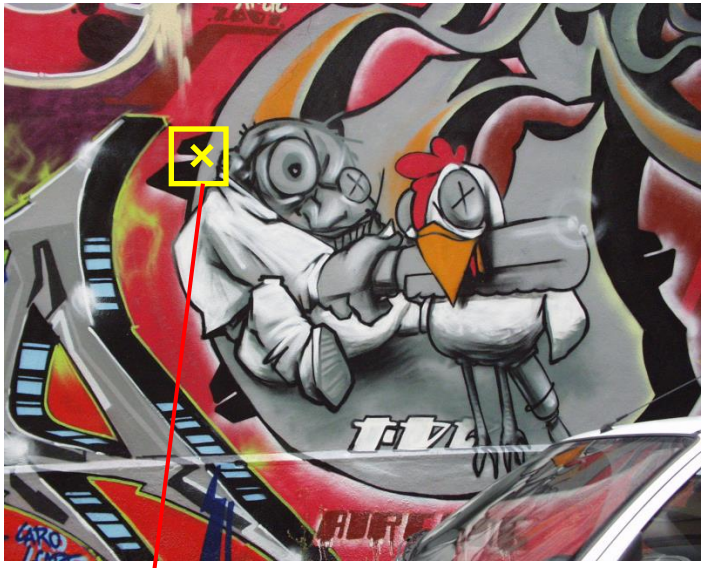
$f(I_{i_1 \ldots i_m}(x,\sigma))$



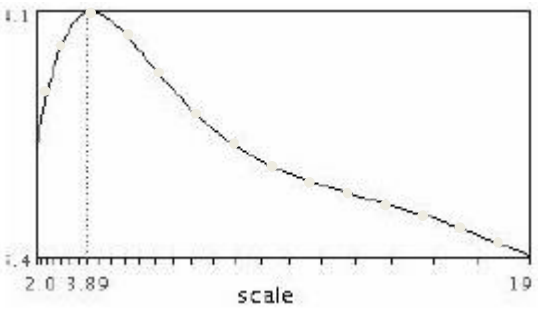
$f(I_{i_1 \ldots i_m}(x',\sigma'))$

Automatic Scale Selection

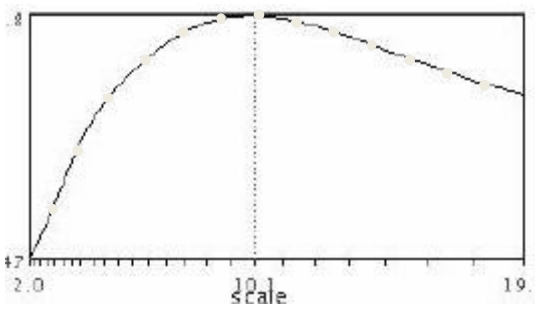
- Function responses for increasing scale (scale signature)



Response of some function *f*

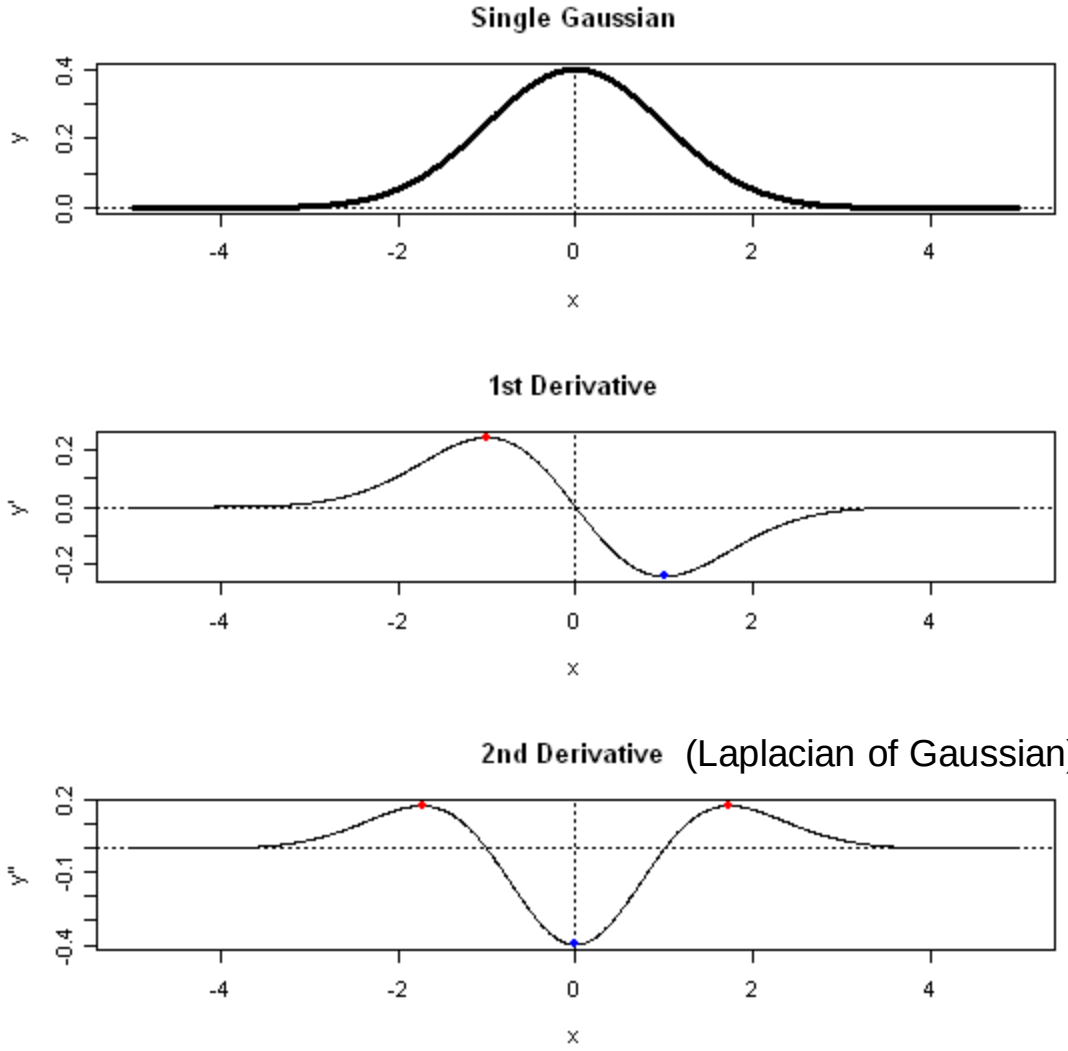


$f(I_{i_1 \ldots i_m}(x,\sigma))$

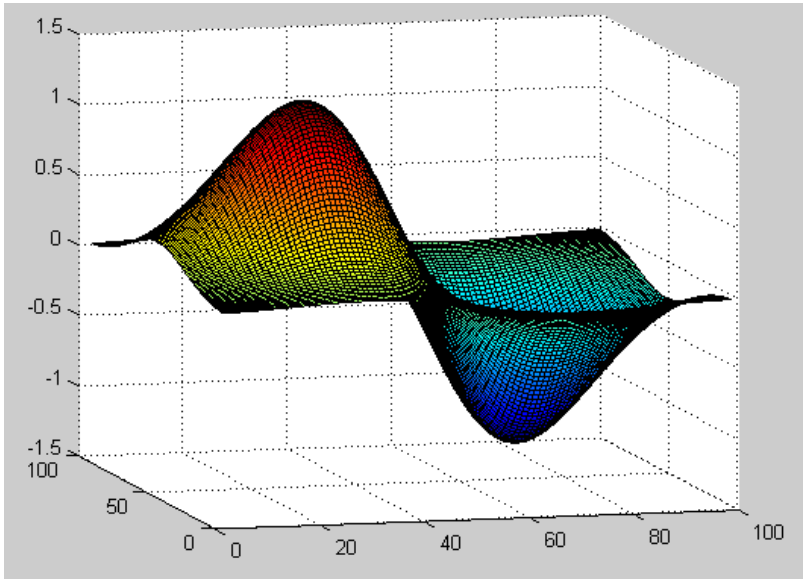


$f(I_{i_1 \ldots i_m}(x',\sigma'))$

What Is A Useful Signature Function *f* ?



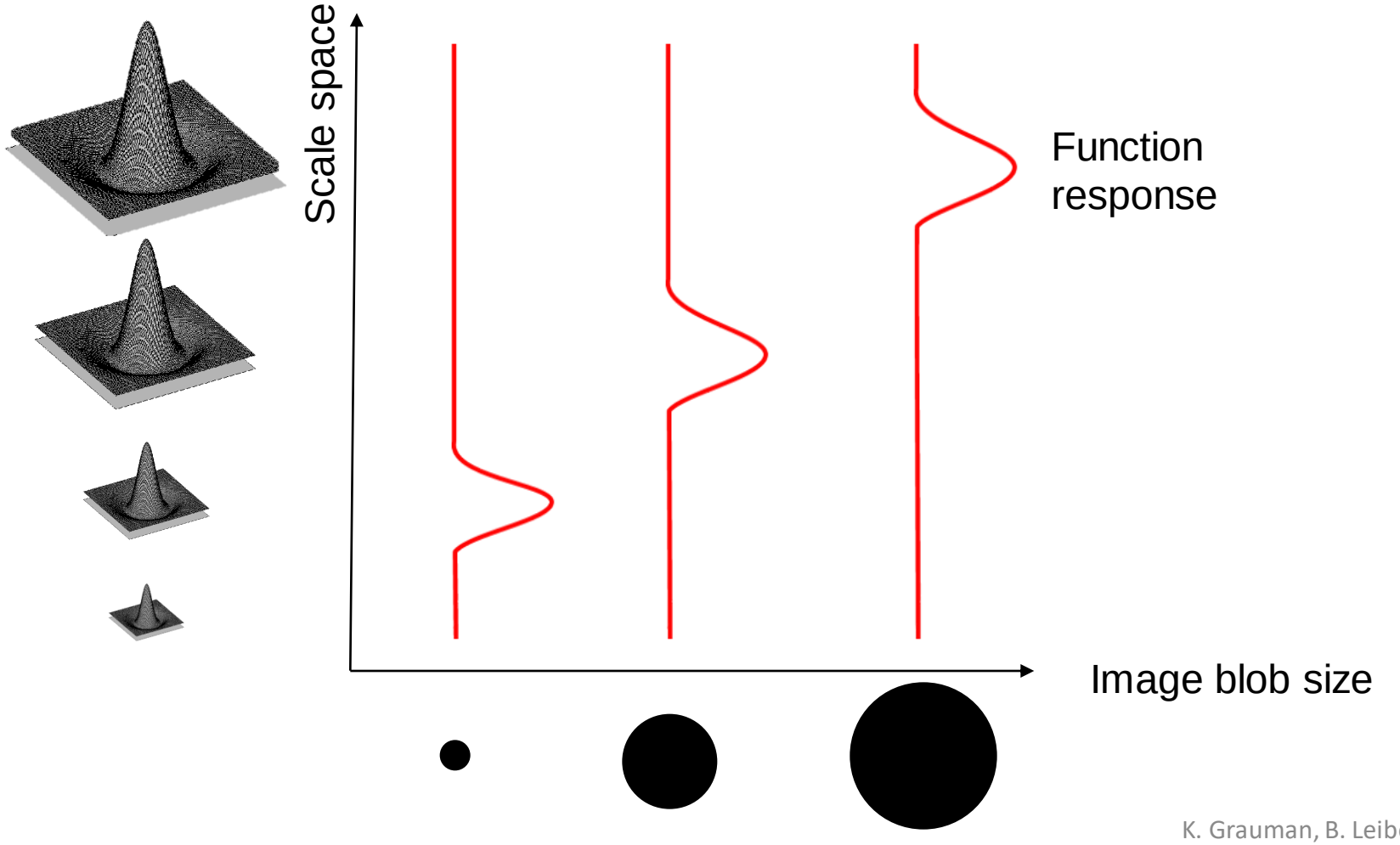
1st Derivative of Gaussian



What Is A Useful Signature Function *f* ?

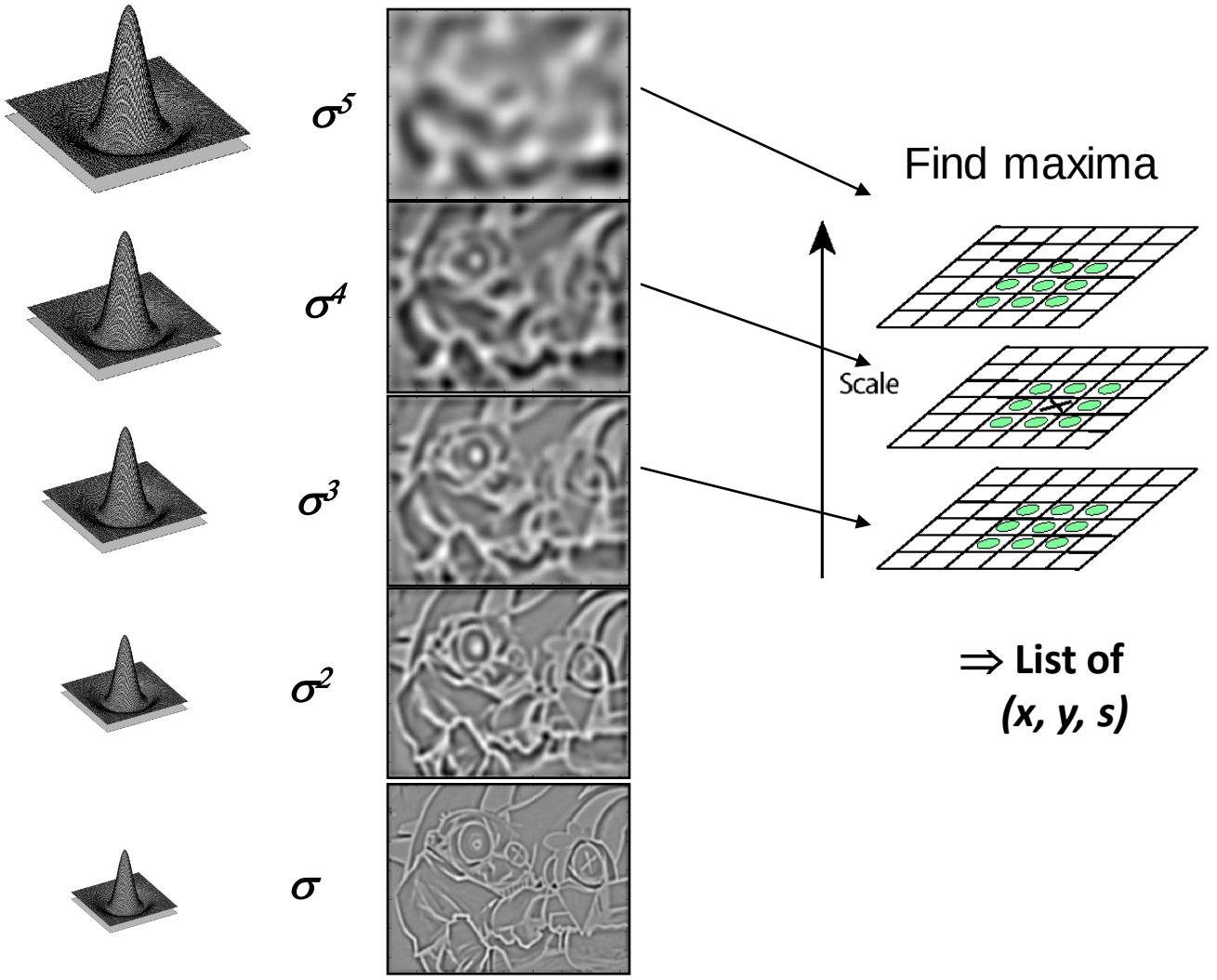
"Blob" detector is common for corners

– Laplacian (2nd derivative) of Gaussian (LoG)

