#### **IMAGE ANALYSIS**

Image analysis methods extract information from an image by using automatic or semiautomatic techniques termed: scene analysis, image description, image understanding, pattern recognition, computer/machine vision etc.).

Image analysis differs from other types of image processing methods, such as *enhancement* or *restoration* in that the final result of image analysis procedures is a *numerical output* rather than a picture.

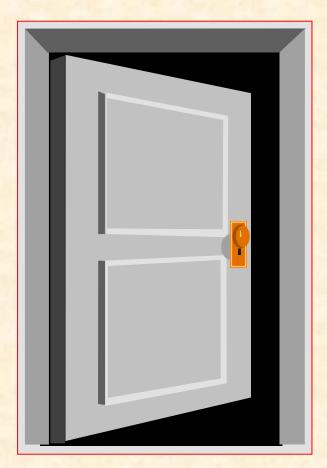
#### **IMAGE ANALYSIS**

#### Classification

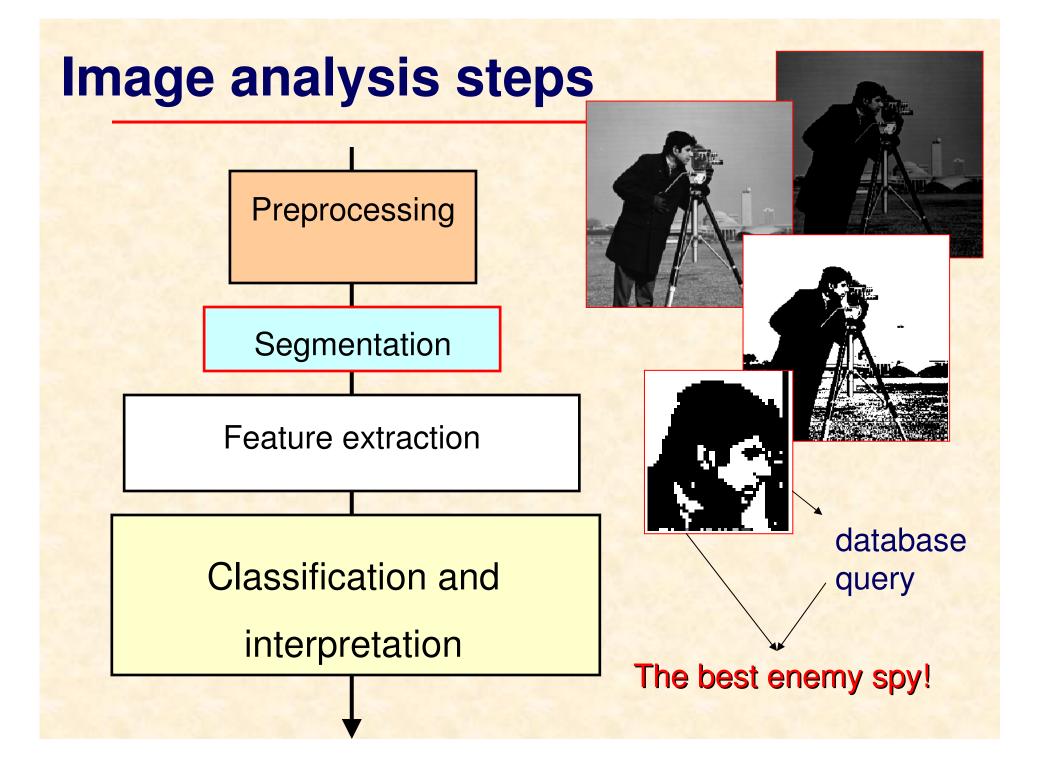


Search the database for this fingerprint

#### Image understanding



Door open?



#### **Examples of Computer Vision Applications**

#### $\Rightarrow$ optical character recognition (OCR)

 mail sorting, label reading, product billing, ban-check processing, text reading,

#### ⇒ Medical image analysis

 Tumor detection, size/shape measurement of organs, chromosome analysis, blood cell count ,...

