Corner detection continued

The correspondence problem

A general pipeline for correspondence

1. If sparse correspondences are enough, *choose points for which we will search for correspondences (feature points)*
2. For each point (or every pixel if dense correspondence), describe point using a *feature descriptor*
3. Find best matching descriptors across two images (*feature matching*)
4. Use feature matches to perform downstream task, e.g., pose estimation

Characteristics of good feature points

- Repeatability / invariance
  - The same feature point can be found in several images despite geometric and photometric transformations
- Saliency / distinctiveness
  - Each feature point is distinctive
  - Fewer ”false” matches

Goal: repeatability

- We want to detect (at least some of) the same points in both images.

No chance to find true matches!

- Yet we have to be able to run the detection procedure *independently* per image.

Kristen Grauman

Repeatability / invariance

- The feature detector should "fire" at consistent places in spite of rotation, translation etc.
- Changes to the underlying image (rotations, translations, deformations) shouldn't change where the detector "fires" : invariance

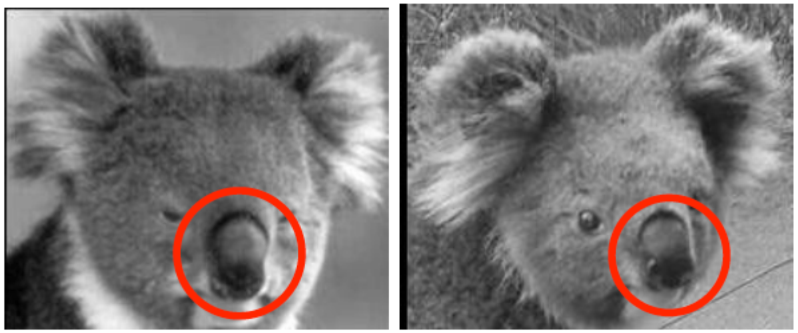


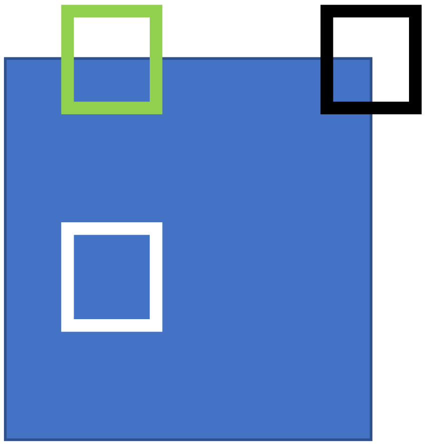
Image credit : L. Fei-Fei

Goal: distinctiveness

- The feature point should be distinctive enough that it is easy to match
  - Should *at least* be distinctive from other patches nearby

Distinctiveness

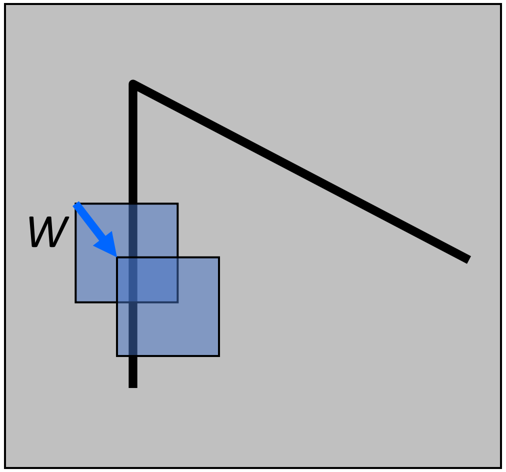
- Main idea: Translating window should cause large differences in patch appearance



Harris corner detection: the math

Consider shifting the window *W* by (*u,v*)

- how do the pixels in W change?
- compare each pixel before and after by summing up the squared differences (SSD)
- this defines an SSD "error" *E*(*u,v*):



$$E(u, v) = \sum_{(x,y)\in W} [I(x+u, y+v) - I(x, y)]^2$$

- We want E(u,v) to be *as high as possible for all u, v!*

Small motion assumption

Taylor Series expansion of *I*:

$$I(x+u, y+v) = I(x,y) + \frac{\partial I}{\partial x}u + \frac{\partial I}{\partial y}v + \text{higher order terms}$$

If the motion (u,v) is small, then first order approximation is good

$$\begin{aligned} I(x+u, y+v) &\approx I(x,y) + \frac{\partial I}{\partial x}u + \frac{\partial I}{\partial y}v \\ &\approx I(x,y) + [I_x \;\; I_y] \begin{bmatrix} u \\ v \end{bmatrix} \end{aligned}$$

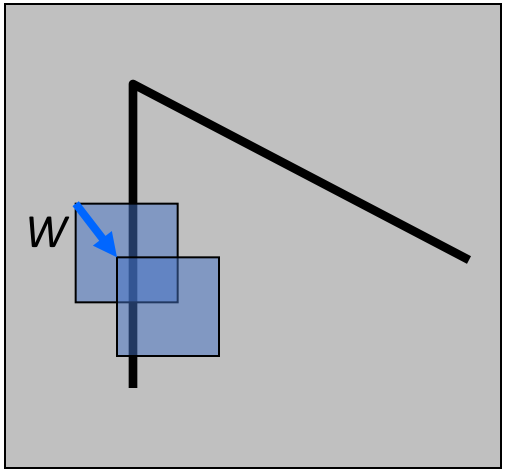
shorthand: $I_x = \frac{\partial I}{\partial x}$

Plugging this into the formula on the previous slide…

Corner detection: the math

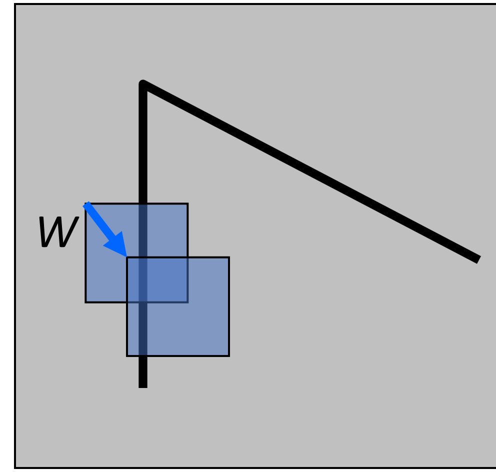
Consider shifting the window *W* by (*u,v*)

- define an SSD "error" *E(u,v)*:



$$
\begin{aligned}
E(u,v) &= \sum_{(x,y)\in W} \left[I(x+u,y+v) - I(x,y)\right]^2 \\
&\approx \sum_{(x,y)\in W} \left[I(x,y) + I_x u + I_y v - I(x,y)\right]^2 \\
&\approx \sum_{(x,y)\in W} \left[I_x u + I_y v\right]^2
\end{aligned}
$$

Corner detection: the math



Consider shifting the window *W* by (*u*,*v*)

- define an "error" *E(u,v)*:

$$E(u,v) \approx \sum_{(x,y)\in W} [I_x u + I_y v]^2$$

$$\approx Au^2 + 2Buv + Cv^2$$

$$A = \sum_{(x,y)\in W} I_x^2 \qquad B = \sum_{(x,y)\in W} I_x I_y \qquad C = \sum_{(x,y)\in W} I_y^2$$

- Thus, *E*(*u*,*v*) is locally approximated as a quadratic error function

Interpreting the second moment matrix

Recall that we want E(u,v) to be as large as possible for all u,v

What does this mean in terms of M?

$$E(u,v) \approx [u \ v] \ M \begin{bmatrix} u \\ v \end{bmatrix}$$

$$\underbrace{M = \sum_{x,y} w(x,y) \begin{bmatrix} I_x^2 & I_x I_y \\ I_x I_y & I_y^2 \end{bmatrix}}_{\text{Second moment matrix}}$$

