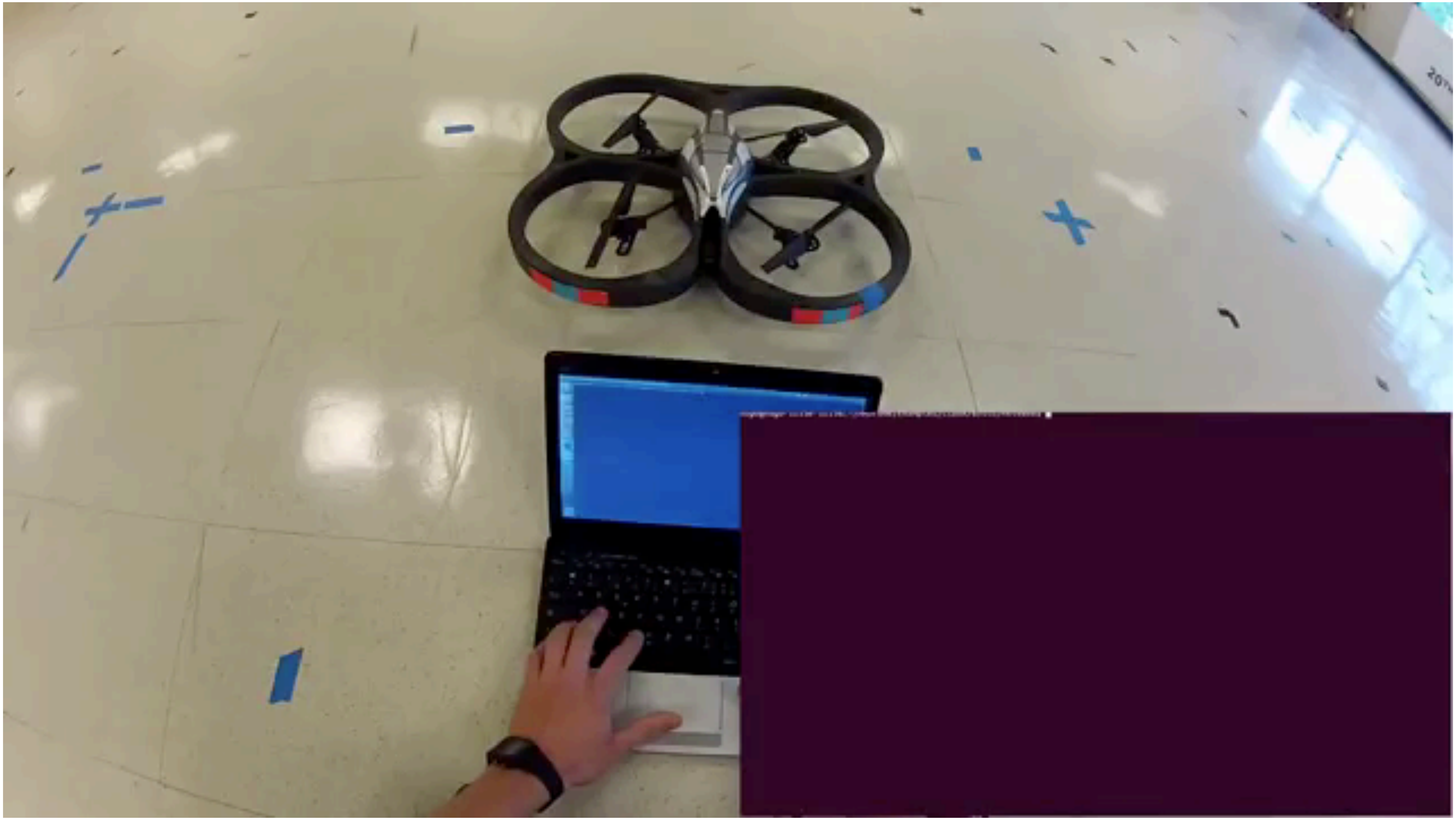
Video and Motion Analysis

16-385 Computer Vision

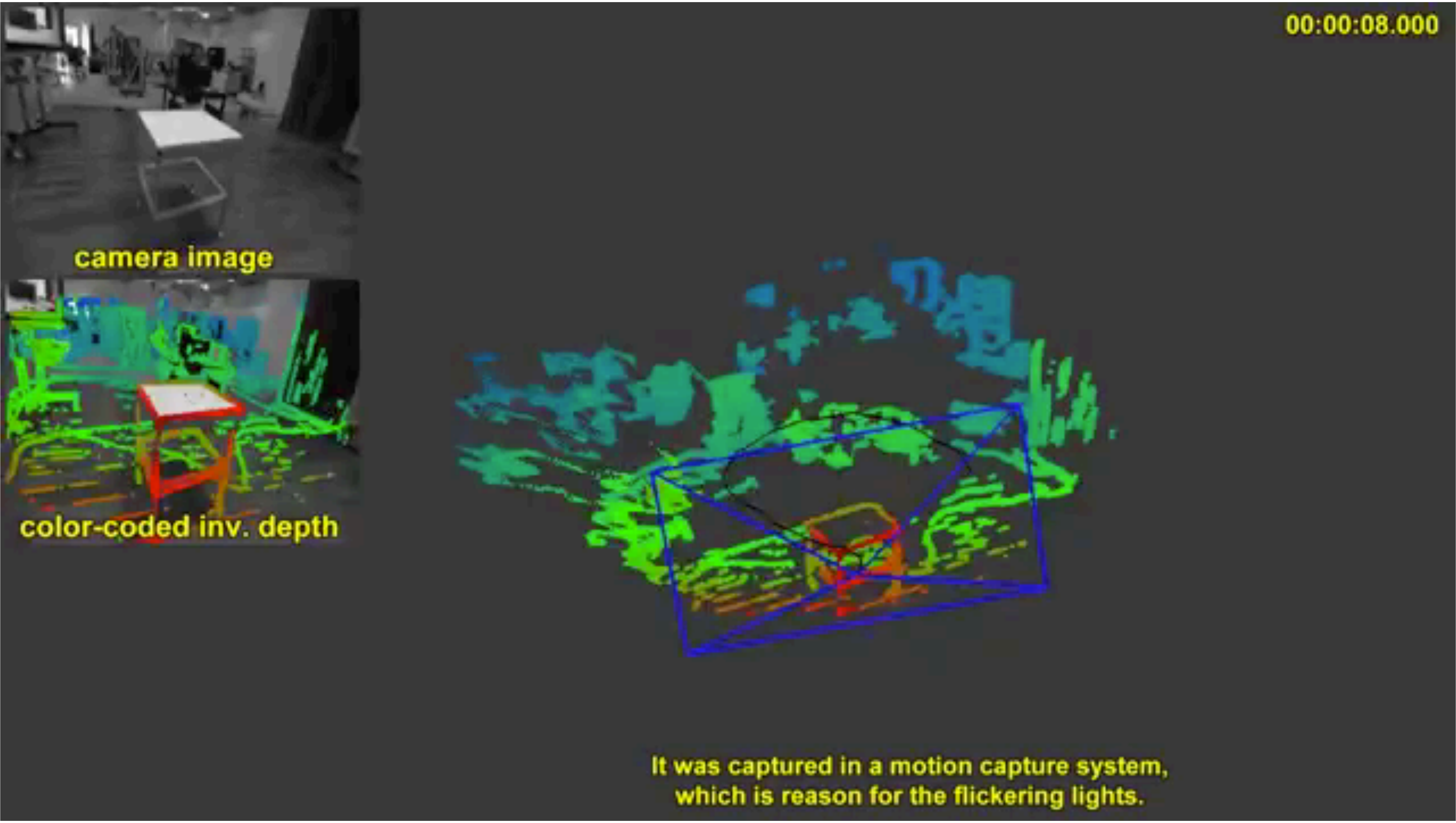
Carnegie Mellon University (Kris Kitani)

