

# Object Recognition and Augmented Reality



Magritte, *The Treachery of Images*

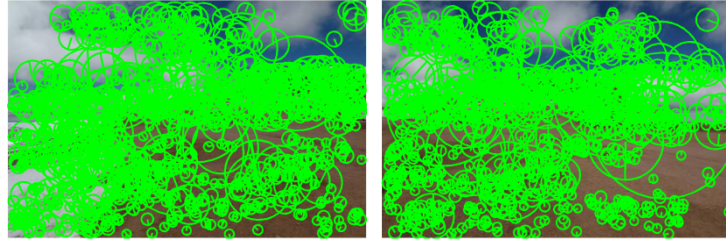
Computational Photography

Yuxiong Wang, University of Illinois

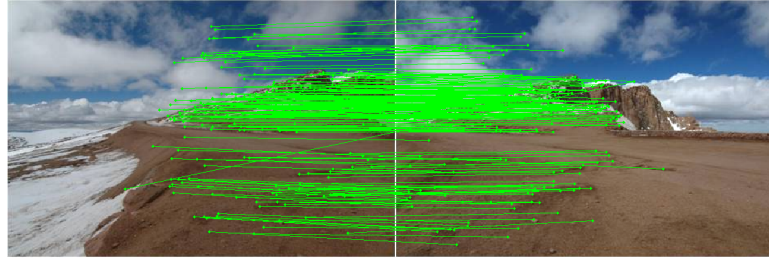
Slides adopted from Derek Hoiem

# Last class: Image Stitching

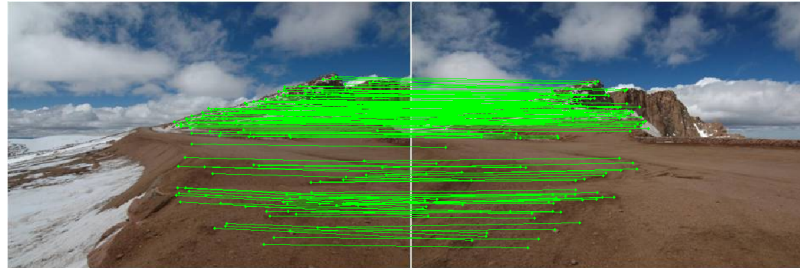
1. Detect keypoints



2. Match keypoints



3. Use RANSAC to estimate homography



4. Project onto a surface and blend



# Project 5

1. Align frames to a central frame
2. Identify background pixels on panorama
3. Map background pixels back to videos
4. Identify and display foreground pixels

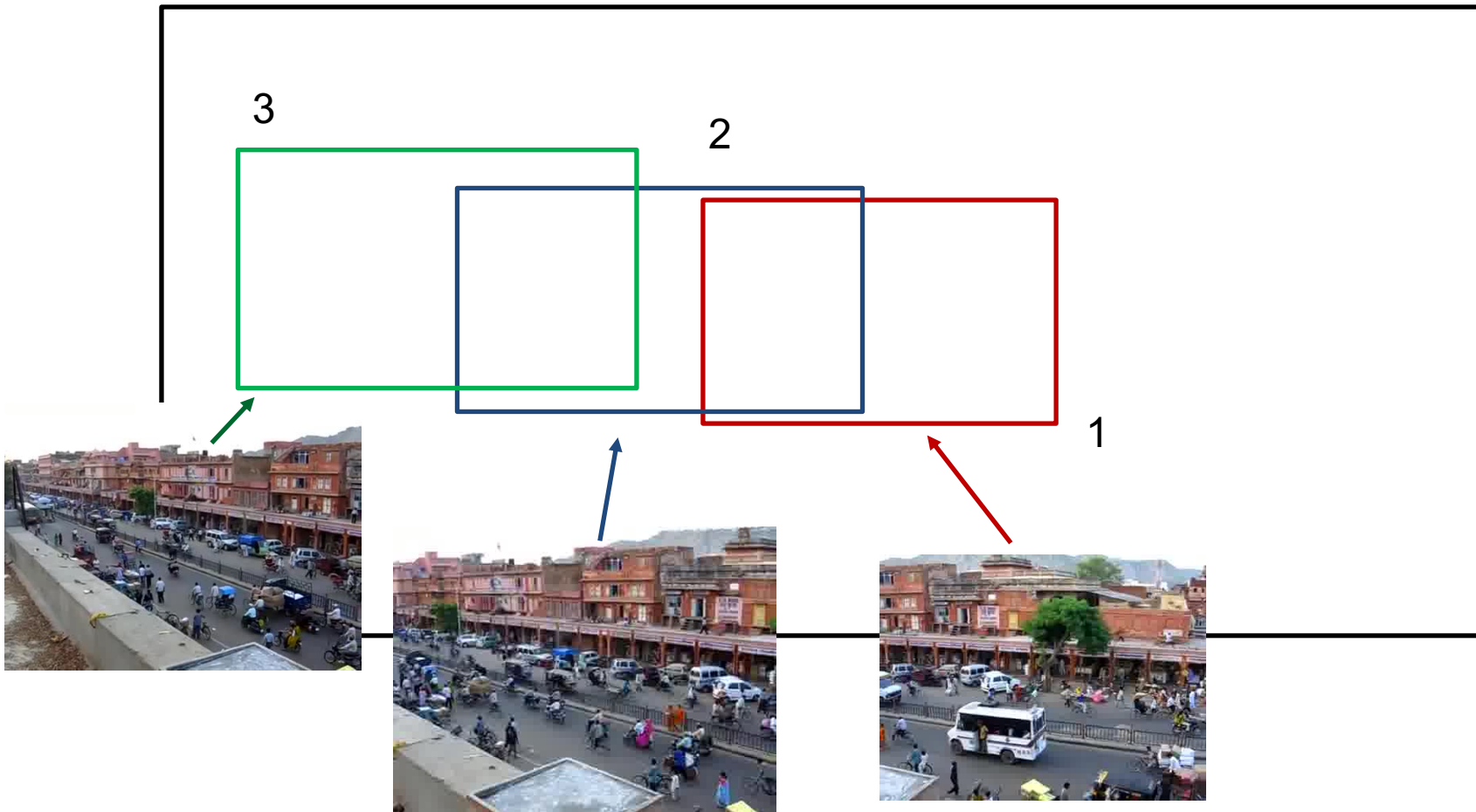
Lots of possible extensions for extra credit

# Aligning frames

$$x_1 = H_{21}x_2$$

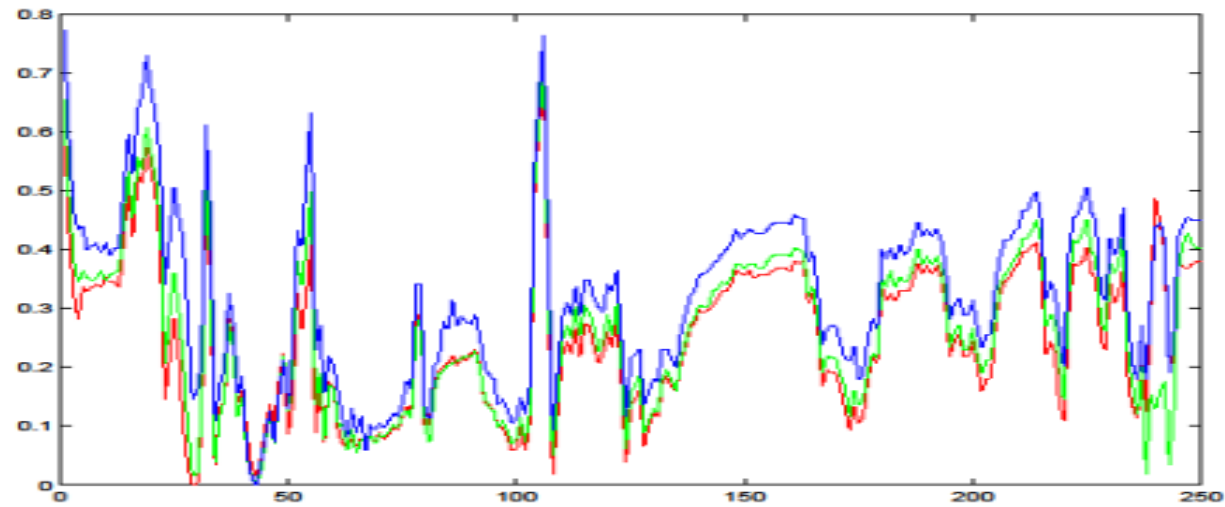
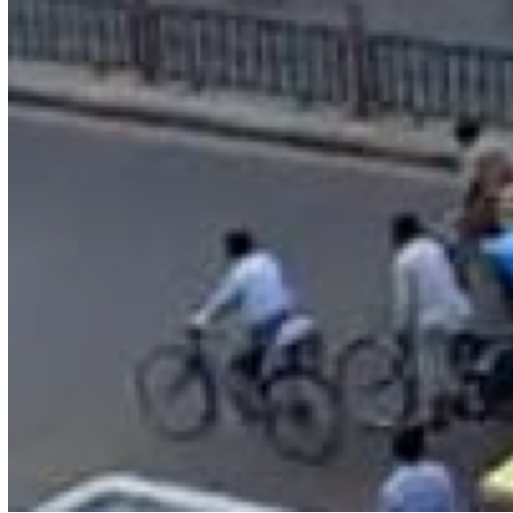
$$x_2 = H_{32}x_3$$

$$x_1 \stackrel{?}{=} x_3$$

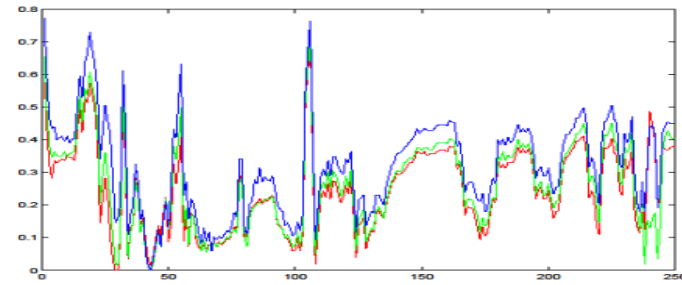




# Background identification

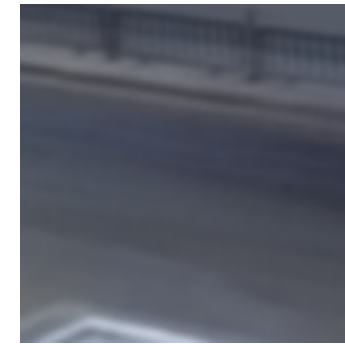


# Background identification



## Idea 1: take average (mean) pixel

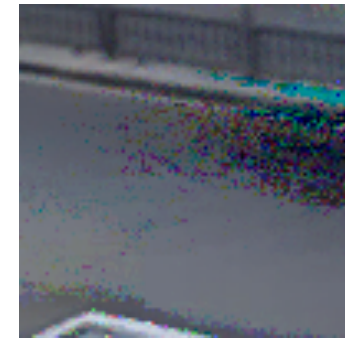
- Not bad but averages over outliers



mean

## Idea 2: take mode (most common) pixel

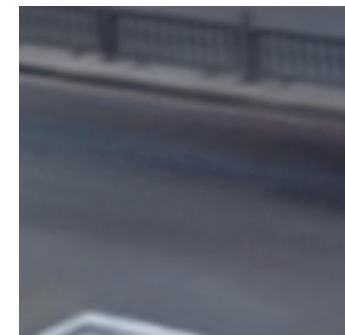
- Can ignore outliers if background shows more than any other single color



mode

## Idea 3: take median pixel

- Can ignore outliers if background shows at least 50% of time, or outliers tend to be well-distributed



median

# Identifying foreground

1. Simple method: foreground pixels are some distance away from background
2. Another method: count times that each color is observed and assign unlikely colors to foreground
  - Can work for repetitive motion, like a tree swaying in the breeze

# Augmented reality

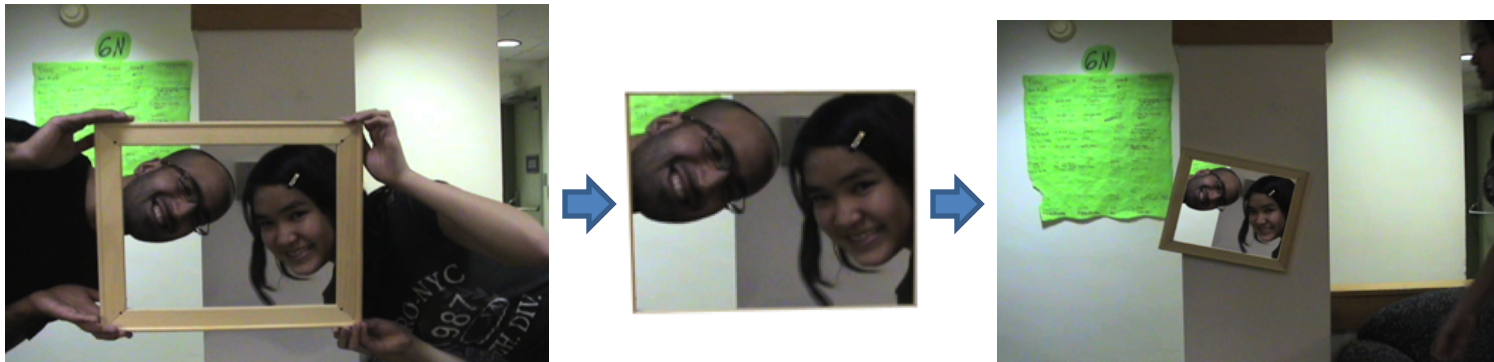
- Insert and/or interact with object in scene
  - [Project by Karen Liu](#)
  - [Responsive characters in AR](#)
  - [KinectFusion](#)
  
- Overlay information on a display
  - [Tagging reality](#)
  - [HoloLens](#)
  - [Google goggles](#)

# Adding fake objects to real video

## Approach

1. Recognize and/or track points that give you a coordinate frame
2. Apply homography (flat texture) or perspective projection (3D model) to put object into scene

Main challenge: dealing with lighting, shadows, occlusion





# Information overlay

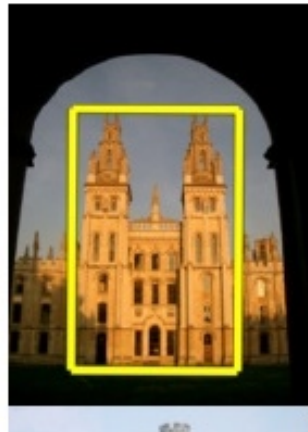
## Approach

1. Recognize object that you've seen before
2. Possibly, compute its pose
3. Retrieve info and overlay

Main challenge: how to match reliably and efficiently?