#### $\Rightarrow$ Industrial robotics

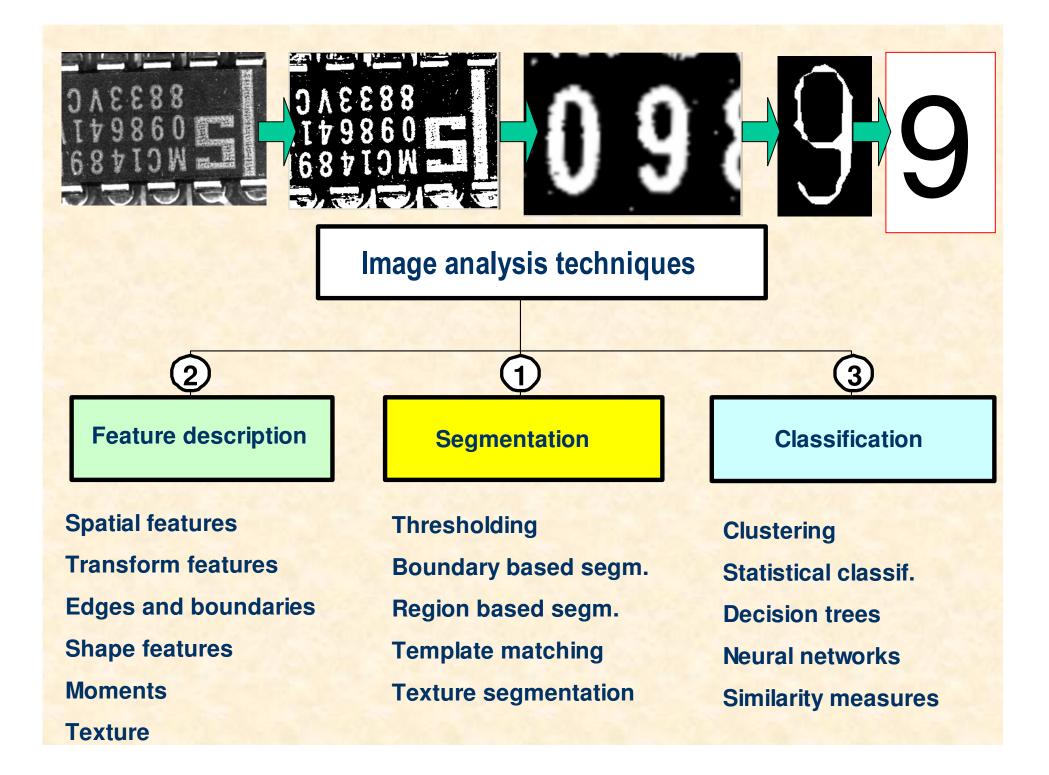
 Recognition and interpretation of objects in a scene, motion control through visual feedback

#### $\Rightarrow$ Cartography, Geology

Map making from photographs, plotting weather maps, oil exploration

#### $\Rightarrow$ forensics (biometry) and military applications

 fingerprint and face recognition, target detection and identification, guidance of helicopters and aircraft in landing, remote guiding of missiles



### Segmentation

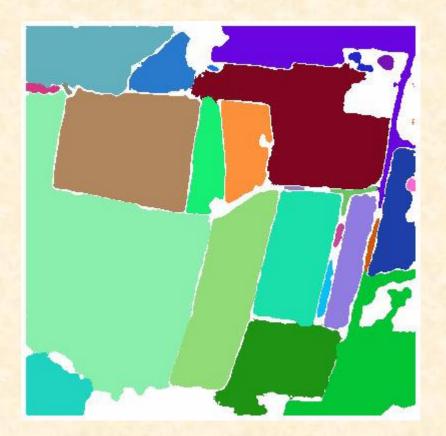
*Image segmentation* is a key step in image analysis.

Segmentation subdivides an image into its components. It distinguishes objects of interest from background, e.g. Optical Character Recognition (OCR) systems first segment character shapes from an image before they start to recognise them.