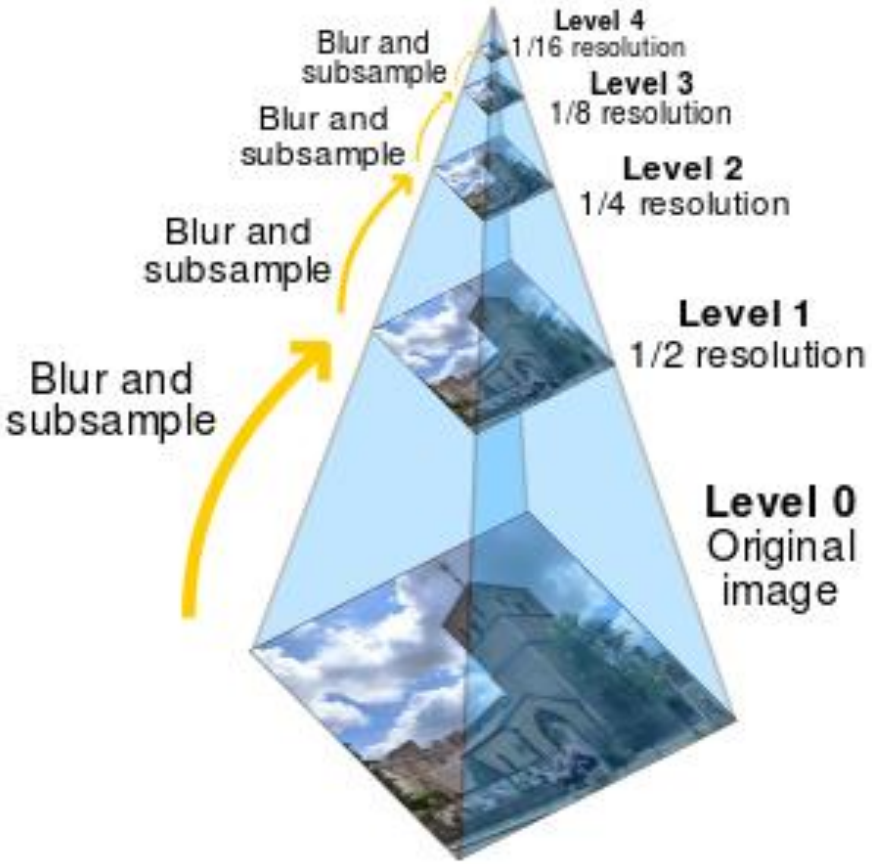


K. Grauman, B. Leibe

Find local maxima in position-scale space



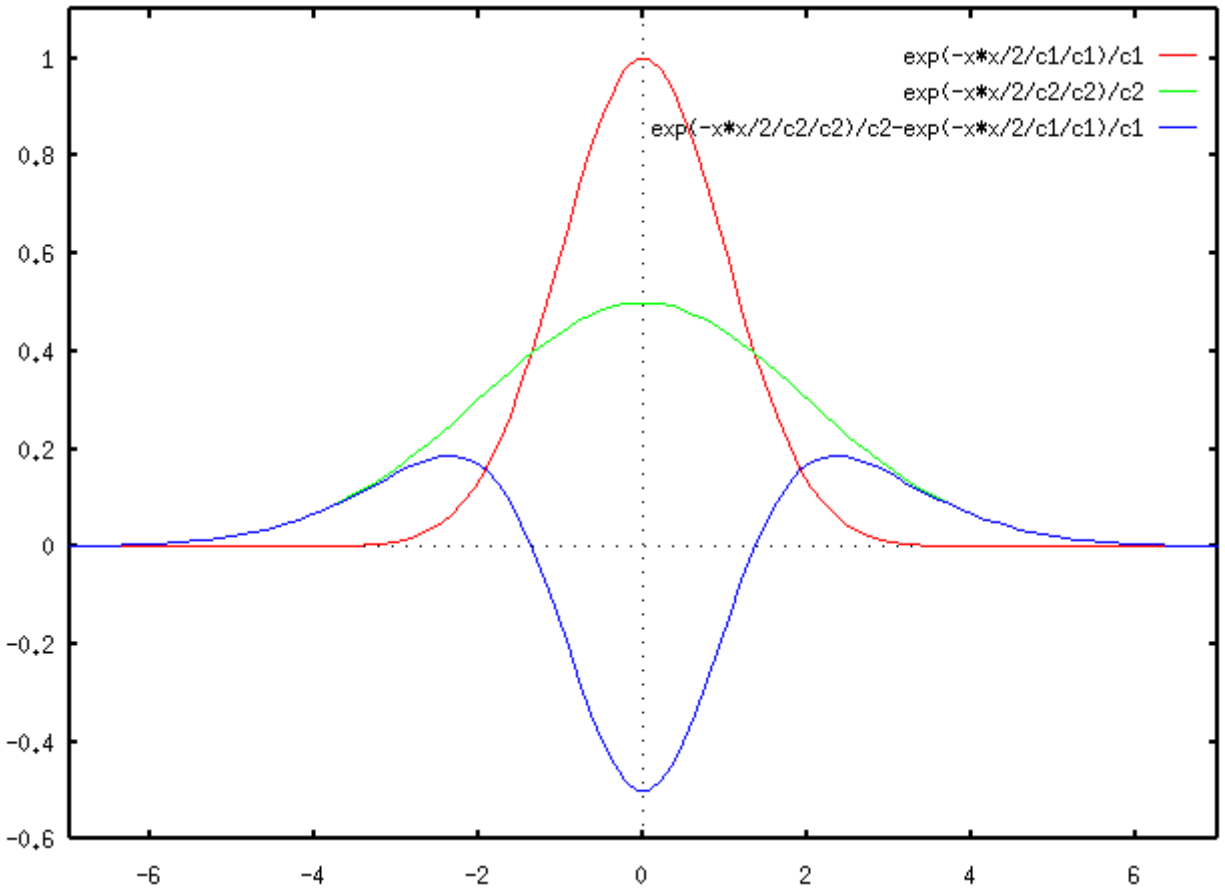
Laplacian pyramid



Like a Gaussian pyramid (left), but subtract layers from each other before subsampling.

Alternative kernel

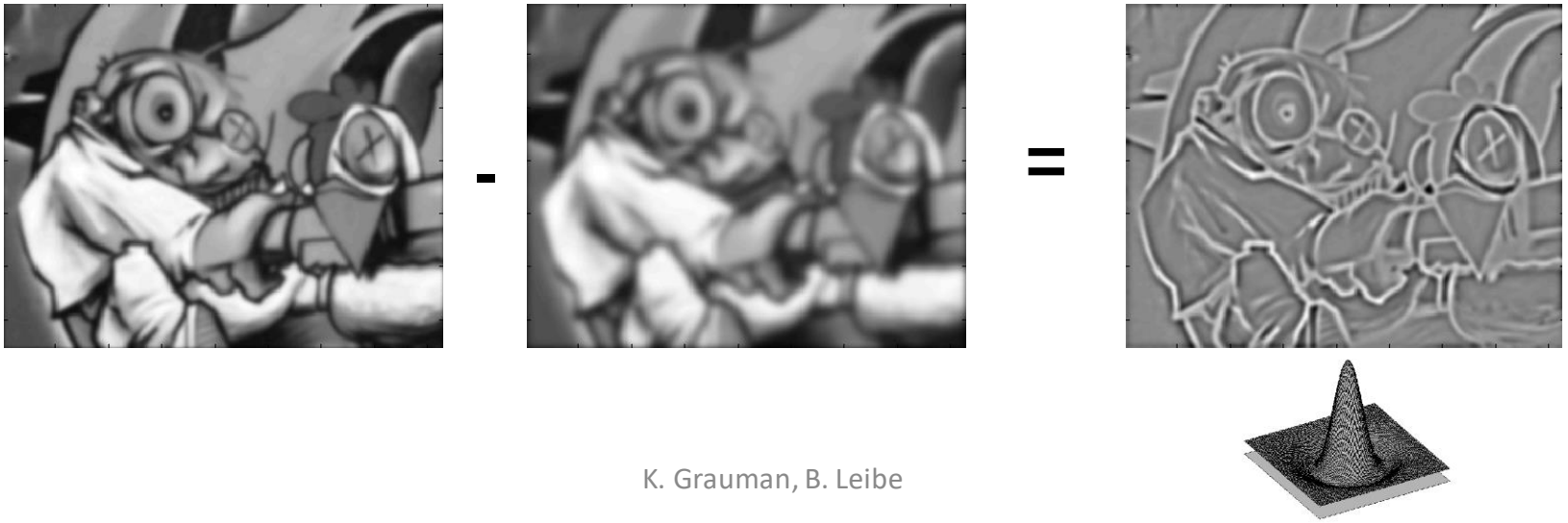
Approximate LoG with Difference-of-Gaussian (DoG).



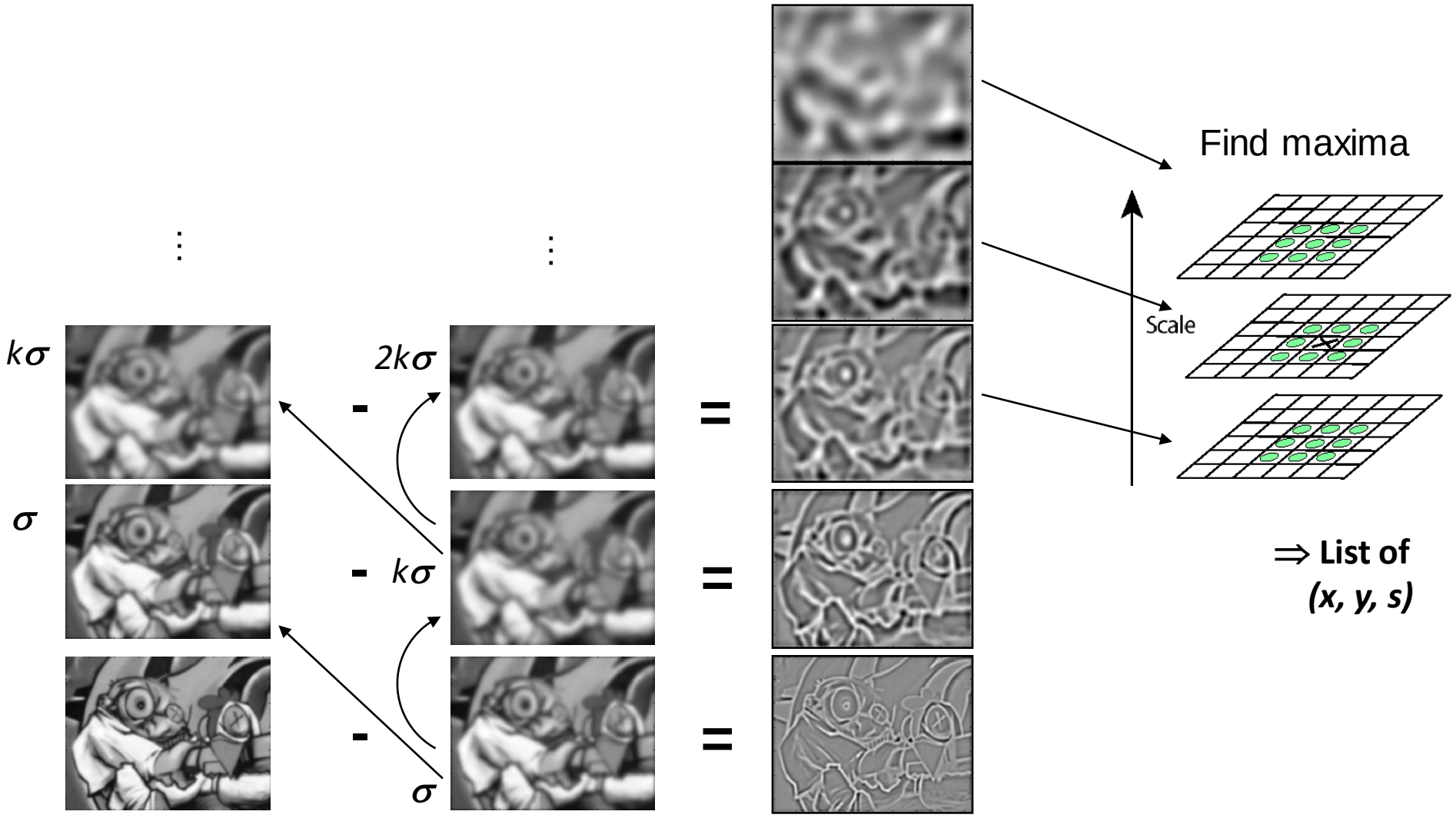
Alternative kernel

Approximate LoG with Difference-of-Gaussian (DoG).