# Today

How to quickly find images in a large database that match a given image region?



# Let's start with interest points

Query



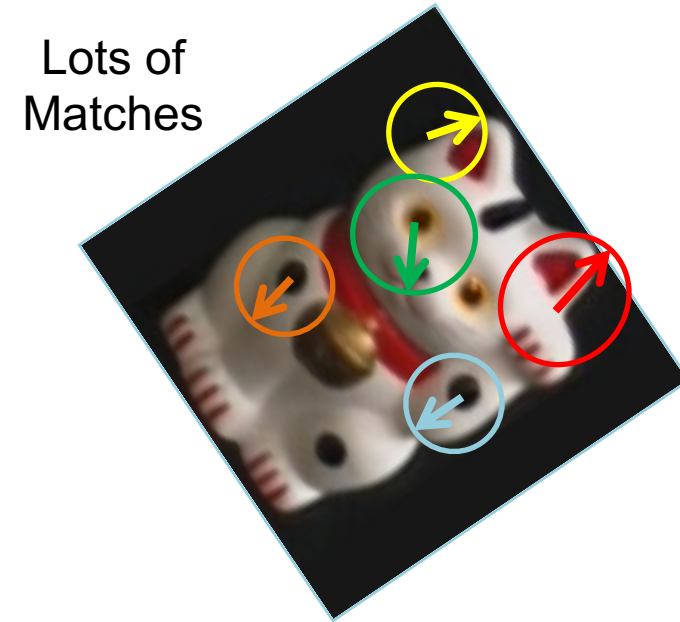
Database



Compute interest points (or keypoints) for every image in the database and the query

# Simple idea

See how many keypoints are close to keypoints in each other image



Few or No Matches



But this will be really, really slow!

# Key idea 1: “Visual Words”

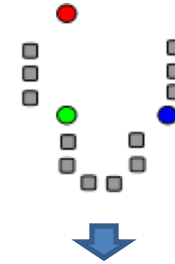
- Cluster the keypoint descriptors



# Key idea 1: “Visual Words”

## K-means algorithm

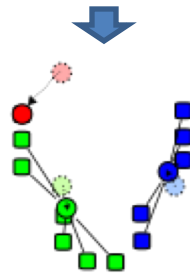
1. Randomly select K centers



2. Assign each point to nearest center



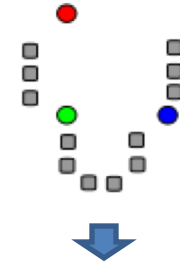
3. Compute new center (mean) for each cluster



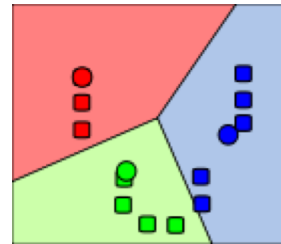
# Key idea 1: “Visual Words”

## K-means algorithm

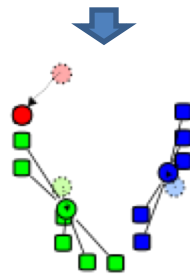
1. Randomly select K centers



2. Assign each point to nearest center



3. Compute new center (mean) for each cluster



Back to 2

# Kmeans: Matlab code

```
function C = kmeans(X, K)
% Initialize cluster centers to be randomly sampled points
[N, d] = size(X);
rp = randperm(N);
C = X(rp(1:K), :);

lastAssignment = zeros(N, 1);
while true
    % Assign each point to nearest cluster center
    bestAssignment = zeros(N, 1);
    mindist = Inf*ones(N, 1);
    for k = 1:K
        for n = 1:N
            dist = sum((X(n, :)-C(k, :)).^2);
            if dist < mindist(n)
                mindist(n) = dist;
                bestAssignment(n) = k;
            end
        end
    end

    % break if assignment is unchanged
    if all(bestAssignment==lastAssignment), break; end;
    lastAssignment = bestAssignment;

    % Assign each cluster center to mean of points within it
    for k = 1:K
        C(k, :) = mean(X(bestAssignment==k, :));
    end
end
end
```

# K-means Demo

<https://www.naftaliharris.com/blog/visualizing-k-means-clustering/>

# Key idea 1: “Visual Words”

- Cluster the keypoint descriptors
- Assign each descriptor to a cluster number
  - What does this buy us?
  - Each descriptor was 128 dimensional floating point, now is 1 integer (easy to match!)
  - Is there a catch?
    - Need **a lot** of clusters (e.g., 1 million) if we want points in the same cluster to be very similar
    - Points that really are similar might end up in different clusters



# Key idea 1: “Visual Words”

- Cluster the keypoint descriptors
- Assign each descriptor to a cluster number
- Represent an image region with a count of these “visual words”



# Key idea 1: “Visual Words”

- Cluster the keypoint descriptors
- Assign each descriptor to a cluster number
- Represent an image region with a count of these “visual words”
- An image is a good match if it has a lot of the same visual words as the query region



# Naïve matching is still too slow

Imagine matching 1,000,000 images, each with 1,000 keypoints

# Key Idea 2: Inverse document file

- Like a book index: keep a list of all the words (keypoints) and all the pages (images) that contain them.
- Rank database images based on tf-idf measure.

tf-idf: Term Frequency – Inverse Document Frequency

$$t_i = \frac{n_{id}}{n_d} \log \frac{N}{n_i}$$

# times word appears in document

# words in document

# documents

# documents that contain the word

# Fast visual search

“Video Google”, Sivic and Zisserman, ICCV 2003

“Scalable Recognition with a Vocabulary Tree”, Nister and Stewenius, CVPR 2006.