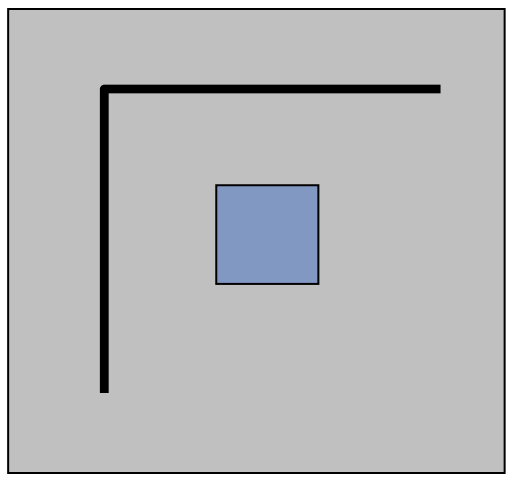
Second moment matrix

$$E(u,v) \approx \begin{bmatrix} u & v \end{bmatrix} \underbrace{\begin{bmatrix} A & B \\ B & C \end{bmatrix}}_{M} \begin{bmatrix} u \\ v \end{bmatrix}$$

$$A = \sum_{(x,y) \in W} I_x^2$$

$$B = \sum_{(x,y) \in W} I_x I_y$$

$$C = \sum_{(x,y) \in W} I_y^2$$



Flat patch: $I_x = 0$

$I_y = 0$

$$M = \begin{bmatrix} 0 & 0 \\ 0 & 0 \end{bmatrix}$$

$$M \begin{bmatrix} u \\ v \end{bmatrix} = \begin{bmatrix} 0 \\ 0 \end{bmatrix}$$

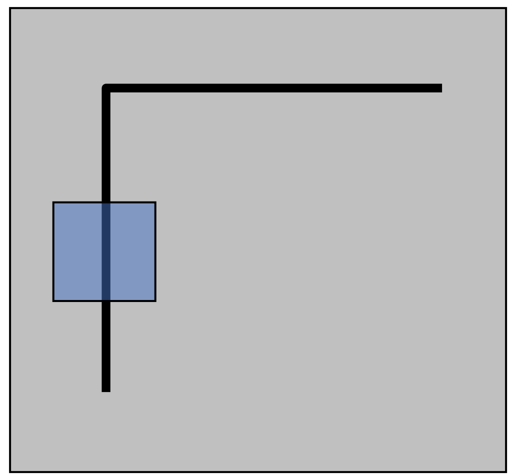
$$E(u,v) = 0 \quad \forall u, v$$

$$E(u,v) \approx \begin{bmatrix} u & v \end{bmatrix} \underbrace{\begin{bmatrix} A & B \\ B & C \end{bmatrix}}_{M} \begin{bmatrix} u \\ v \end{bmatrix}$$

$$A = \sum_{(x,y)\in W} I_x^2$$

$$B = \sum_{(x,y)\in W} I_x I_y$$

$$C = \sum_{(x,y)\in W} I_y^2$$



Vertical edge: $I_y = 0$

$$M = \begin{bmatrix} A & 0 \\ 0 & 0 \end{bmatrix}$$

$$M \begin{bmatrix} 0 \\ v \end{bmatrix} = \begin{bmatrix} 0 \\ 0 \end{bmatrix}$$

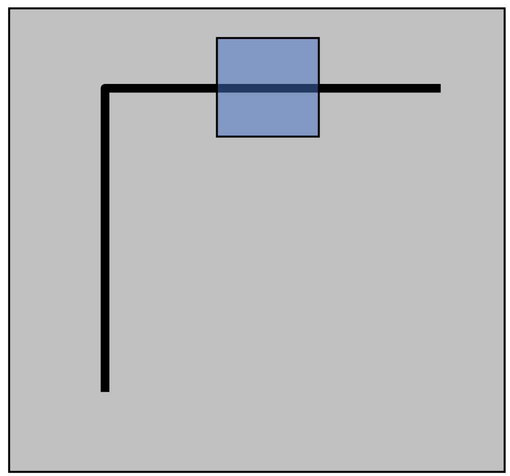
$$E(0,v) = 0 \;\; \forall v$$

$$E(u,v) \approx \begin{bmatrix} u & v \end{bmatrix} \underbrace{\begin{bmatrix} A & B \\ B & C \end{bmatrix}}_{M} \begin{bmatrix} u \\ v \end{bmatrix}$$

$$A = \sum_{(x,y)\in W} I_x^2$$

$$B = \sum_{(x,y)\in W} I_x I_y$$

$$C = \sum_{(x,y)\in W} I_y^2$$



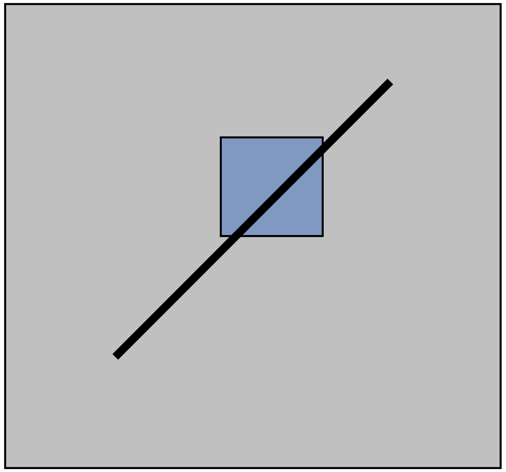
Horizontal edge: $I_x = 0$

$$M = \begin{bmatrix} 0 & 0 \\ 0 & C \end{bmatrix}$$

$$M \begin{bmatrix} u \\ 0 \end{bmatrix} = \begin{bmatrix} 0 \\ 0 \end{bmatrix}$$

$$E(u,0) = 0 \ \forall u$$

What about edges in arbitrary orientation?



$$E(u,v) \approx \begin{bmatrix} u & v \end{bmatrix} M \begin{bmatrix} u \\ v \end{bmatrix}$$

$$M \begin{bmatrix} u \\ v \end{bmatrix} = \begin{bmatrix} 0 \\ 0 \end{bmatrix} \Rightarrow E(u,v) = 0$$

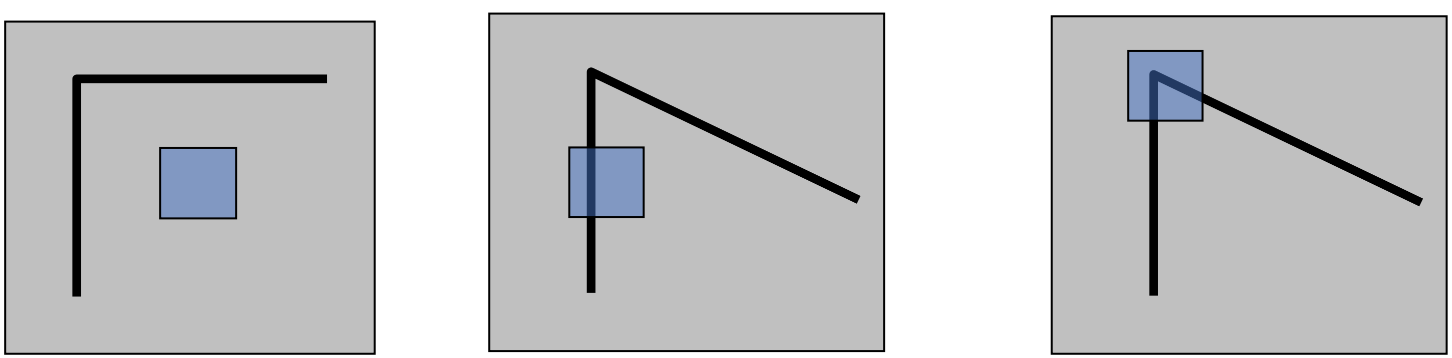
$$M \begin{bmatrix} u \\ v \end{bmatrix} = \begin{bmatrix} 0 \\ 0 \end{bmatrix} \Leftrightarrow E(u,v) = 0$$