1. Blur image with σ Gaussian kernel
2. Blur image with *k*σ Gaussian kernel
3. Subtract 2. from 1.

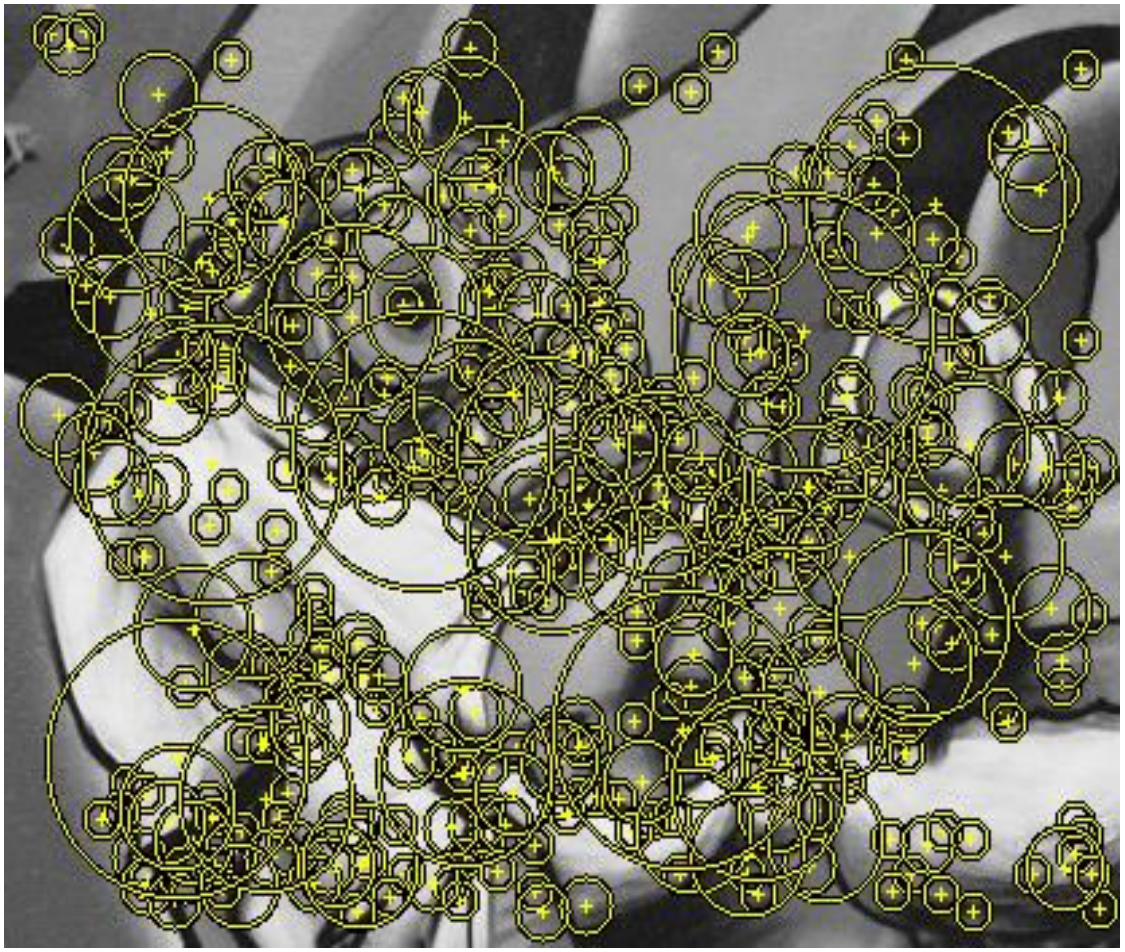


Find local maxima in position-scale space of DoG



Results: Difference-of-Gaussian

- Larger circles = larger scale
- Descriptors with maximal scale response



K. Grauman, B. Leibe

Comparison of Keypoint Detectors

Table 7.1 Overview of feature detectors.

Feature Detector	Corner	Blob	Region	Rotation invariant	Scale invariant	Affine invariant	Repeatability	Localization accuracy	Robustness	Efficiency
Harris	√			√			+++	+++	+++	++
Hessian		√		√			++	++	++	+
SUSAN	√			√			++	++	++	+++
Harris-Laplace	√	(√)		√	√		+++	+++	++	+
Hessian-Laplace	(√)	√		√	√		+++	+++	+++	+
DoG	(√)	√		√	√		++	++	++	++
SURF	(√)	√		√	√		++	++	++	+++
Harris-Affine	√	(√)		√	√	√	+++	+++	++	++
Hessian-Affine	(√)	√		√	√	√	+++	+++	+++	++
Salient Regions	(√)	√		√	√	(√)	+	+	++	+
Edge-based	√			√	√	√	+++	+++	+	+
MSER			√	√	√	√	+++	+++	++	+++
Intensity-based			√	√	√	√	++	++	++	++
Superpixels			√	√	(√)	(√)	+	+	+	+

Tuytelaars Mikolajczyk 2008

Local Image Descriptors

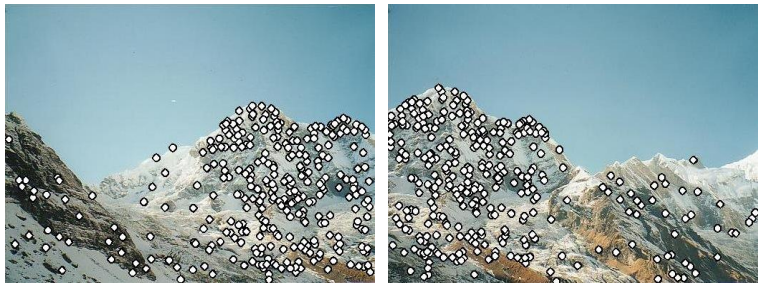
Read Szeliski 4.1

Acknowledgment: Many slides from James Hays, Derek Hoiem and Grauman & Leibe 2008 AAAI Tutorial

Local features: main components

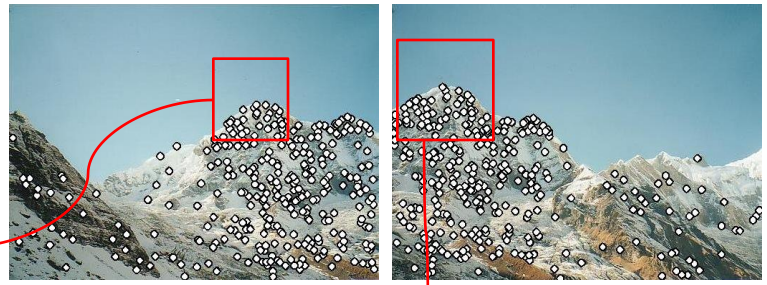
1) Detection:

Find a set of distinctive key points.



2) Description:

Extract feature descriptor around each interest point as vector.

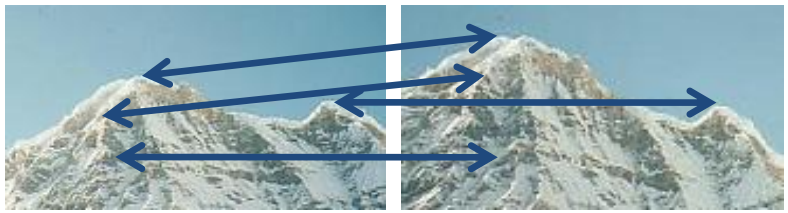


$$\mathbf{x}_1 = [x_1^{(1)}, \ldots, x_d^{(1)}]$$

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

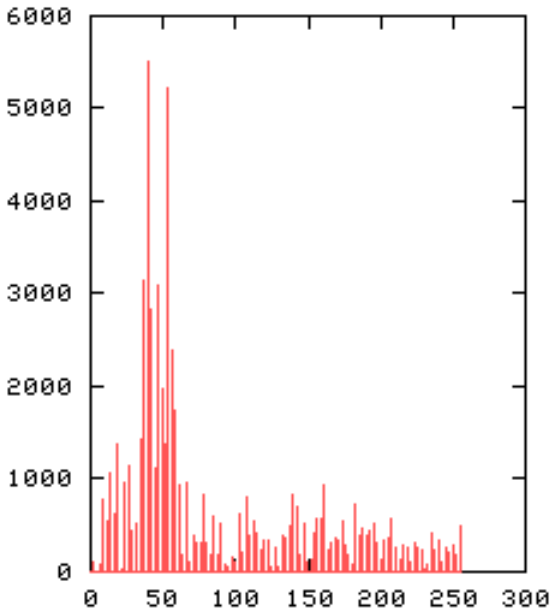
3) Matching:

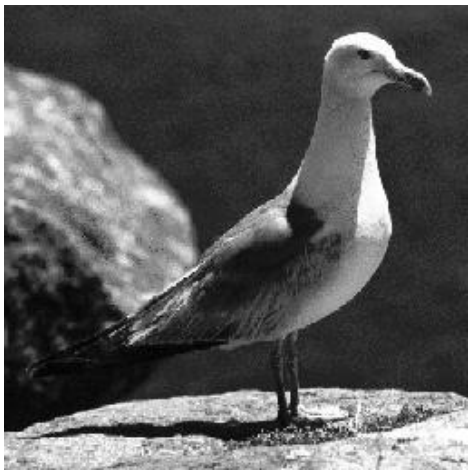
Compute distance between feature vectors to find correspondence.



$$d(\mathbf{x}_1, \mathbf{x}_2) < T$$

Image Representations: Histograms





Global histogram to represent distribution of features

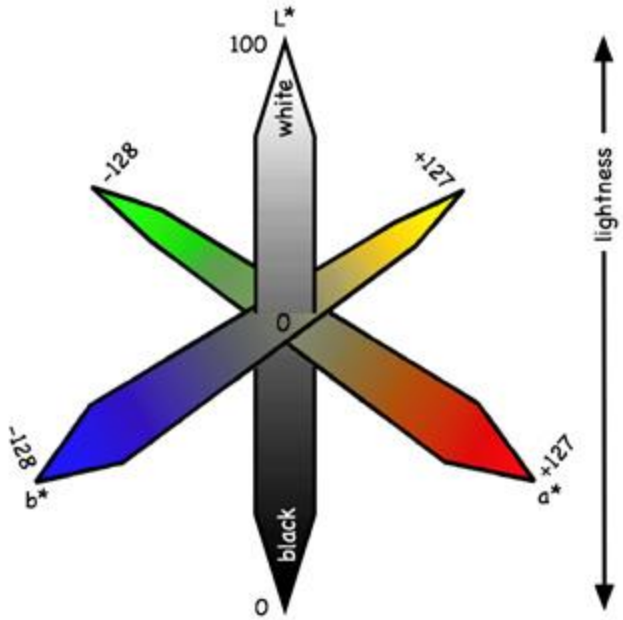
- Color, texture, depth, …

Local histogram per detected point

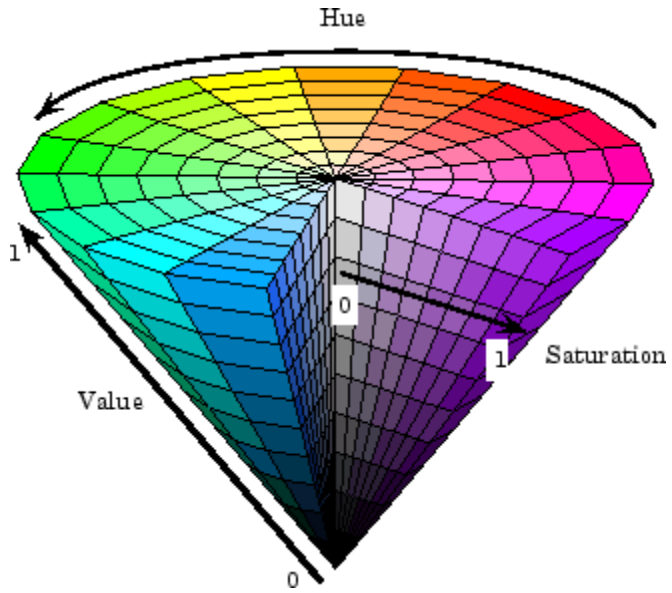
Images from Dave Kauchak

For what things might we compute histograms?

- Color



L*a*b* color space

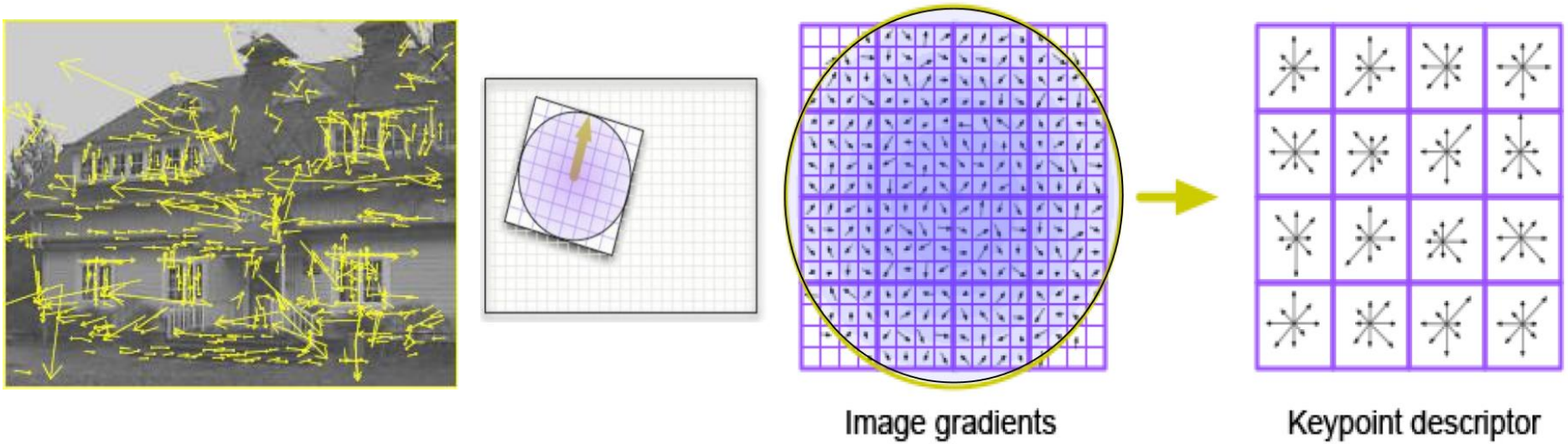


HSV color space

- Model local appearance

For what things might we compute histograms?