# 110,000,000 Images in 5.8 Seconds



Slide Credit: Nister





Slide Credit: Nister





Slide Credit: Nister



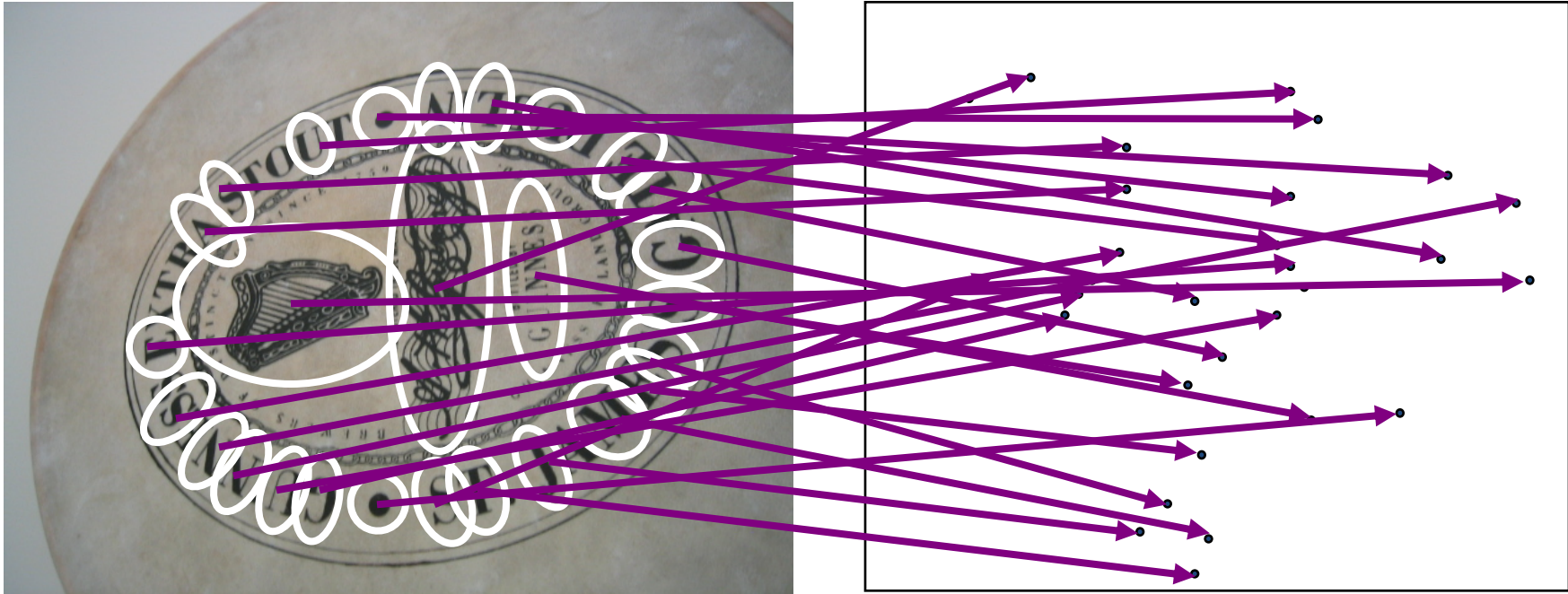
(C) L.W. Wildervanck

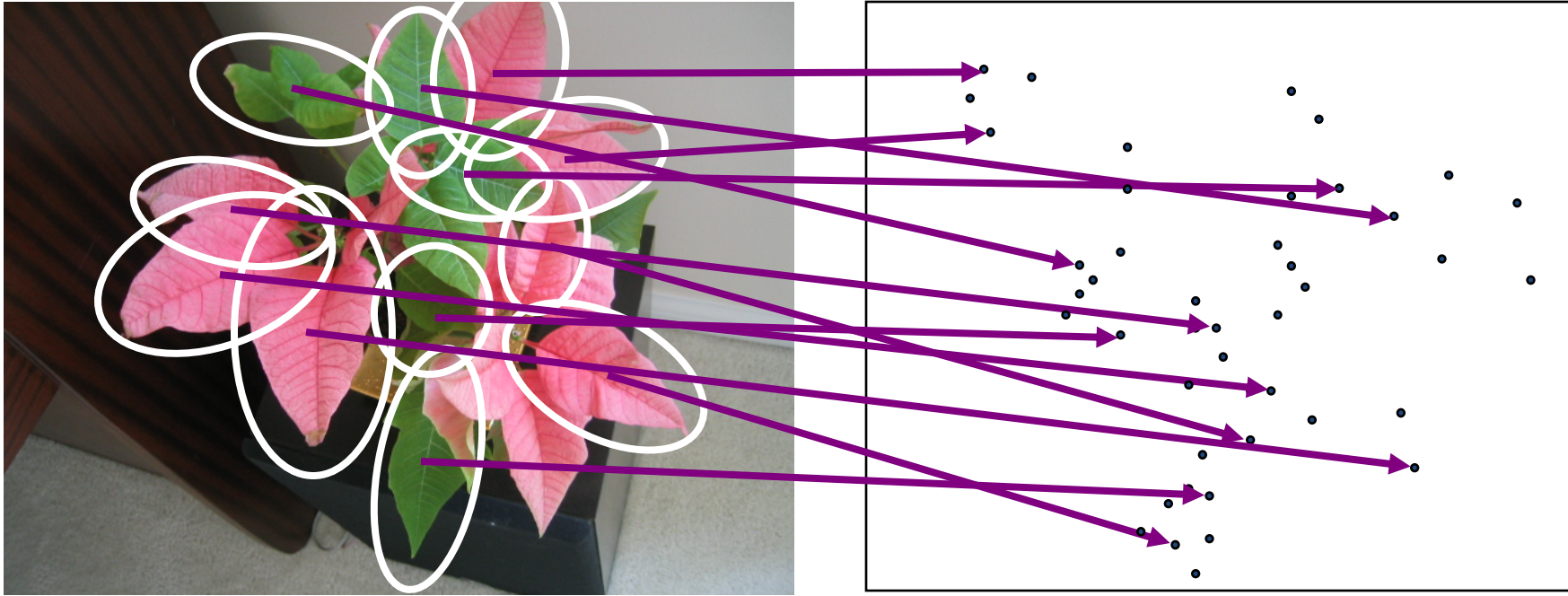
Slide Credit: Nister

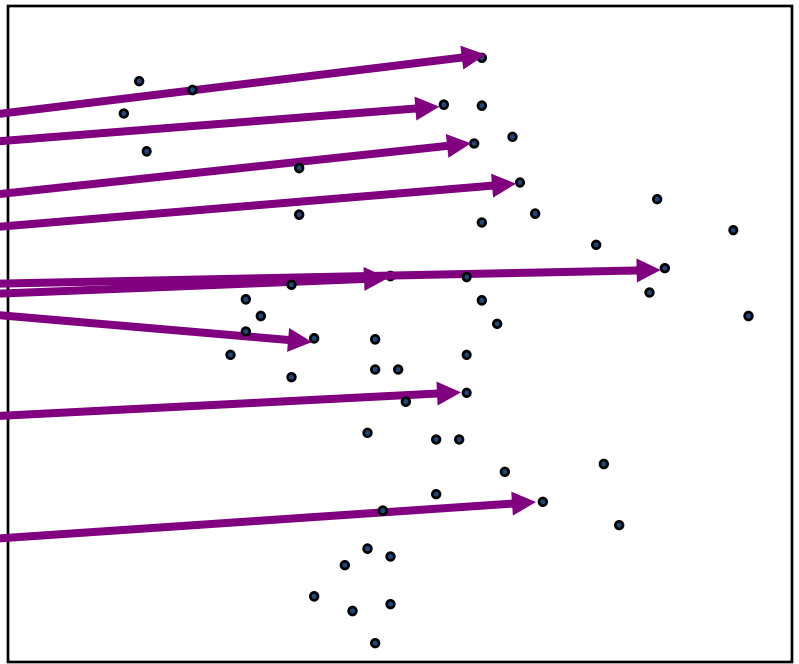
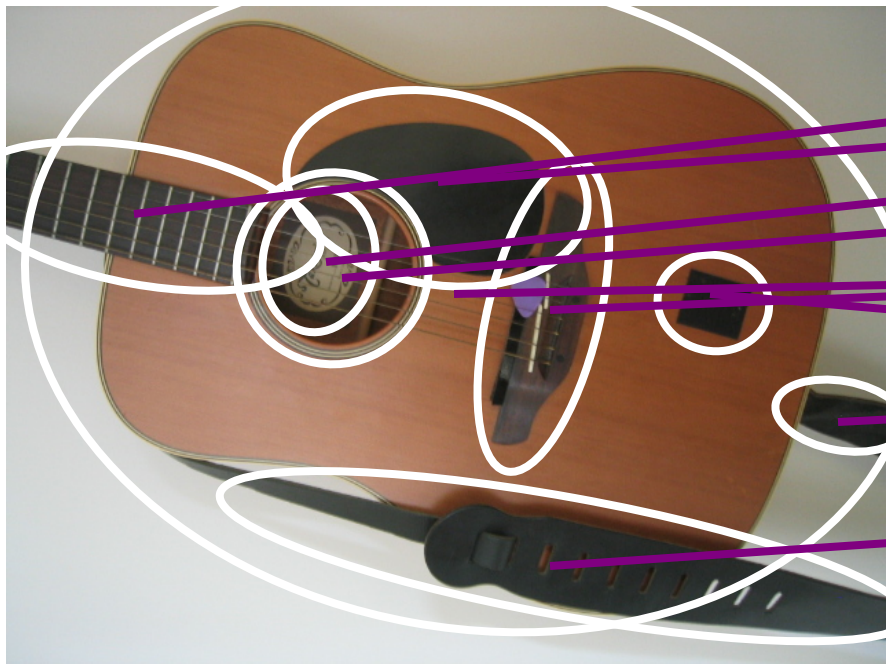
# Recognition with K-tree

Following slides by David Nister (CVPR 2006)

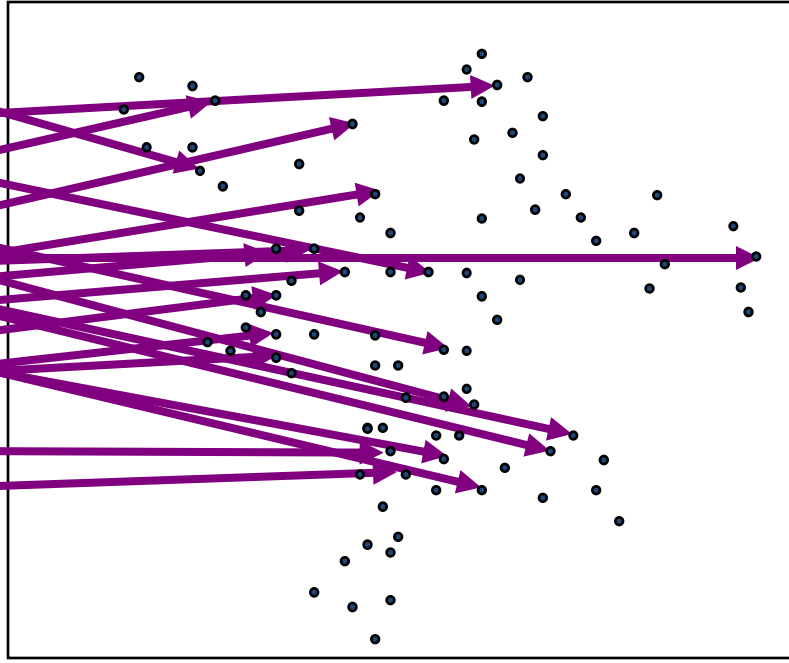
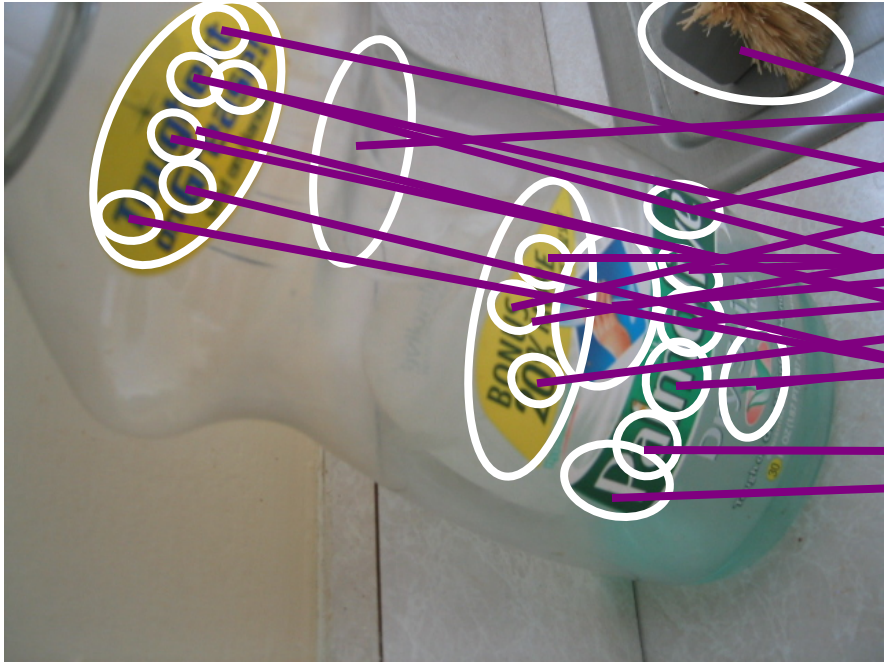


