The Kadir Operator Saliency, Scale and Image Description

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The issues…

- salient – standing out from the rest, noticeable, conspicous, prominent

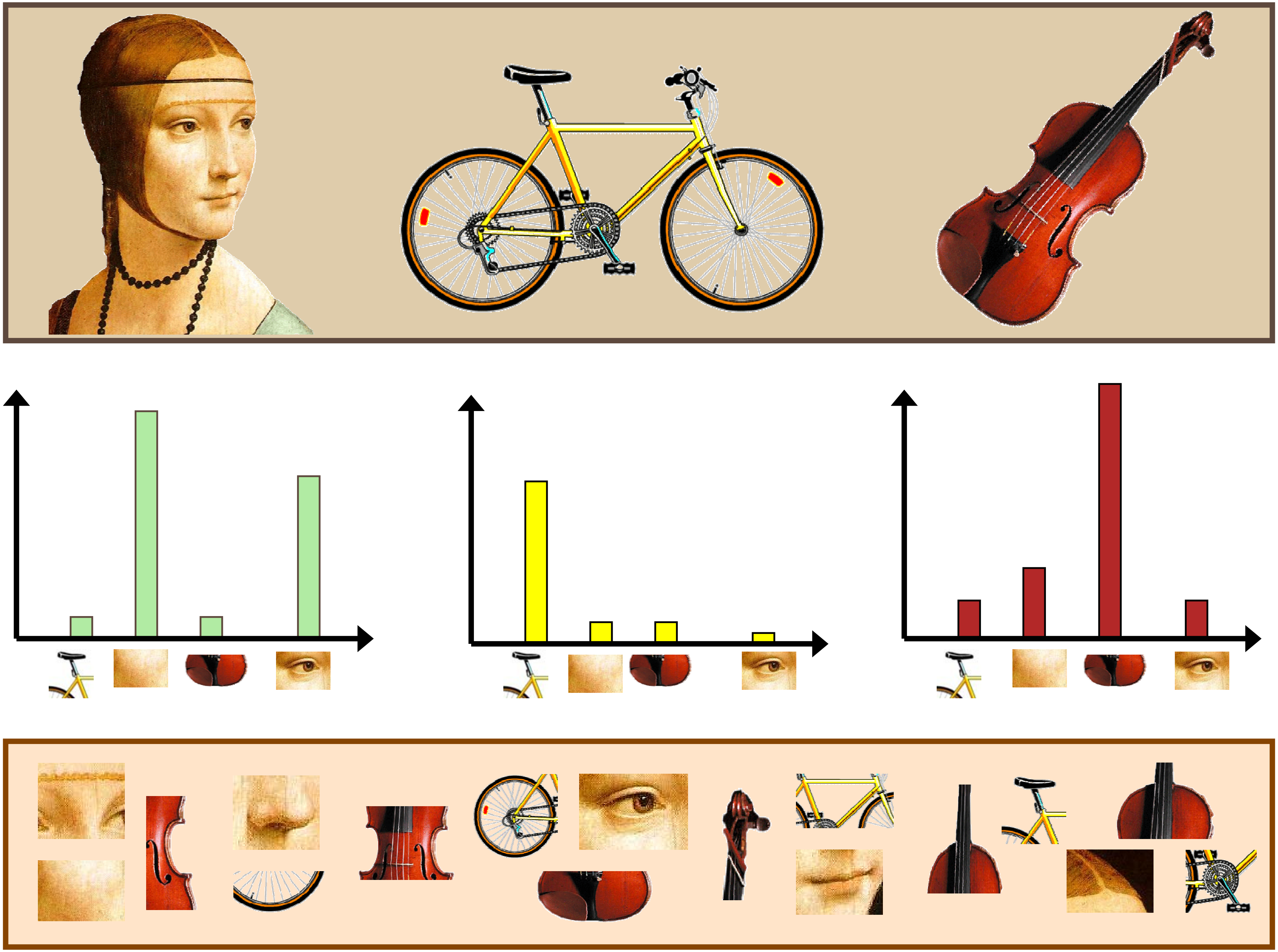
- scale – find the best scale for a feature