- Texture
- Local histograms of oriented gradients
- SIFT: Scale Invariant Feature Transform
  - Extremely popular (40k citations)



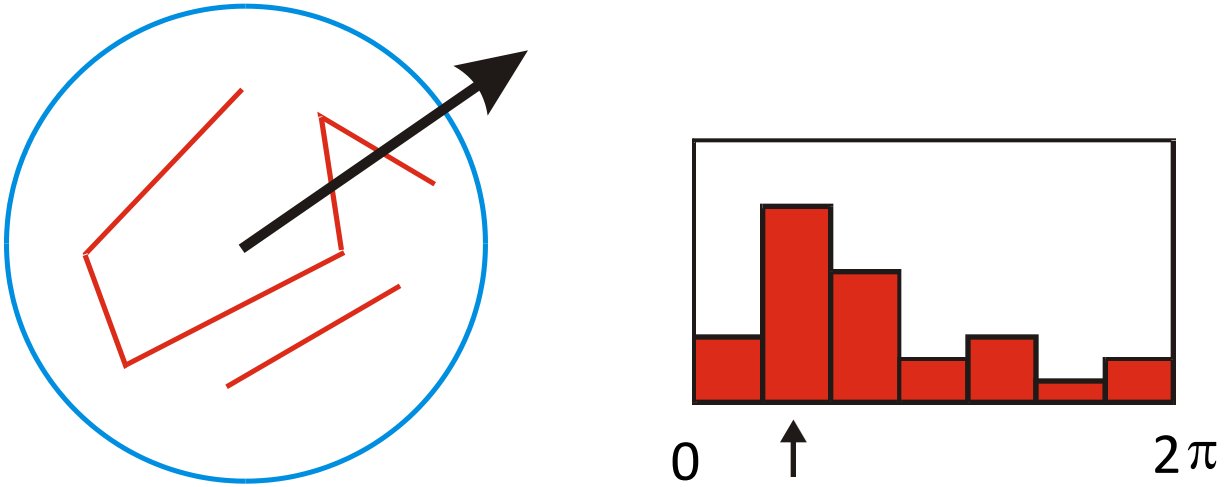
SIFT – Lowe IJCV 2004

SIFT preprocessing

- Find Difference of Gaussian scale-space extrema as feature point locations
- Post-processing
  - Subpixel position interpolation
  - Discard low-contrast points
  - Eliminate points along edges
- Orientation estimation per feature point

SIFT Orientation estimation

- Compute gradient orientation histogram
- Select dominant orientation Θ



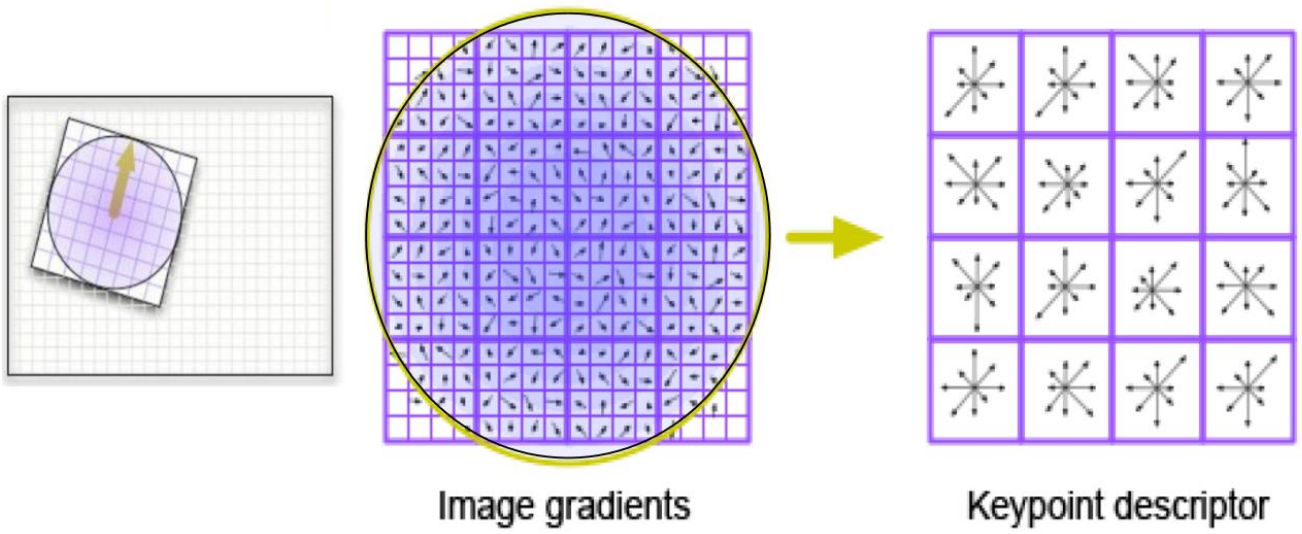
[Lowe, SIFT, 1999]

SIFT

- Find Difference of Gaussian scale-space extrema
- Post-processing
  - Position interpolation
  - Discard low-contrast points
  - Eliminate points along edges
- Orientation estimation
- Descriptor extraction
  - Motivation: We want some sensitivity to spatial layout, but not too much, so blocks of histograms give us that.

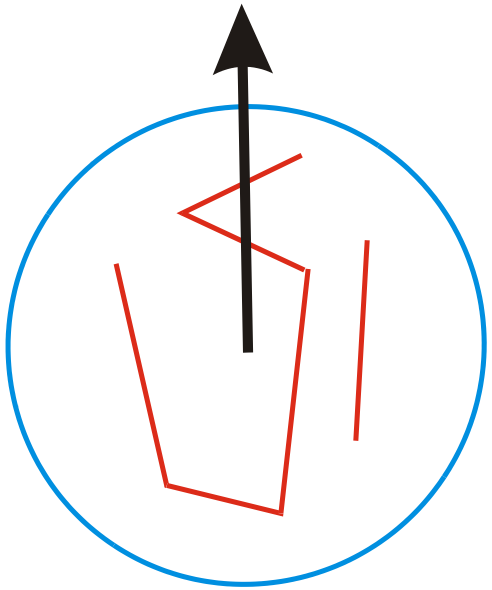
SIFT Descriptor Extraction

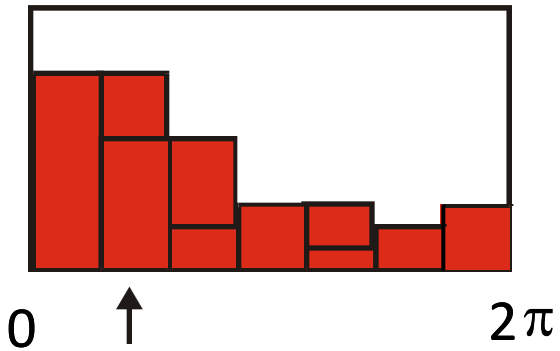
- Given a keypoint with scale and orientation:
  - Pick scale-space image which most closely matches estimated scale
  - Resample image to match orientation OR
  - Subtract detector orientation from vector to give invariance to general image rotation.



SIFT Orientation Normalization

- Compute orientation histogram
- Select dominant orientation θ
- Normalize: rotate to fixed orientation

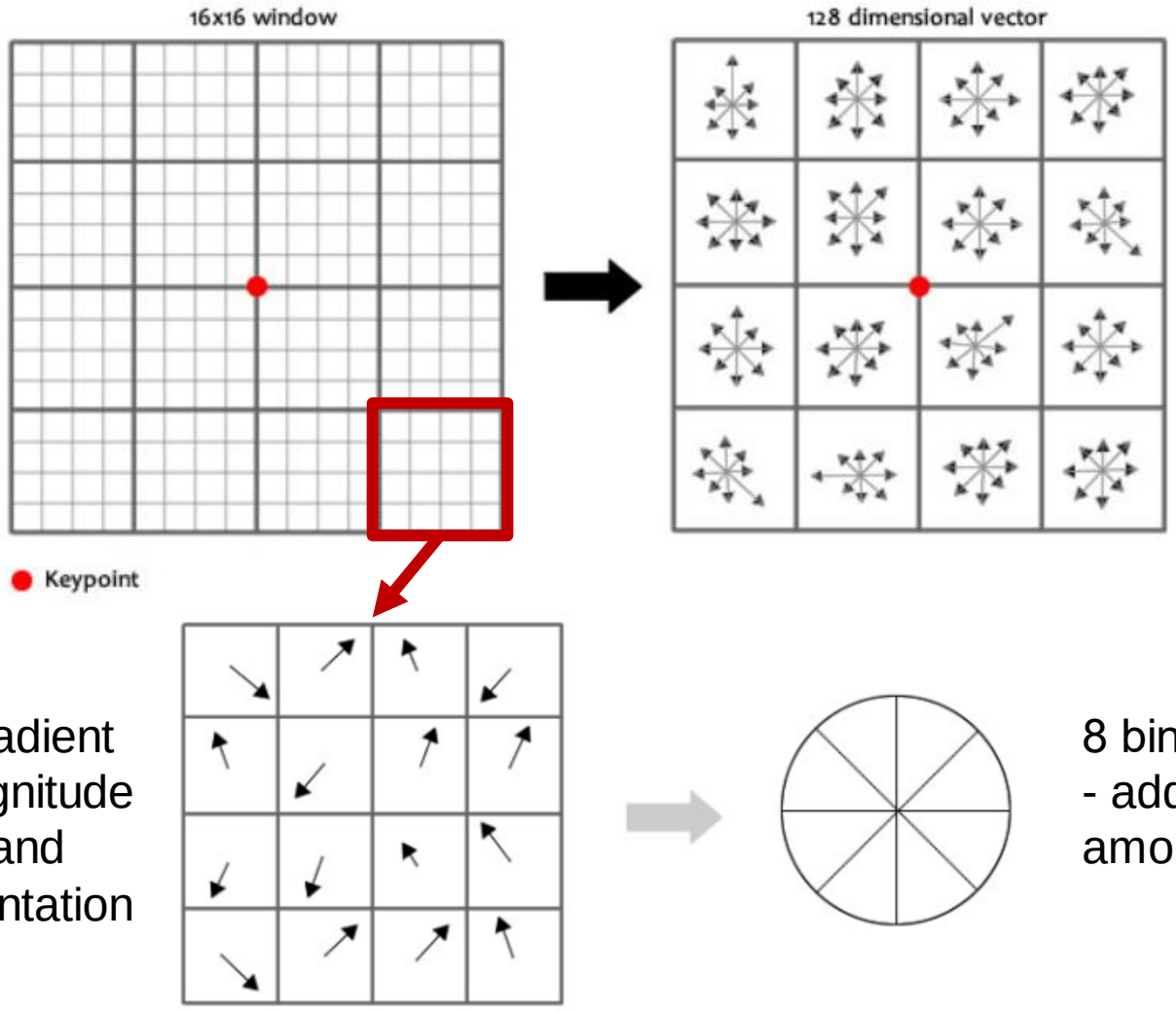




[Lowe, SIFT, 1999]

SIFT Descriptor Extraction

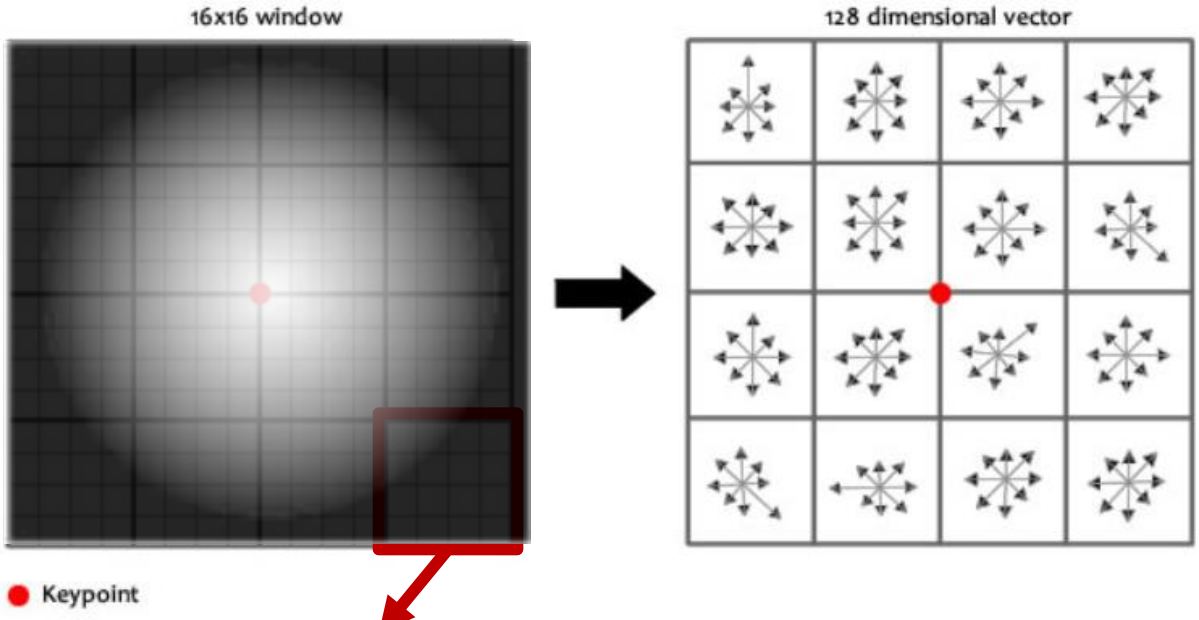
- Given a keypoint with scale and orientation



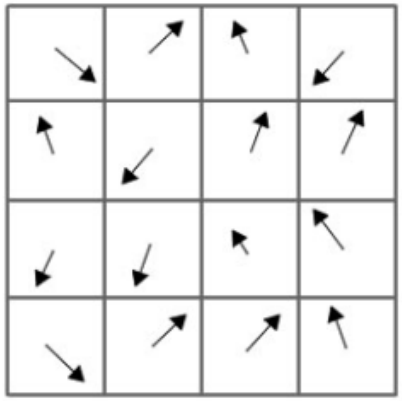
SIFT Descriptor Extraction

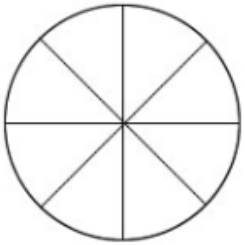
Weight 16x16 grid by Gaussian to add location robustness and reduce effect of outer regions

σ = half window width



Gradient magnitude and orientation





8 bin ‘histogram’ - add magnitude amounts!