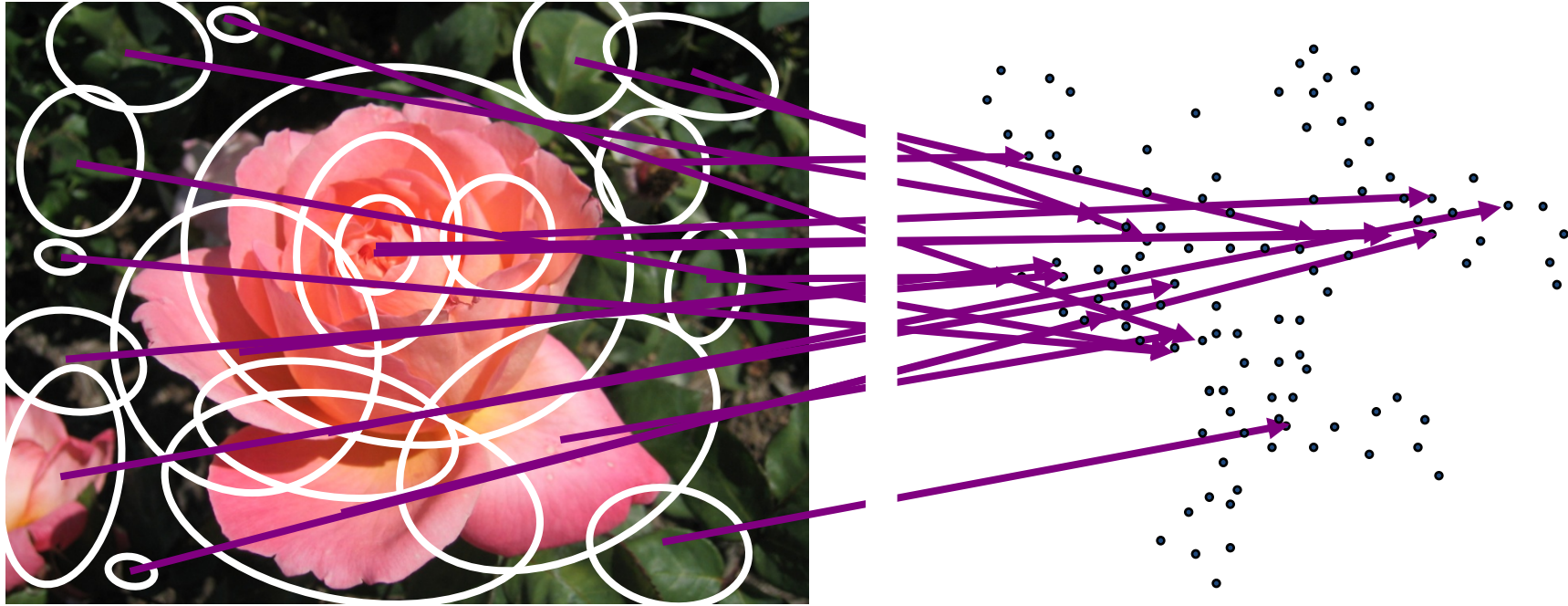


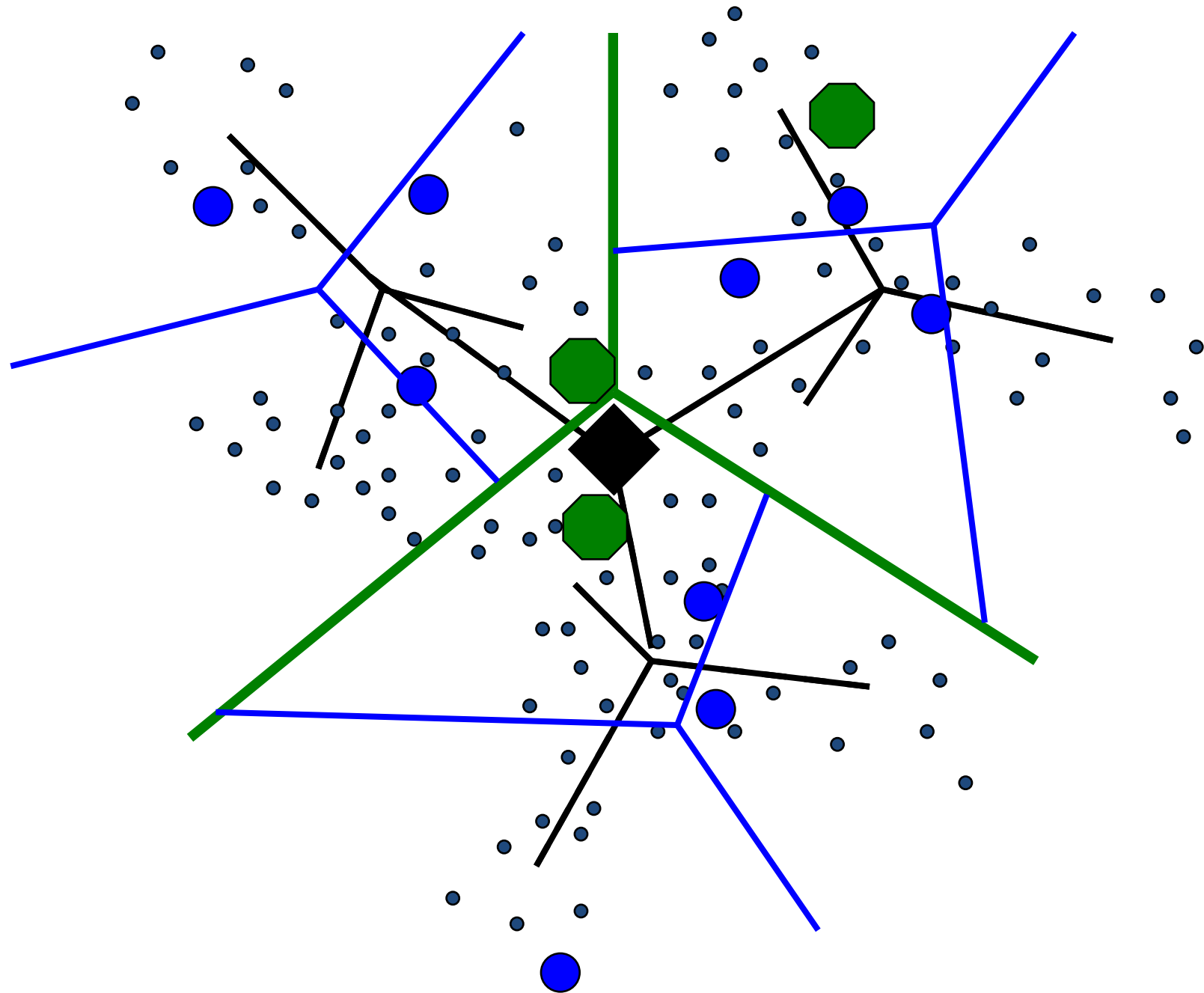


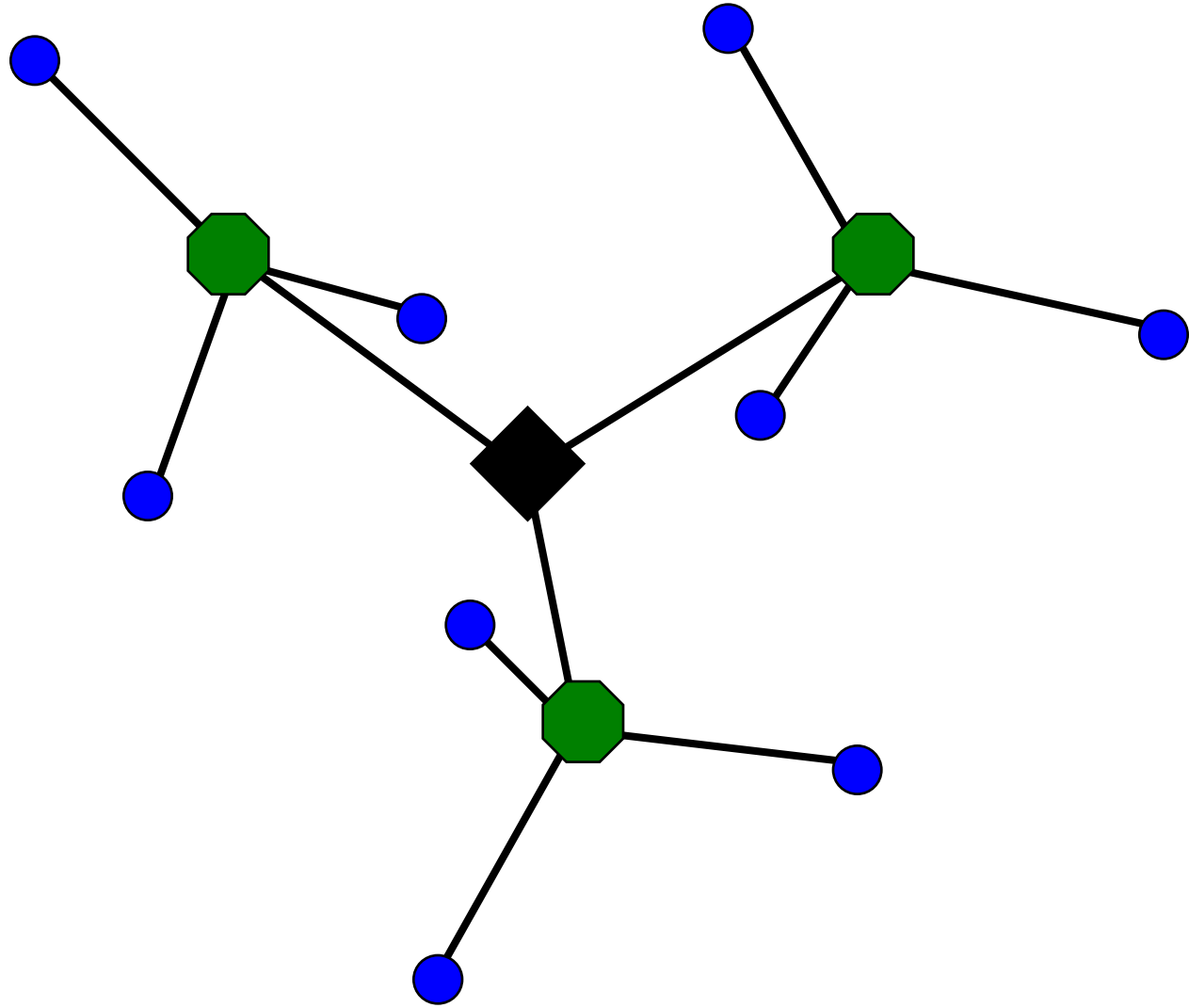


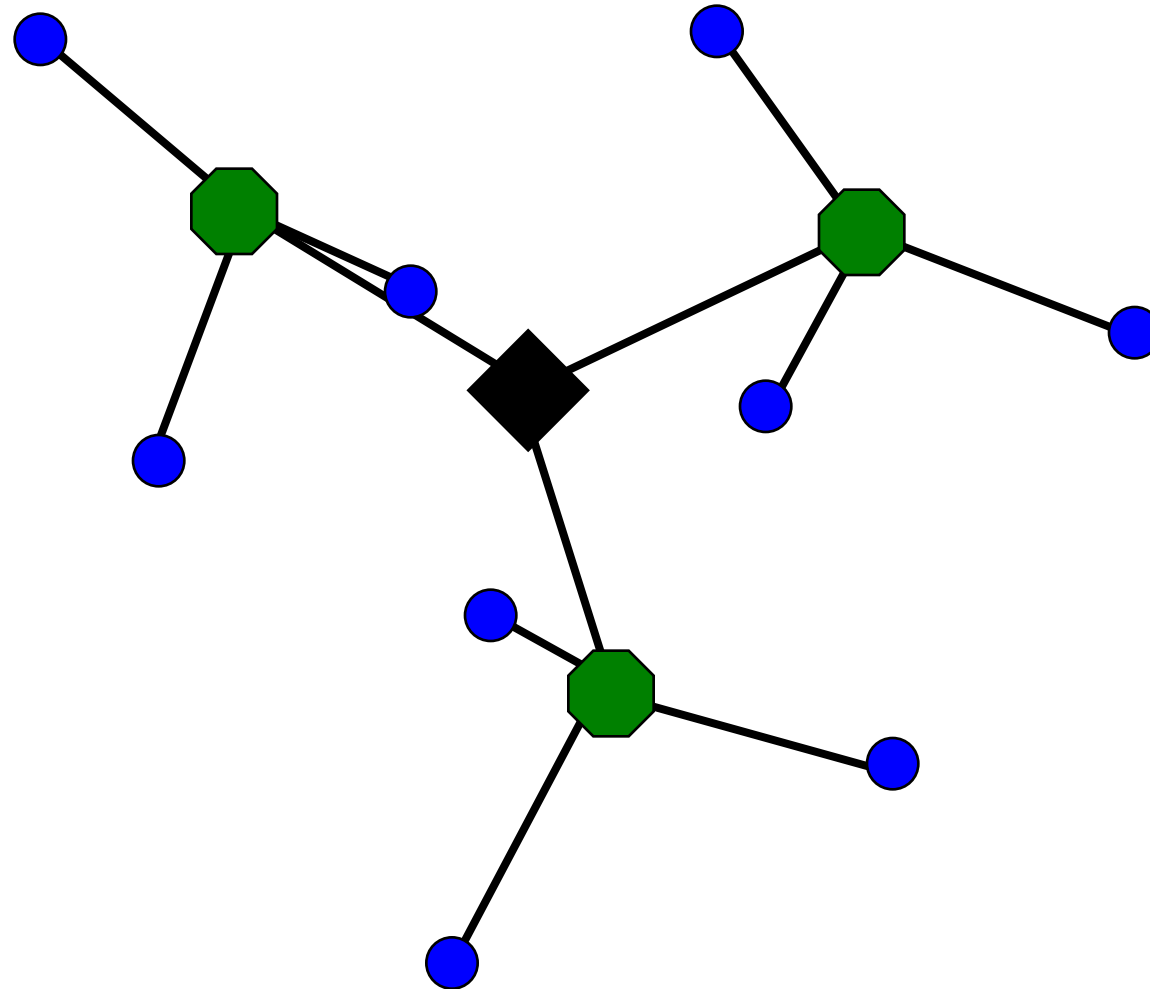


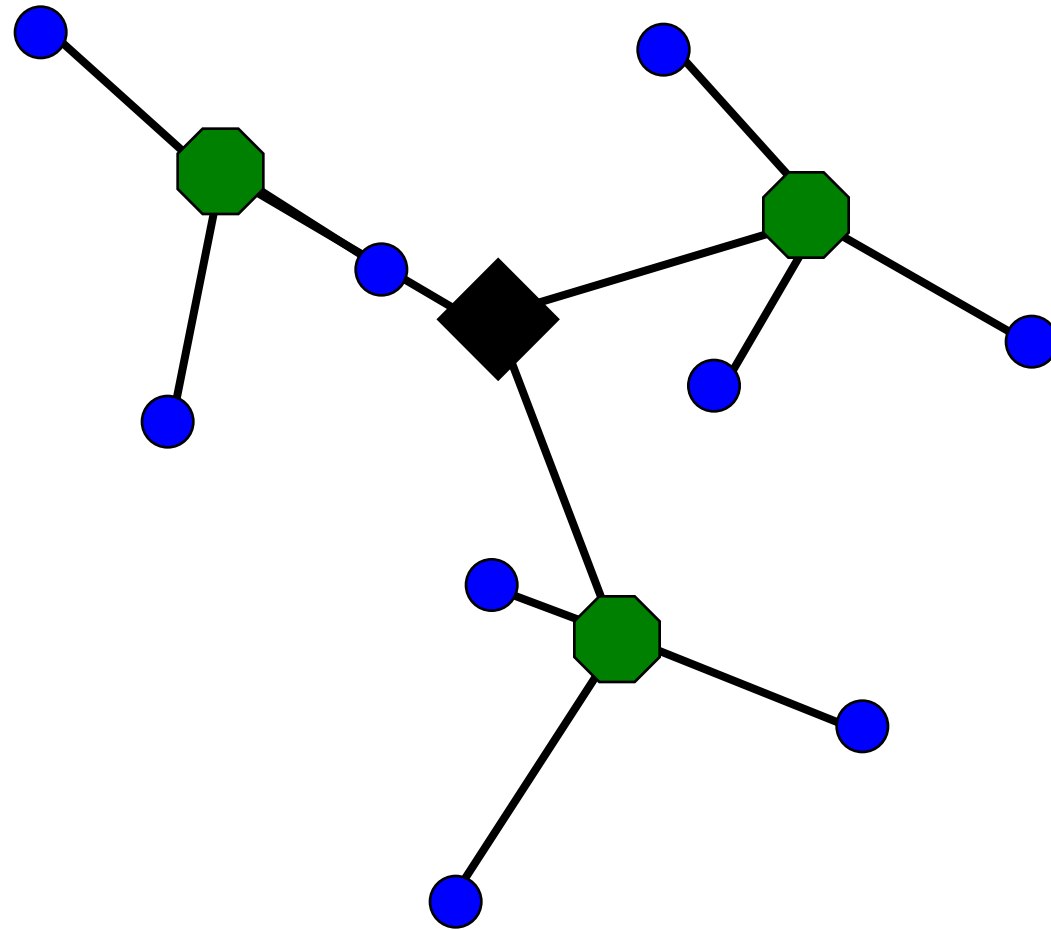


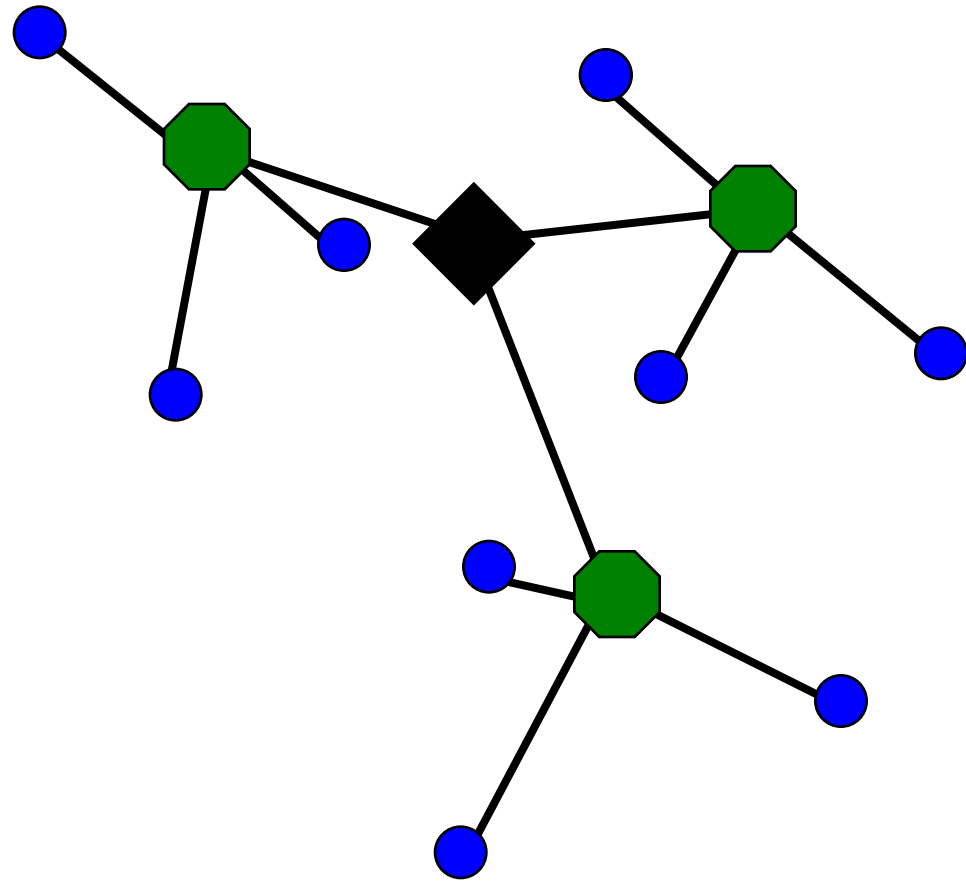


