
Contents

1	Image Data	1
1.1	Images in the Spatial Domain	1
1.1.1	Pixels and Windows	1
1.1.2	Image Values and Basic Statistics	3
1.1.3	Spatial and Temporal Data Measures	8
1.1.4	Step-Edges	10
1.2	Images in the Frequency Domain	14
1.2.1	Discrete Fourier Transform	14
1.2.2	Inverse Discrete Fourier Transform	16
1.2.3	The Complex Plane	17
1.2.4	Image Data in the Frequency Domain	19
1.2.5	Phase-Congruency Model for Image Features	24
1.3	Colour and Colour Images	27
1.3.1	Colour Definitions	27
1.3.2	Colour Perception, Visual Deficiencies, and Grey Levels	31
1.3.3	Colour Representations	34
1.4	Exercises	39
1.4.1	Programming Exercises	39
1.4.2	Non-programming Exercises	41
2	Image Processing	43
2.1	Point, Local, and Global Operators	43
2.1.1	Gradation Functions	43
2.1.2	Local Operators	46
2.1.3	Fourier Filtering	48
2.2	Three Procedural Components	50
2.2.1	Integral Images	51
2.2.2	Regular Image Pyramids	53
2.2.3	Scan Orders	54
2.3	Classes of Local Operators	56
2.3.1	Smoothing	56

2.3.2	Sharpening	60
2.3.3	Basic Edge Detectors	62
2.3.4	Basic Corner Detectors	65
2.3.5	Removal of Illumination Artefacts	69
2.4	Advanced Edge Detectors	72
2.4.1	LoG and DoG, and Their Scale Spaces	72
2.4.2	Embedded Confidence	76
2.4.3	The Kovesi Algorithm	79
2.5	Exercises	85
2.5.1	Programming Exercises	85
2.5.2	Non-programming Exercises	86
3	Image Analysis	89
3.1	Basic Image Topology	89
3.1.1	4- and 8-Adjacency for Binary Images	90
3.1.2	Topologically Sound Pixel Adjacency	94
3.1.3	Border Tracing	97
3.2	Geometric 2D Shape Analysis	100
3.2.1	Area	101
3.2.2	Length	102
3.2.3	Curvature	106
3.2.4	Distance Transform (by Gisela Klette)	109
3.3	Image Value Analysis	116
3.3.1	Co-occurrence Matrices and Measures	116
3.3.2	Moment-Based Region Analysis	118
3.4	Detection of Lines and Circles	121
3.4.1	Lines	121
3.4.2	Circles	127
3.5	Exercises	128
3.5.1	Programming Exercises	128
3.5.2	Non-programming Exercises	132
4	Dense Motion Analysis	135
4.1	3D Motion and 2D Optical Flow	135
4.1.1	Local Displacement Versus Optical Flow	135
4.1.2	Aperture Problem and Gradient Flow	138
4.2	The Horn–Schunck Algorithm	140
4.2.1	Preparing for the Algorithm	141
4.2.2	The Algorithm	147
4.3	Lucas–Kanade Algorithm	151
4.3.1	Linear Least-Squares Solution	152
4.3.2	Original Algorithm and Algorithm with Weights	154
4.4	The BBPW Algorithm	155
4.4.1	Used Assumptions and Energy Function	156
4.4.2	Outline of the Algorithm	158
4.5	Performance Evaluation of Optical Flow Results	159

4.5.1	Test Strategies	159
4.5.2	Error Measures for Available Ground Truth	162
4.6	Exercises	164
4.6.1	Programming Exercises	164
4.6.2	Non-programming Exercises	165
5	Image Segmentation	167
5.1	Basic Examples of Image Segmentation	167
5.1.1	Image Binarization	169
5.1.2	Segmentation by Seed Growing	172
5.2	Mean-Shift Segmentation	177
5.2.1	Examples and Preparation	177
5.2.2	Mean-Shift Model	180
5.2.3	Algorithms and Time Optimization	183
5.3	Image Segmentation as an Optimization Problem	188
5.3.1	Labels, Labelling, and Energy Minimization	188
5.3.2	Examples of Data and Smoothness Terms	191
5.3.3	Message Passing	193
5.3.4	Belief-Propagation Algorithm	195
5.3.5	Belief Propagation for Image Segmentation	200
5.4	Video Segmentation and Segment Tracking	202
5.4.1	Utilizing Image Feature Consistency	203
5.4.2	Utilizing Temporal Consistency	204
5.5	Exercises	208
5.5.1	Programming Exercises	208
5.5.2	Non-programming Exercises	212
6	Cameras, Coordinates, and Calibration	215
6.1	Cameras	216
6.1.1	Properties of a Digital Camera	216
6.1.2	Central Projection	220
6.1.3	A Two-Camera System	222
6.1.4	Panoramic Camera Systems	224
6.2	Coordinates	227
6.2.1	World Coordinates	227
6.2.2	Homogeneous Coordinates	229
6.3	Camera Calibration	231
6.3.1	A User's Perspective on Camera Calibration	231
6.3.2	Rectification of Stereo Image Pairs	235
6.4	Exercises	240
6.4.1	Programming Exercises	240
6.4.2	Non-programming Exercises	242
7	3D Shape Reconstruction	245
7.1	Surfaces	245
7.1.1	Surface Topology	245
7.1.2	Local Surface Parameterizations	249