Optical flow used for feature tracking on a drone



Interpolated optical flow used for super slow-mo

optical flow used for motion estimation in visual odometry



Roadmap

(Where we have been and where we are going)

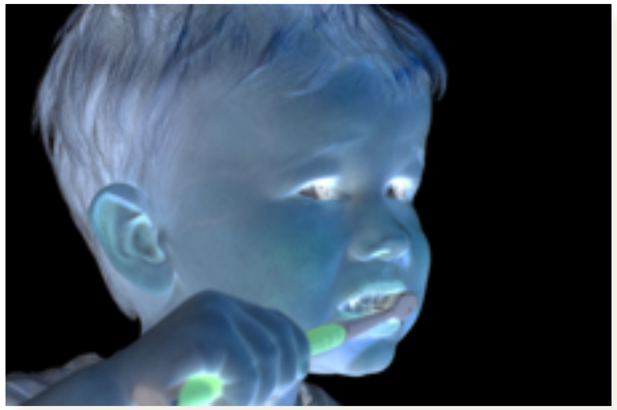


Image filtering

Frequency domain

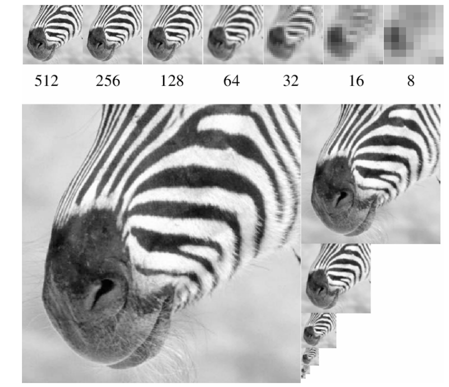


image pyramids

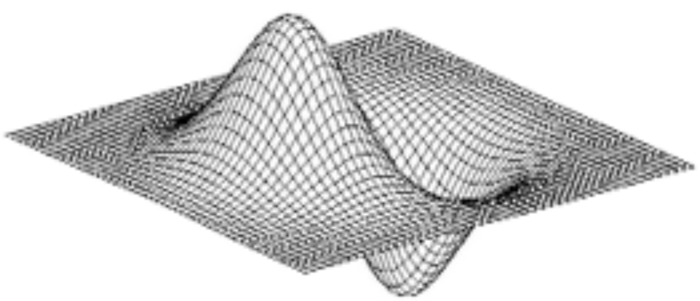
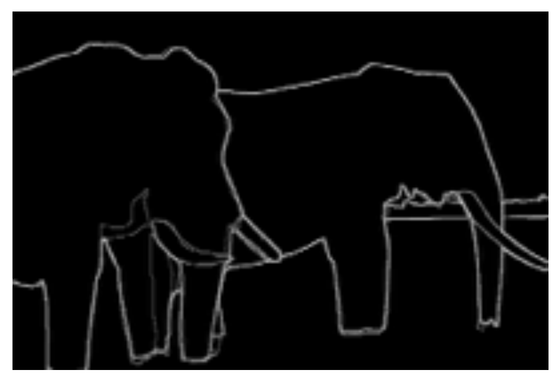
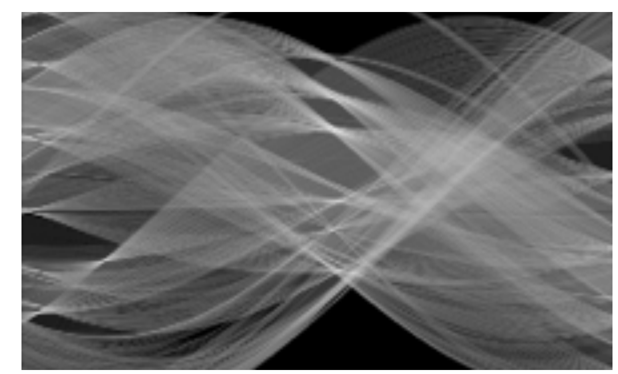


Image gradients



Boundaries



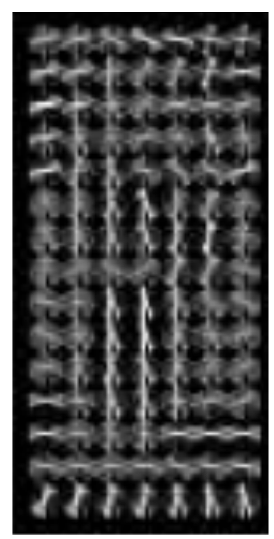
Hough Transform

Image Manipulation (January)

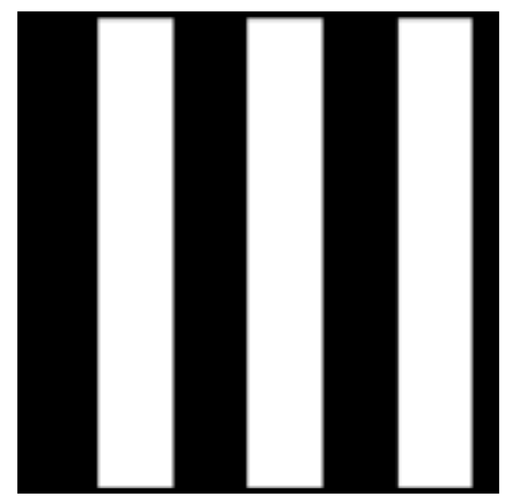
Corner detection

Multi-scale detection

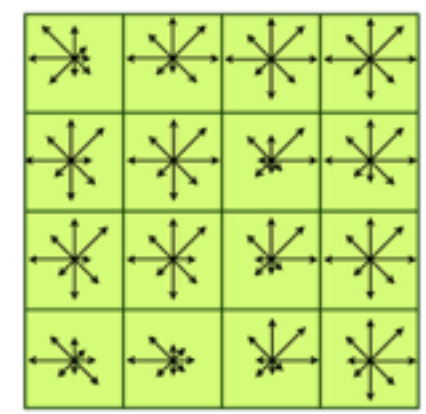
Haar-like



HOG

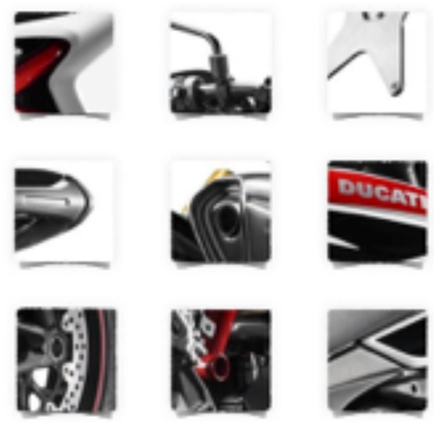


SURF

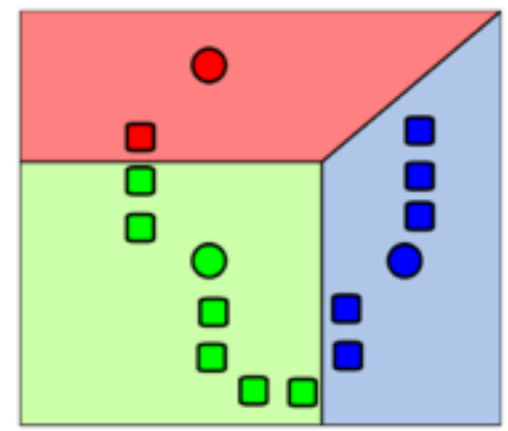


SIFT

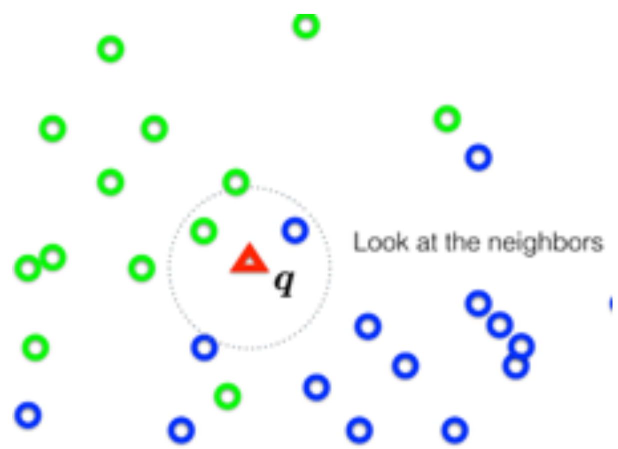
Image Features (February)