- image description – create a descriptor for use in object recognition

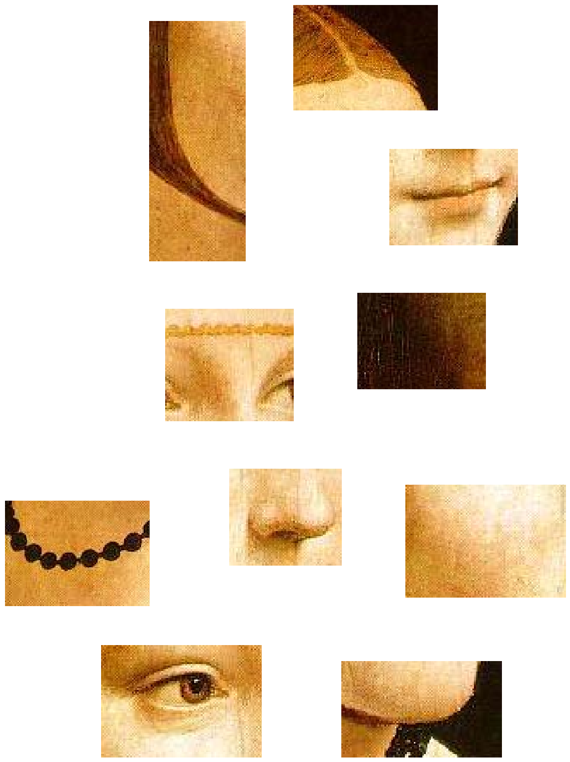
Early Vision Motivation

- pre-attentive stage: features pop out

- attentive stage: relationships between features and grouping



Detection of Salient Features for an Object Class

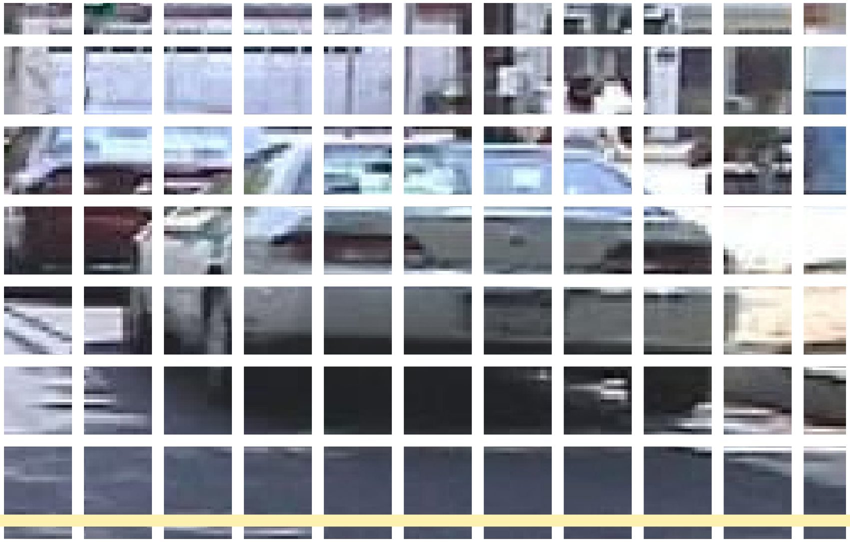


How do we do this?

1. fixed size windows (simple approach)

2. Harris detector, Lowe detector, etc.

3. Kadir's approach



Kadir's Approach

- Scale is intimately related to the problem of determining saliency and extracting relevant descriptions.

- Saliency is related to the local image complexity, ie. Shannon entropy.

