Harris Corner Detection

Mohammad Nayeem Teli
Corner detection

Corners contain more edges than lines.

A point on a line is hard to match.
Corners contain more edges than lines.

A corner is easier
Edge Detectors Tend to Fail at Corners
Finding Corners

Intuition:

• Right at corner, gradient is ill defined.
• Near corner, gradient has two different values.
Background
Background
Sum of Square Differences (SSD)

Intuition:

• Uses SSD to detect any fluctuation in the gradient of the image.

• Gradient should have significant change in two directions.
Smoothing
Gradient Images \((I_x, I_y)\)
Finding Corners

\[ E(u, v) = \sum_{x,y} w(x, y)[I(x + u, y + v) - I(x, y)]^2 \]

\( E \) is the difference between the original and the moved window
\( u \) is the window's displacement in the \( x \) direction
\( v \) is the window's displacement in the \( y \) direction
\( w(x, y) \) is the window at position \((x, y)\). This acts like a mask.
\( I \) is the intensity of the image at a position \((x, y)\)
\( I(x + u, y + v) \) is the intensity of the moved window
Finding Corners

\[ E(u, v) = \sum_{x,y} w(x, y)[I(x + u, y + v) - I(x, y)]^2 \]

maximize \( E \)

\[ \implies \maximize \sum_{x,y} [I(x + u, y + v) - I(x, y)]^2 \]

Taylor series expansion:

\[ I(x + u, y + v) \approx I(x, y) + u \frac{\partial}{\partial x} I(x, y) + v \frac{\partial}{\partial y} I(x, y) \]

\[ I(x + u, y + v) \approx I(x, y) + u I_x + v I_y \]

\[ E(u, v) \approx \sum_{x,y} w(x, y)[I(x, y) + u I_x + v I_y - I(x, y)]^2 \]
Finding Corners

\[ E(u, v) = \sum_{x,y} w(x, y)[I(x + u, y + v) - I(x, y)]^2 \]

\[ E(u, v) \approx \sum_{x,y} w(x, y)[I(x, y) + uI_x + vI_y - I(x, y)]^2 \]

\[ = \sum_{x,y} w(x, y)[uI_x + vI_y]^2 \]

\[ = \sum_{x,y} w(x, y)[u^2I_x^2 + 2uvI_xI_y + v^2I_y^2] \]

\[ [u^2I_x^2 + 2uvI_xI_y + v^2I_y^2] = [u \ v] \begin{bmatrix} I_x^2 & I_xI_y \\ I_xI_y & I_y^2 \end{bmatrix} [u \ v] \]
Finding Corners

\[ [u^2 I_x^2 + 2uv I_x I_y + v^2 I_y^2] = [u \ v] \begin{bmatrix} I_x^2 & I_x I_y \\ I_x I_y & I_y^2 \end{bmatrix} [u \ v] \]

\[ E(u, v) \approx \sum_{x,y} w(x, y)[u^2 I_x^2 + 2uv I_x I_y + v^2 I_y^2] \]

\[ E(u, v) \approx [u \ v] \left( \sum w(x, y) \begin{bmatrix} I_x^2 & I_x I_y \\ I_x I_y & I_y^2 \end{bmatrix} \right) [u \ v] \]

\[ E(u, v) \approx [u \ v] M [u \ v] \]

\[ M = \sum w(x, y) \begin{bmatrix} I_x^2 & I_x I_y \\ I_x I_y & I_y^2 \end{bmatrix} \]

windowing function - computing a weighted sum
Gradient plots - $I_x$ vs. $I_y$
Gradient plots - $I_x$ vs. $I_y$
Gradient plots - $I_x$ vs. $I_y$

- $\lambda_1 \approx \lambda_2$ small
- $\lambda_1 \approx \lambda_2$ large
- $\lambda_1$ large; $\lambda_2$ small
Score for each window

\[ E(u, v) \approx [u \ v] M \begin{bmatrix} u \\ v \end{bmatrix} \]

\[ M = \sum w(x, y) \begin{bmatrix} I_x^2 & I_x I_y \\ I_x I_y & I_y^2 \end{bmatrix} \]

Eigen values of the matrix, \( M \), can help determine the suitability of a window

Score, \( R = \det(M) - k(\text{trace}(M))^2 \)

\[ \det(M) = \lambda_1 \lambda_2 \]

\[ \text{trace}(M) = \lambda_1 + \lambda_2 \]

\( k \) is an empirically determined constant; \( k = 0.04 - 0.06 \)
Corner detection

− If $\lambda_1$ and $\lambda_2$ are small, means we are in a flat region
− If $\lambda_1 > > \lambda_2$ significant change in one direction, it is an edge
− If $\lambda_1 \approx \lambda_2$, and both are large, it is a corner

Score, $R = det(M) - k(trace(M))^2$

$det(M) = \lambda_1 \lambda_2$

$trace(M) = \lambda_1 + \lambda_2$

$k$ is an empirically determined constant; $k = 0.04 - 0.06$
Harris corner detector algorithm

- Compute magnitude of the gradient everywhere in x and y directions $I_x, I_y$

- Compute $I_x^2, I_y^2, I_xI_y$

- Convolve these three images with a Gaussian window, $w$. Find $M$ for each pixel,

$$M = \sum w(x, y) \begin{bmatrix} I_x^2 & I_xI_y \\ I_xI_y & I_y^2 \end{bmatrix}$$

- Compute detector response, $R$ at each pixel.

$$R = \text{det}(M) - k(\text{trace}(M))^2$$

- find local maxima above some threshold on $R$. Compute nonmax suppression.