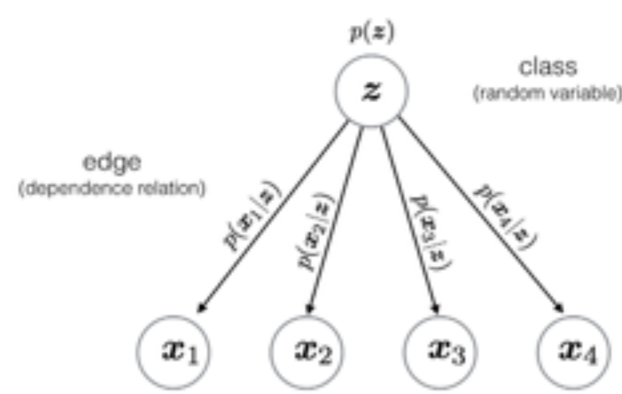
Bag-of-words



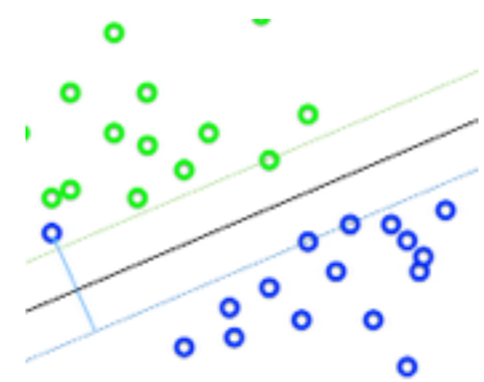
K-means



Nearest Neighbor



Naive Bayes



SVM

Object Recognition (February)

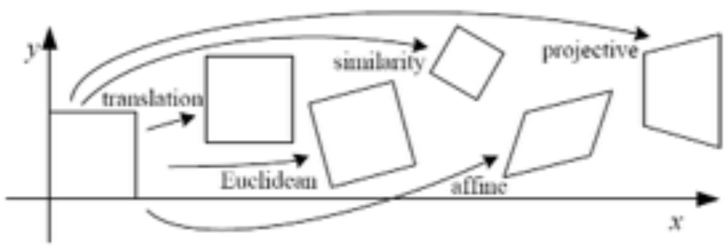
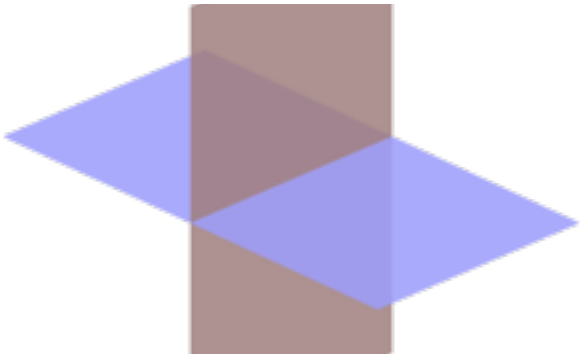
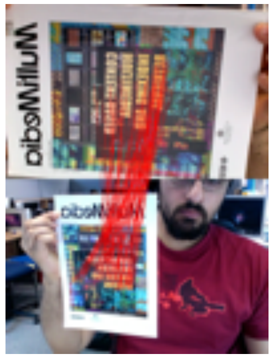


Figure 1: Basic set of 2D planar transformations

2D Transforms



DLT



RANSAC

2D Alignment (March)

$$x = \mathbf{P}\mathbf{X}$$

camera matrix

$$\mathbf{P}$$

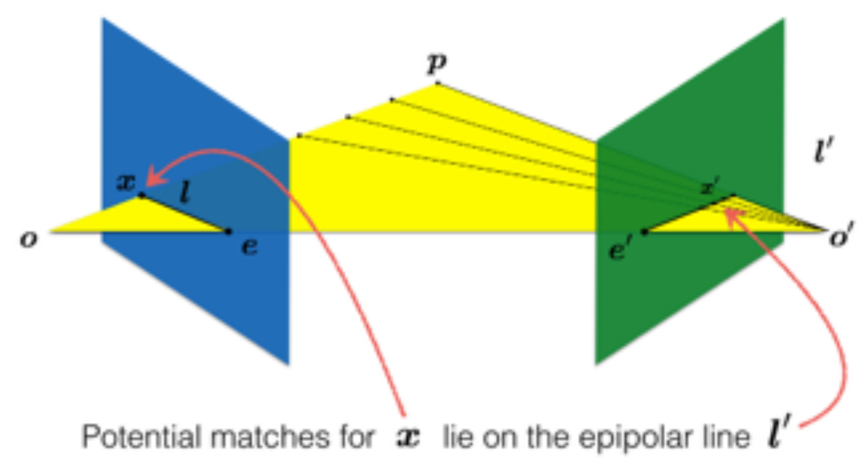
pose estimation

$$\mathbf{X}$$

triangulation

$$\mathbf{F}$$

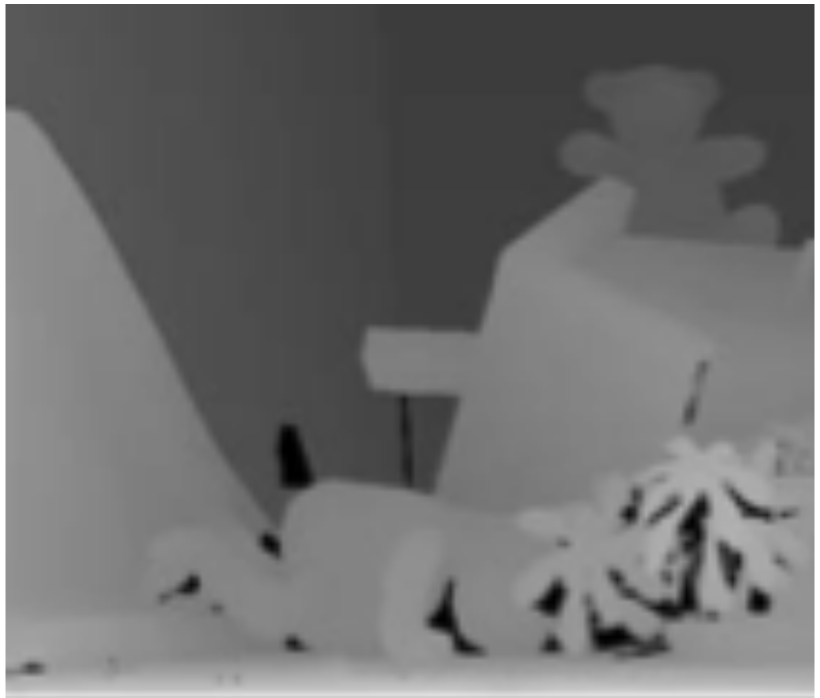
fundamental matrix



epipolar geometry

Reconstruction

2 view geometry (March)