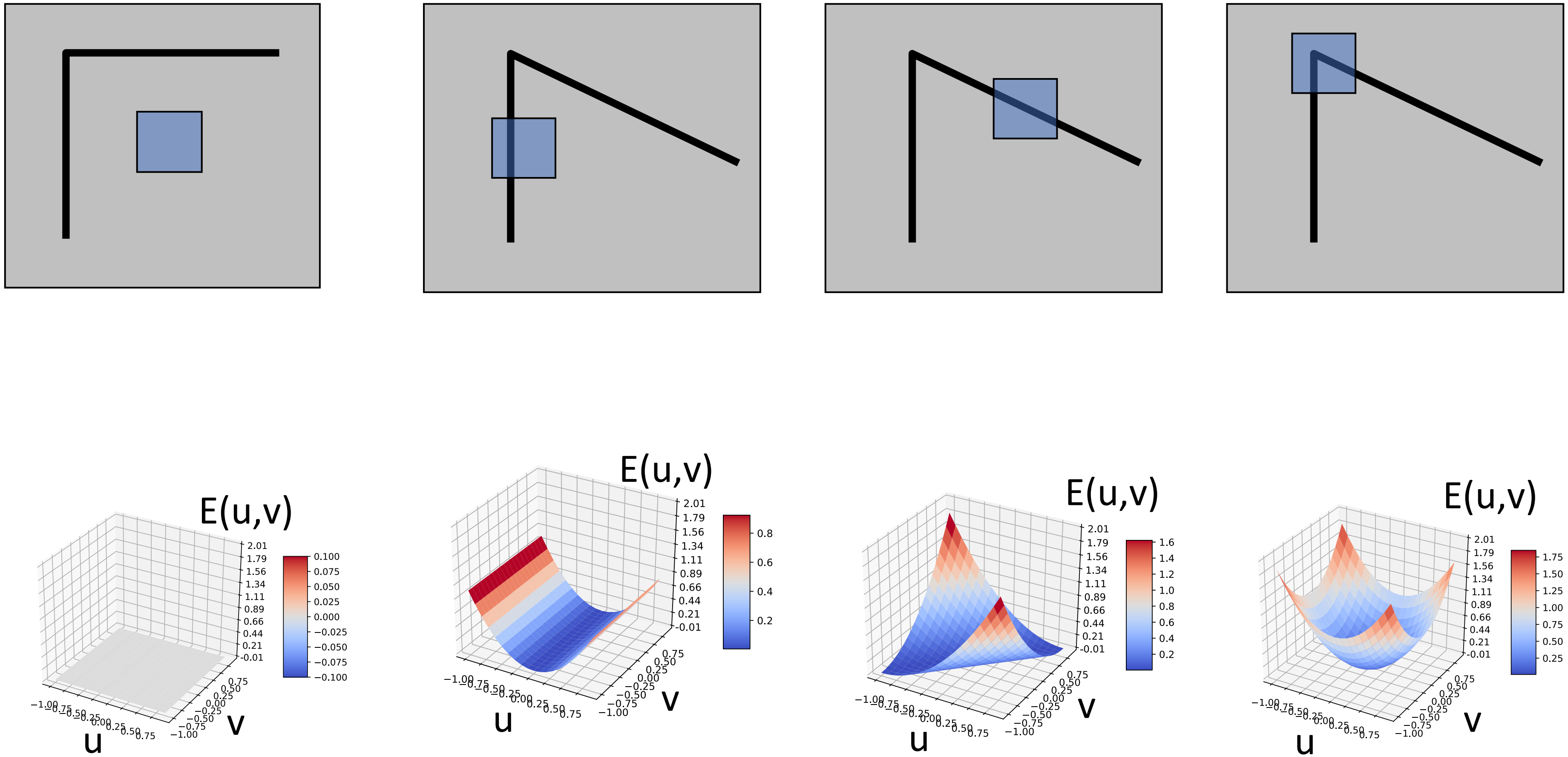
Solutions to Mx = 0 are directions for which E is 0: window can slide in this direction without changing appearance

$$E(u,v) \approx \begin{bmatrix} u & v \end{bmatrix} M \begin{bmatrix} u \\ v \end{bmatrix}$$

Solutions to Mx = 0 are directions for which E is 0: window can slide in this direction without changing appearance

For corners, we want no such directions to exist



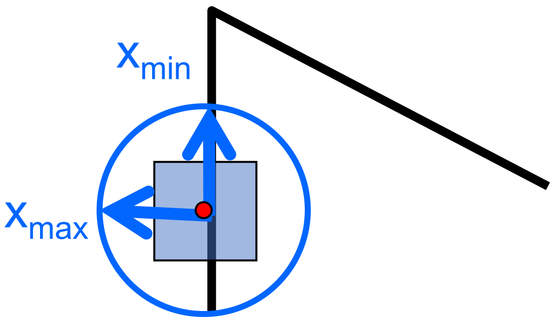

E(u,v)
u
v
E(u,v)
u
v
E(u,v)
u
v
E(u,v)
u
v

Eigenvalues and eigenvectors of M

- $Mx = 0 \Rightarrow Mx = \lambda x$: x is an eigenvector of M with eigenvalue 0
- M is 2 x 2, so it has 2 eigenvalues $(\lambda_{max}, \lambda_{min})$ with eigenvectors (x_{max}, x_{min})
- $E(x_{max}) = \ x_{max}^T M x_{max} = \lambda_{max} ||x_{max}||^2 = \lambda_{max}$ (eigenvectors have unit norm)
- $E(x_{min}) = x_{min}^T M x_{min} = \lambda_{min} ||x_{min}||^2 = \lambda_{min}$

Eigenvalues and eigenvectors of M

$$E(u,v) \approx \begin{bmatrix} u & v \end{bmatrix} M \begin{bmatrix} u \\ v \end{bmatrix}$$



M $\text{ax} = \lambda_{\text{max}} x_{\text{max}}$

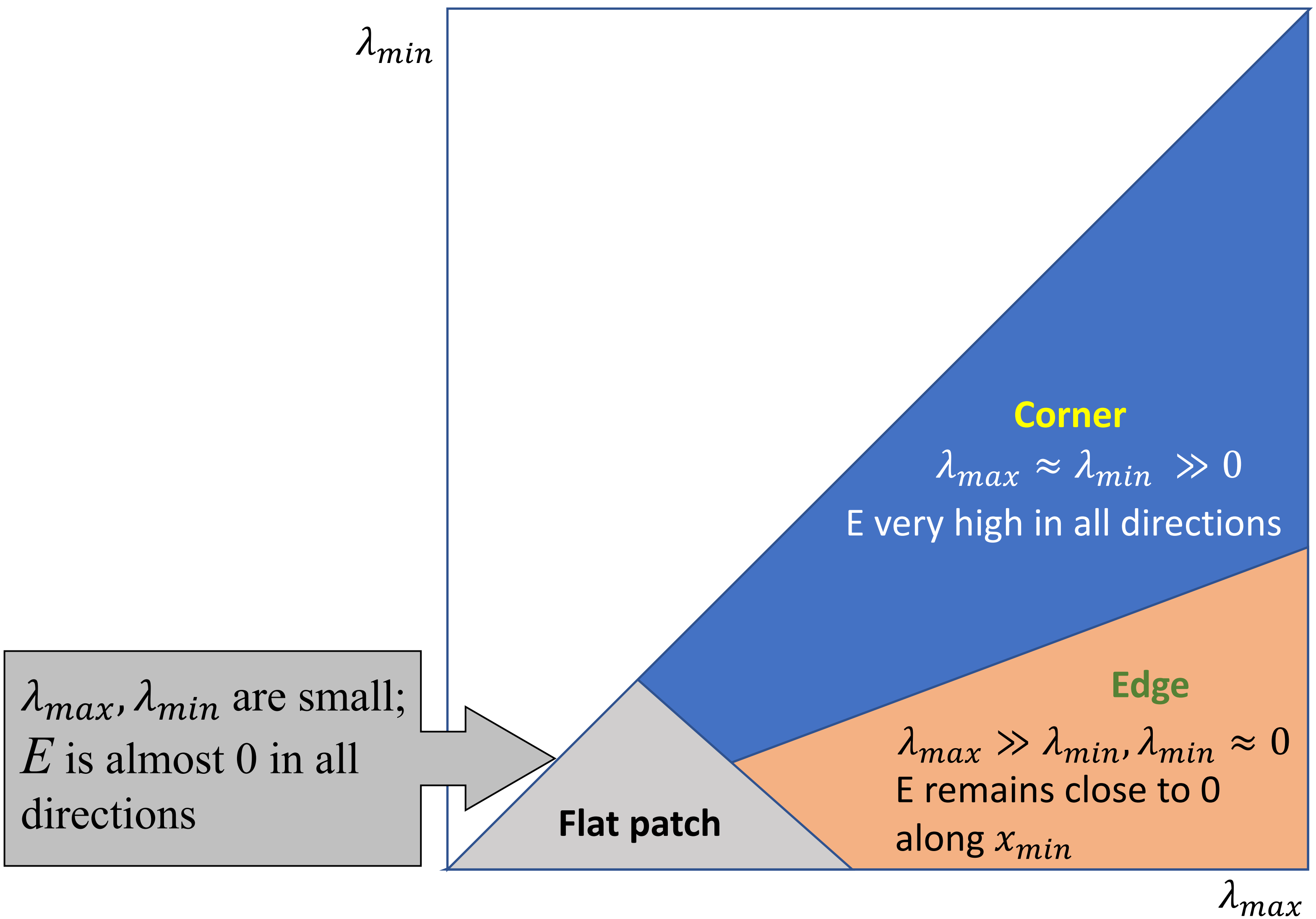
$\text{in} = \lambda_{\text{min}} x_{\text{min}}$

