

## Motion estimation

Digital Visual Effects, Spring 2007

Yung-Yu Chuang

2007/4/10

*with slides by Michael Black and P. Anandan*

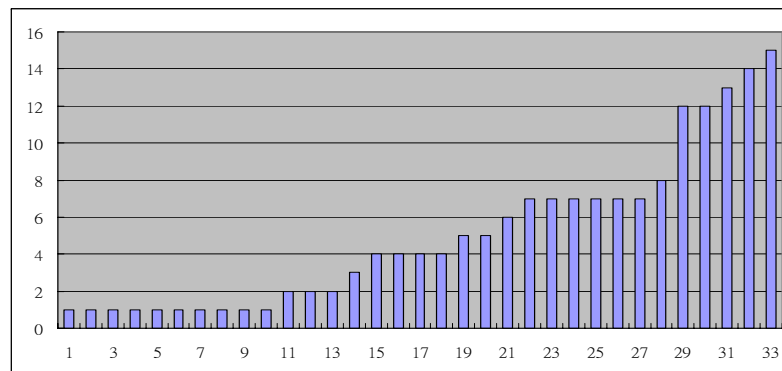
## Announcement

- The first part of project #2 (feature detection and matching) is due on Sunday, please send your source code and two images showing your results to TAs.




## Project #1 artifact voting

- 55 voters; 78.6%
- Total 168 votes
- 33 of 38 artifacts got votes



## Honorable mention(12): 蔡宗佑




Honorable mention(12): 李昆霖 施亮宇 




Third place (13): 劉恆溫 黃惟婷 



Second place (14): 方紀穎 蕭名傑 



First place (15): 鄭逸廷 陳柏叡 



## Motion estimation

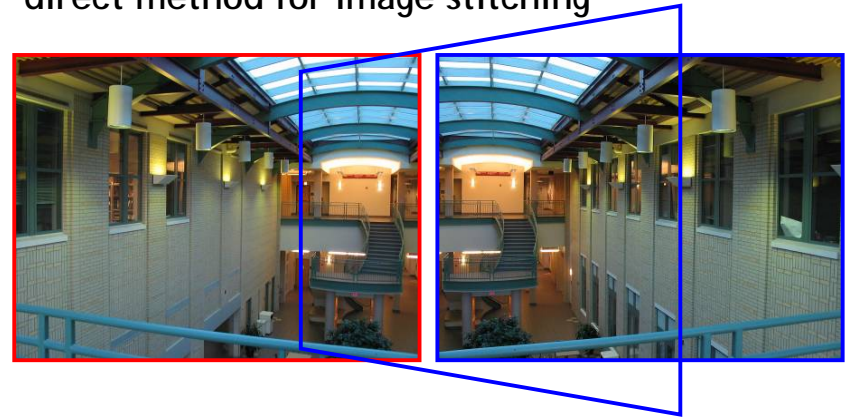
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- Parametric motion (image alignment)
- Tracking
- Optical flow

## Parametric motion

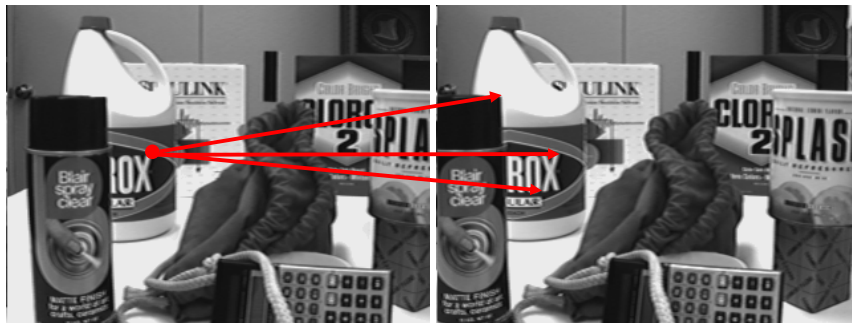
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direct method for image stitching