Block matching

Energy minimization

Stereo (March)

What you can do now

- Detect lines (circles, shapes) in an image
- Recognize objects using a bag-of-words model
- Automatic image warping and basic AR
- Reconstruct 3D scene structure from two images

What you will learn next

- Object tracking in video

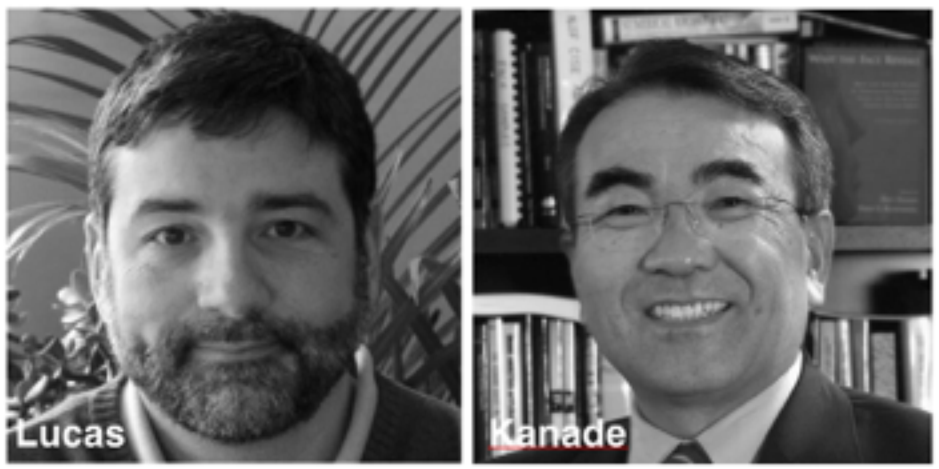
$$\begin{bmatrix} I_x(\boldsymbol{p}_1) & I_y(\boldsymbol{p}_1) \\ I_x(\boldsymbol{p}_2) & I_y(\boldsymbol{p}_2) \\ \vdots & \vdots \\ I_x(\boldsymbol{p}_{25}) & I_y(\boldsymbol{p}_{25}) \end{bmatrix} \begin{bmatrix} u \\ v \end{bmatrix} = - \begin{bmatrix} I_t(\boldsymbol{p}_1) \\ I_t(\boldsymbol{p}_2) \\ \vdots \\ I_t(\boldsymbol{p}_{25}) \end{bmatrix}$$

Constant Flow

$$\min_{\boldsymbol{u},\boldsymbol{v}} \sum_{ij} \left\{ E_d(i,j) + \lambda E_s(i,j) \right\}$$

Horn Schunck

Optical Flow (April)

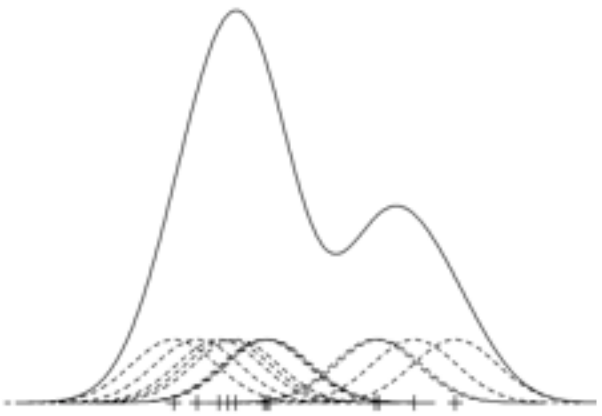


Lucas Kanade
(Forward additive)

Baker Matthews
(Inverse Compositional)

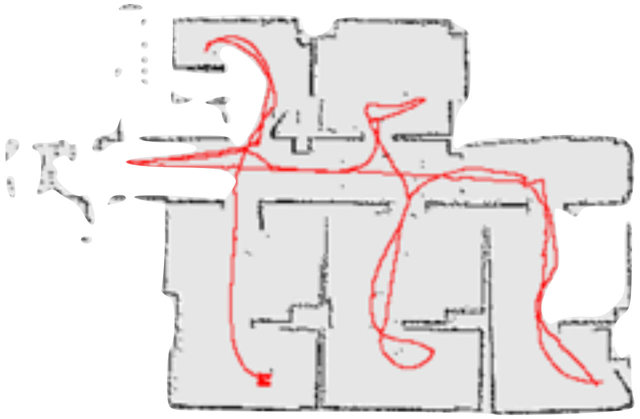
Image Alignment (April)

KLT



Mean shift

Kalman Filtering



SLAM

Tracking in Video (April-May)