SIFT Descriptor Extraction

- Extract 8 x 16 values into 128-dim vector
- Illumination invariance:
  - Working in gradient space, so robust to $I = I + b$
  - Normalize vector to [0…1]
    - Robust to $I = \alpha I$ brightness changes
  - Clamp all vector values > 0.2 to 0.2.
    - Robust to “non-linear illumination effects”
    - Image value saturation / specular highlights
  - Renormalize

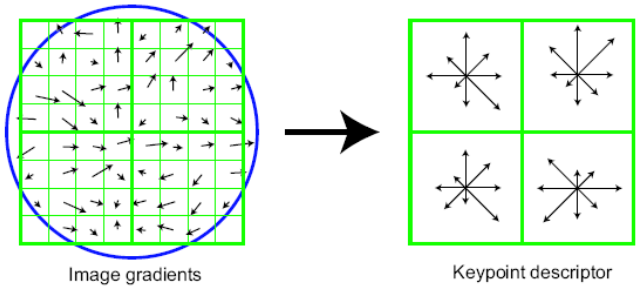
Specular highlights move between image pairs!

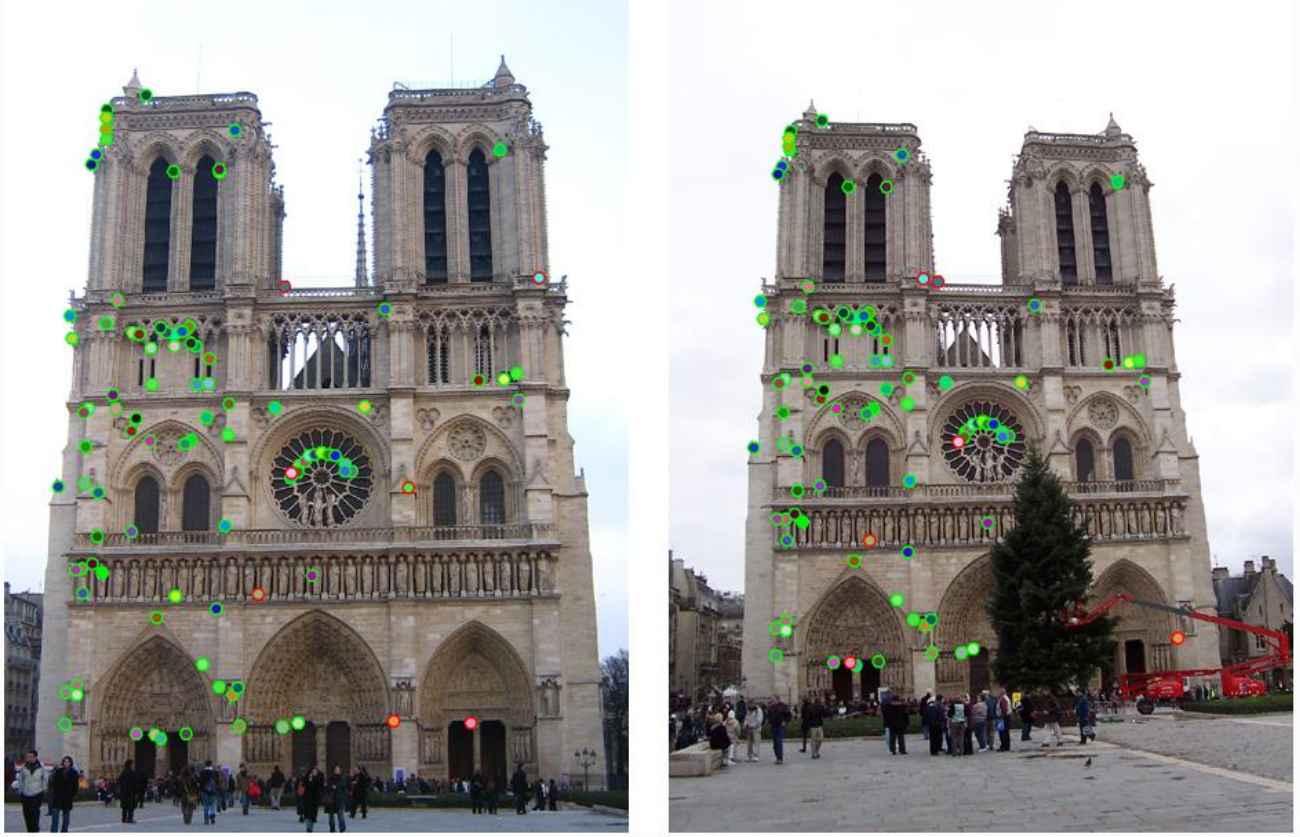
Efficient Implementation

- Filter using oriented kernels based on directions of histogram bins.
- Called ‘steerable filters’

Review: Local Descriptors

- Most features can be thought of as templates, histograms (counts), or combinations
- The ideal descriptor should be
  - Robust and Distinctive
  - Compact and Efficient
- Most available descriptors focus on edge/gradient information
  - Capture texture information
  - Color rarely used





The top 100 most confident local feature matches from a baseline implementation of project 2. In this case, 93 were correct (highlighted in green) and 7 were incorrect (highlighted in red).

Project 2: Local Feature Matching
CSCI 1430: Introduction to Computer Vision

Logistics

- Files: proj2.zip (6.9 MB).
- Part 1: Questions
  - Questions + template: Now in the zip: questions/
  - Hand-in process: Gradescope as PDF. Submit anonymous materials please!

- Part 2: Code
  - Writeup template: In the zip: writeup/
  - Required files: code/, writeup/writeup.pdf
  - Hand-in process: Gradescope as ZIP file. Submit anonymous materials please!

SIFT-like descriptor in Project 2

- SIFT is hand designed based on intuition
- You implement your own SIFT-like descriptor
  - Ignore scale/orientation to start.

- Parameters: stick with defaults + minor tweaks
- Feel free to look at papers / resources for inspiration

2017 Spring TA Martin Zhu recommends this tutorial:
http://aishack.in/tutorials/sift-scale-invariant-feature-transform-features/

- Note an error in here: Gaussian weight is applied to the larger 16x16 block and not the smaller 4x4 blocks. See Lowe's original paper, Sec. 6.1 par 2.

Lowe's original paper: http://www.cs.ubc.ca/~lowe/papers/ijcv04.pdf

Feature Matching

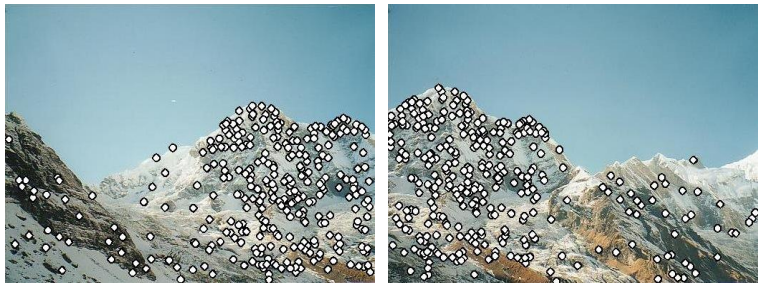
Read Szeliski 4.1

Many slides from James Hays, Derek Hoiem, and Grauman&Leibe 2008 AAAI Tutorial

Local features: main components

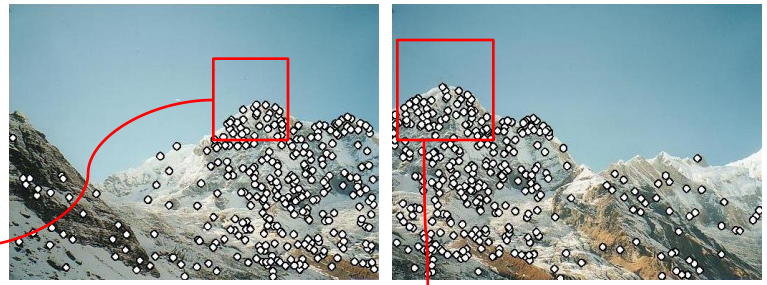
1) Detection:

Find a set of distinctive key points.



2) Description:

Extract feature descriptor around each interest point as vector.

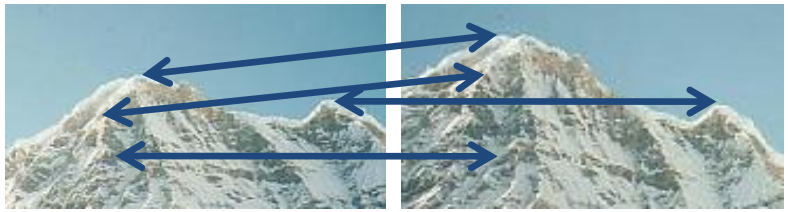


$$\mathbf{x}_1 = [x_1^{(1)}, \ldots, x_d^{(1)}]$$

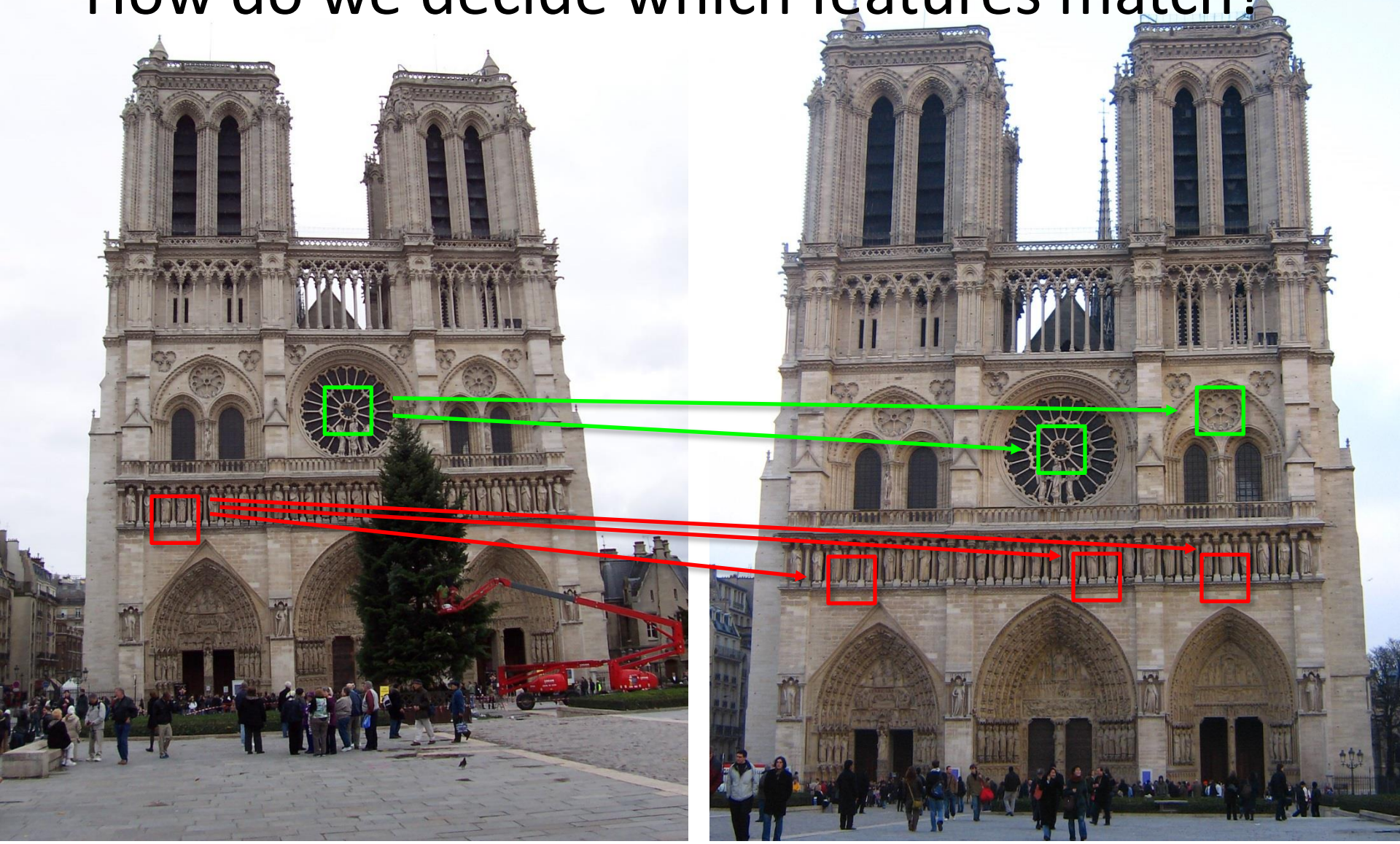
$$\mathbf{x}_2 = [x_1^{(2)}, \ldots, x_d^{(2)}]$$

3) Matching:

Compute distance between feature vectors to find correspondence.



How do we decide which features match?