M

Eigenvalues and eigenvectors of M

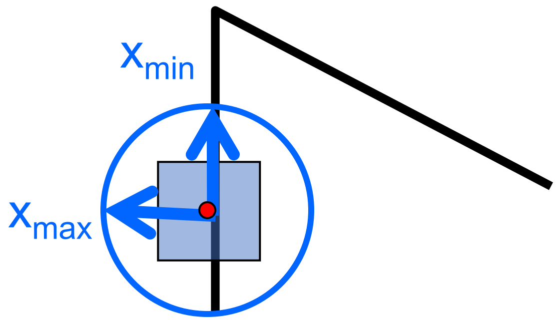
- Define shift directions with the smallest and largest change in error
- x_{max} = direction of largest increase in *E*
- λ_{max} = amount of increase in direction x_{max}
- x_{min} = direction of smallest increase in *E*
- λ_{min} = amount of increase in direction x_{min}

Interpreting the eigenvalues



Eigenvalues and eigenvectors of M

$$E(u,v) \approx \begin{bmatrix} u & v \end{bmatrix} M \begin{bmatrix} u \\ v \end{bmatrix}$$



$$M\, x_{\max} = \lambda_{\max} x_{\max}$$

$$M\, x_{\min} = \lambda_{\min} x_{\min}$$

Eigenvalues and eigenvectors of M

- Define shift directions with the smallest and largest change in error
- x_{max} = direction of largest increase in *E*
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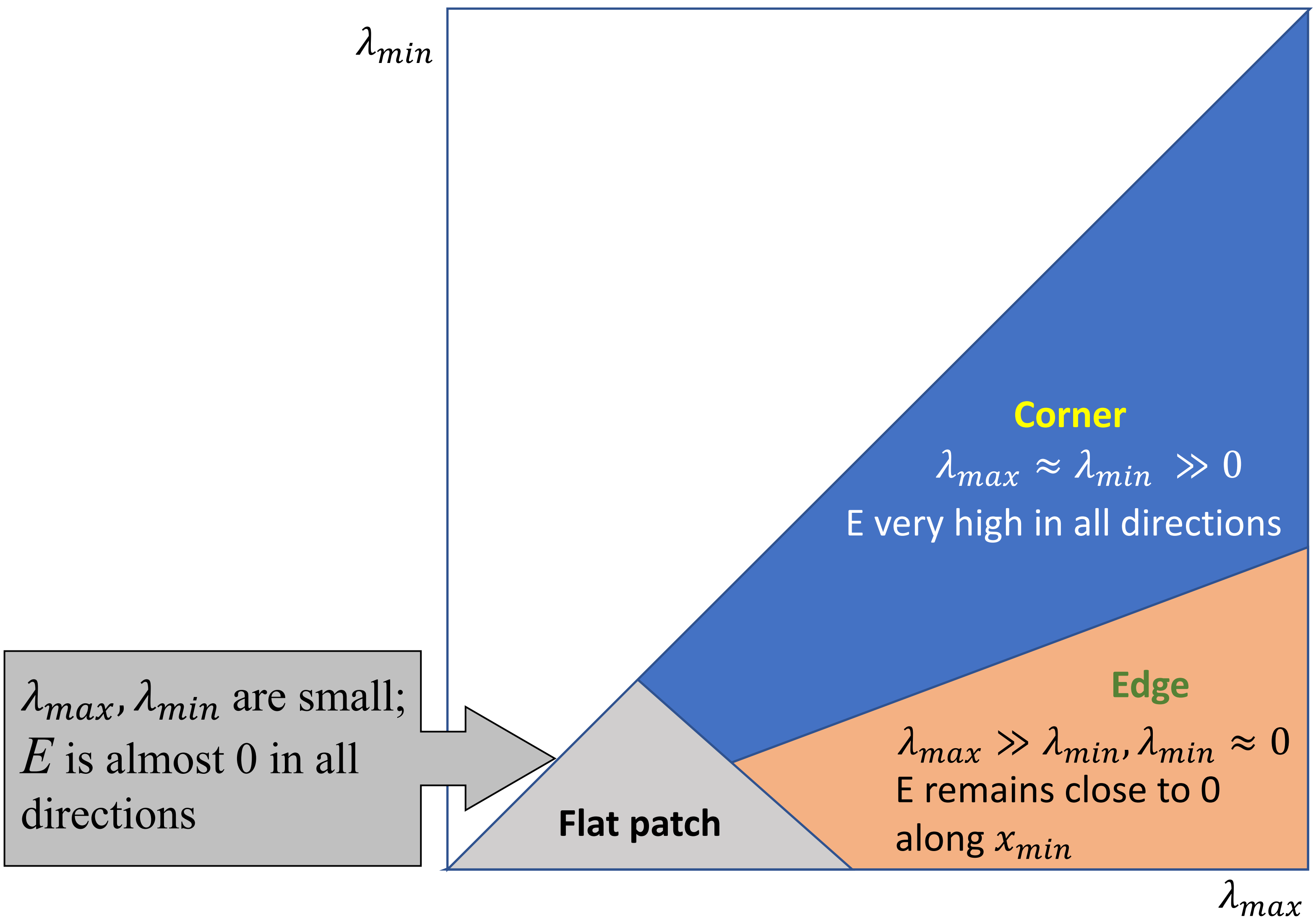
Interpreting the eigenvalues



Corner detection: the math

How are λ_{max}, x_{max}, λ_{min}, and x_{min} relevant for feature detection?