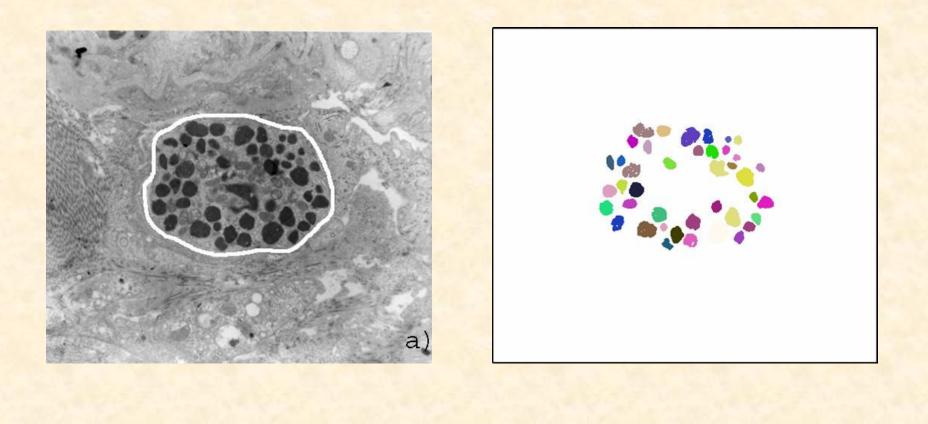
The segmentation operation only subdivides an image; it does not attempt to recognise the segmented image parts.

# **Aerial photos**





### **Microscope image of cells**



## Thresholding

Amplitude **thresholding** (i.e. in the brightness domain) is the basis approach to image segmentation.

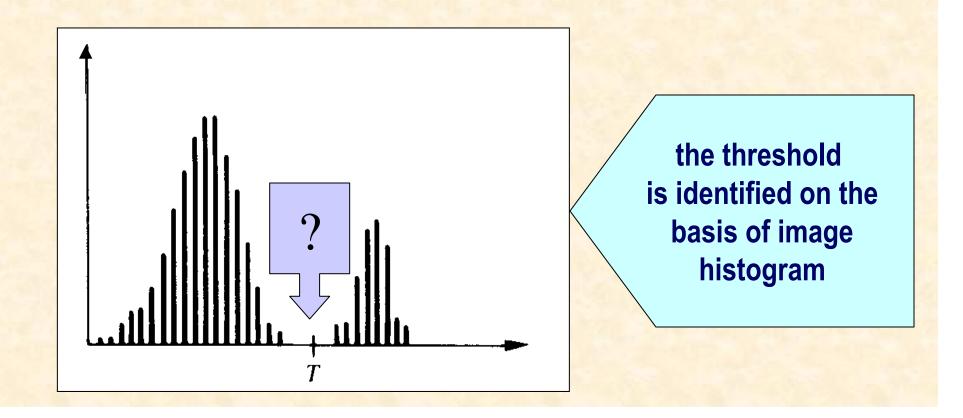
A threshold T is selected a that would separate the two modes, i.e. any image point for which f(x,y)>T is considered as an **object**; otherwise, the point is called a **background** point.

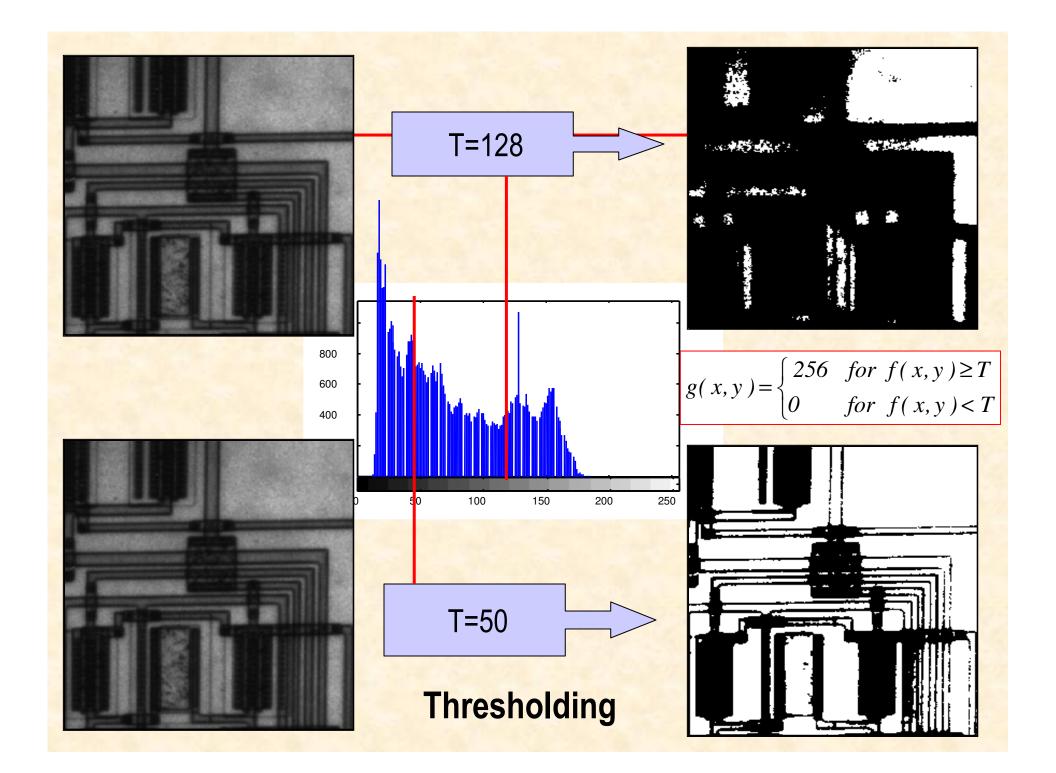
The thresholded image (binary image) is defined by:

$$g(x, y) = \begin{cases} 1 & for \ f(x, y) \ge T & \text{object points} \\ 0 & for \ f(x, y) < T & \text{background points} \end{cases}$$

# Thresholding

Suppose an image f(x,y) contains bright objects surrounded by dark background and its gray-level histogram is shown in the figure.





### **DEMO MATLAB**

### **DEMO MATLAB**



#### %MATLAB x=imread('cameraman.tif'); figure(1), imshow(x); bw=im2bw(x,0.5); figure(2), imshow(bw)

## Thresholding

When T is set on the basis of the entire image f(x,y) the threshold is called **global**.

If T depends on spatial coordinates (x,y) the threshold is termed **dynamic**.

If *T* depends on both f(x,y) and some local image property p(x,y) - e.g., the average gray level in a neighbourhood centred on (x,y), the threshold is called **local** and *T* is set according to a test function:

$$T = T[p(x, y), f(x, y)]$$

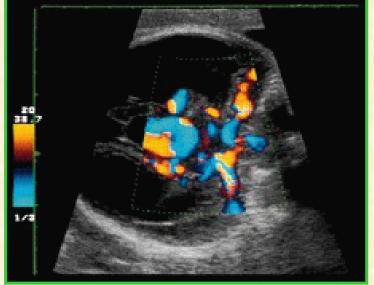
## Thresholding

In the case of **multilevel thresholding** the threshold becomes a vector  $T = [T_1, T_2, ..., T_N]$  and an image is partitioned into N+1sub-regions, e.g. for two-level thresholding:

R1: if  $f(x,y) \le T_1$ , R2: if  $T_1 \le f(x,y) \le T_2$ , R3: if  $f(x,y) > T_2$ .

Image thresholding can be extended into more than one dimensions.

This may apply to **multi-band thresholding of colour images** in any colour coordinates, e.g. RGB or HIS.