Brightness Constancy

16-385 Computer Vision

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Optical Flow

Problem Definition

Given two consecutive image frames,
estimate the motion of each pixel

Assumptions

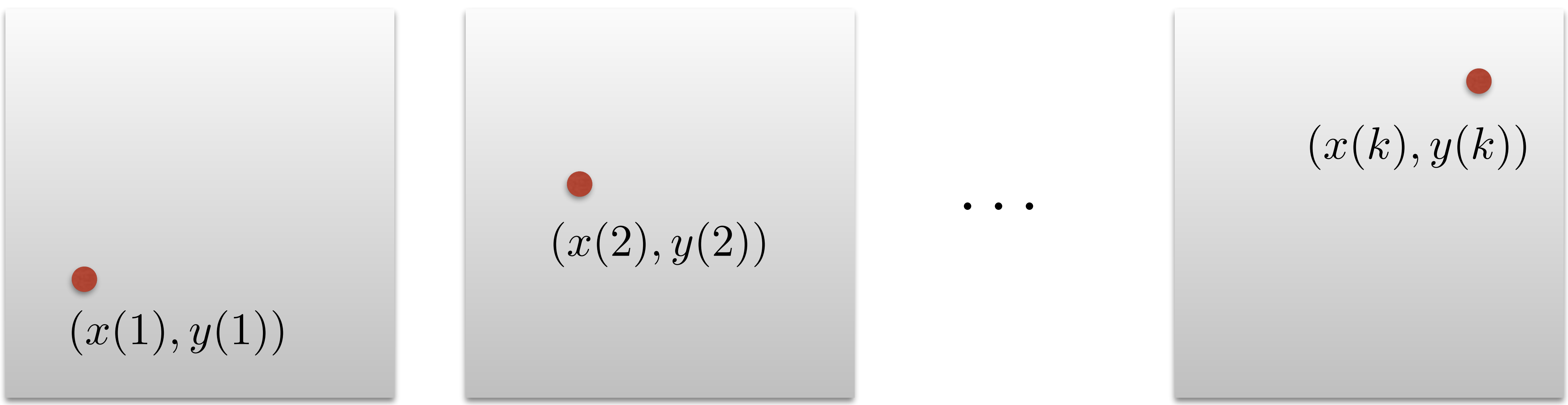
Brightness constancy

Small motion

Assumption 1

Brightness constancy

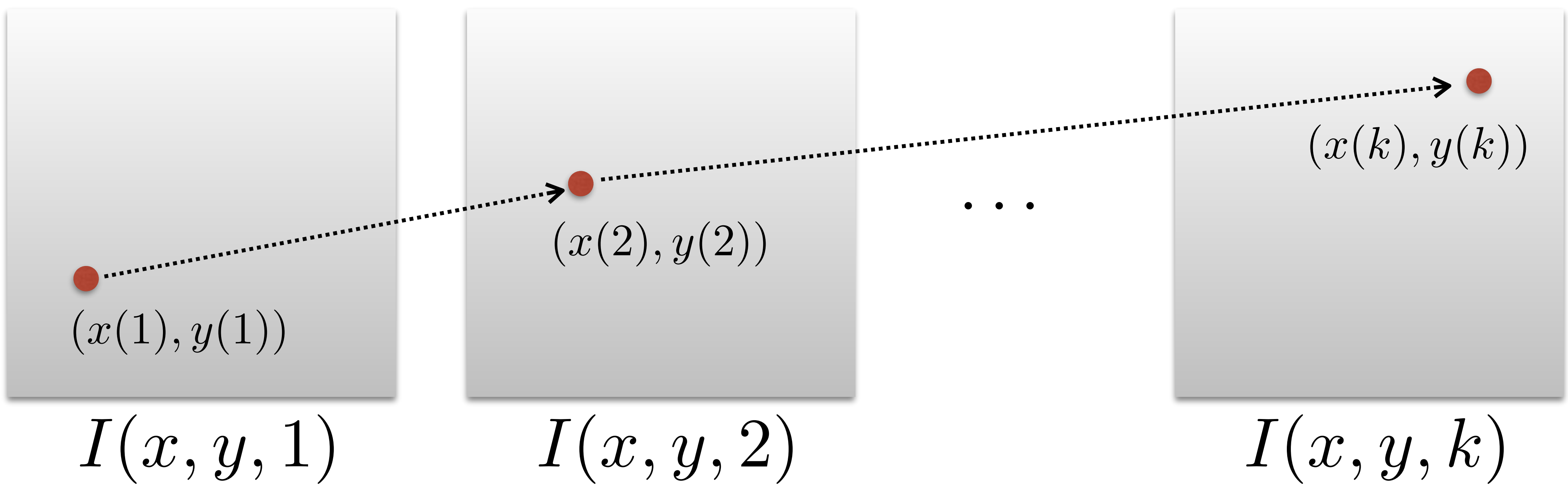
Scene point moving through image sequence



Assumption 1

Brightness constancy

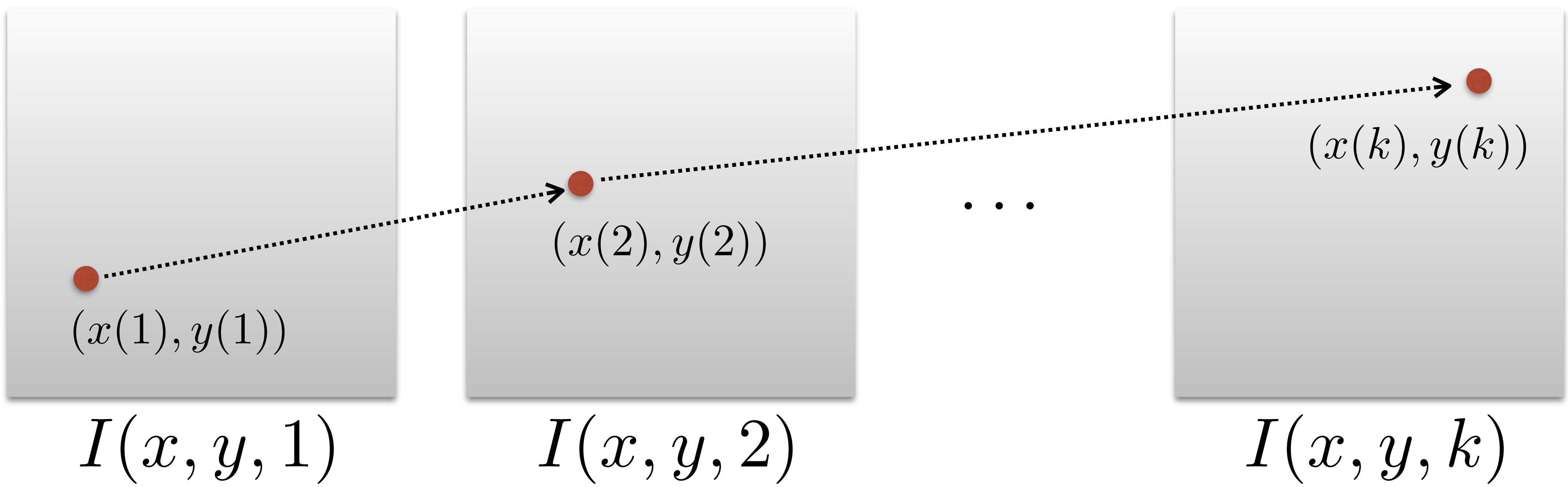
Scene point moving through image sequence



Assumption 1

Brightness constancy

Scene point moving through image sequence

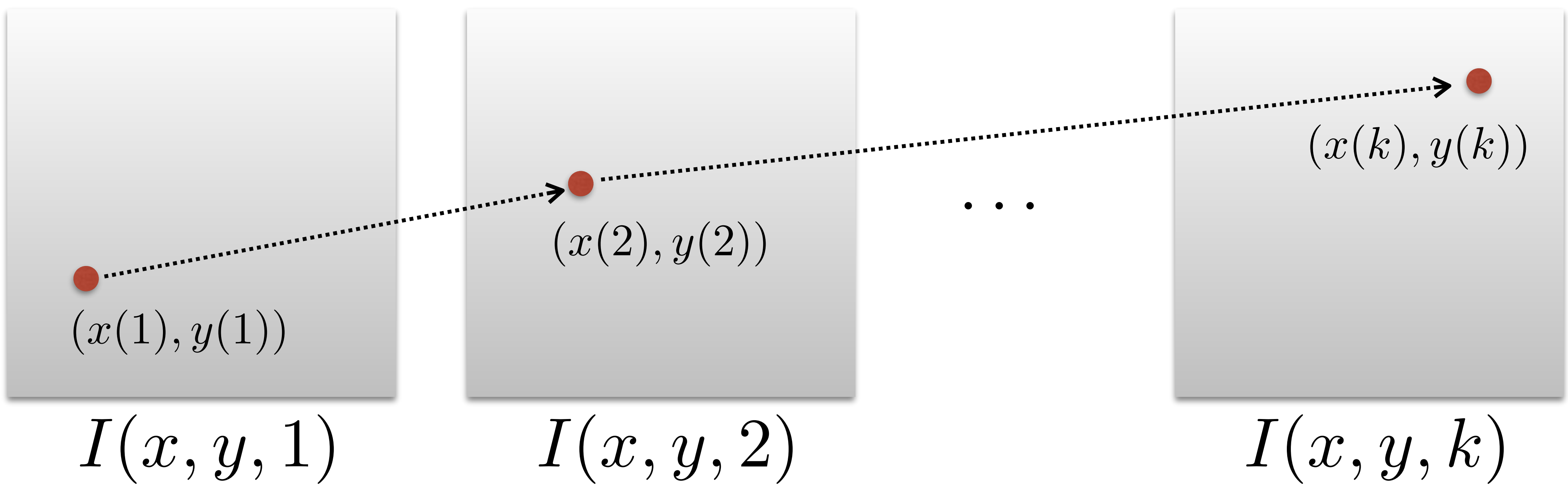


Assumption:Brightness of the point will remain the same

Assumption 1

Brightness constancy

Scene point moving through image sequence



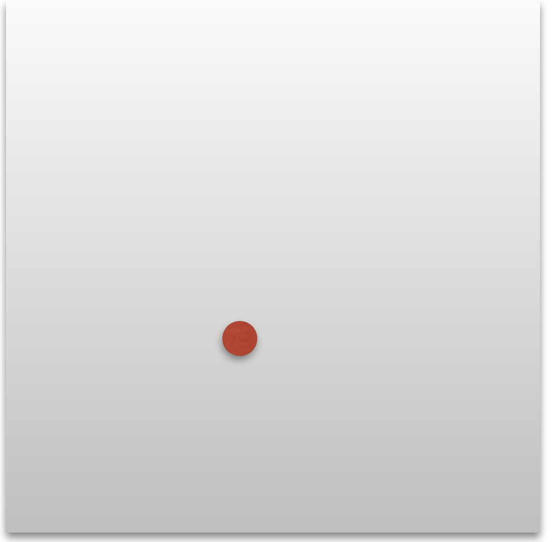
Assumption:Brightness of the point will remain the same