- Need a feature scoring function

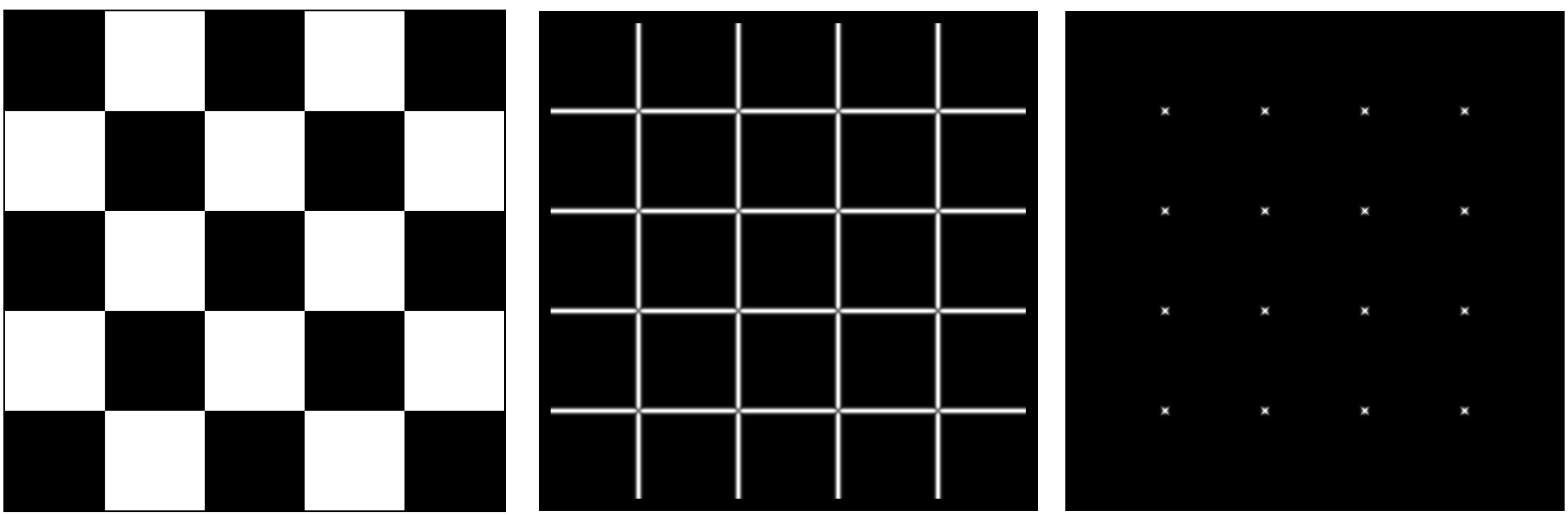
Corner detection: the math

How are λ_{max}, x_{max}, λ_{min}, and x_{min} relevant for feature detection?

- Need a feature scoring function

Want $E(u,v)$ to be large for small shifts in all directions

- the minimum of $E(u,v)$ should be large, over all unit vectors $[u\ v]$
- this minimum is given by the smaller eigenvalue (λ_{min}) of M

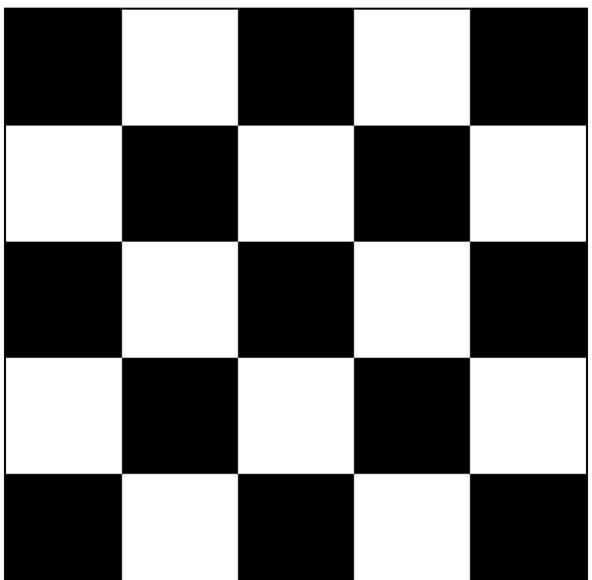


I $\quad$ $\lambda_{\max}$ $\quad$ $\lambda_{\min}$

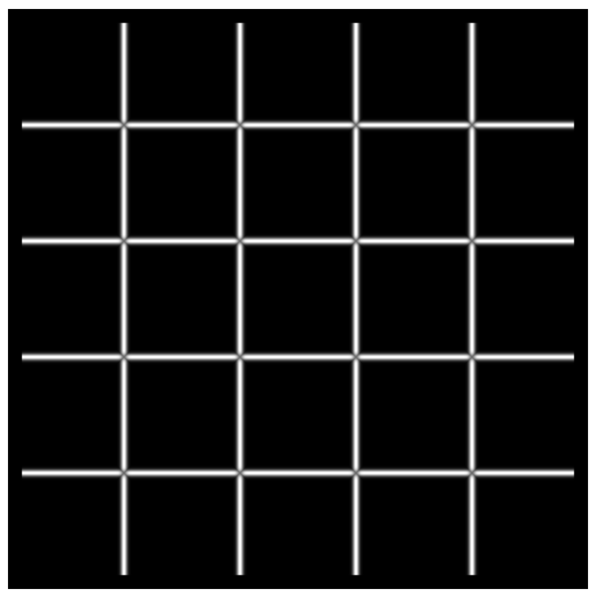
Corner detection summary

Here's what you do

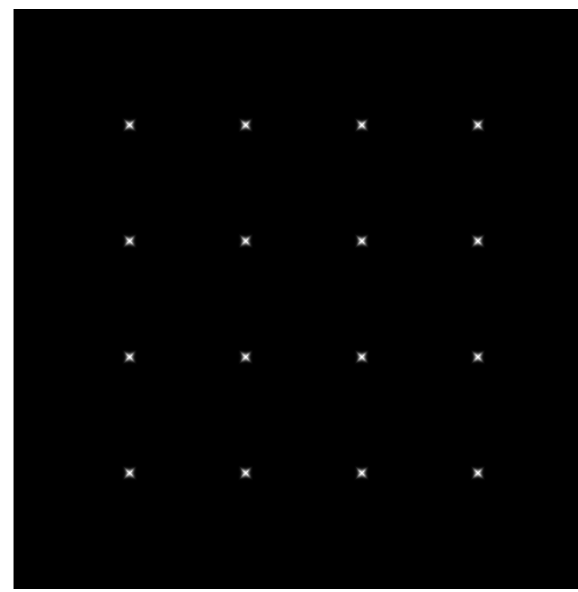
- Compute the gradient at each point in the image
- Create the *M* matrix from the entries in the gradient
- Compute the eigenvalues
- Find points with large response (λ_{min} > threshold)
- Choose those points where λ_{min} is a local maximum as features



I



$\lambda_{\max}$

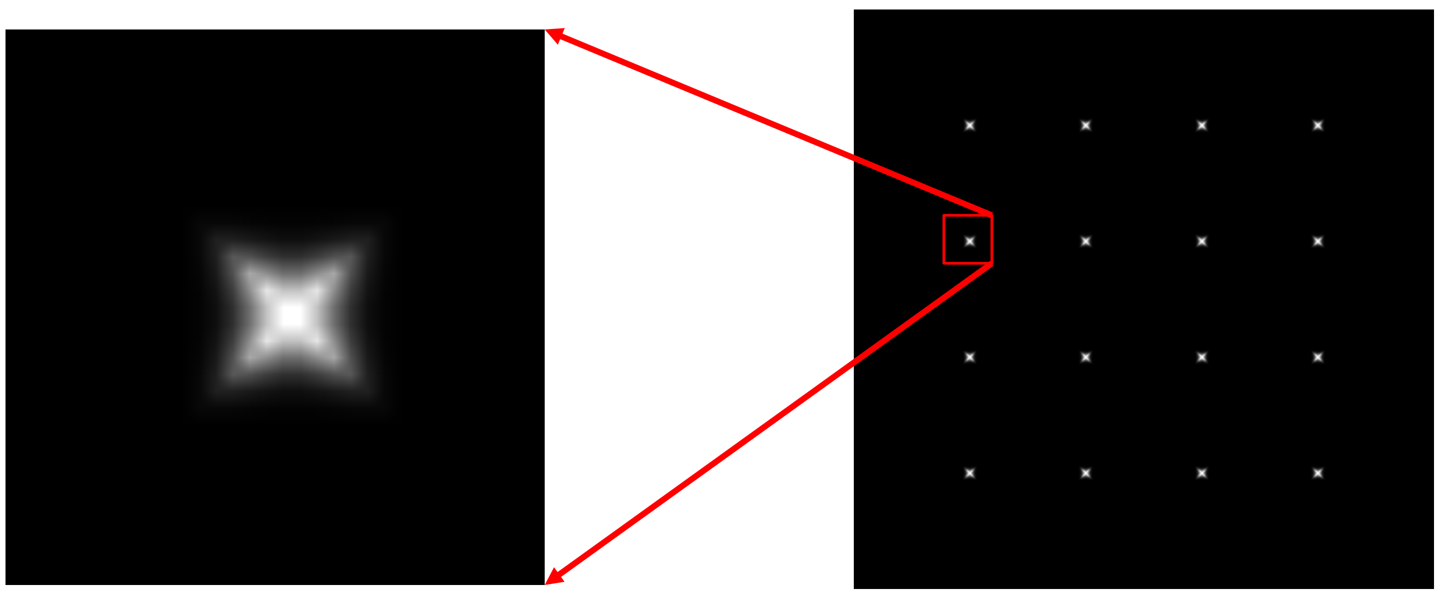


$\lambda_{\min}$

Corner detection summary

Here's what you do

- Compute the gradient at each point in the image
- Create the *H* matrix from the entries in the gradient
- Compute the eigenvalues.
- Find points with large response (λ_{min} > threshold)
- Choose those points where λ_{min} is a local maximum as features