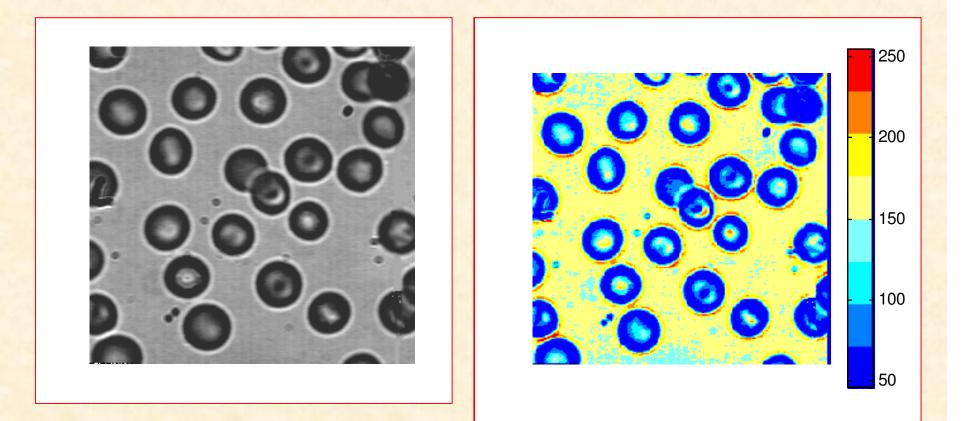


### **DEMO MATLAB**



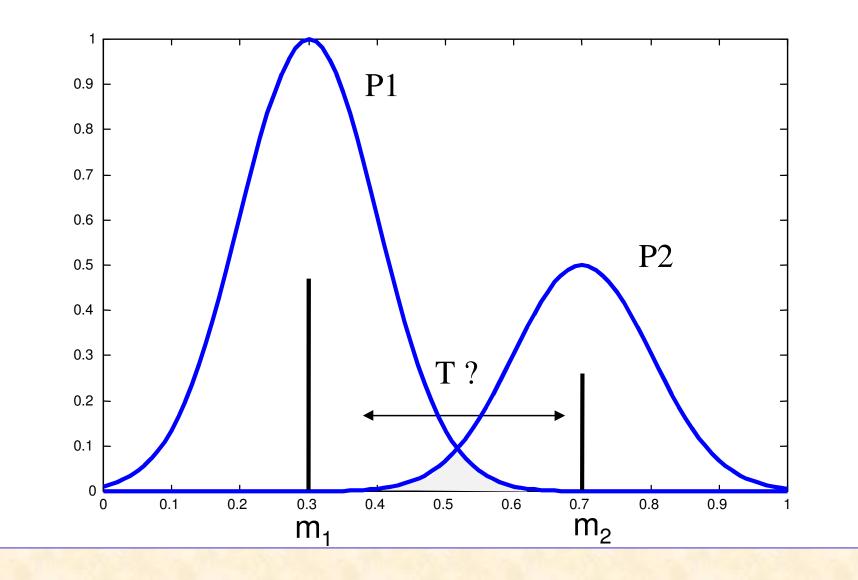
#### %MATLAB x=imread('cameraman.tif'); figure(1), imshow(x); bw=im2bw(x,0.5); figure(2), imshow(bw)

#### **Multilevel thresholding -example**



x=imread('blood1.tif');
figure(1), imshow(x);
figure(2),imshow(x), colormap(jet(16))

## **Thresholding - revisited**



## **Optimum Threshold**

Suppose an image contains two intensity values  $m_1$ ,  $m_2$  combined with additive Gaussian noise N(0, $\sigma$ ) that appear in an image with apriori probabilities P<sub>1</sub> and P<sub>2</sub> correspondingly P<sub>1</sub> + P<sub>2</sub>=1.

The task is to define a threshold level T that would minimise the overall segmentation error

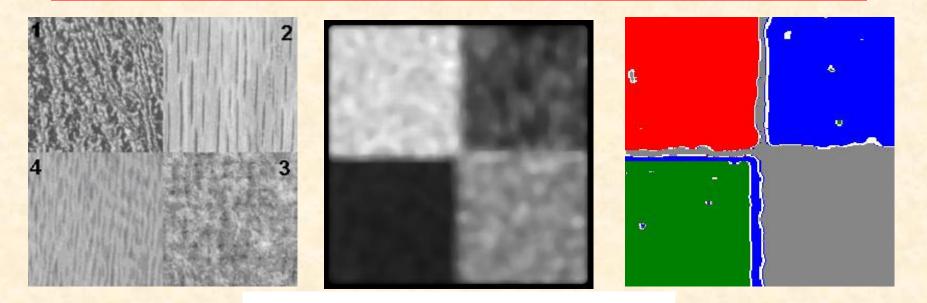
## **Optimum Threshold**

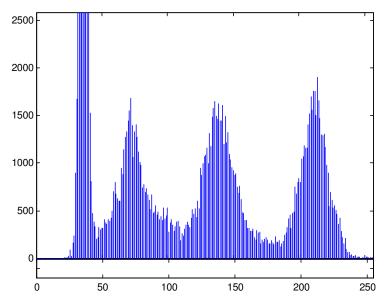
For  $\sigma_1$ ,  $\sigma_2$  solution to this optimisation problem is the following:

$$T = \frac{m_1 + m_2}{2} + \frac{\sigma^2}{m_1 - m_2} \ln\left(\frac{P_2}{P_1}\right)$$

If  $P_1 = P_2$ , the optimal threshold is the average of the image intensities.