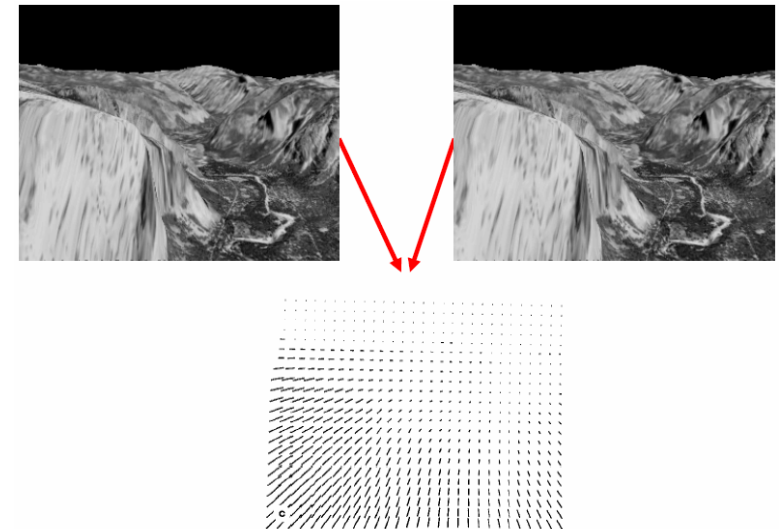
## Tracking

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## Optical flow

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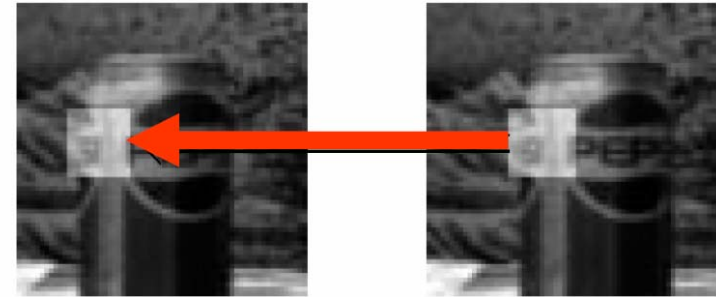
## Three assumptions

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- Brightness consistency
- Spatial coherence
- Temporal persistence

## Brightness consistency

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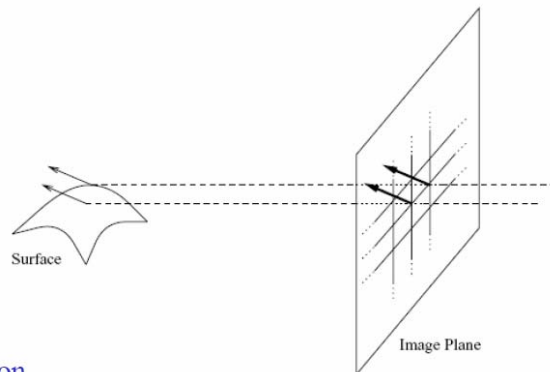


### Assumption

Image measurements (e.g. brightness) in a small region remain the same although their location may change.

## Spatial coherence

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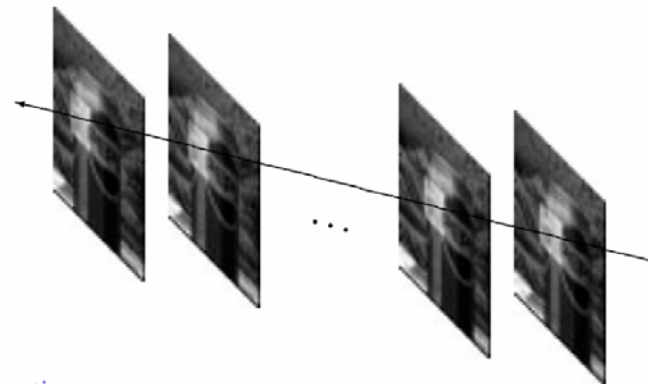


### Assumption

- \* Neighboring points in the scene typically belong to the same surface and hence typically have similar motions.
- \* Since they also project to nearby points in the image, we expect spatial coherence in image flow.

## Temporal persistence

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### Assumption:

The image motion of a surface patch changes gradually over time.