$\lambda_{\min}$

The Harris operator

λ_{min} is a variant of the "Harris operator" for feature detection

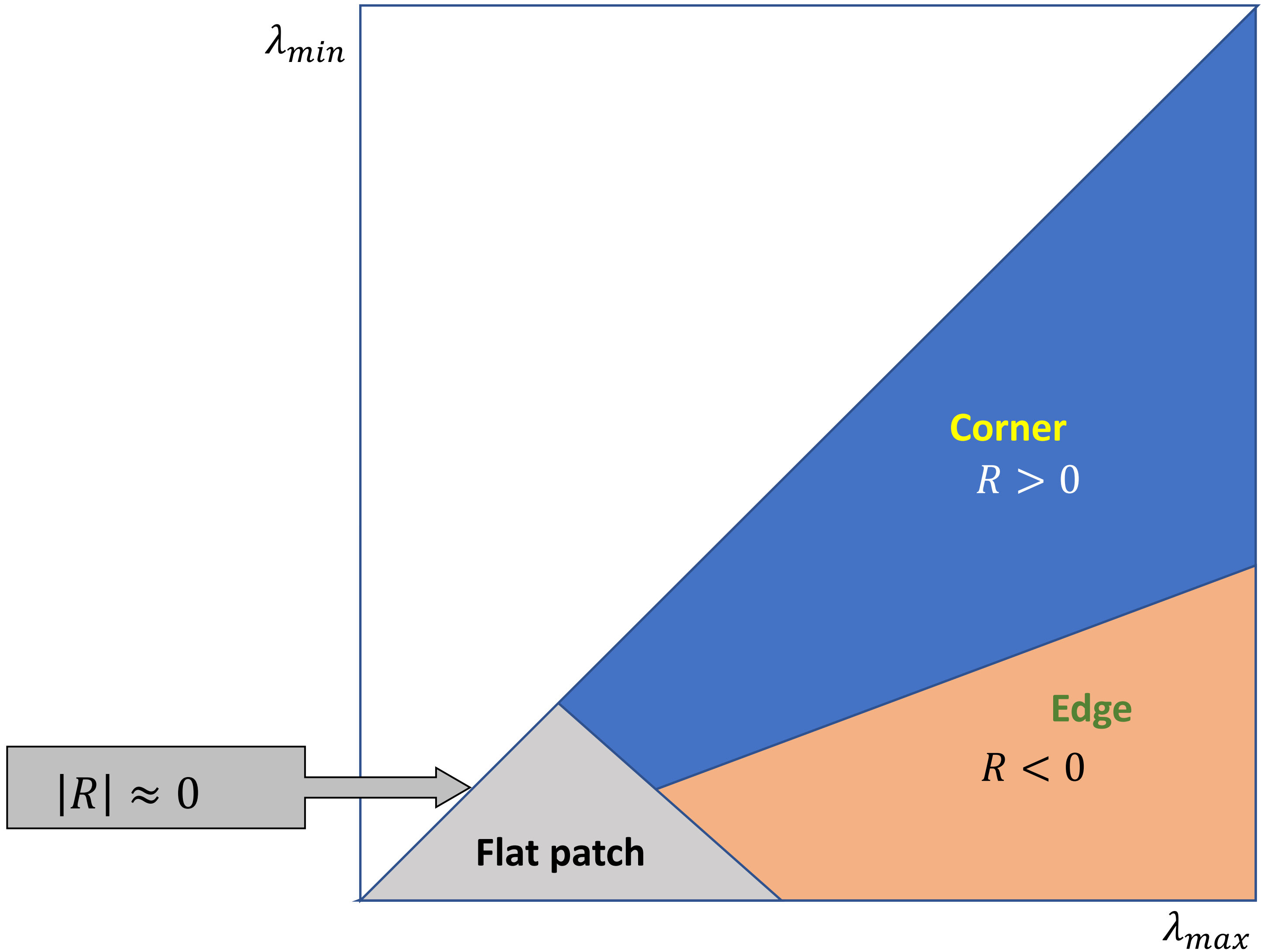
$$f = \frac{\lambda_1 \lambda_2}{\lambda_1 + \lambda_2}$$

$$= \frac{determinant(H)}{trace(H)}$$

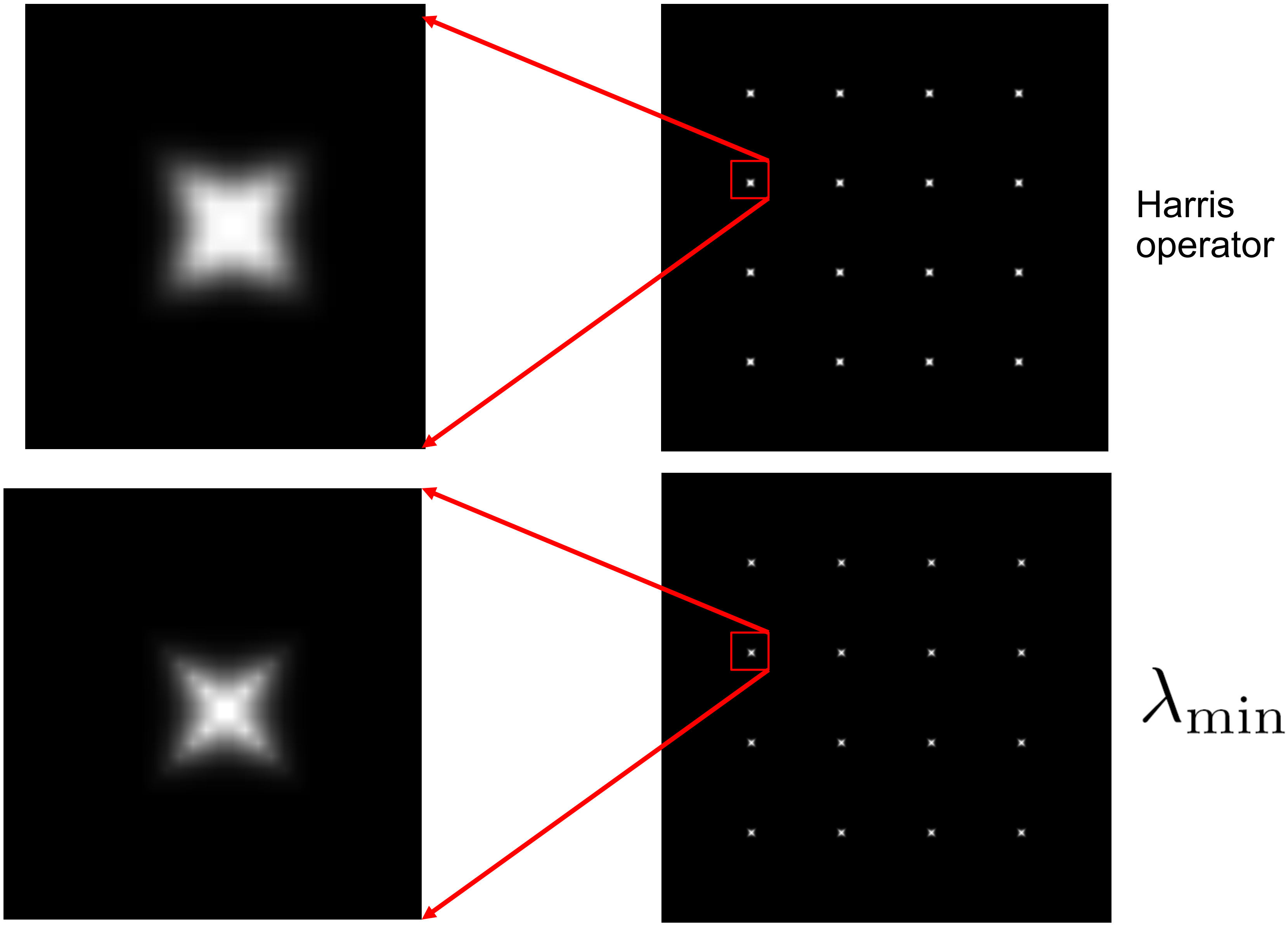
- The *trace* is the sum of the diagonals, i.e., $trace(H) = h_{11} + h_{22}$
- Very similar to λ_{min} but less expensive (no square root)
- Called the "Harris Corner Detector" or "Harris Operator"
  - Actually the Noble variant of the Harris Corner Detector
- Lots of other detectors, this is one of the most popular