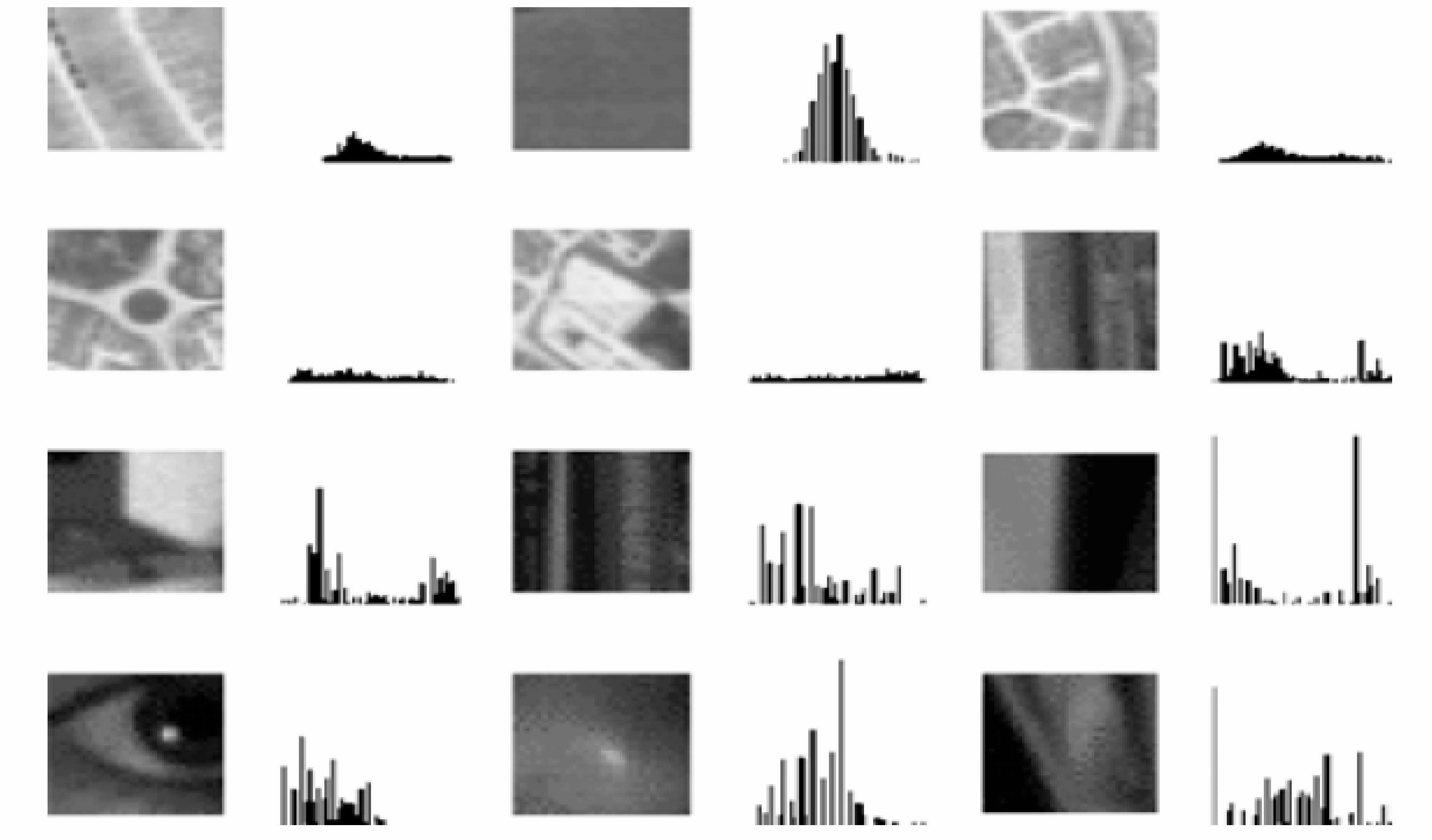
- entropy definition $H = -\sum_{\substack{i \text{ in set} \\ \text{of interest}}} P_i \log_2 P_i$

Specifically

- x is a point on the image
- R_x is its local neighborhood
- D is a descriptor and has values $\{d_1, \ldots d_r\}$.
- $P_{D,Rx}(d_i)$ is the probability of descriptor D taking the value d_i in the local region R_x.

$$H_{D,R_X} = -\sum_i P_{D,R_X}(d_i) \log_2 P_{D,R_X}(d_i)$$

Local Histograms of Intensity



Neighborhoods with structure have flatter distributions which converts to higher entropy.

