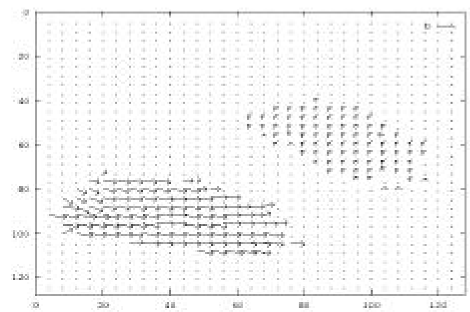
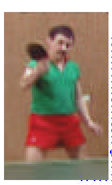
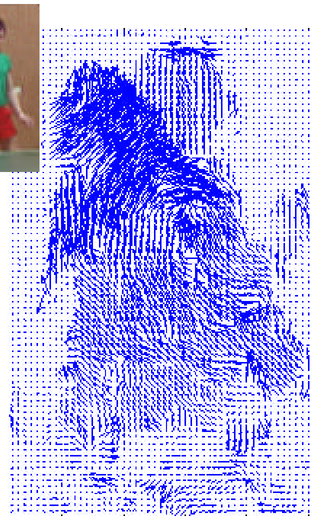
Lecture-3

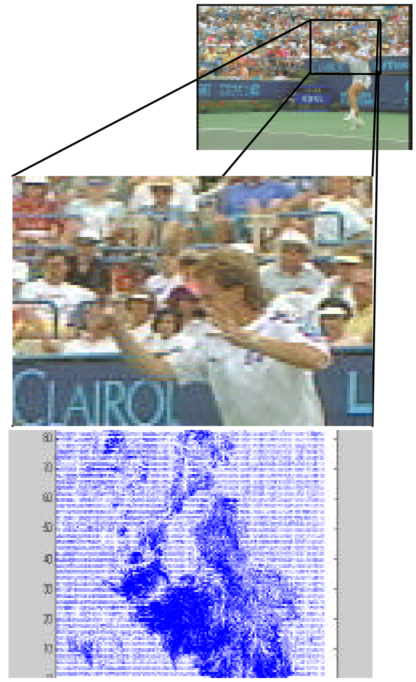
Computing Optical Flow

Hamburg Taxi seq





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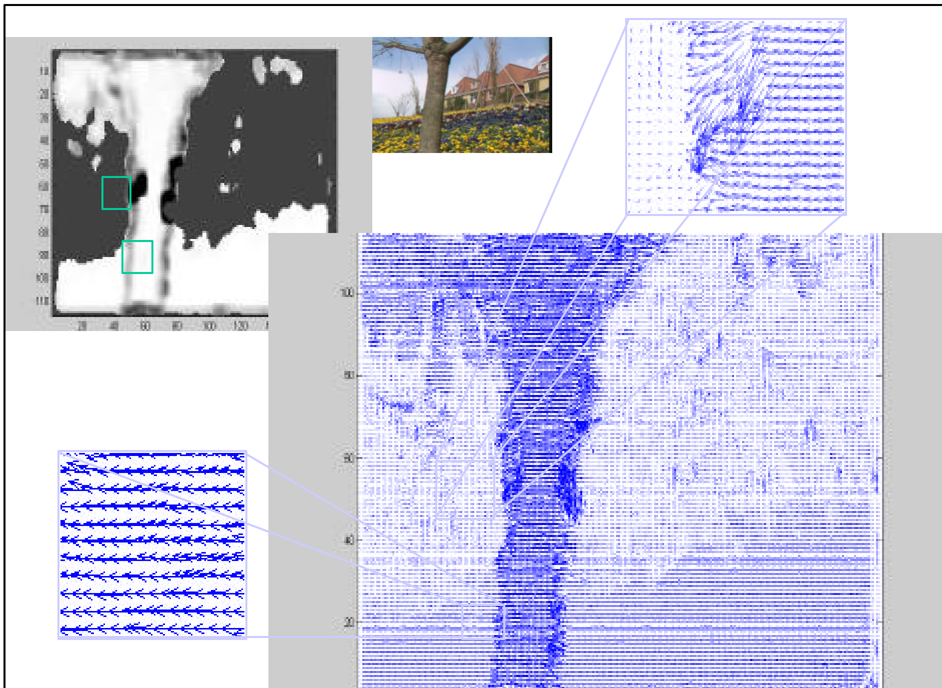


Horn&Schunck Optical Flow

$$\frac{df(x,y,t)}{dt} = \frac{\partial f}{\partial x}\frac{dx}{dt} + \frac{\partial f}{\partial y}\frac{dx}{dt} + \frac{\partial f}{\partial t} = 0$$

brightness constancy eq

Horn&Schunck Optical Flow

$$f(x,y,t) = f(x+dx, y+dy, t+dt)$$

Taylor Series

$$f(x,y,t) = f(x,y,t) + \frac{\partial f}{\partial x}dx + \frac{\partial f}{\partial y}dy + \frac{\partial f}{\partial t}dt$$