Distance: 0.34, 0.30, 0.40

Distance: 0.61, 1.22

Euclidean distance vs. Cosine Similarity

- Euclidean distance:

$$\mathrm{d}(\mathbf{p}, \mathbf{q}) = \mathrm{d}(\mathbf{q}, \mathbf{p}) = \sqrt{(q_1 - p_1)^2 + (q_2 - p_2)^2 + \cdots + (q_n - p_n)^2}$$

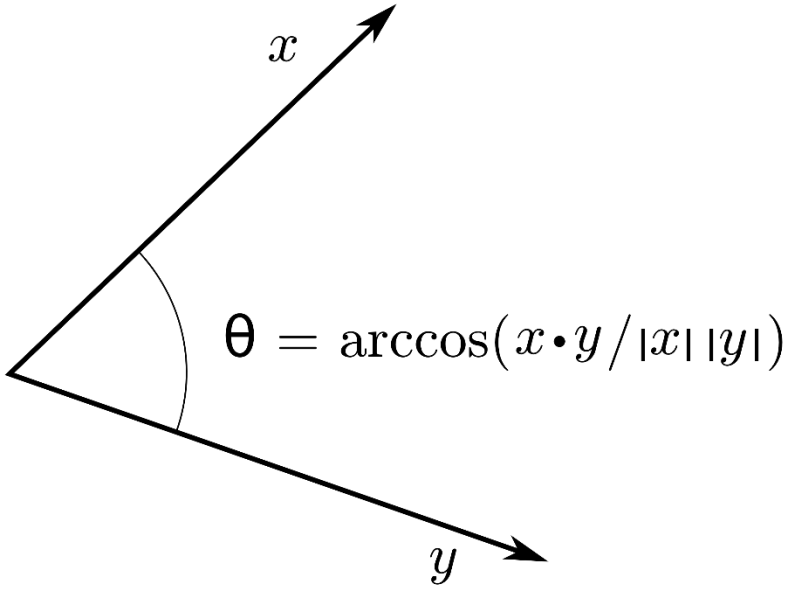
$$= \sqrt{\sum_{i=1}^{n} (q_i - p_i)^2}.$$

$$\|\mathbf{q} - \mathbf{p}\| = \sqrt{(\mathbf{q} - \mathbf{p}) \cdot (\mathbf{q} - \mathbf{p})}.$$

- Cosine similarity:

$$\mathbf{a} \cdot \mathbf{b} = \|\mathbf{a}\|_2 \|\mathbf{b}\|_2 \cos\theta$$

$$\mathbf{similarity} = \cos(\theta) = \frac{\mathbf{A} \cdot \mathbf{B}}{\|\mathbf{A}\|_2 \|\mathbf{B}\|_2}$$



Wikipedia

Feature Matching

- Criteria 1:
  - Compute distance in feature space, e.g., Euclidean distance between 128-dim SIFT descriptors
  - Match point to lowest distance (nearest neighbor)

- Problems:
  - Does everything have a match?

Feature Matching

- Criteria 2:
  - Compute distance in feature space, e.g., Euclidean distance between 128-dim SIFT descriptors
  - Match point to lowest distance (nearest neighbor)
  - Ignore anything higher than threshold (no match!)

- Problems:
  - Threshold is hard to pick
  - Non-distinctive features could have lots of close matches, only one of which is correct

Nearest Neighbor Distance Ratio

Compare distance of closest (NN1) and second-closest (NN2) feature vector neighbor.

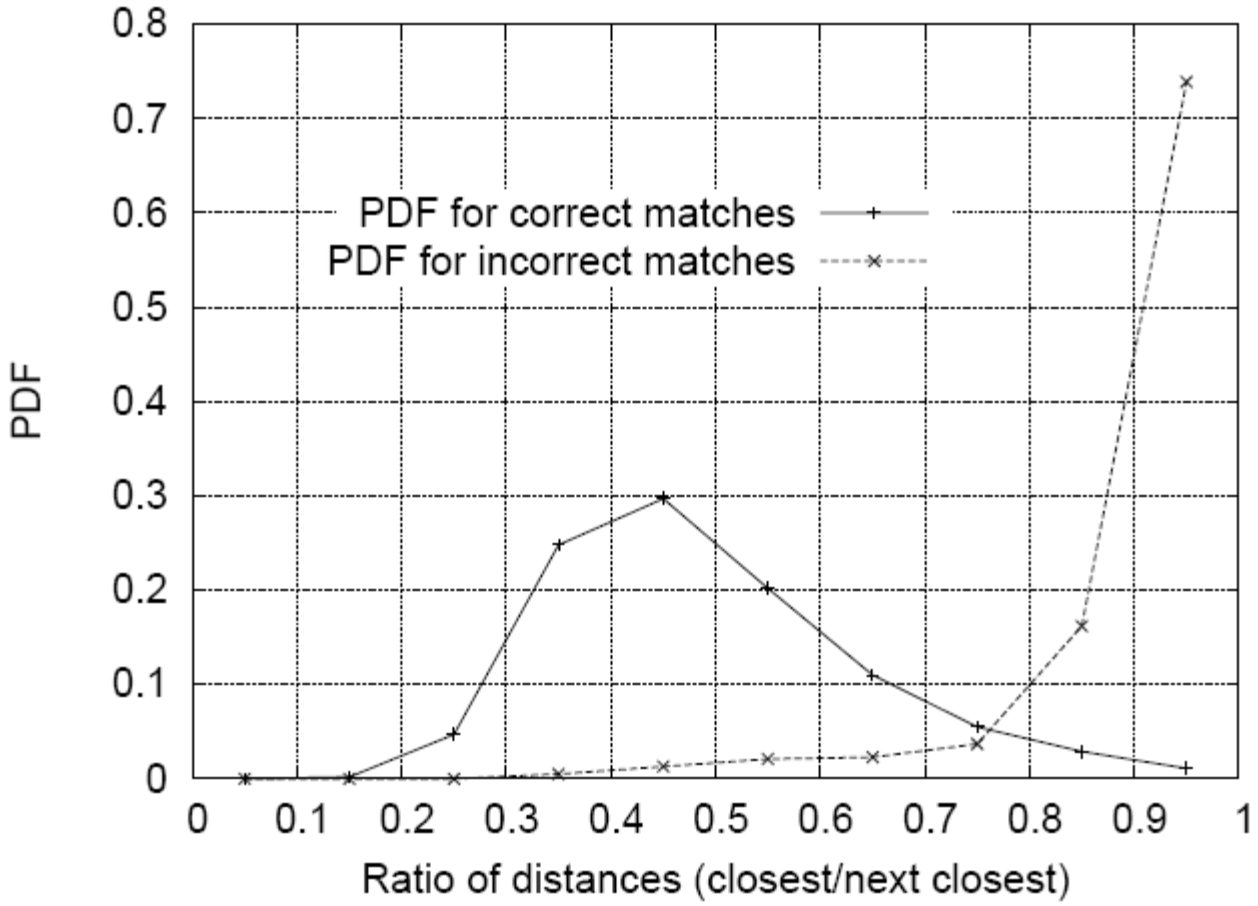
- If NN1 ≈ NN2, ratio $\frac{NN1}{NN2}$ will be ≈ 1 -> matches too close.
- As NN1 << NN2, ratio $\frac{NN1}{NN2}$ tends to 0.

Sorting by this ratio puts matches in order of confidence.

Threshold ratio – but how to choose?

Nearest Neighbor Distance Ratio

- Lowe computed a probability distribution functions of ratios
- 40,000 keypoints with hand-labeled ground truth



Ratio threshold depends on your application's view on the trade-off between the number of false positives and true positives!

Lowe IJCV 2004

Efficient compute cost

- Naïve looping: Expensive

- Operate on matrices of descriptors
- E.g., for row vectors,

  $\texttt{features\_image1} * \texttt{features\_image2}^{T}$

  produces matrix of dot product results for all pairs of features

Live SIFT Demo

Actually a similar alternative, called SURF.

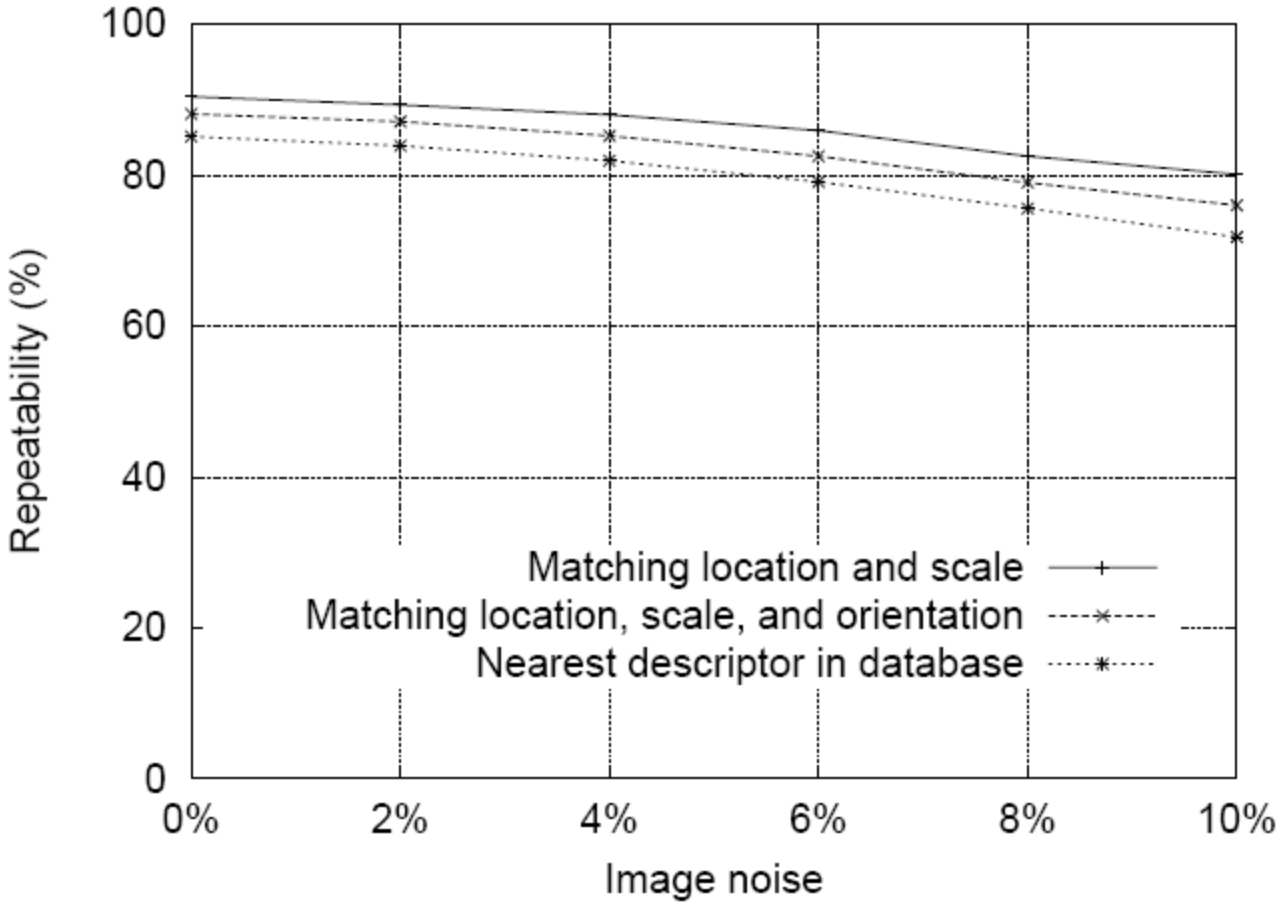
Speeded-Up Robust Features

Bay et al., ECCV 2006

(Both are patented; SURF has non-commercial license.)

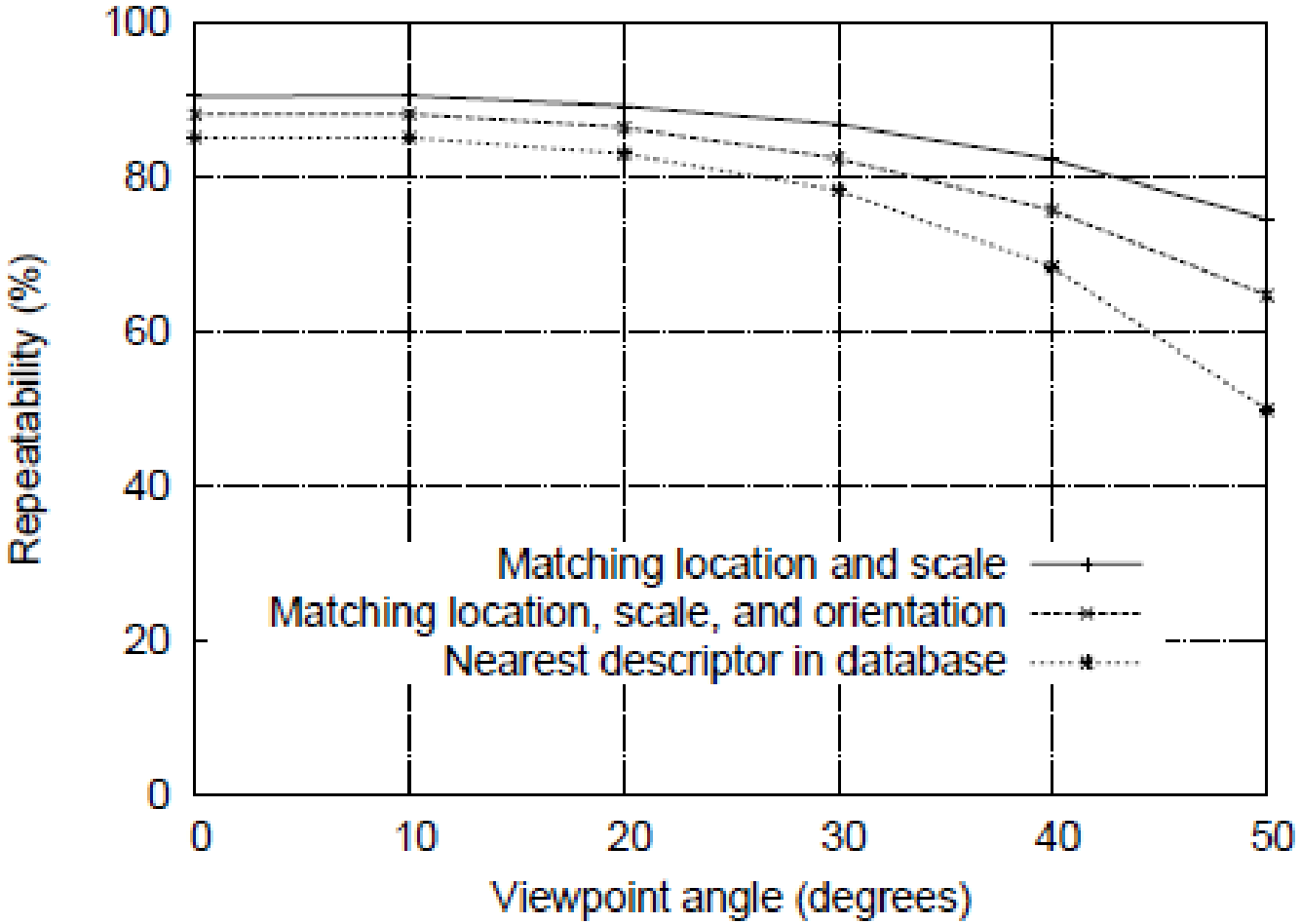
HOW GOOD IS SIFT?