## Image registration

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Goal: register a template image  $J(x)$  and an input image  $I(x)$ , where  $x=(x,y)^T$ . (warp  $I$  so that it matched  $J$ )

Image alignment:  $I(x)$  and  $J(x)$  are two images

Tracking:  $I(x)$  is the image at time  $t$ .  $J(x)$  is a small patch around the point  $p$  in the image at  $t+1$ .

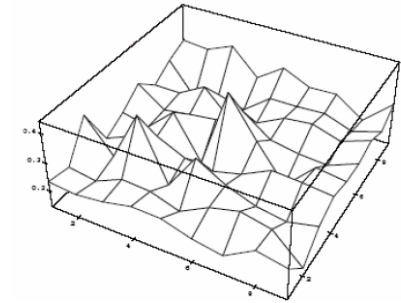
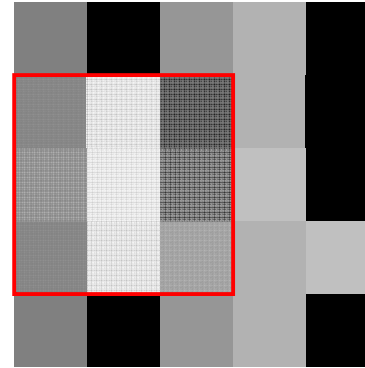
Optical flow:  $I(x)$  and  $J(x)$  are images of  $t$  and  $t+1$ .

## Simple approach (for translation)

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- Minimize brightness difference

$$E(u, v) = \sum_{x, y} (I(x+u, y+v) - J(x, y))^2$$



## Simple SSD algorithm

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For each offset  $(u, v)$

compute  $E(u, v)$ ;

Choose  $(u, v)$  which minimizes  $E(u, v)$ ;

Problems:

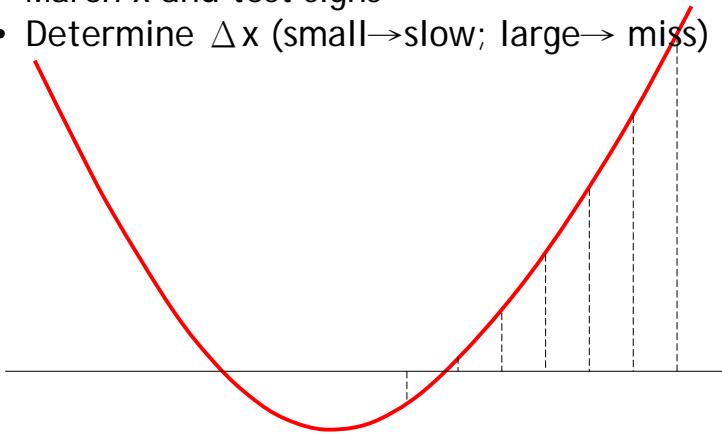
- Not efficient
- No sub-pixel accuracy

## Lucas-Kanade algorithm

## Newton's method

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- Root finding for  $f(x)=0$
- March  $x$  and test signs
- Determine  $\Delta x$  (small  $\rightarrow$  slow; large  $\rightarrow$  miss)



## Newton's method

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- Root finding for  $f(x)=0$
- Taylor's expansion:

$$f(x_0 + \varepsilon) = f(x_0) + f'(x_0)\varepsilon + \frac{1}{2}f''(x_0)\varepsilon^2 + \dots$$

$$f(x_0 + \varepsilon) \approx f(x_0) + f'(x_0)\varepsilon$$

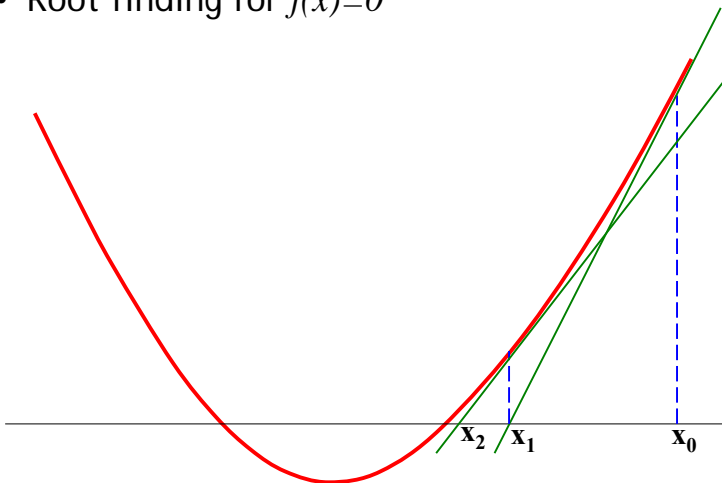
$$\varepsilon_n = -\frac{f(x_n)}{f'(x_n)}$$

$$x_{n+1} = x_n - \frac{f(x_n)}{f'(x_n)}$$

## Newton's method

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- Root finding for  $f(x)=0$