Corner response function

$$R = \det(M) - \alpha\, \mathrm{trace}(M)^2 = \lambda_1\lambda_2 - \alpha(\lambda_1 + \lambda_2)^2$$

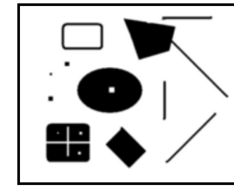


The Harris operator



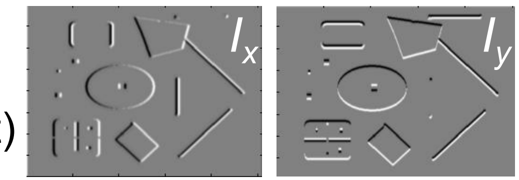
Harris Detector [Harris88]

- Second moment matrix



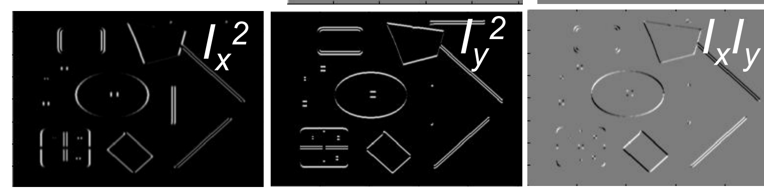
$$\mu(\sigma_I,\sigma_D)=g(\sigma_I)*\begin{bmatrix} I_x^2(\sigma_D) & I_xI_y(\sigma_D) \\ I_xI_y(\sigma_D) & I_y^2(\sigma_D)\end{bmatrix}$$

1. Image derivatives (optionally, blur first)



$$\det M = \lambda_1\lambda_2$$
$$\operatorname{trace} M = \lambda_1 + \lambda_2$$

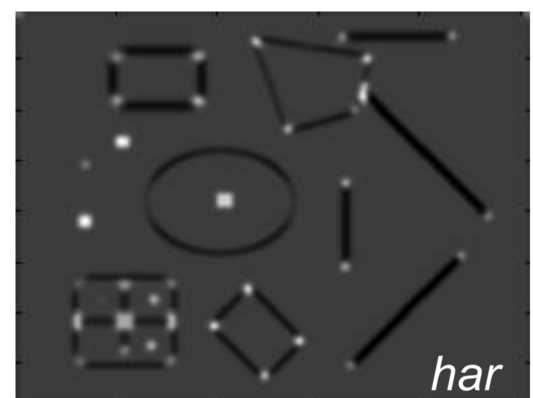
2. Square of derivatives



3. Gaussian filter $g(\sigma_I)$

4. Cornerness function – both eigenvalues are strong

$$har = \det[\mu(\sigma_I,\sigma_D)] - \alpha[\operatorname{trace}(\mu(\sigma_I,\sigma_D))^2] =$$
$$g(I_x^2)g(I_y^2) - [g(I_xI_y)]^2 - \alpha[g(I_x^2)+g(I_y^2)]^2$$



5. Non-maxima suppression

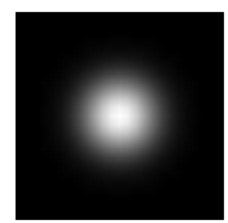
Weighting the derivatives

- In practice, using a simple window *W* doesn't work too well

$$H = \sum_{(x,y) \in W} \left[\begin{array}{cc} I_x^2 & I_x I_y \\ I_x I_y & I_y^2 \end{array} \right]$$

- Instead, we'll *weight* each derivative value based on its distance from the center pixel

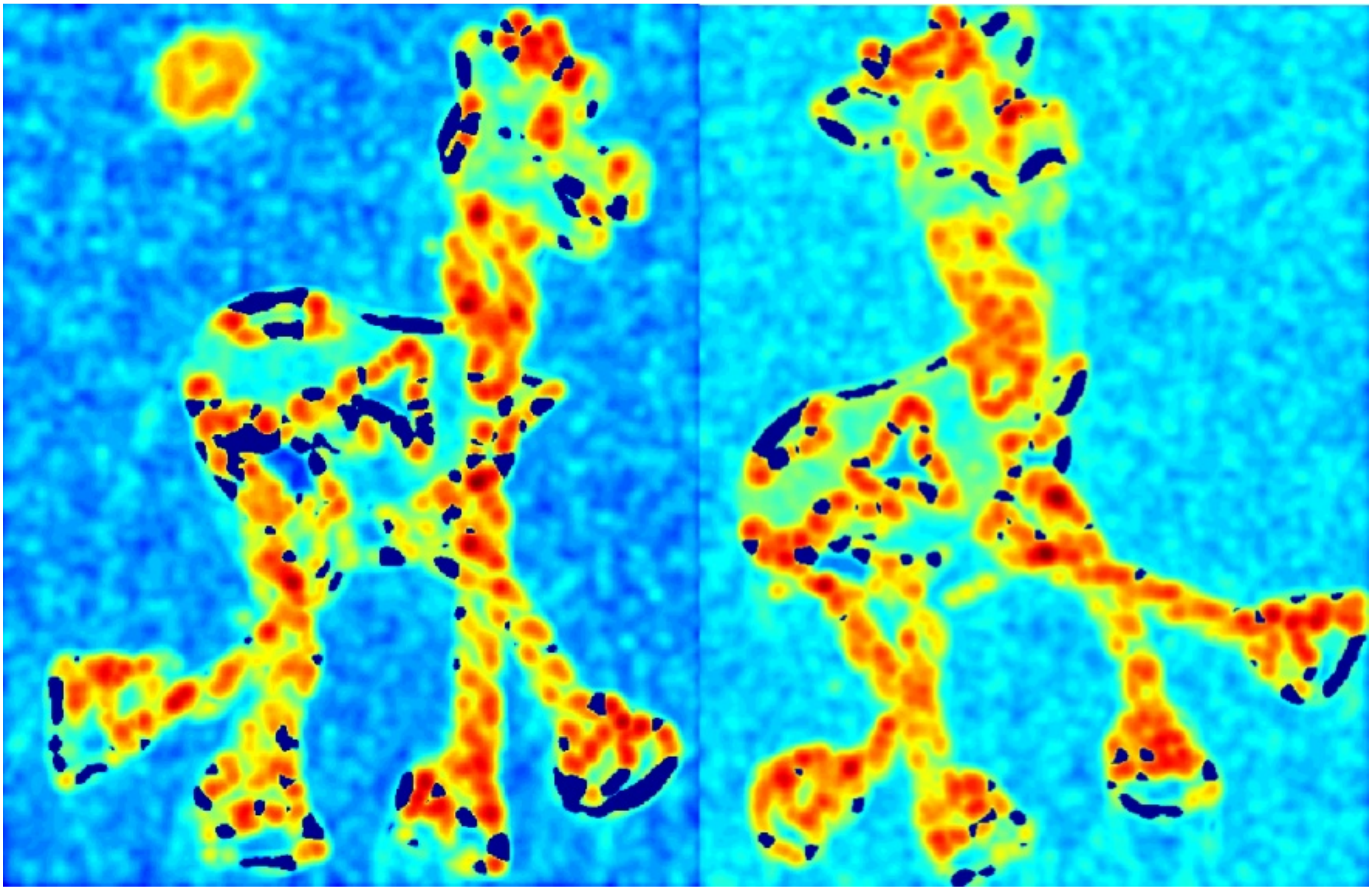
$$H = \sum_{(x,y) \in W} w_{x,y} \left[\begin{array}{cc} I_x^2 & I_x I_y \\ I_x I_y & I_y^2 \end{array} \right]$$