$$I(x(t), y(t), t) = C$$

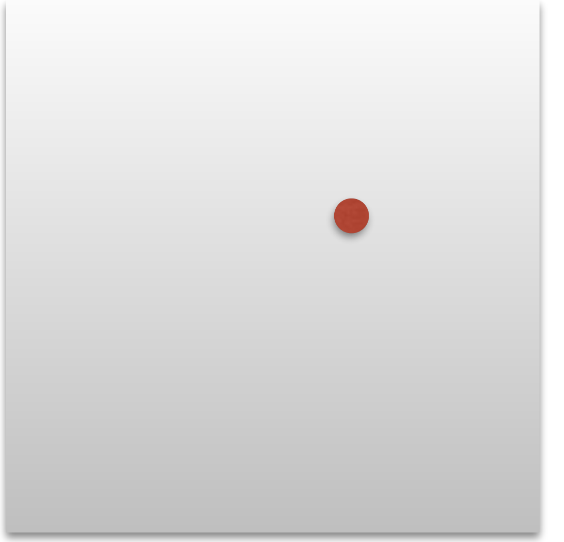
constant

Assumption 2

Small motion



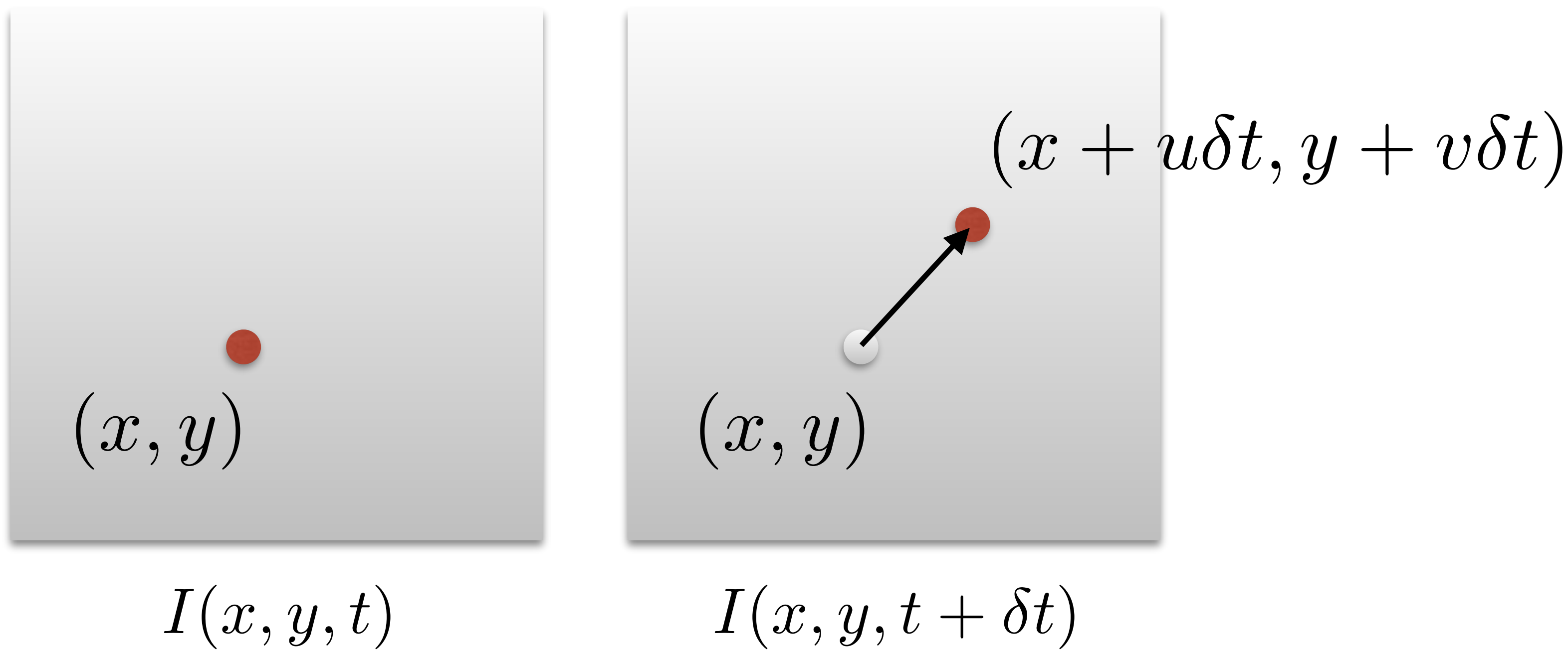
$I(x, y, t)$



$I(x, y, t + \delta t)$

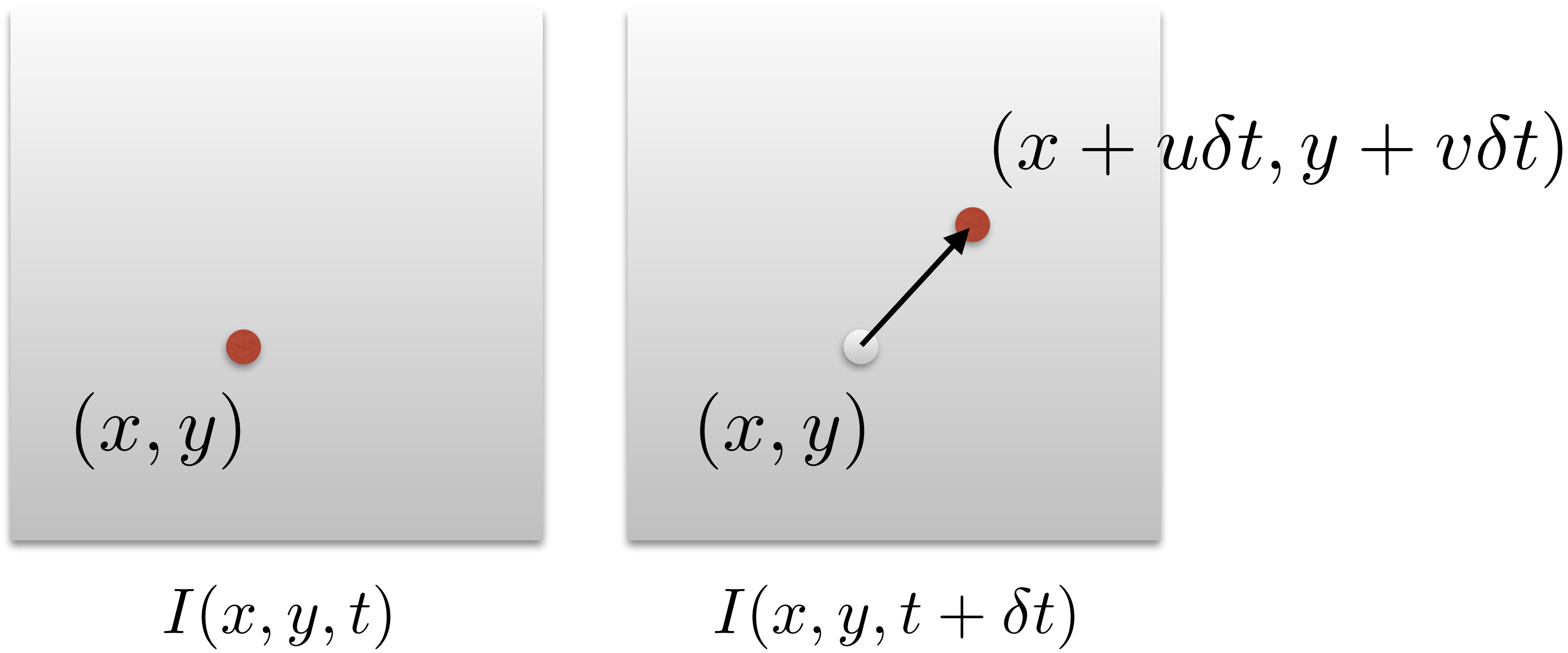
Assumption 2

Small motion



Assumption 2

Small motion

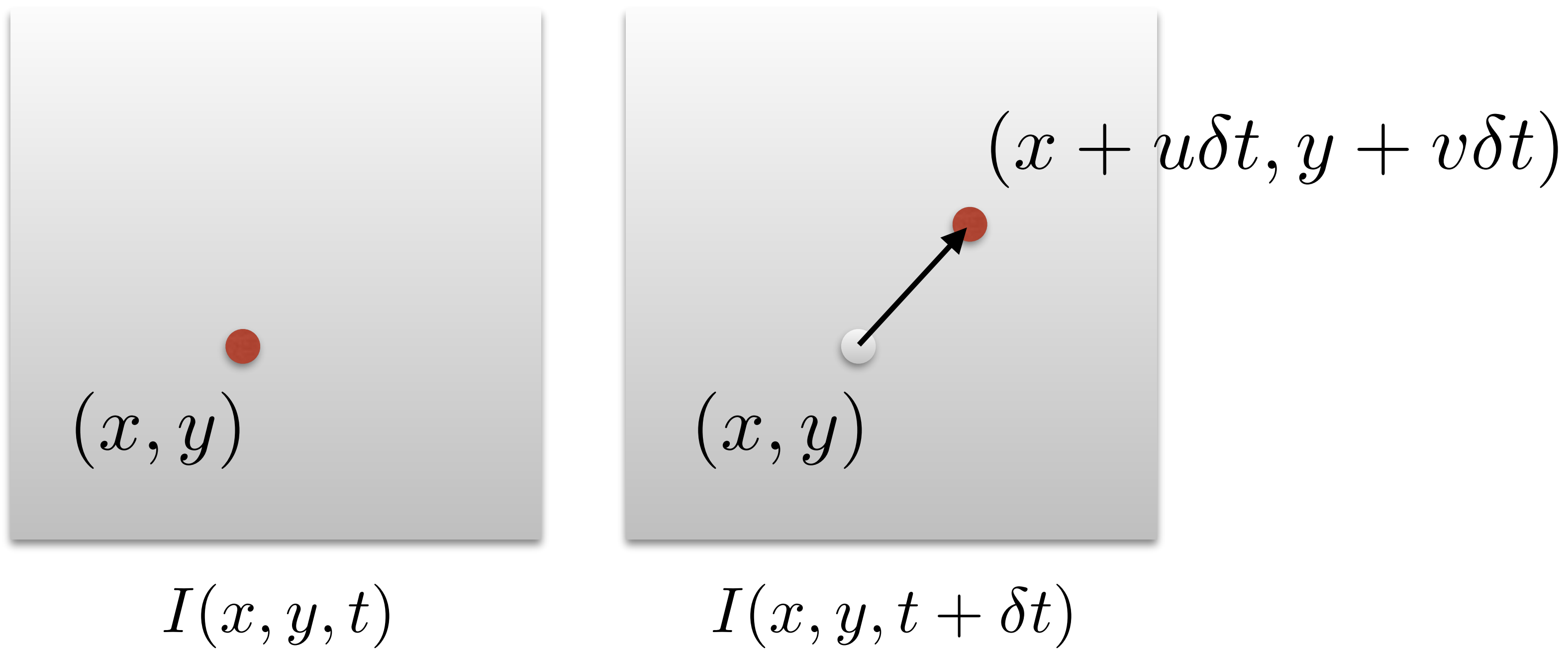


Optical flow (velocities): (u, v)

Displacement: $(\delta x, \delta y) = (u\delta t, v\delta t)$

Assumption 2

Small motion



Optical flow (velocities): (u, v) Displacement: $(\delta x, \delta y) = (u\delta t, v\delta t)$

For a *really small space-time step*…

$$I(x + u\delta t, y + v\delta t, t + \delta t) = I(x, y, t)$$

… the brightness between two consecutive image frames is the same

These assumptions yield the …

Brightness Constancy Equation

$$\frac{dI}{dt} = \frac{\partial I}{\partial x}\frac{dx}{dt} + \frac{\partial I}{\partial y}\frac{dy}{dt} + \frac{\partial I}{\partial t} = 0$$

total derivative

partial derivative

Where does this come from?

$$I(x + u\delta t, y + v\delta t, t + \delta t) = I(x, y, t)$$

For small space-time step, brightness of a point is the same

If the time step is really small,
we can *linearize* the intensity function

$$I(x + u\delta t, y + v\delta t, t + \delta t) = I(x, y, t)$$

Multivariable Taylor Series Expansion

(First order approximation, two variables)

$$f(x,y) \approx f(a,b) + f_x(a,b)(x-a) - f_y(a,b)(y-b)$$