$$f_x dx + f_y dy + f_t dt = 0$$

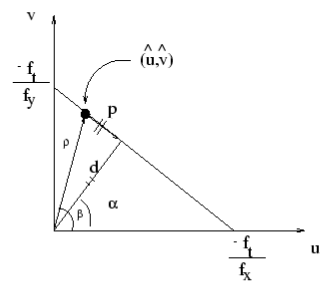
brightness constancy eq

Interpretation of optical flow eq

$$f_x u + f_y v + f_t = 0$$

$$v = -\frac{f_x}{f_y} u - \frac{f_t}{f_y}$$

Equation of st.line



d=normal flow

p=parallel flow

$$d = \frac{f_t}{\sqrt{f_x^2 + f_y^2}}$$

Horn&Schunck (contd)

$$\iint \{(f_x u + f_y v + f_t)^2 + \lambda(u_x^2 + u_y^2 + v_x^2 + v_y^2)\} dx dy$$

min

$$(f_x u + f_y v + f_t) f_x + \lambda(\Delta^2 u) = 0$$

$$(f_x u + f_y v + f_t) f_y + \lambda((\Delta^2 v) = 0$$

discrete version

$$(f_x u + f_y v + f_t) f_x + \lambda(u - u_{av}) = 0$$

$$(f_x u + f_y v + f_t) f_y + \lambda((v - v_{av}) = 0$$

variational calculus

$$u = u_{av} - f_x \frac{P}{D}$$

$$v = v_{av} - f_y \frac{P}{D}$$

$$P = f_x u_{av} + f_y v_{av} + f_t$$

$$D = \lambda + f_x^2 + f_y^2$$

Algorithm-1

- k=0
- Initialize $u^K \quad v^K$
- Repeat until some error measure is satisfied

$$u^K = u_{av}^{k-1} - f_x \frac{P}{D}$$

$$v = v_{av}^{K-1} - f_y \frac{P}{D}$$

$$P = f_x u_{av} + f_y v_{av} + f_t$$

$$D = l + f_x^2 + f_y^2$$

Derivatives

- Derivative: Rate of change of some quantity
  - Speed is a rate of change of a distance
  - Acceleration is a rate of change of speed

Derivative

$$\frac{df}{dx} = \lim_{\Delta x \to 0} \frac{f(x) - f(x - \Delta x)}{\Delta x} = f'(x) = f_x$$

$$v = \frac{ds}{dt}$$ speed

$$a = \frac{dv}{dt}$$ acceleration

Examples

$$y = x^2 + x^4 \qquad y = \sin x + e^{-x}$$

$$\frac{dy}{dx} = 2x + 4x^3 \qquad \frac{dy}{dx} = \cos x + (-1)e^{-x}$$

Second Derivative

$$\frac{df_x}{dx} = f''(x) = f_{xx}$$

$$y = x^2 + x^4$$

$$\frac{dy}{dx} = 2x + 4x^3$$

$$\frac{d^2y}{dx^2} = 2 + 12x^2$$

Discrete Derivative

$$\frac{df}{dx} = \lim_{\Delta x \to 0} \frac{f(x) - f(x - \Delta x)}{\Delta x} = f'(x)$$

$$\frac{df}{dx} = \frac{f(x) - f(x-1)}{1} = f'(x)$$

$$\frac{df}{dx} = f(x) - f(x-1) = f'(x)$$

(Finite Difference)

Discrete Derivative

$$\frac{df}{dx} = f(x) - f(x-1) = f'(x)$$ Left difference

$$\frac{df}{dx} = f(x) - f(x+1) = f'(x)$$ Right difference

$$\frac{df}{dx} = f(x+1) - f(x-1) = f'(x)$$ Center difference

Example

Left difference	F(x)=10	10	10	10	20	20	20
	F'(x)=0	0	0	0	10	0	0
	F''(x)=0	0	0	0	10	-10	0

-1	1		left difference
1	-1		right difference
-1	0	1	center difference

Derivatives in Two Dimensions

$f(x,y)$

(partial Derivatives)

$$\frac{\partial f}{\partial x} = f_x = \lim_{\Delta x \to 0} \frac{f(x,y) - f(x-\Delta x, y)}{\Delta x}$$

$$\frac{\partial f}{\partial y} = f_y = \lim_{\Delta y \to 0} \frac{f(x,y) - f(x, y-\Delta y)}{\Delta y}$$

(f_x, f_y) Gradient Vector

magnitude $= \sqrt{(f_x^2 + f_y^2)}$

direction $= q = \tan^{-1} \frac{f_y}{f_x}$

$$\Delta^2 f = f_{xx} + f_{yy} = \text{Laplacian}$$

Derivatives of an Image

Derivative & average

$$\begin{matrix} -1 & 0 & 1 \\ -1 & 0 & 1 \\ -1 & 0 & 1 \end{matrix} \quad f_x \qquad \begin{matrix} -1 & -1 & -1 \\ 0 & 0 & 0 \\ 1 & 1 & 1 \end{matrix} \quad f_y$$