#### **Textures from the Brodatz album**



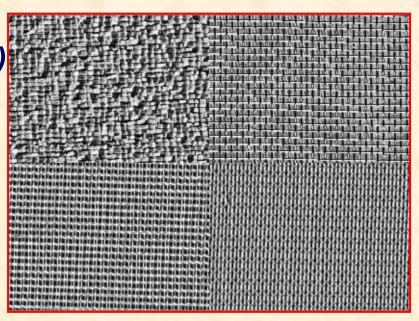


#### **Region-oriented segmentation**

The main idea in *region-based* segmentation techniques is to identify different regions in an image that have similar features (gray level, colour, texture, etc.).

There are two main r segmentation techniques: **I region growing (merging) I region splitting**.

region-based image



# **General formulation**

Let *R* represent the entire image. Segmentation may be viewed as a process that partitions *R* into *N* disjoint regions,  $R_1, R_1, ..., R_N$ , such that:

a) 
$$\sum_{i=1}^{N} R_i = R$$

b)  $R_i$  is a connected region, i = 1, 2, ...N,

c) 
$$R_i \cap R_i = \emptyset$$
 for all *i* and *j*,  $i \neq j$ ,

d)  $P(R_i) = TRUE$  for i = 1, 2, ...N,

e) 
$$P(R_i \cup R_j) = FALSE$$
 for  $i \neq j$ 

where  $P(R_i)$  is a logical predicate over the points in set  $R_i$  and  $\emptyset$  is the empty set.

# **General formulation**

Condition **a)** indicates that the segmentation must be complete (all points assigned a region).

Condition **c**) indicates that the regions must be disjoint. Condition **d**) states that all pixels in a segmented region must satisfy the assumed predicate.

Condition **e**) indicates that distinct regions must be different according to predicate *P*. An example predicate:

$$|z(x, y) - m_i| \leq 2\sigma_i$$

where: z(x,y) is a gray level in (x,y) coordinate,  $m_i$ ,  $\sigma_i$  are the mean and standard variation of the analysed region.

# **Region growing**

In region growing the image is divided into *atomic regions* (e.g., pixels, templates). These "**seed**" points grow by appending to each point other points that have similar properties. The key problem lies in selecting proper criterion (predicate) for merging. A frequently used merging rule is:

Merge two regions if they are "similar" (in terms of a predefined features)

### **Similarity measures**

Popular similarity measures are:

dot product (projection of one vector onto direction of the other):

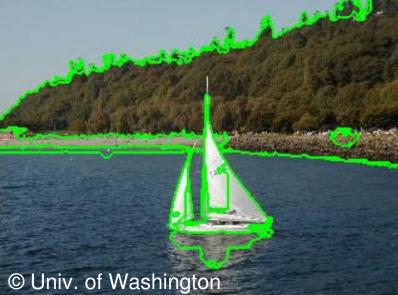
$$\langle x_i^T x_j \rangle = \|x_i\| \|x_j\| \cos(x_i, x_j)$$

and Euclidean distance:

$$d(x_i, x_j) = \sqrt{\sum_k (x_i(k) - x_j(k))^2}$$

#### Image segmentation example



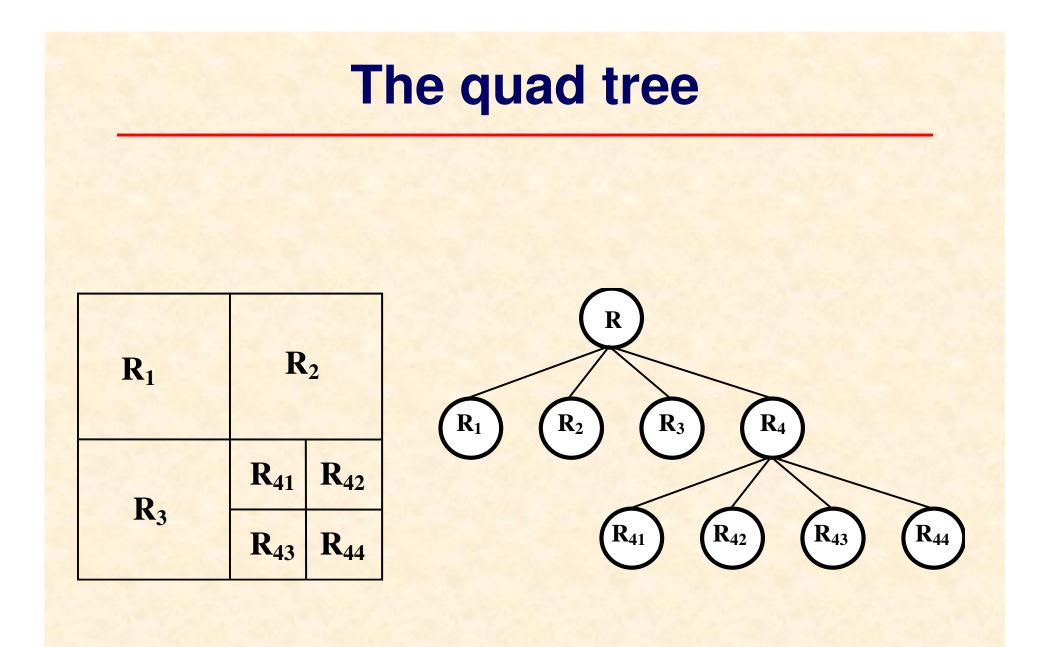


# **Region splitting**

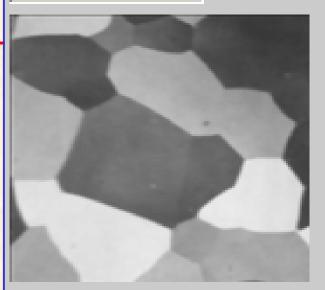
Initially, the image is subdivided into a set of arbitrary disjoint regions, then splits of the regions take place in attempt to satisfy region uniformity criteria (a-e). An example split algorithm works as follows:

Subdivide the entire image successively into smaller and smaller quadrant regions until P(Ri) = TRUE for any region; that is if P is FALSE for any quadrant, subdivide the quadrant into sub-quadrants, and so on.

This splitting technique is called the **quad-tree decomposition**.

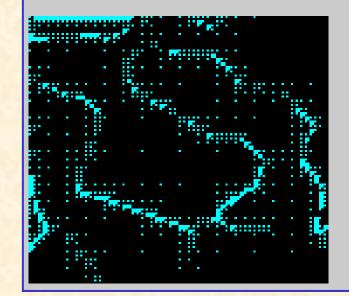




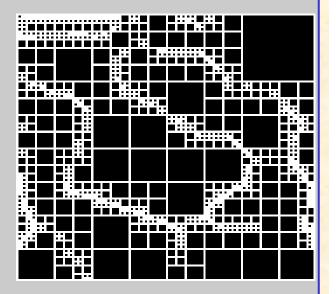


#### DEMO MATLAB (quad tree)

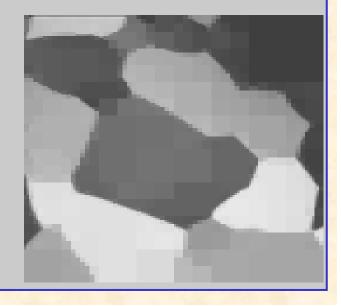




#### Quadtree decomposition



Block means



# **Region splitting and merging**

However, if only splitting is used the final result likely would contain adjacent regions with identical properties. This can be improved by allowing merging as well as splitting. The following procedure can be implemented:

•Split any region Ri if P(Ri) = FALSE,

•Merge any adjacent regions for which  $P(Ri \cup Rj) = TRUE$ ,

•Stop when no further merging or splitting is possible.

An important problem in image analysis is the **detection** of a presence of an object in a scene.

This problem can be solved by using a special type of an image segmentation technique in which an a priori knowledge about the detected object (**a template**) is used to identify its location in a given scene.