Problems Kadir wanted to solve

1. Scale should not be a global, preselected parameter

2. Highly textured regions can score high on entropy, but not be useful

3. The algorithm should not be sensitive to small changes in the image or noise.

Kadir's Methodology

- use a scale-space approach

- features will exist over multiple scales
  - Berghoml (1986) regarded features (edges) that existed over multiple scales as best.

- Kadir took the opposite approach.
  - He considers these too self-similar.
  - Instead he looks for peaks in (weighted) entropy over the scales.

The Algorithm

1. For each pixel location x
   a. For each scale s between smin and smax
      
      i. Measure the local descriptor values within a window of scale s
      ii. Estimate the local PDF (use a histogram)
   b. Select scales (set S) for which the entropy is peaked (S may be empty)
   c. Weight the entropy values in S by the sum of absolute difference of the PDFs of the local descriptor around S.

Finding salient points

- the math for saliency discretized

$$Y_D(\mathbf{s},\mathbf{x}) = H_D(\mathbf{s},\mathbf{x})W_D(\mathbf{s},\mathbf{x})$$

$$H_D(\mathbf{s},\mathbf{x}) = -\sum_{d\in D} p_{\mathbf{s},\mathbf{x}}(d)\log_2 p_{\mathbf{s},\mathbf{x}}(d)$$

$$W_D(\mathbf{s},\mathbf{x}) = \frac{s^2}{2s-1}\sum_{d\in D}\left|p_{\mathbf{s},\mathbf{x}}(d) - p_{\mathbf{s}-1,\mathbf{x}}(d)\right|$$