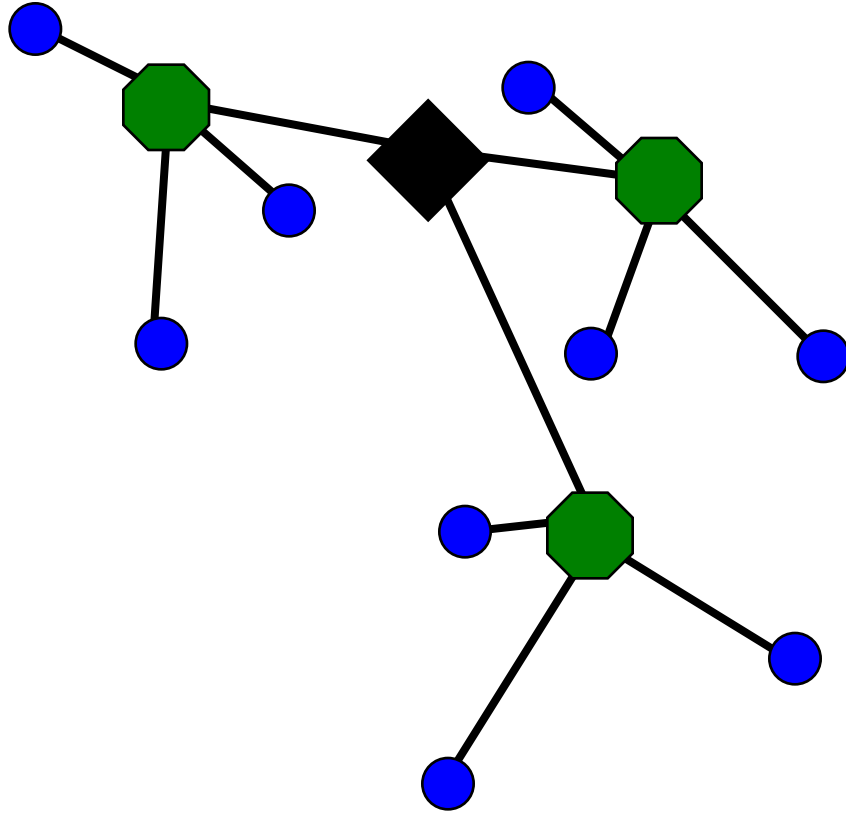




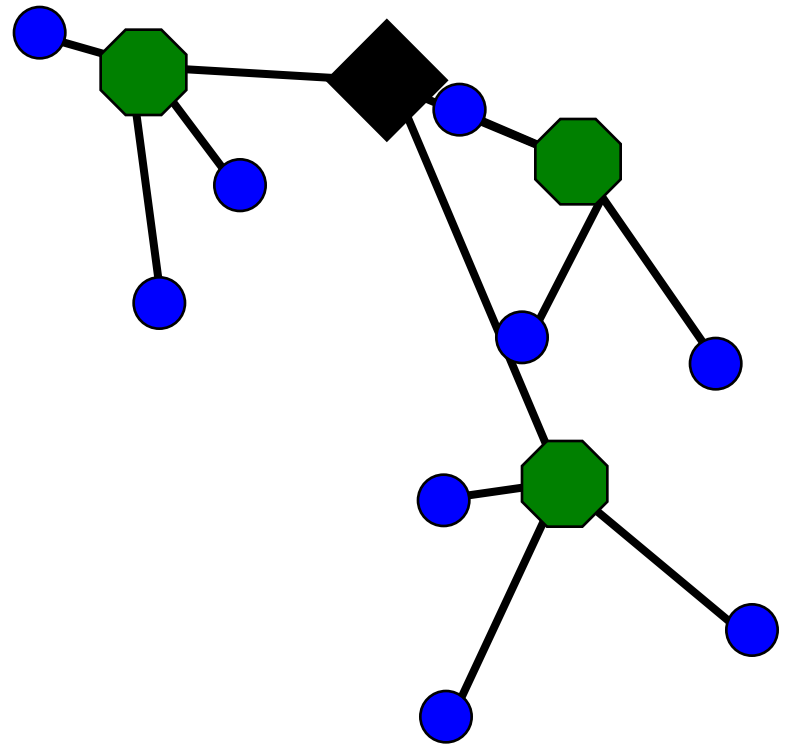


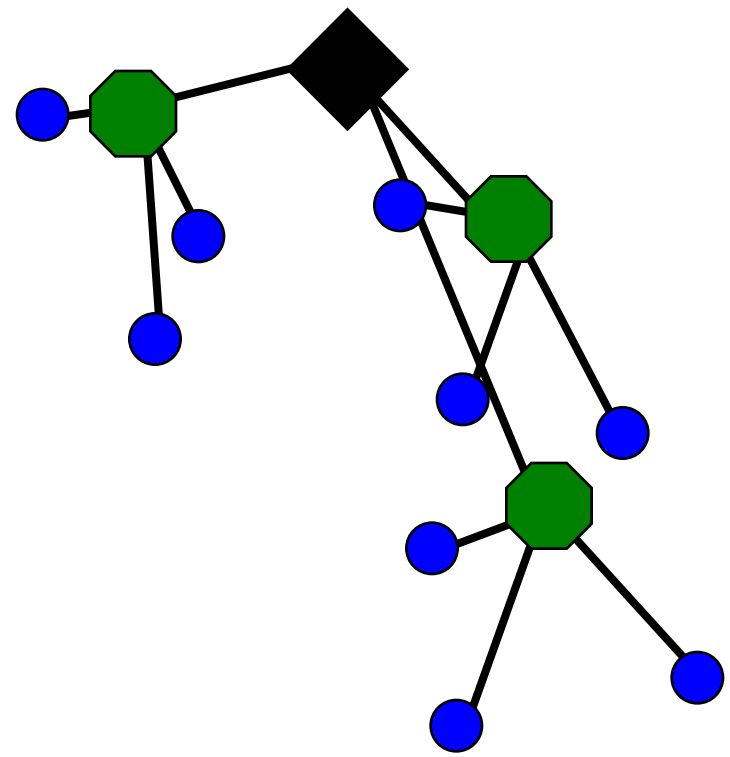


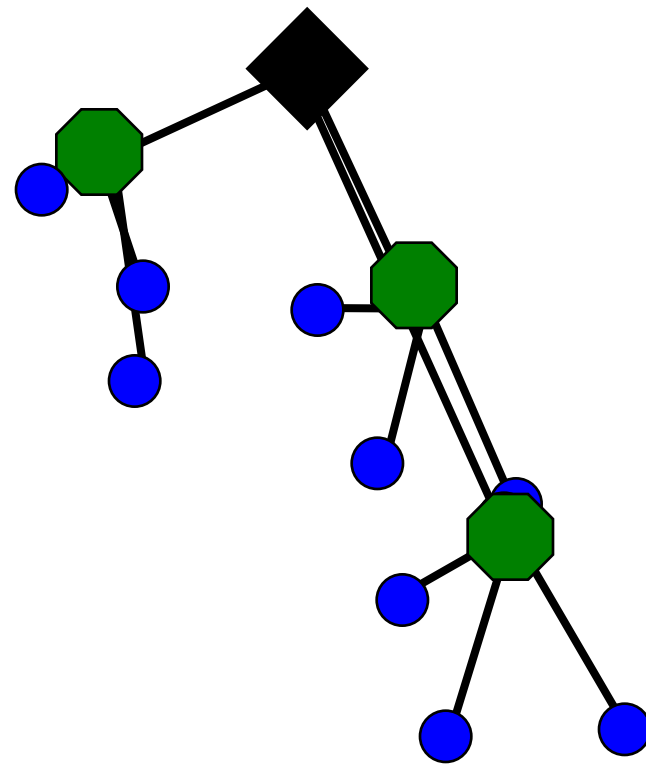


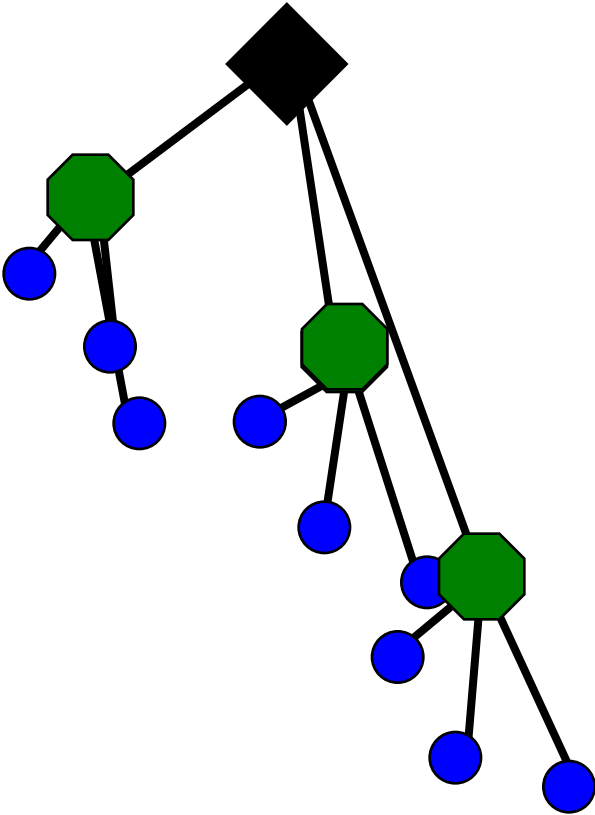


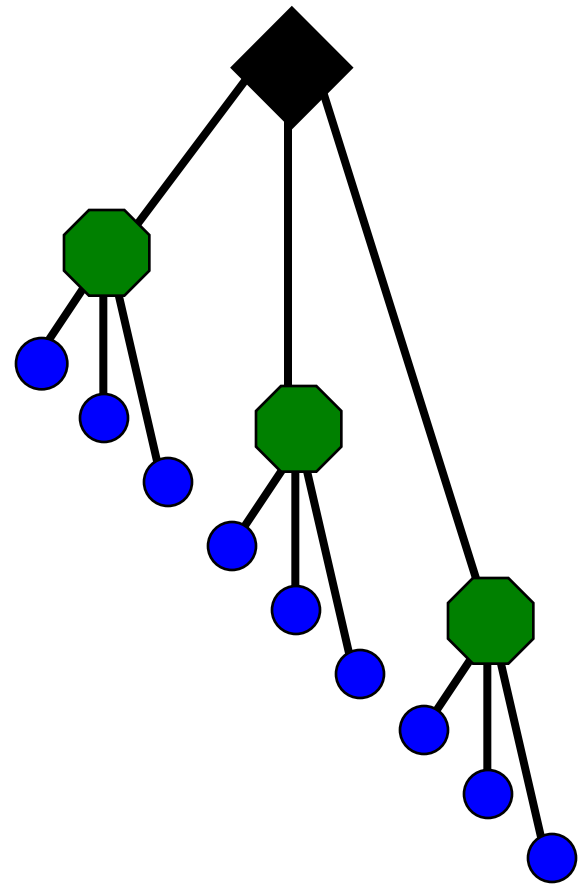


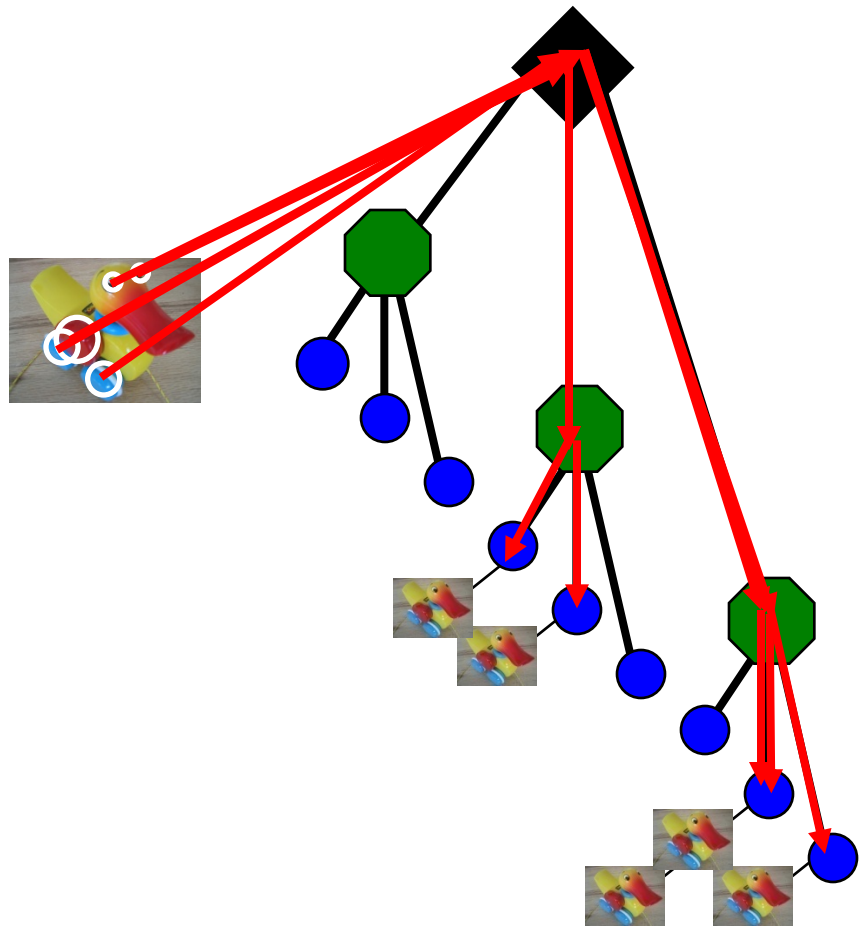