7.1.3	Surface Curvature	252
7.2	Structured Lighting	255
7.2.1	Light Plane Projection	256
7.2.2	Light Plane Analysis	258
7.3	Stereo Vision	260
7.3.1	Epipolar Geometry	261
7.3.2	Binocular Vision in Canonical Stereo Geometry	262
7.3.3	Binocular Vision in Convergent Stereo Geometry	266
7.4	Photometric Stereo Method	269
7.4.1	Lambertian Reflectance	269
7.4.2	Recovering Surface Gradients	272
7.4.3	Integration of Gradient Fields	274
7.5	Exercises	283
7.5.1	Programming Exercises	283
7.5.2	Non-programming Exercises	285
8	Stereo Matching	287
8.1	Matching, Data Cost, and Confidence	287
8.1.1	Generic Model for Matching	289
8.1.2	Data-Cost Functions	292
8.1.3	From Global to Local Matching	295
8.1.4	Testing Data Cost Functions	297
8.1.5	Confidence Measures	299
8.2	Dynamic Programming Matching	301
8.2.1	Dynamic Programming	302
8.2.2	Ordering Constraint	304
8.2.3	DPM Using the Ordering Constraint	306
8.2.4	DPM Using a Smoothness Constraint	311
8.3	Belief-Propagation Matching	316
8.4	Third-Eye Technique	320
8.4.1	Generation of Virtual Views for the Third Camera	321
8.4.2	Similarity Between Virtual and Third Image	324
8.5	Exercises	326
8.5.1	Programming Exercises	326
8.5.2	Non-programming Exercises	329
9	Feature Detection and Tracking	331
9.1	Invariance, Features, and Sets of Features	331
9.1.1	Invariance	331
9.1.2	Keypoints and 3D Flow Vectors	333
9.1.3	Sets of Keypoints in Subsequent Frames	336
9.2	Examples of Features	339
9.2.1	Scale-Invariant Feature Transform	340
9.2.2	Speeded-Up Robust Features	342
9.2.3	Oriented Robust Binary Features	344
9.2.4	Evaluation of Features	346

9.3	Tracking and Updating of Features	349
9.3.1	Tracking Is a Sparse Correspondence Problem	349
9.3.2	Lucas–Kanade Tracker	351
9.3.3	Particle Filter	357
9.3.4	Kalman Filter	363
9.4	Exercises	370
9.4.1	Programming Exercises	370
9.4.2	Non-programming Exercises	374
10	Object Detection	375
10.1	Localization, Classification, and Evaluation	375
10.1.1	Descriptors, Classifiers, and Learning	375
10.1.2	Performance of Object Detectors	381
10.1.3	Histogram of Oriented Gradients	382
10.1.4	Haar Wavelets and Haar Features	384
10.1.5	Viola–Jones Technique	387
10.2	AdaBoost	391
10.2.1	Algorithm	391
10.2.2	Parameters	393
10.2.3	Why Those Parameters?	396
10.3	Random Decision Forests	398
10.3.1	Entropy and Information Gain	398
10.3.2	Applying a Forest	402
10.3.3	Training a Forest	403
10.3.4	Hough Forests	407
10.4	Pedestrian Detection	409
10.5	Exercises	411
10.5.1	Programming Exercises	411
10.5.2	Non-programming Exercises	413
	Name Index	415
	Index	419

<http://www.springer.com/978-1-4471-6319-0>

Concise Computer Vision

An Introduction into Theory and Algorithms

Klette, R.

2014, XVIII, 429 p. 298 illus., 229 illus. in color.,

Softcover

ISBN: 978-1-4471-6319-0