$$\mathbf{x} = \text{point}$$

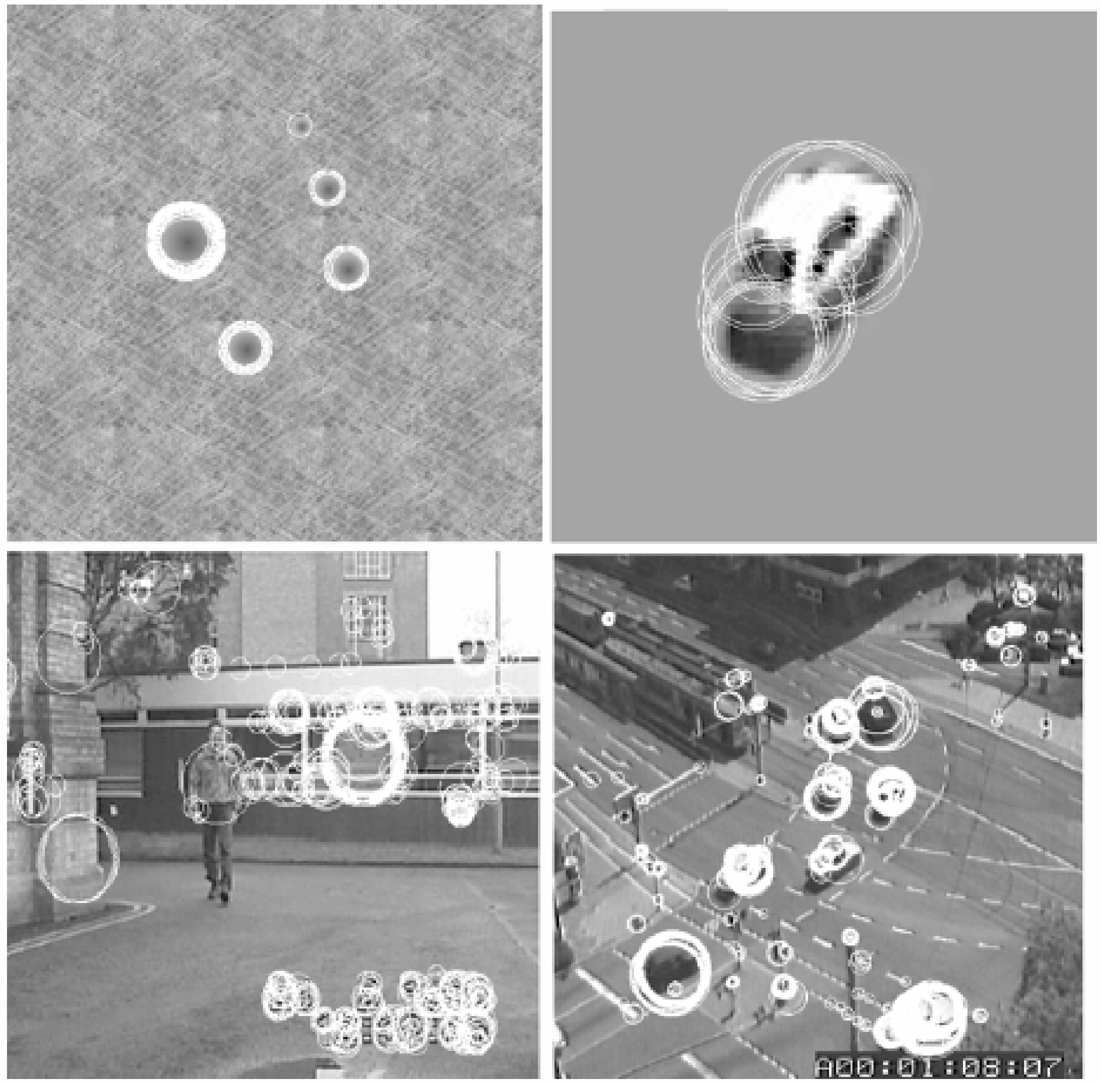
$$\mathbf{s} = (\mathrm{s},\mathrm{r},\theta) = (\text{scale, eccentricity, orientation})$$

$$D = \text{low-level feature domain}$$

$$p_{\mathbf{s},\mathbf{x}}(d) = \text{histogram of values of } D \text{ in region } \mathbf{s},\mathbf{x}$$

- saliency
- entropy
- weight based on difference between scales

Picking salient points and their scales



Getting rid of texture

- One goal was to not select highly textured regions such as grass or bushes, which are not the type of objects the Oxford group wanted to recognize

- Such regions are highly salient with just entropy, because they contain a lot of gray tones in roughly equal proportions

- But they are similar at different scales and thus the weights make them go away

Salient Regions

- Instead of just selecting the most salient points (based on weighted entropy), select salient regions (more robust).

- Regions are like volumes in scale space.

- Kadir used clustering to group selected points into regions.

- We found the clustering was a critical step.

Kadir’s clustering (VERY ad hoc)