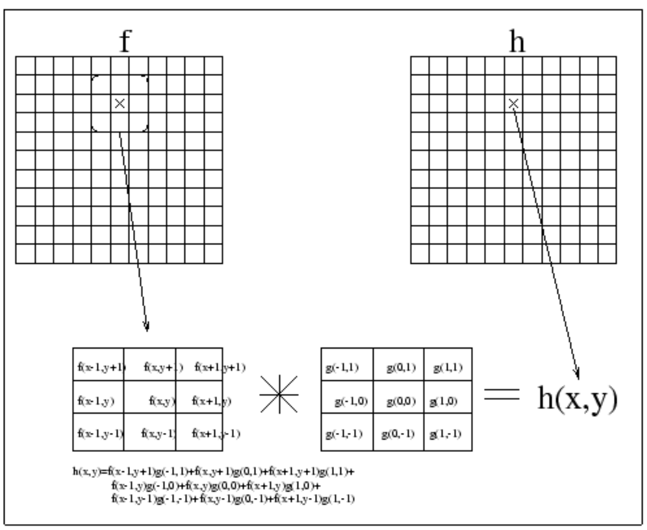
Prewit

$$I(x,y) = \begin{bmatrix} 10 & 10 & 20 & 20 & 20 \\ 10 & 10 & 20 & 20 & 20 \\ 10 & 10 & 20 & 20 & 20 \\ 10 & 10 & 20 & 20 & 20 \\ 10 & 10 & 20 & 20 & 20 \end{bmatrix} \quad I_x = \begin{bmatrix} 0 & 0 & 0 & 0 & 0 \\ 0 & 30 & 30 & 0 & 0 \\ 0 & 30 & 30 & 0 & 0 \\ 0 & 30 & 30 & 0 & 0 \\ 0 & 0 & 0 & 0 & 0 \end{bmatrix}$$

Derivatives of an Image

$$I(x,y) = \begin{bmatrix} 10 & 10 & 20 & 20 & 20 \\ 10 & 10 & 20 & 20 & 20 \\ 10 & 10 & 20 & 20 & 20 \\ 10 & 10 & 20 & 20 & 20 \\ 10 & 10 & 20 & 20 & 20 \end{bmatrix} \quad I_y = \begin{bmatrix} 0 & 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 & 0 \end{bmatrix}$$

Convolution



Convolution (contd)

$$h(x,y) = \sum_{i=-1}^{1}\sum_{j=-1}^{1} f(x+i, y+j)g(i,j)$$

$$h(x,y) = f(x,y) * g(x,y)$$

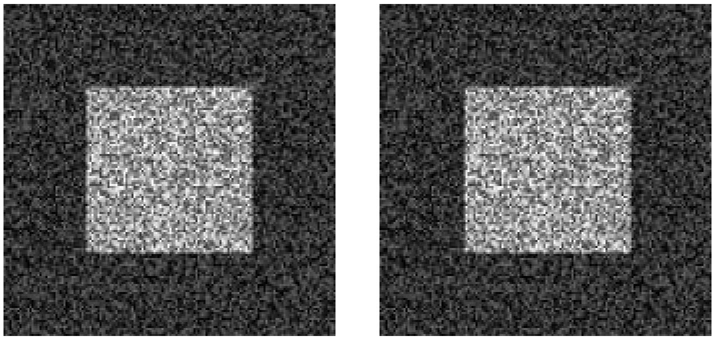
Derivative Masks

$$\begin{bmatrix} -1 & 1 \\ -1 & 1 \end{bmatrix} \text{first image} \quad \begin{bmatrix} -1 & -1 \\ 1 & 1 \end{bmatrix} \text{first image} \quad \begin{bmatrix} -1 & -1 \\ -1 & -1 \end{bmatrix} \text{first image}$$

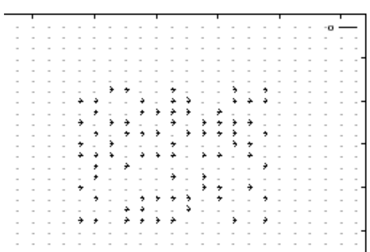
$$\begin{bmatrix} -1 & 1 \\ -1 & 1 \end{bmatrix} \text{second image} \quad \begin{bmatrix} -1 & -1 \\ 1 & 1 \end{bmatrix} \text{second image} \quad \begin{bmatrix} 1 & 1 \\ 1 & 1 \end{bmatrix} \text{second image}$$

f_x f_y f_t

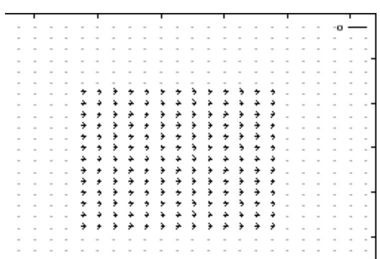
Synthetic Images



Results



One iteration



10 iterations

Homework Due 9/5/00

- Derive Euler Angles matrix from three rotations around x, y and Z. (Lecture-1, slide 27).
- Derive bi-quadratic motion model from the projective motion model using Taylor series. (Lecture-2, slide 12).
- Verify 3-D rigid motion using instantaneous motion model can be written as a cross product of rotational velocities Ω and object location (X). Lecture-2, slide 22.
- Verify that pseudo perspective motion model can be derived assuming planar scene and perspective projection. Lecture-2, Slide 26.