$$I(x+u\delta t, y+v\delta t, t+\delta t) = I(x,y,t)$$

Multivariable Taylor Series Expansion

(First order approximation, two variables)

$$f(x,y) \approx f(a,b) + f_x(a,b)(x-a) - f_y(a,b)(y-b)$$

$$I(x,y,t) + \frac{\partial I}{\partial x}\delta x + \frac{\partial I}{\partial y}\delta y + \frac{\partial I}{\partial t}\delta t = I(x,y,t)$$

assuming small motion

$$I(x + u\delta t, y + v\delta t, t + \delta t) = I(x, y, t)$$

Multivariable Taylor Series Expansion

(First order approximation, two variables)

$$f(x, y) \approx f(a, b) + f_x(a, b)(x - a) - f_y(a, b)(y - b)$$

$$I(x, y, t) + \frac{\partial I}{\partial x}\delta x + \frac{\partial I}{\partial y}\delta y + \frac{\partial I}{\partial t}\delta t = I(x, y, t)$$

assuming small motion

cancel terms

$$I(x + u\delta t, y + v\delta t, t + \delta t) = I(x, y, t)$$

Multivariable Taylor Series Expansion

(First order approximation, two variables)

$$f(x, y) \approx f(a, b) + f_x(a, b)(x - a) - f_y(a, b)(y - b)$$

$$I(x, y, t) + \frac{\partial I}{\partial x}\delta x + \frac{\partial I}{\partial y}\delta y + \frac{\partial I}{\partial t}\delta t = I(x, y, t)$$

assuming small motion

$$\frac{\partial I}{\partial x}\delta x + \frac{\partial I}{\partial y}\delta y + \frac{\partial I}{\partial t}\delta t = 0$$

cancel terms

$$I(x + u\delta t, y + v\delta t, t + \delta t) = I(x, y, t)$$

Multivariable Taylor Series Expansion

(First order approximation, two variables)