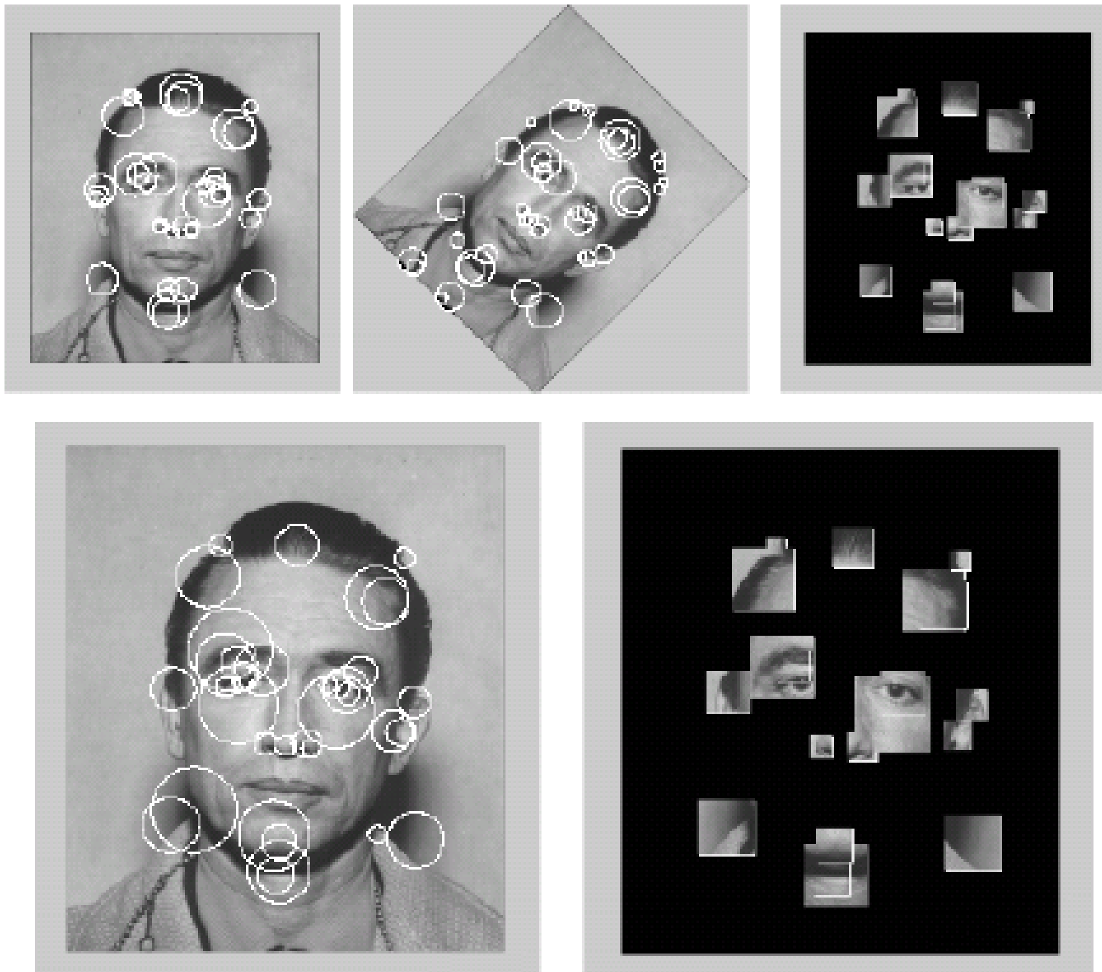
- Apply a global threshold on saliency.
- Choose the highest salient points (50% works well).
- Find the K nearest neighbors (K=8 preset)
- Check variance at center points with these neighbors.
- Accept if far enough away from existant clusters and variance small enough.
- Represent with mean scale and spatial location of the K points
- Repeat with next highest salient point