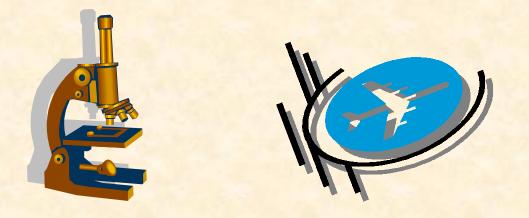


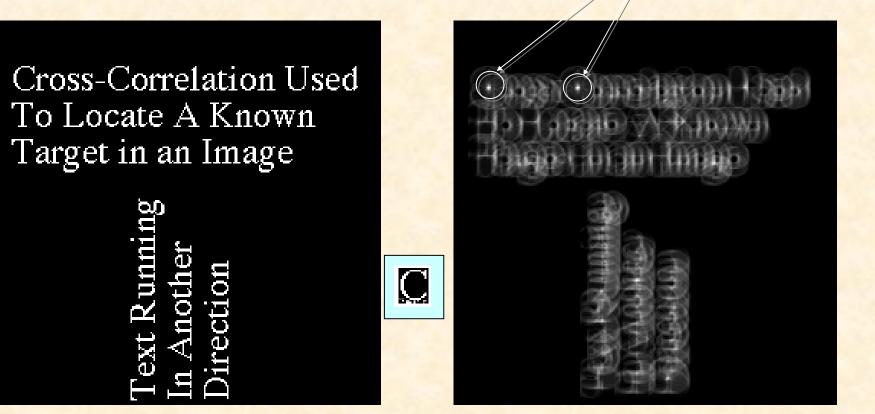
Image correlation technique can be used as the basis for finding matches of a searched pattern w(x,y) of size  $J \times K$  within an image f(x,y) of a larger size  $M \times N$ .

$$c(s,t) = \sum_{x} \sum_{y} f(x,y) w(x-s,y-t) \quad \forall (s,t)$$

the summation is taken over the image region where *w* and *f* overlap.

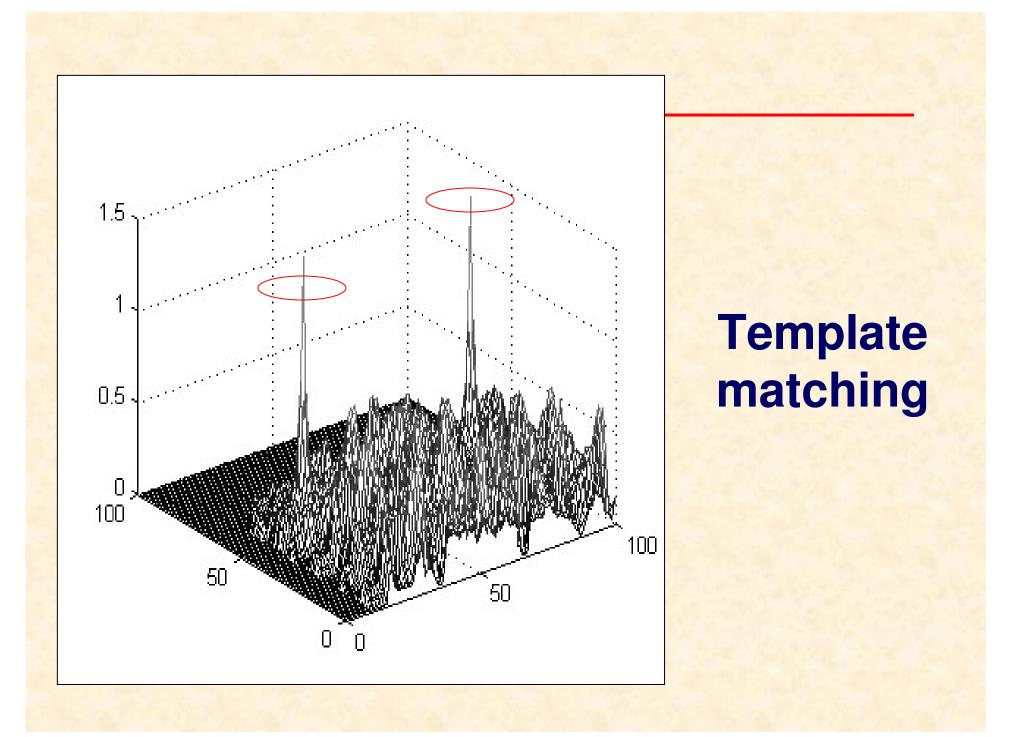
The correlation function has the disadvantage of being sensitive to local intensities of w(x,y) and f(x,y). In order to get rid of this difficulty pattern matching by using the *correlation coefficient* is used:

$$\gamma(s,t) = \frac{\sum_{x \in y} [f(x,y) - \bar{f}(x,y)] [w(x-s,y-t) - \bar{w}]}{\{\sum_{x \in y} [f(x,y) - \bar{f}(x,y)]^2 \sum_{x \in y} [w(x-s,y-t) - \bar{w}]^2 \}^{1/2}}$$



%MATLAB z=xcorr2(c,x); imshow(z,[]);

Illustration of the template matching technique (above and below). The detected patter is letter "C".



#### **Template matching - example**

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**Correlation result** 

#### Theresholding