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assuming small motion

$$\frac{\partial I}{\partial x}\delta x + \frac{\partial I}{\partial y}\delta y + \frac{\partial I}{\partial t}\delta t = 0$$

divide by δt

take limit $\delta t \rightarrow 0$

$$I(x + u\delta t, y + v\delta t, t + \delta t) = I(x, y, t)$$

Multivariable Taylor Series Expansion

(First order approximation, two variables)

$$f(x, y) \approx f(a, b) + f_x(a, b)(x - a) - f_y(a, b)(y - b)$$

$$I(x, y, t) + \frac{\partial I}{\partial x}\delta x + \frac{\partial I}{\partial y}\delta y + \frac{\partial I}{\partial t}\delta t = I(x, y, t)$$

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$$\frac{\partial I}{\partial x}\frac{dx}{dt} + \frac{\partial I}{\partial y}\frac{dy}{dt} + \frac{\partial I}{\partial t} = 0$$

$$I(x + u\delta t, y + v\delta t, t + \delta t) = I(x, y, t)$$

Multivariable Taylor Series Expansion

(First order approximation, two variables)

$$f(x, y) \approx f(a, b) + f_x(a, b)(x - a) - f_y(a, b)(y - b)$$

$$I(x, y, t) + \frac{\partial I}{\partial x}\delta x + \frac{\partial I}{\partial y}\delta y + \frac{\partial I}{\partial t}\delta t = I(x, y, t)$$

assuming small motion

$$\frac{\partial I}{\partial x}\delta x + \frac{\partial I}{\partial y}\delta y + \frac{\partial I}{\partial t}\delta t = 0$$

divide by δt

take limit $\delta t \rightarrow 0$

$$\frac{\partial I}{\partial x}\frac{dx}{dt} + \frac{\partial I}{\partial y}\frac{dy}{dt} + \frac{\partial I}{\partial t} = 0$$

Brightness Constancy Equation

$$\frac{\partial I}{\partial x}\frac{dx}{dt} + \frac{\partial I}{\partial y}\frac{dy}{dt} + \frac{\partial I}{\partial t} = 0$$

Brightness Constancy Equation

$$I_x u + I_y v + I_t = 0$$

(displacement)

shorthand notation

$$\nabla I^\top \boldsymbol{v} + I_t = 0$$

vector form

(putting the math aside for a second…)

What do the term of the brightness constancy equation represent?

$$I_x u + I_y v + I_t = 0$$

(putting the math aside for a second…)

What do the term of the brightness constancy equation represent?

$$I_x u + I_y v + I_t = 0$$

Image gradients

(putting the math aside for a second…)

What do the term of the
brightness constancy equation represent?

flow velocities

$$I_x u + I_y v + I_t = 0$$

Image gradients

(putting the math aside for a second…)

What do the term of the
brightness constancy equation represent?

flow velocities

$$I_x u + I_y v + I_t = 0$$

Image gradients

temporal gradient

How do you compute these terms?

$$I_x u + I_y v + I_t = 0$$

How do you compute …

$$I_x = \frac{\partial I}{\partial x} \quad I_y = \frac{\partial I}{\partial y}$$

spatial derivative

$$I_x u + I_y v + I_t = 0$$

How do you compute …

$$I_x = \frac{\partial I}{\partial x} \quad I_y = \frac{\partial I}{\partial y}$$

spatial derivative

Forward difference
Sobel filter
Scharr filter
…

$$I_x u + I_y v + I_t = 0$$

How do you compute …

$$I_x = \frac{\partial I}{\partial x} \quad I_y = \frac{\partial I}{\partial y}$$

spatial derivative

$$I_t = \frac{\partial I}{\partial t}$$

temporal derivative

Forward difference
Sobel filter
Scharr filter
…

$$I_x u + I_y v + I_t = 0$$

How do you compute …

$$I_x = \frac{\partial I}{\partial x} \quad I_y = \frac{\partial I}{\partial y}$$

spatial derivative

$$I_t = \frac{\partial I}{\partial t}$$

temporal derivative

Forward difference
Sobel filter
Scharr filter
…

frame differencing

Frame differencing

t

1	1	1	1	1
1	1	1	1	1
1	10	10	10	10
1	10	10	10	10
1	10	10	10	10
1	10	10	10	10

-

$t+1$

1	1	1	1	1
1	1	1	1	1
1	1	1	1	1
1	1	10	10	10
1	1	10	10	10
1	1	10	10	10

=

$$I_t = \frac{\partial I}{\partial t}$$

0	0	0	0	0
0	0	0	0	0
0	9	9	9	9
0	9	0	0	0
0	9	0	0	0
0	9	0	0	0

(example of a forward difference)

Example:

t

3 x 3 patch

1	1	1	1	1
1	1	1	1	1
1	10	10	10	10
1	10	10	10	10
1	10	10	10	10
1	10	10	10	10

$t+1$

1	1	1	1	1
1	1	1	1	1
1	1	1	1	1
1	1	10	10	10
1	1	10	10	10
1	1	10	10	10

$$I_x = \frac{\partial I}{\partial x}$$

-	0	0	0	-
-	0	0	0	-
-	9	0	0	-
-	9	0	0	-
-	9	0	0	-
-	9	0	0	-

-1 0 1

$$I_y = \frac{\partial I}{\partial y}$$

-	-	-	-	-
0	0	0	0	0
0	9	9	9	9
-	0	0	0	0
0	0	0	0	0
-	-	-	-	-

-1
0
1

$$I_t = \frac{\partial I}{\partial t}$$

0	0	0	0	0
0	0	0	0	0
0	9	9	9	9
0	9	0	0	0
0	9	0	0	0
0	9	0	0	0

$$I_x u + I_y v + I_t = 0$$

How do you compute …

$$I_x = \frac{\partial I}{\partial x} \quad I_y = \frac{\partial I}{\partial y}$$

spatial derivative

$$u = \frac{dx}{dt} \quad v = \frac{dy}{dt}$$

optical flow

$$I_t = \frac{\partial I}{\partial t}$$

temporal derivative

Forward difference
Sobel filter
Scharr filter
…

How do you compute this?

frame differencing

$$I_x u + I_y v + I_t = 0$$

How do you compute …

$$I_x = \frac{\partial I}{\partial x} \quad I_y = \frac{\partial I}{\partial y}$$

spatial derivative

$$u = \frac{dx}{dt} \quad v = \frac{dy}{dt}$$

optical flow

$$I_t = \frac{\partial I}{\partial t}$$

temporal derivative

Forward difference
Sobel filter
Scharr filter
…

We need to solve for this!
(this is the unknown in the optical flow problem)

frame differencing

$$I_x u + I_y v + I_t = 0$$

How do you compute …

$$I_x = \frac{\partial I}{\partial x} \quad I_y = \frac{\partial I}{\partial y}$$

spatial derivative

$$u = \frac{dx}{dt} \quad v = \frac{dy}{dt}$$

optical flow

$$I_t = \frac{\partial I}{\partial t}$$

temporal derivative

Forward difference
Sobel filter
Scharr filter
…

(u, v)
Solution lies on a line

Cannot be found uniquely
with a single constraint

frame differencing

$$I_x u + I_y v + I_t = 0$$

$$I_x = \frac{\partial I}{\partial x} \quad I_y = \frac{\partial I}{\partial y}$$

spatial derivative

$$u = \frac{dx}{dt} \quad v = \frac{dy}{dt}$$

optical flow

$$I_t = \frac{\partial I}{\partial t}$$

temporal derivative

How can we use the brightness constancy equation to estimate the optical flow?

unknown

$$I_x u + I_y v + I_t = 0$$

known

We need at least ____ equations to solve for 2 unknowns.

unknown

$$I_x u + I_y v + I_t = 0$$

known

Where do we get more equations (constraints)?