More examples

Robustness Claims

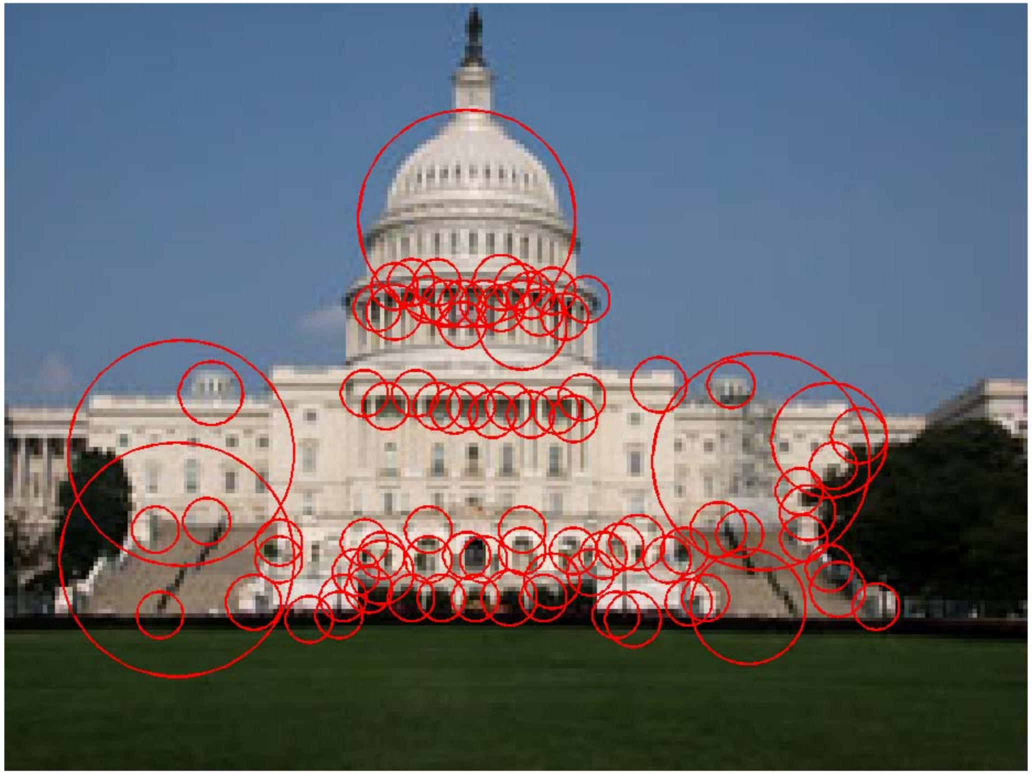
- scale invariant (chooses its scale)
- rotation invariant (uses circular regions and histograms)
- somewhat illumination invariant (why?)
- not affine invariant (able to handle small changes in viewpoint)