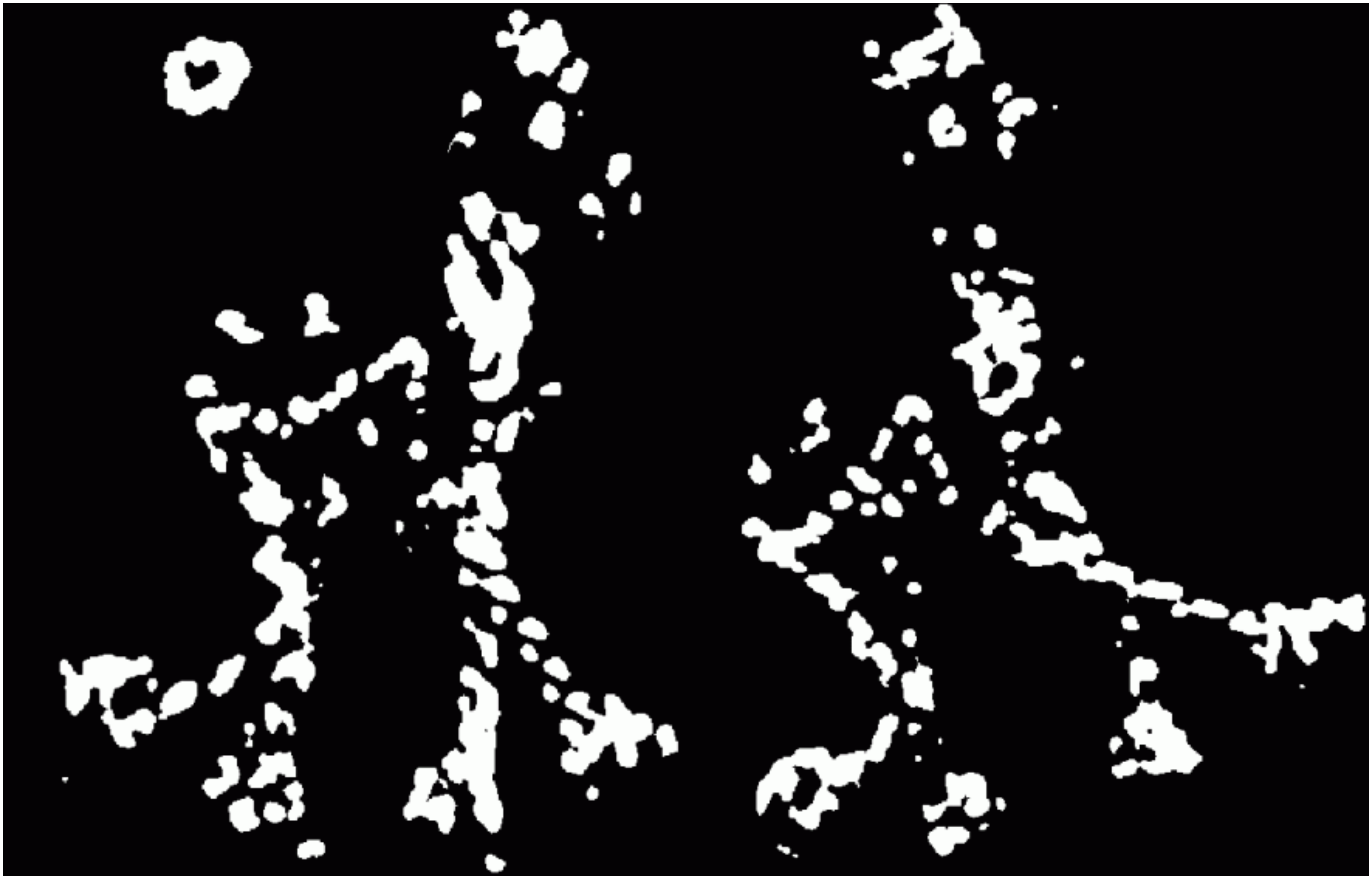
$w_{x,y}$

Harris detector example

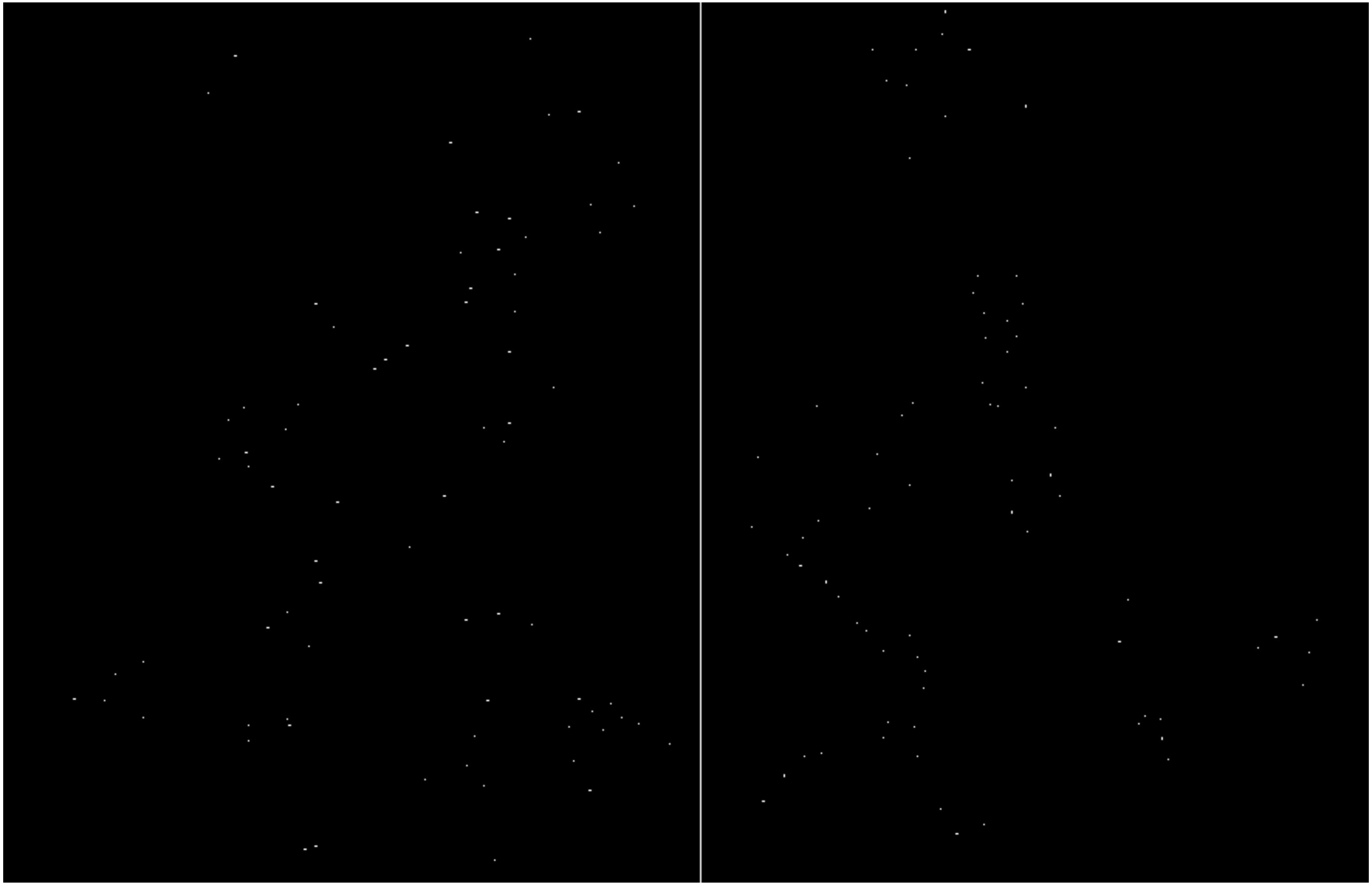
f value (red high, blue low)



Threshold (f > value)



Find local maxima of f



Harris features (in red)