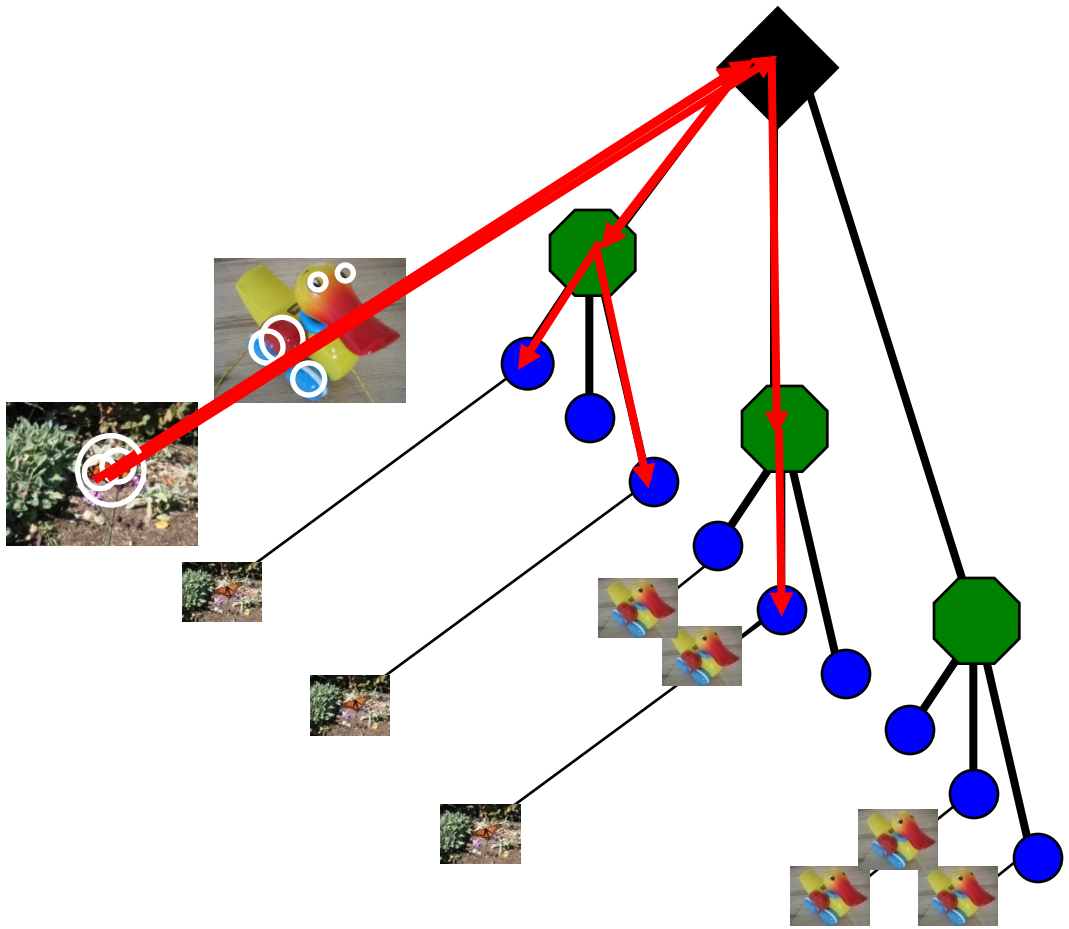


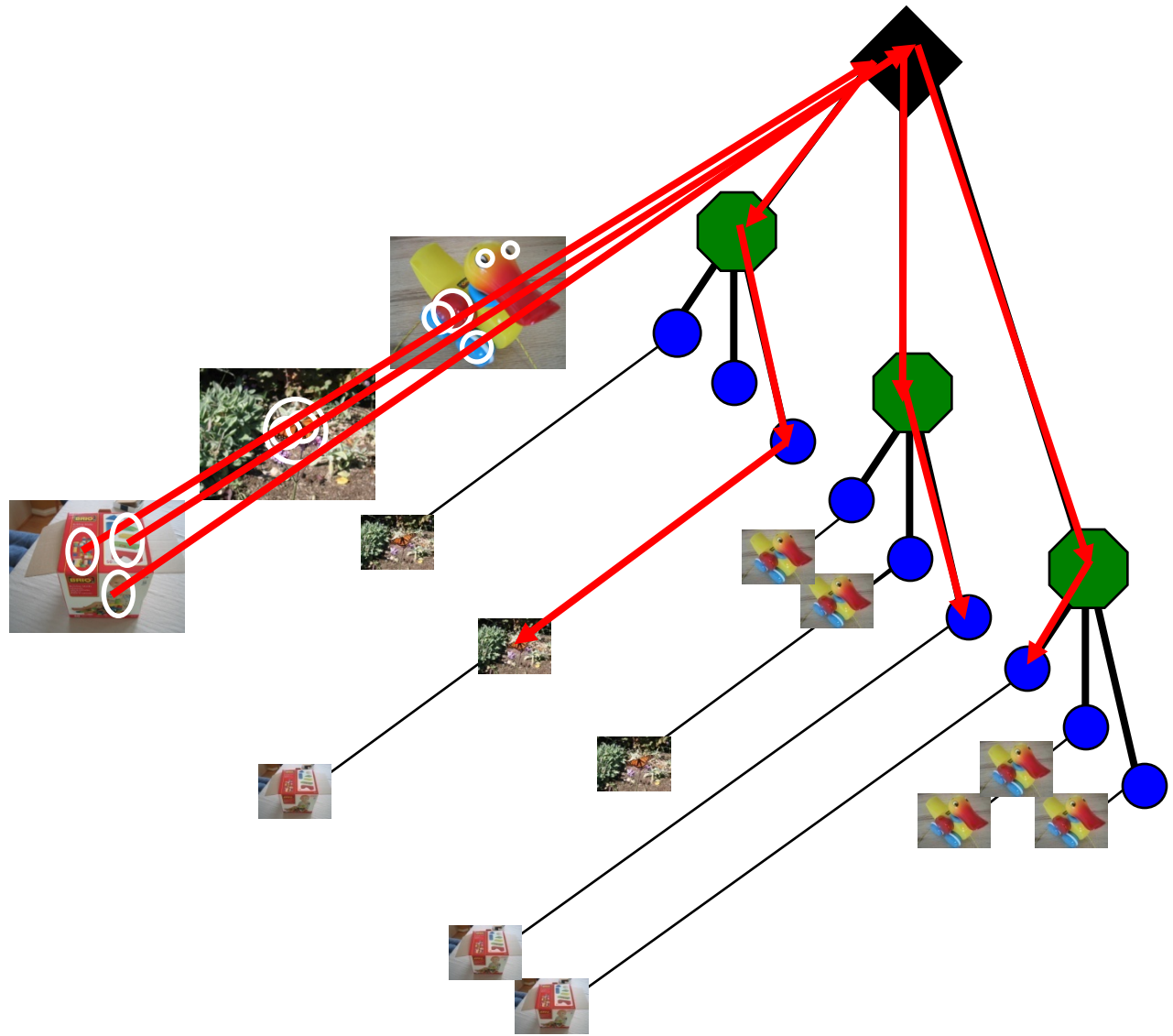




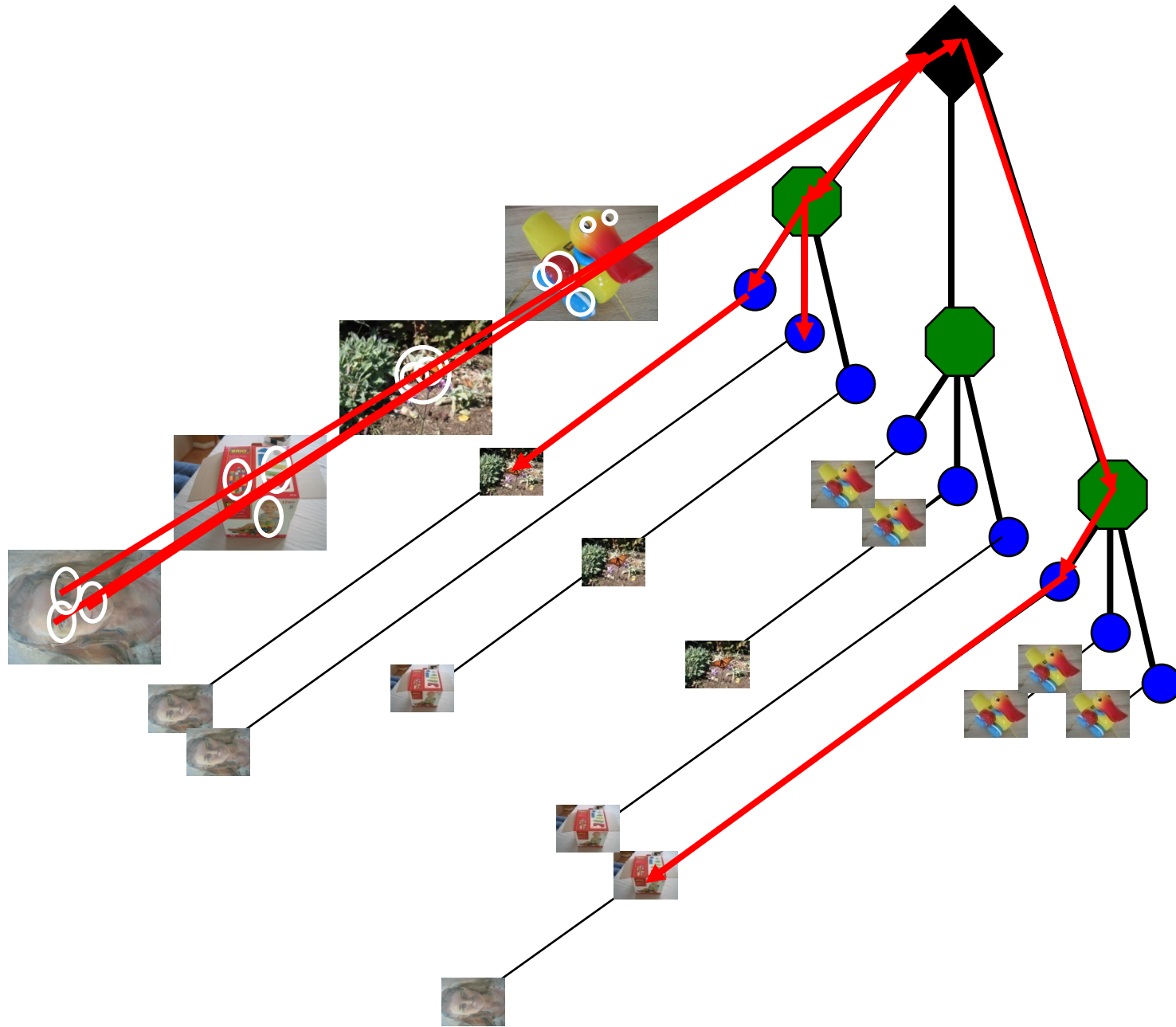


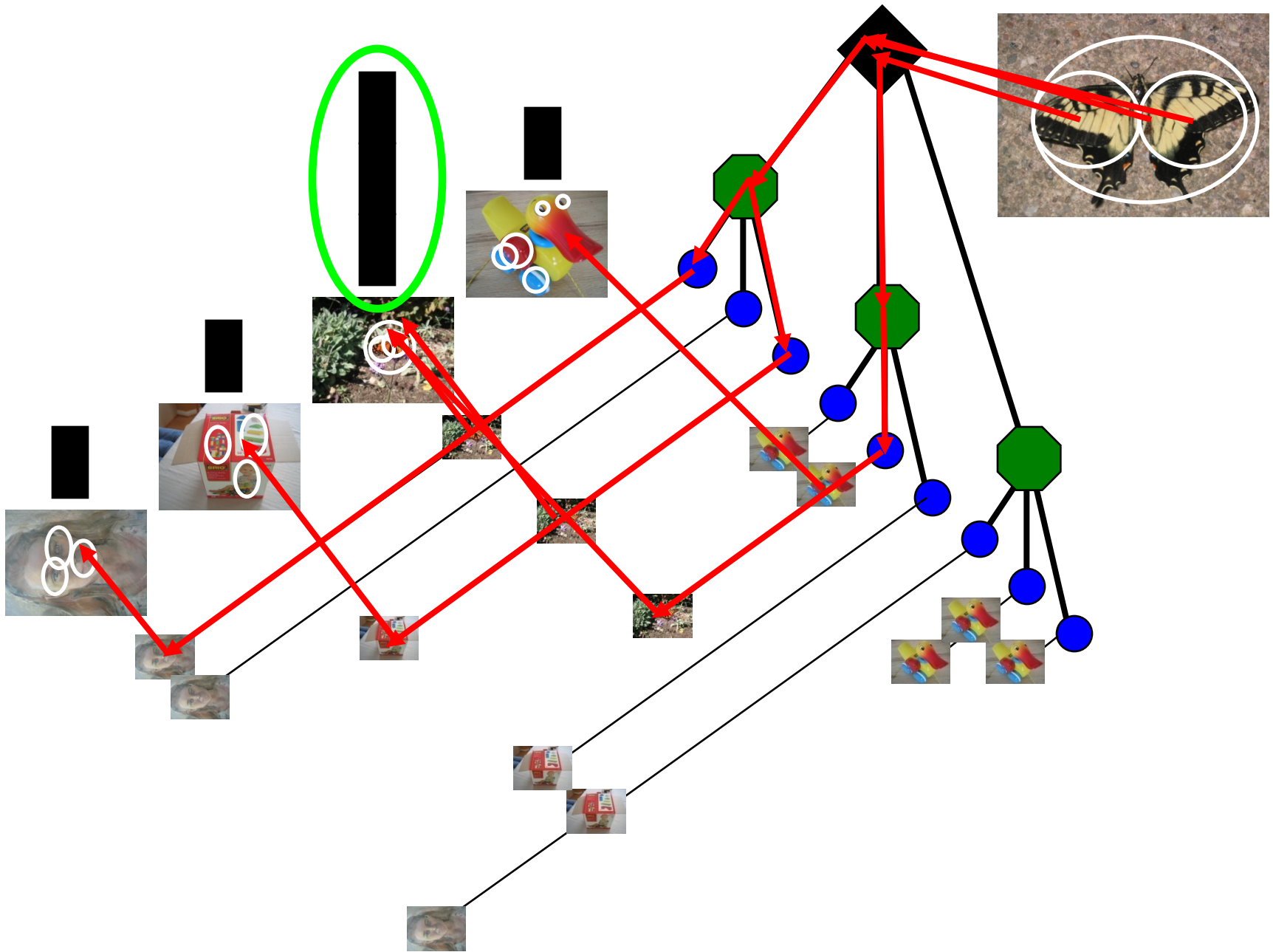




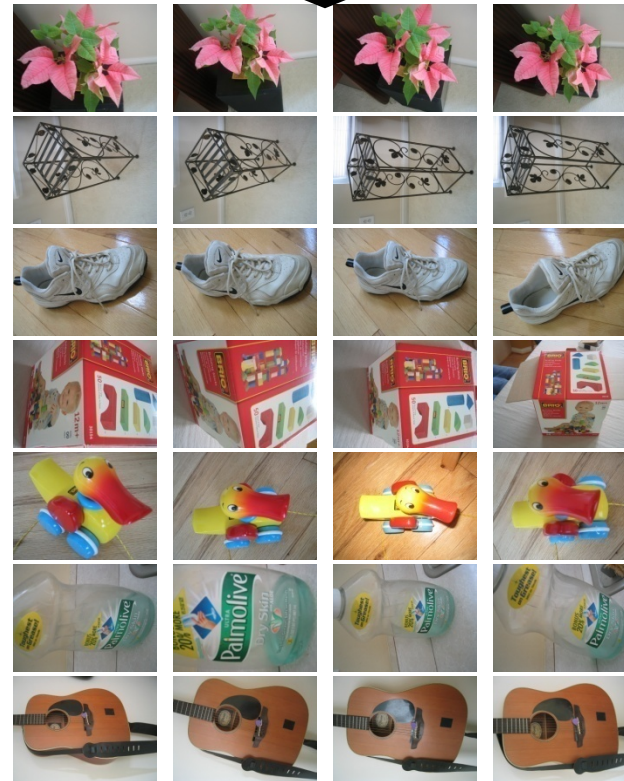
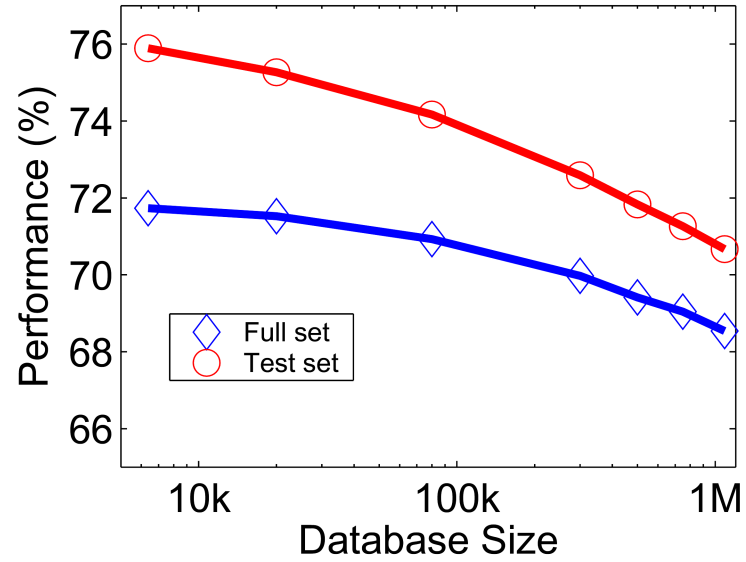








# Performance



## ImageSearch at the VizCentre

New query:

File is 500x320

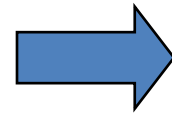


Top n results of your query.

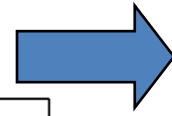


bourne/im1000043322.pgm bourne/im1000043323.pgm bourne/im1000043326.pgm bourne/im1000043327.pgm