More Examples



Temple

Capitol

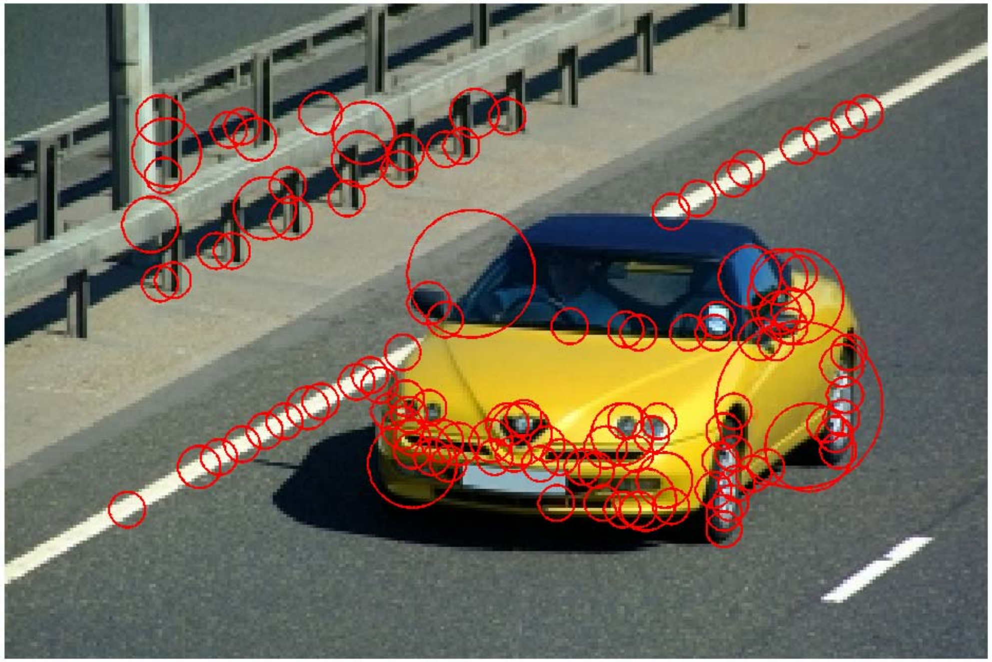


Houses and Boats

Houses and Boats

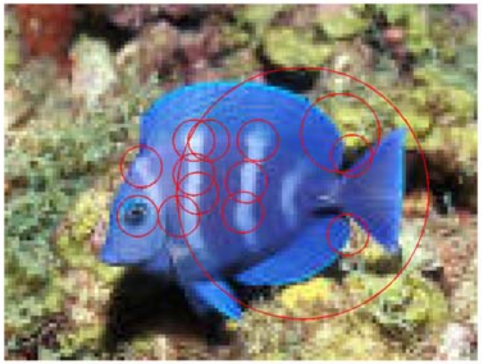
Sky Scraper

Car

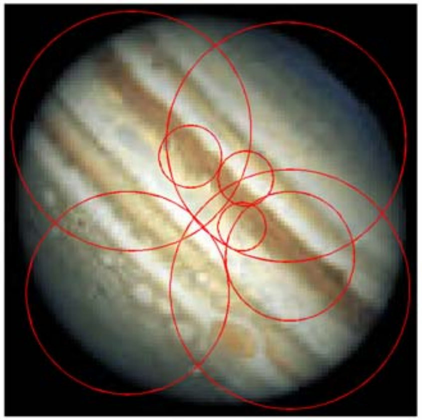


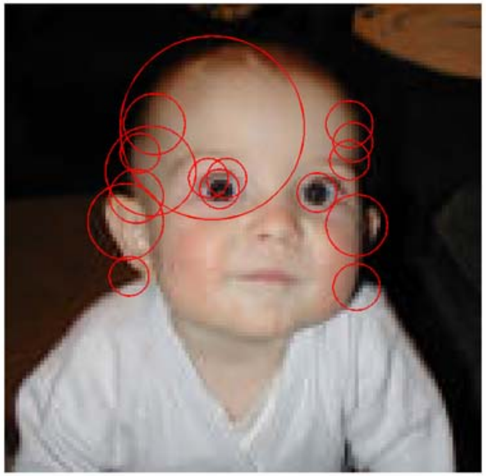
Trucks

Fish

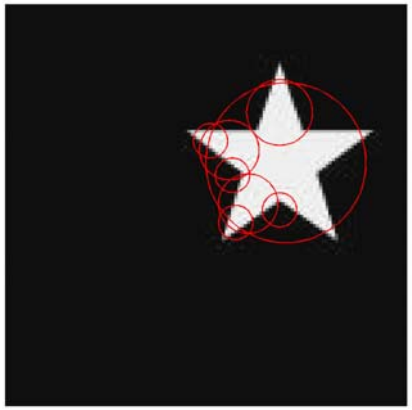


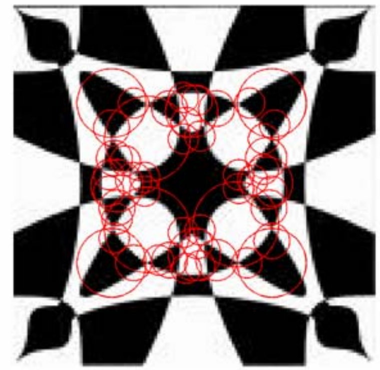
Other





Symmetry and More





Benefits

- General feature: not tied to any specific object
- Can be used to detect rather complex objects that are not all one color
- Location invariant, rotation invariant
- Selects relevant scale, so scale invariant
- What else is good?
- Anything bad?

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