SIFT Repeatability



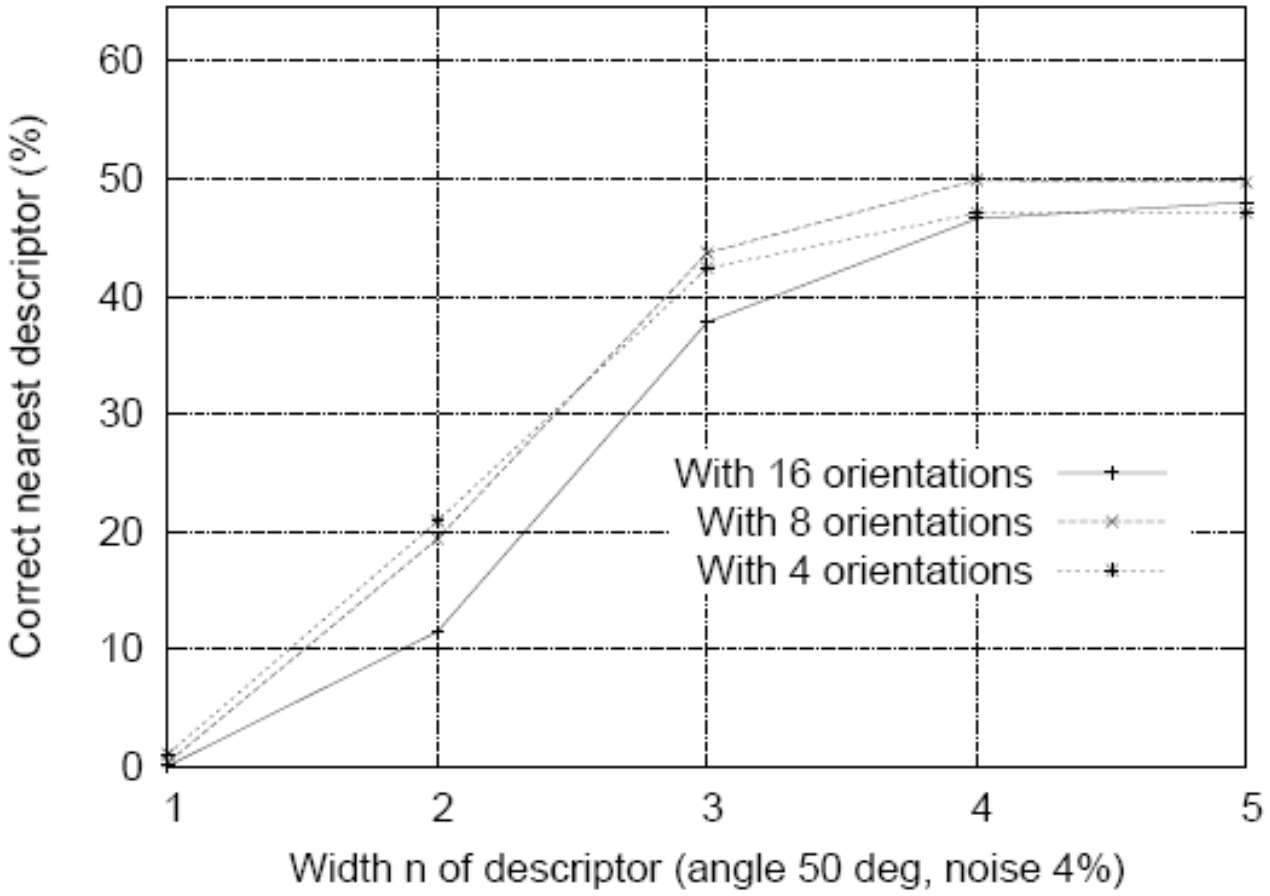
Lowe IJCV 2004

SIFT Repeatability



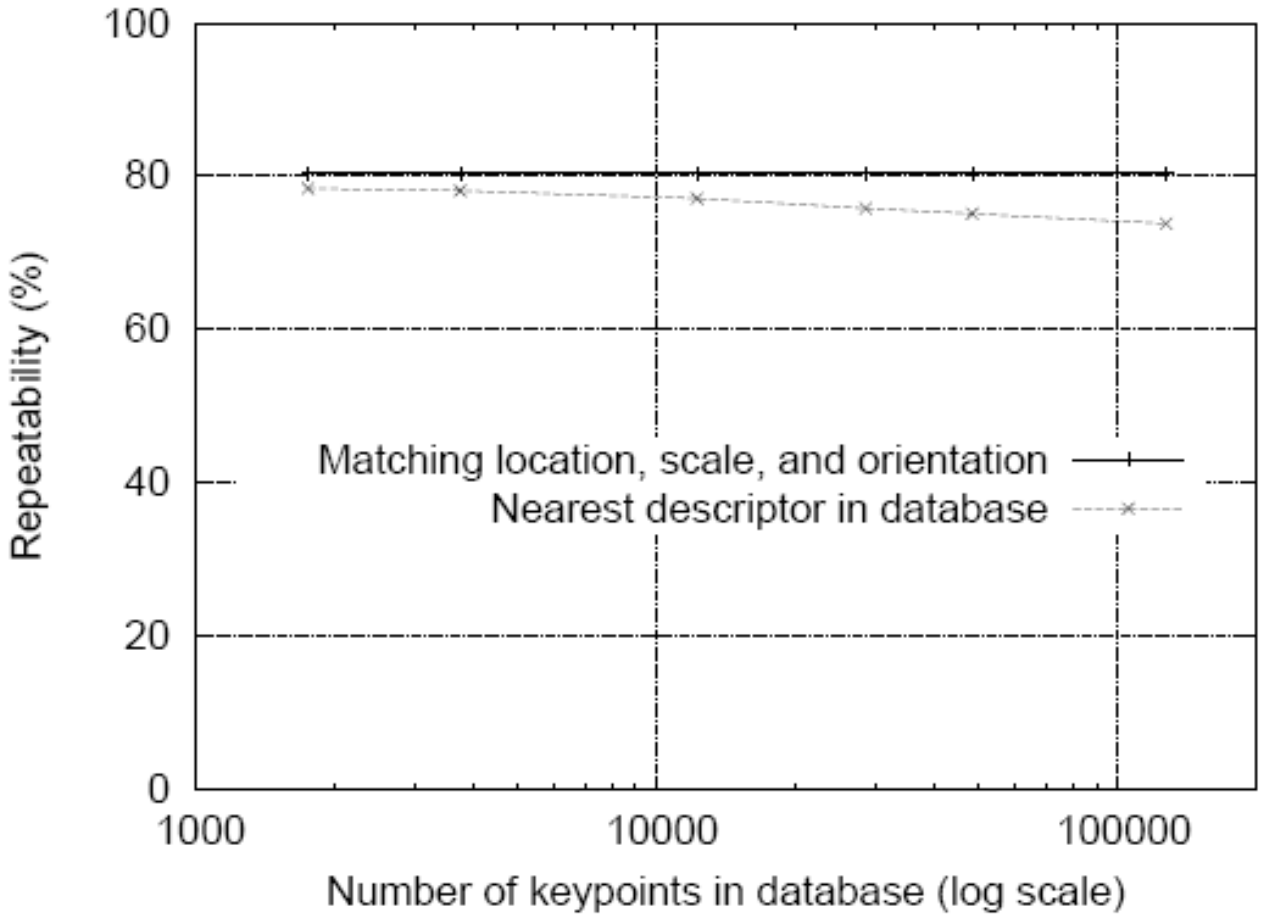
Lowe IJCV 2004

SIFT Repeatability



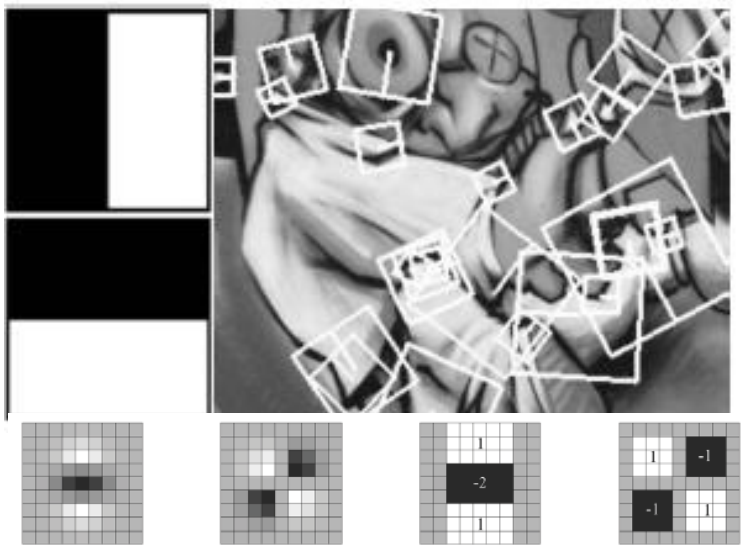
Lowe IJCV 2004

SIFT Repeatability



Lowe IJCV 2004

Local Descriptors: SURF



Fast approximation of SIFT idea

Efficient computation by 2D box filters & integral images

⇒ 6 times faster than SIFT

Equivalent quality for object identification

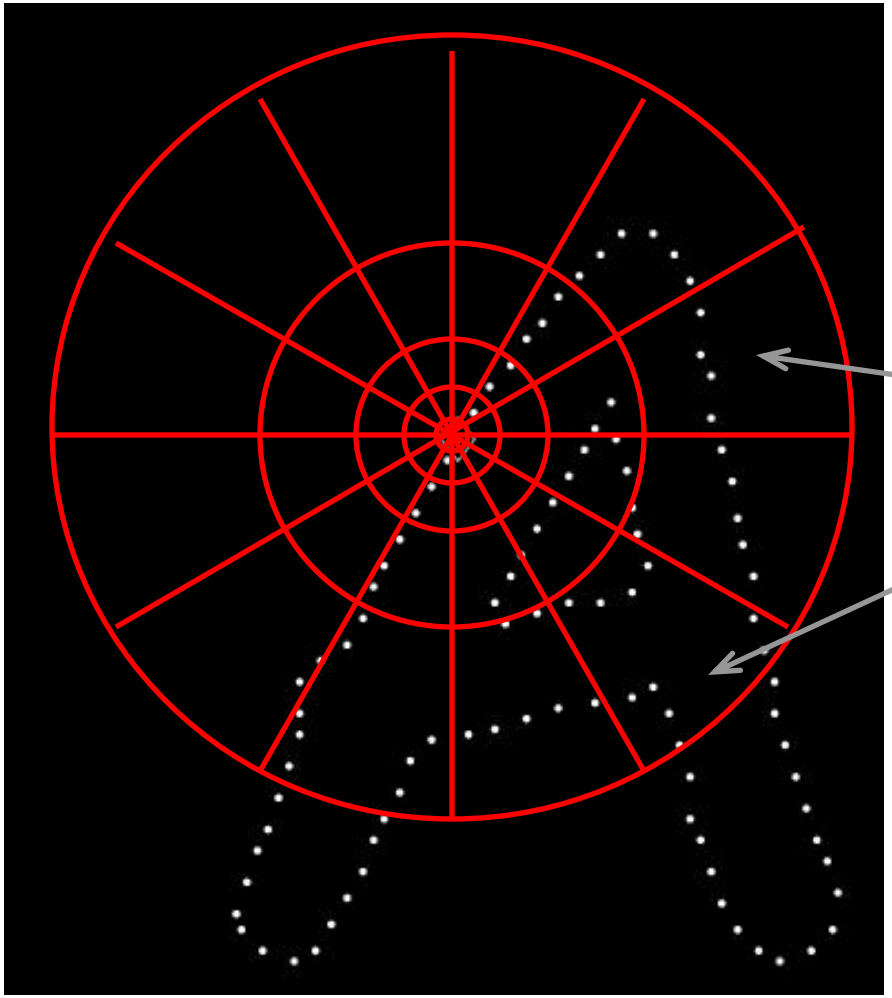
GPU implementation available

Feature extraction @ 200Hz (detector + descriptor, 640×480 img)

http://www.vision.ee.ethz.ch/~surf

[Bay, ECCV'06], [Cornelis, CVGPU'08]

Local Descriptors: Shape Context



Count the number of points inside each bin, e.g.:

Count = 4

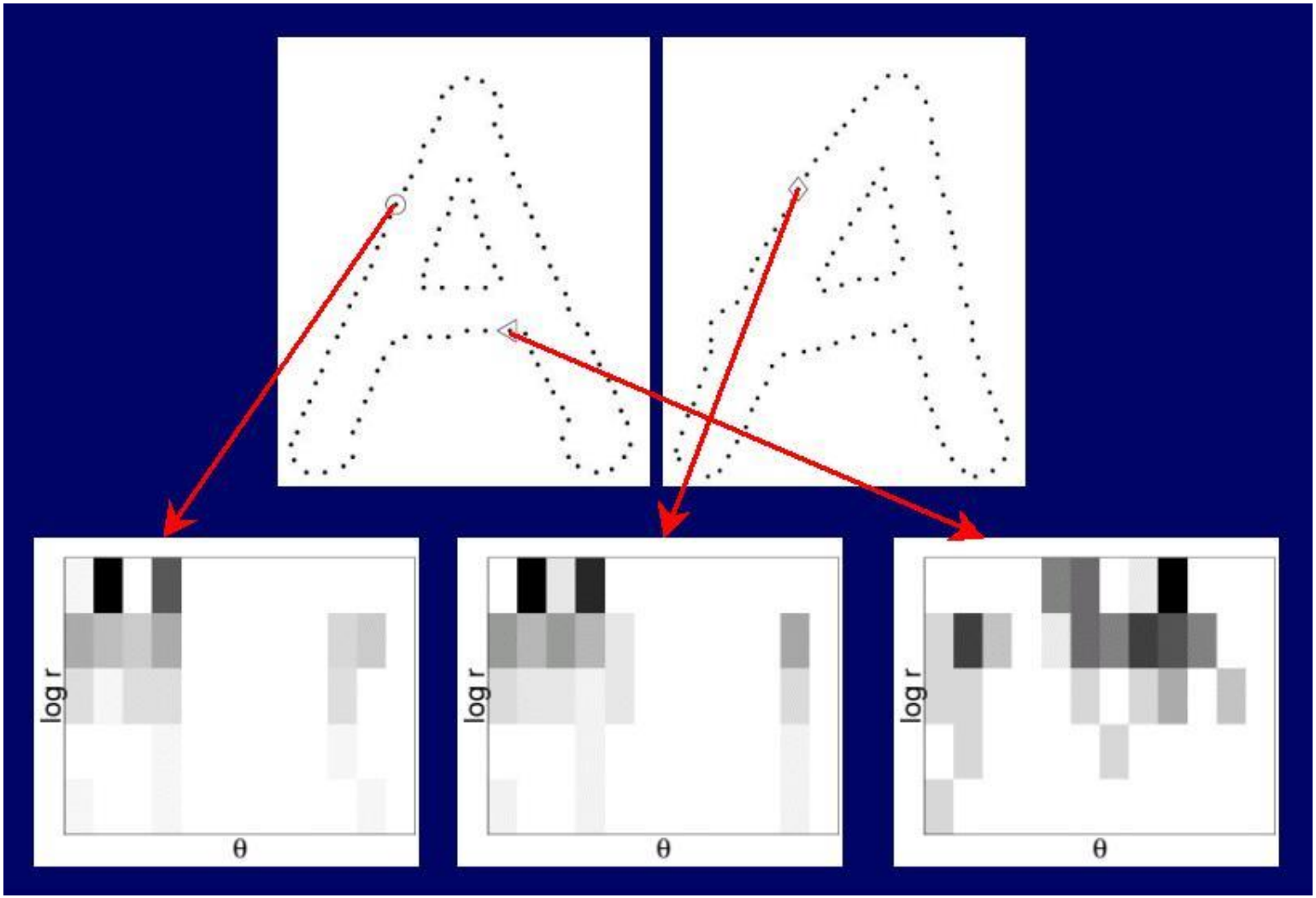
⋮

Count = 10

Log-polar binning:
More precision for nearby points, more flexibility for farther points.