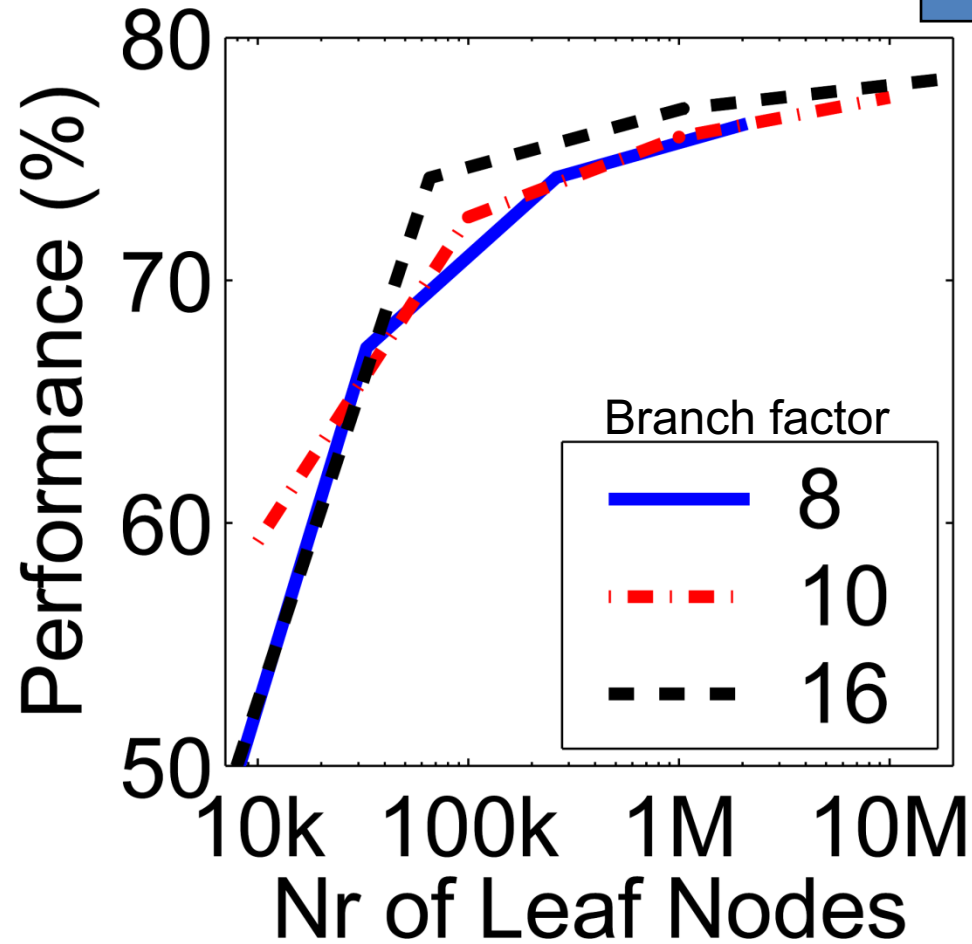
# More words is better



Improves  
Retrieval

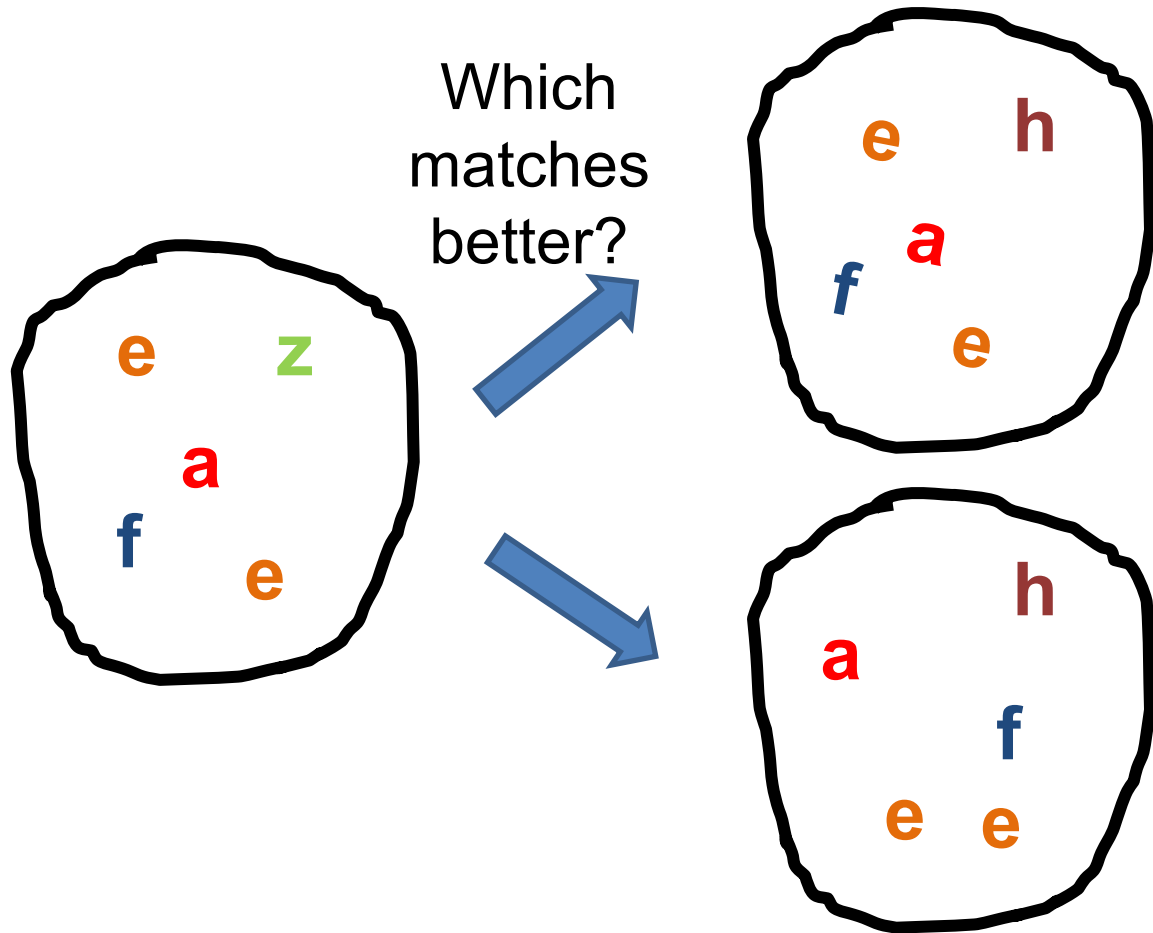


Improves  
Speed



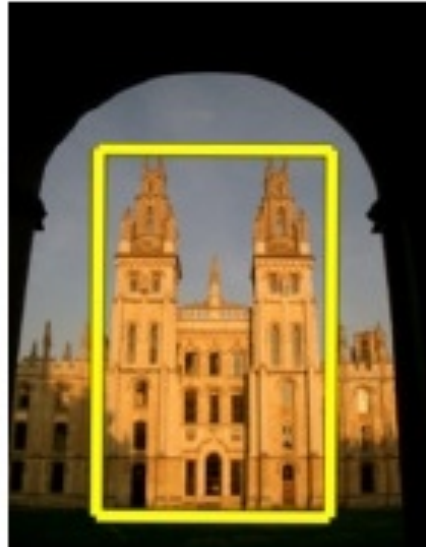
# Can we be more accurate?

So far, we treat each image as containing a “bag of words”,  
with no spatial information



# Can we be more accurate?

So far, we treat each image as containing a “bag of words”,  
with no spatial information



Real objects have consistent geometry

# Final key idea: geometric verification

- Goal: Given a set of possible keypoint matches, figure out which ones are geometrically consistent

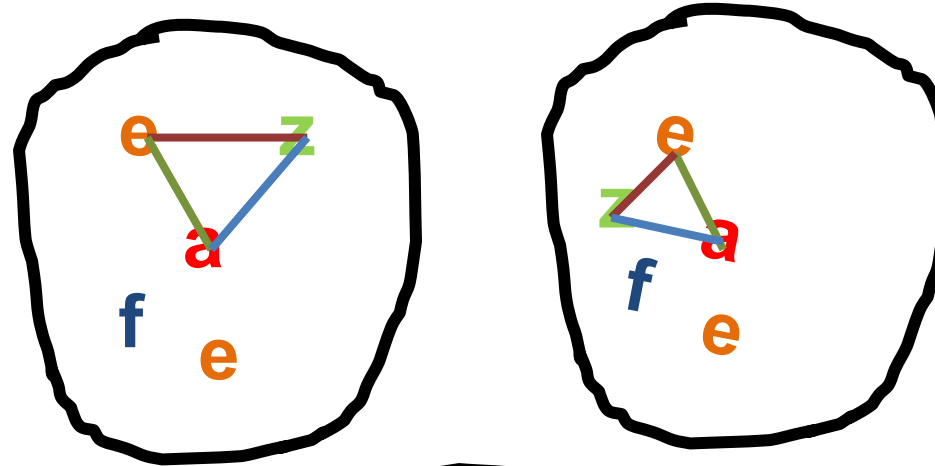
**How can we do this?**

# Final key idea: geometric verification

## RANSAC for affine transform

Repeat N times:

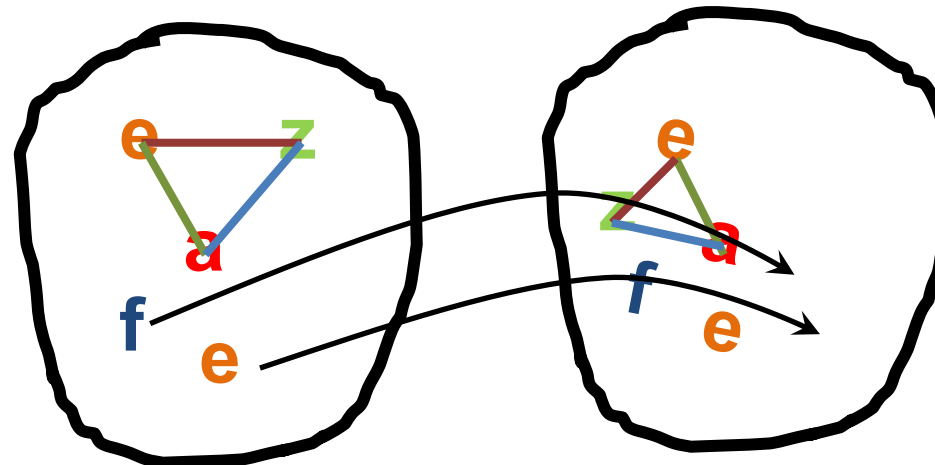
Randomly choose 3 matching pairs



Estimate transformation

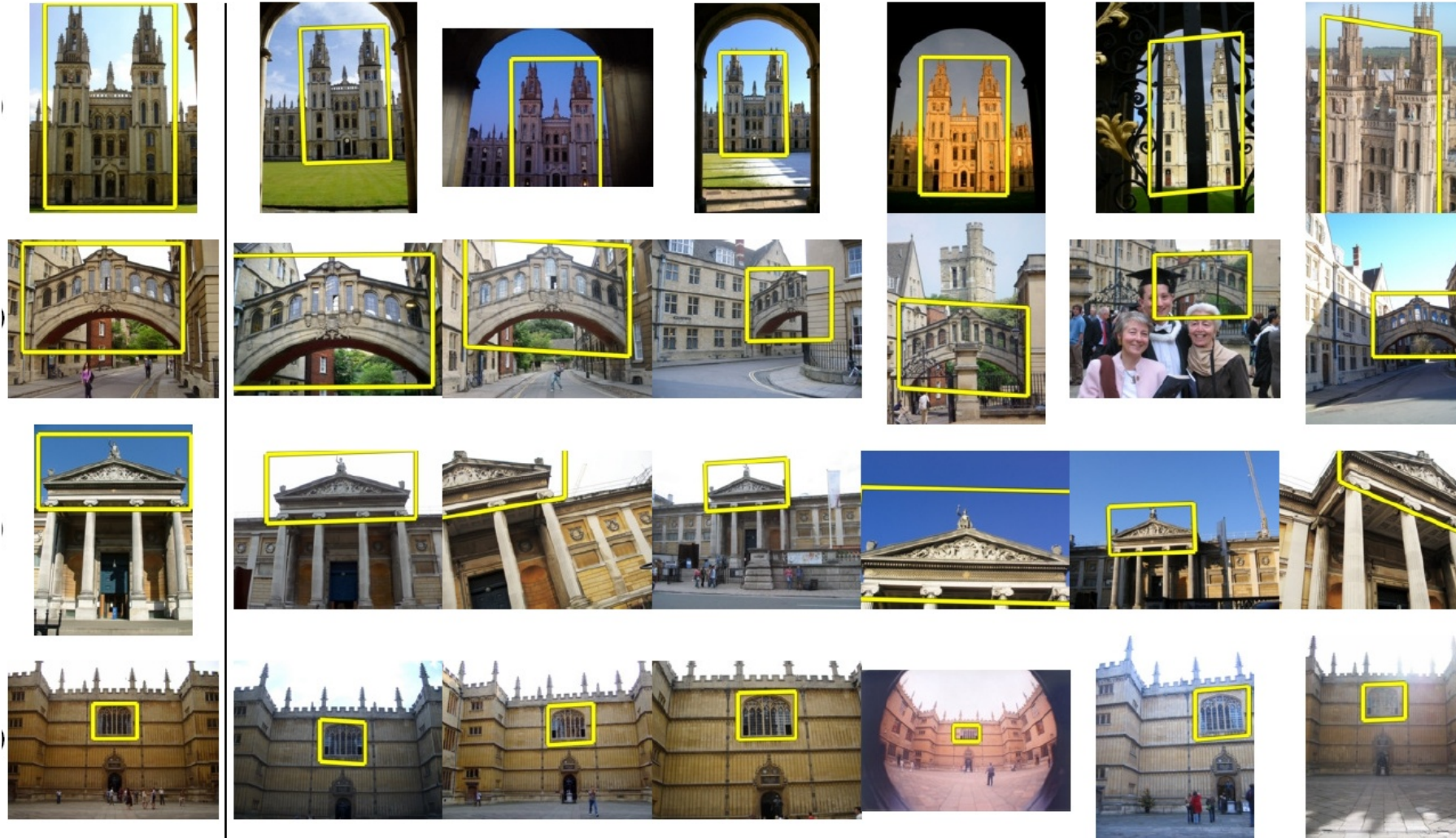


Predict remaining points and count "inliers"





# Application: Large-Scale Retrieval

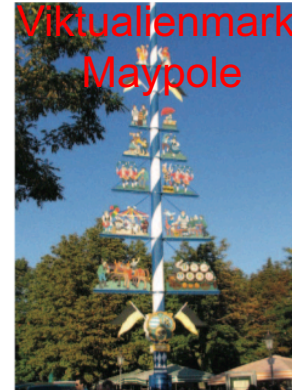


Query

Results on 5K (demo available for 100K)

[Philbin CVPR'07]

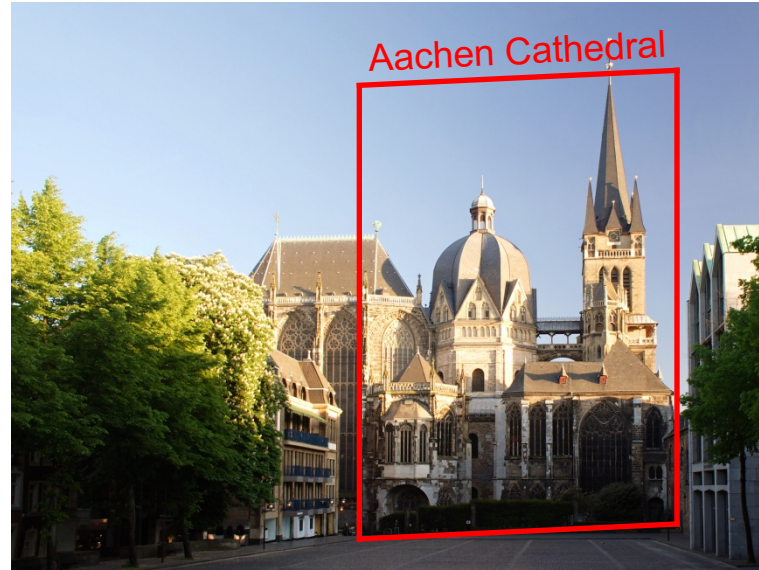
# Application: Image Auto-Annotation



Left: Wikipedia image  
Right: closest match from Flickr



# Example Applications



## Mobile tourist guide

Self-localization

Object/building recognition

Photo/video augmentation

# Video Google System

1. Collect all words within query region
2. Inverted file index to find relevant frames
3. Compare word counts
4. Spatial verification

Sivic & Zisserman, ICCV 2003

- Demo online at :  
<http://www.robots.ox.ac.uk/~vgg/research/vgoogle/index.html>



Query region



Retrieved frames

# Summary: Uses of Interest Points

- Interest points can be detected reliably in different images at the same 3D location
  - DOG interest points are localized in  $x$ ,  $y$ , scale
- SIFT is robust to rotation and small deformation
- Interest points provide correspondence
  - For image stitching
  - For defining coordinate frames for object insertion
  - For object recognition and retrieval

# Next class

- Opportunities of scale: stuff you can do with millions of images
  - Texture synthesis of large regions
  - Recover GPS coordinates
  - Etc.