Belongie & Malik, ICCV 2001

Shape Context Descriptor

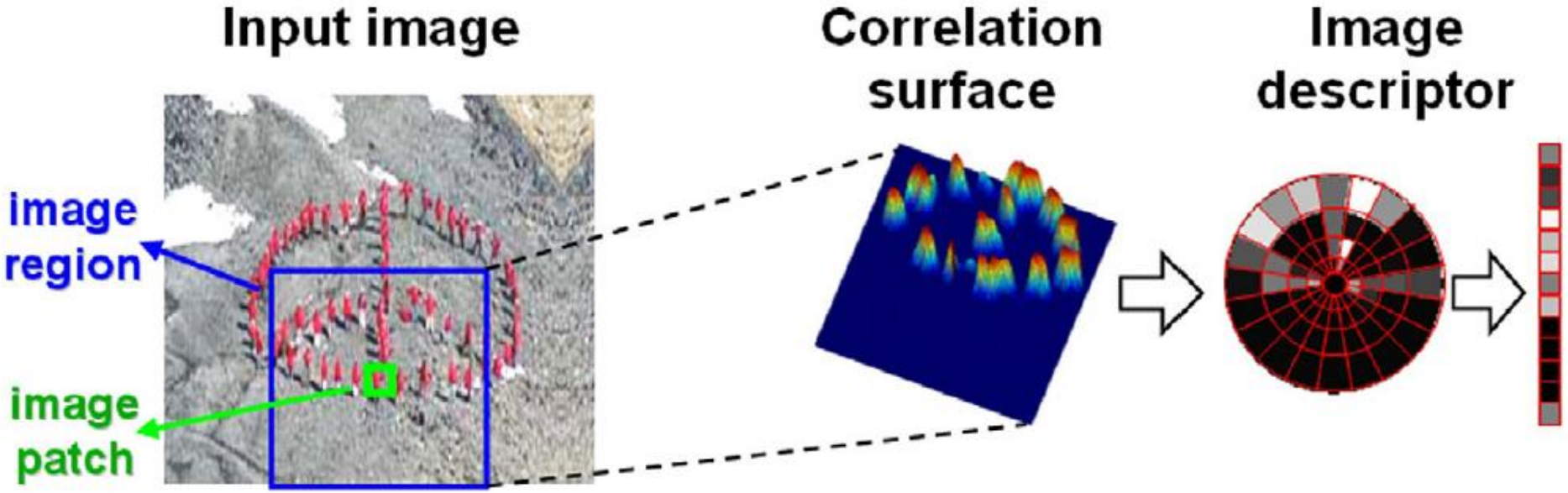


Self-similarity Descriptor

Figure 1. *These images of the same object (a heart) do NOT share common image properties (colors, textures, edges), but DO share a similar geometric layout of local internal self-similarities.*

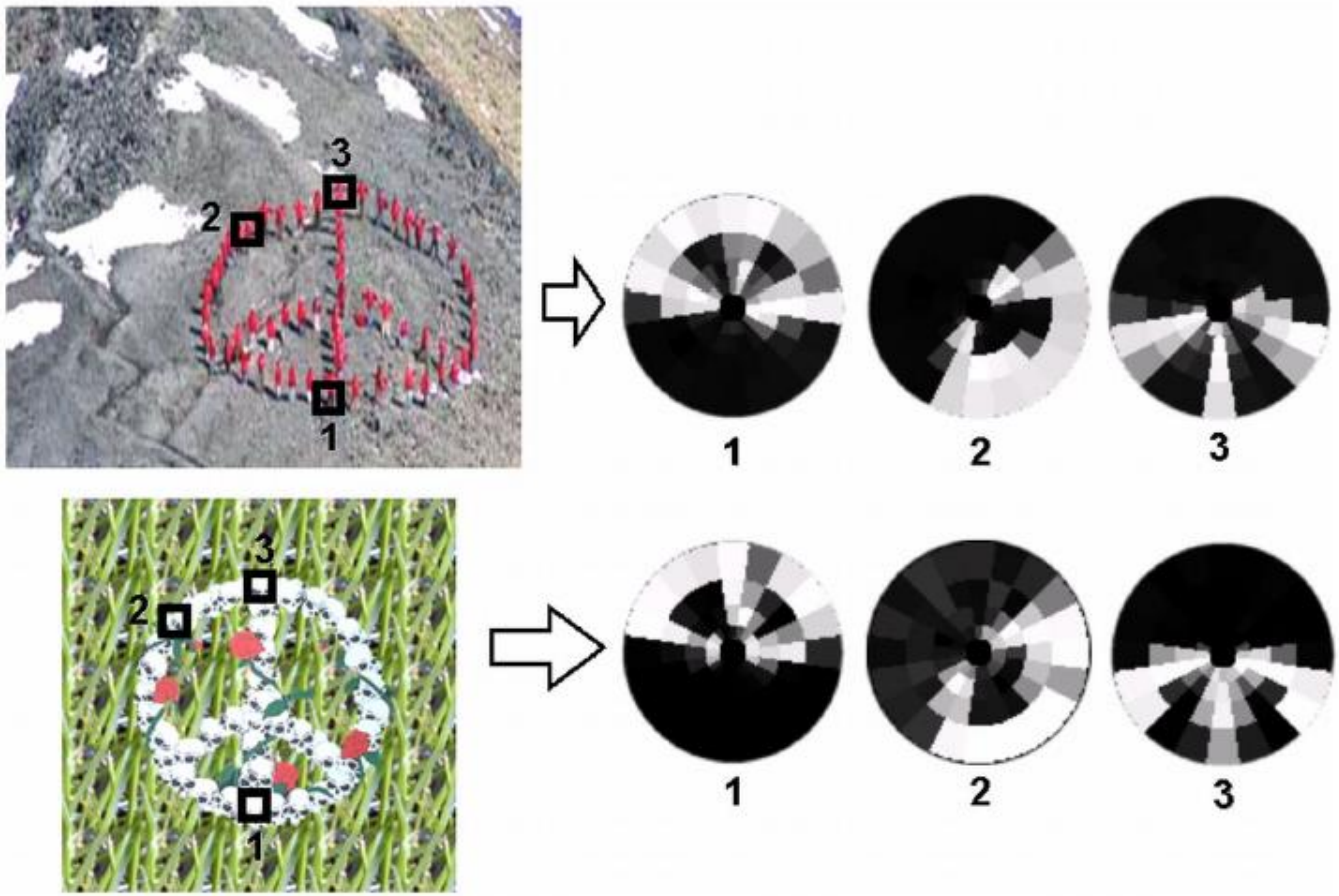
Matching Local Self-Similarities across Images and Videos, Shechtman and Irani, 2007

Self-similarity Descriptor



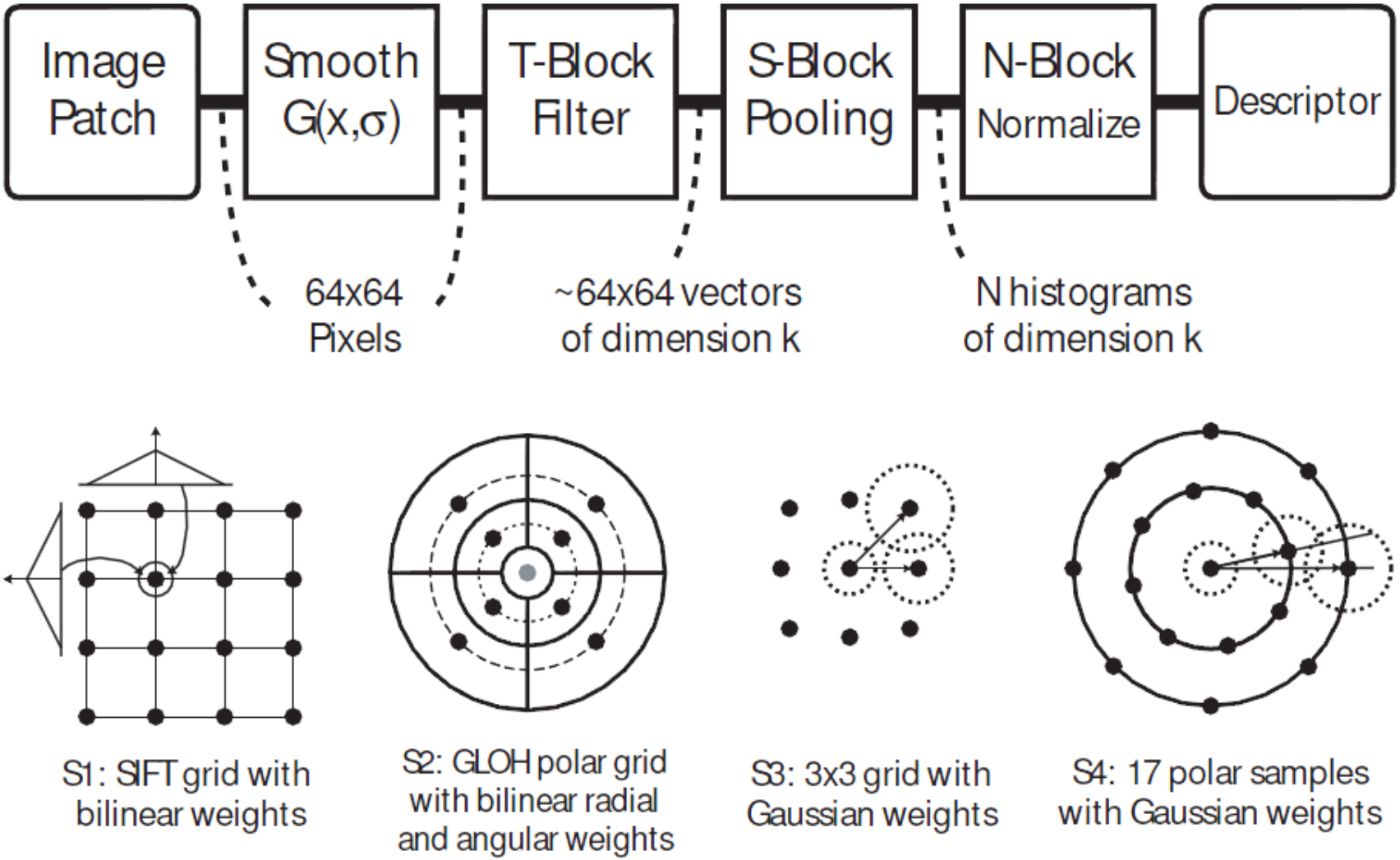
Matching Local Self-Similarities across Images and Videos, Shechtman and Irani, 2007

Self-similarity Descriptor



Matching Local Self-Similarities across Images and Videos, Shechtman and Irani, 2007

Learning Local Image Descriptors
Winder and Brown, 2007



Right features are application specific

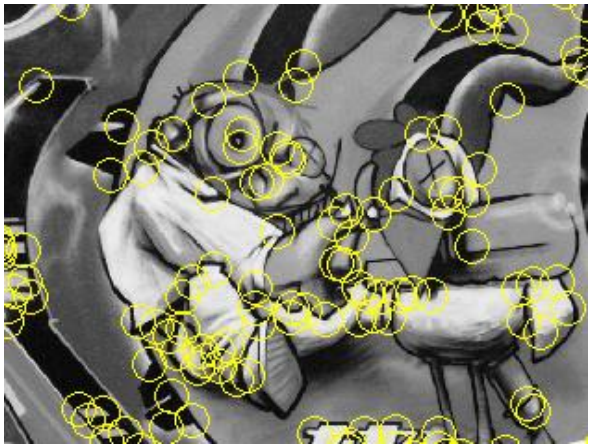
- Shape: scene-scale, object-scale, detail-scale
  - 2D form, shading, shadows, texture, linear perspective
- Material properties: albedo, feel, hardness, …
  - Color, texture
- Motion
  - Optical flow, tracked points
- Distance
  - Stereo, position, occlusion, scene shape
  - If known object: size, other objects

Available at a web site near you…

- Many local feature detectors have executables available online:
  - http://www.robots.ox.ac.uk/~vgg/research/affine
  - http://www.cs.ubc.ca/~lowe/keypoints/
  - http://www.vision.ee.ethz.ch/~surf

Review: Interest points

- Keypoint detection: repeatable and distinctive
  - Corners, blobs, stable regions
  - Harris, DoG



- Descriptors: robust and selective
  - Spatial histograms of orientation
  - SIFT