## Newton's method

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pick up  $x=x_0$   
iterate

compute  $\Delta x = -\frac{f(x)}{f'(x)}$

update  $x$  by  $x+\Delta x$   
until converge

Finding root is useful for optimization because  
Minimize  $g(x) \rightarrow$  find root for  $f(x)=g'(x)=0$

## Lucas-Kanade algorithm

$$E(u, v) = \sum_{x,y} (I(x+u, y+v) - J(x, y))^2$$

$$I(x+u, y+v) \approx I(x, y) + uI_x + vI_y$$

$$= \sum_{x,y} (I(x, y) - J(x, y) + uI_x + vI_y)^2$$

$$0 = \frac{\partial E}{\partial u} = \sum_{x,y} 2I_x (I(x, y) - J(x, y) + uI_x + vI_y)$$

$$0 = \frac{\partial E}{\partial v} = \sum_{x,y} 2I_y (I(x, y) - J(x, y) + uI_x + vI_y)$$

## Lucas-Kanade algorithm

$$0 = \frac{\partial E}{\partial u} = \sum_{x,y} 2I_x (I(x, y) - J(x, y) + uI_x + vI_y)$$

$$0 = \frac{\partial E}{\partial v} = \sum_{x,y} 2I_y (I(x, y) - J(x, y) + uI_x + vI_y)$$

$$\rightarrow \begin{cases} \sum_{x,y} I_x^2 u + \sum_{x,y} I_x I_y v = \sum_{x,y} I_x (J(x, y) - I(x, y)) \\ \sum_{x,y} I_x I_y u + \sum_{x,y} I_y^2 v = \sum_{x,y} I_y (J(x, y) - I(x, y)) \end{cases}$$

$$\rightarrow \begin{bmatrix} \sum_{x,y} I_x^2 & \sum_{x,y} I_x I_y \\ \sum_{x,y} I_x I_y & \sum_{x,y} I_y^2 \end{bmatrix} \begin{bmatrix} u \\ v \end{bmatrix} = \begin{bmatrix} \sum_{x,y} I_x (J(x, y) - I(x, y)) \\ \sum_{x,y} I_y (J(x, y) - I(x, y)) \end{bmatrix}$$

## Lucas-Kanade algorithm

iterate

shift  $I(x, y)$  with  $(u, v)$

compute gradient image  $I_x, I_y$

compute error image  $J(x, y) - I(x, y)$

compute Hessian matrix

solve the linear system

$(u, v) = (u, v) + (\Delta u, \Delta v)$

until converge

$$\begin{bmatrix} \sum_{x,y} I_x^2 & \sum_{x,y} I_x I_y \\ \sum_{x,y} I_x I_y & \sum_{x,y} I_y^2 \end{bmatrix} \begin{bmatrix} u \\ v \end{bmatrix} = \begin{bmatrix} \sum_{x,y} I_x (J(x, y) - I(x, y)) \\ \sum_{x,y} I_y (J(x, y) - I(x, y)) \end{bmatrix}$$

## Parametric model

$$E(u, v) = \sum_{x,y} (I(x+u, y+v) - J(x, y))^2$$

$$\rightarrow E(\mathbf{p}) = \sum_{\mathbf{x}} (I(\mathbf{W}(\mathbf{x}; \mathbf{p})) - J(\mathbf{x}))^2 \leftarrow \text{Our goal is to find } \mathbf{p} \text{ to minimize } E(\mathbf{p})$$

translation  $\mathbf{W}(\mathbf{x}; \mathbf{p}) = \begin{pmatrix} x + d_x \\ y + d_y \end{pmatrix}, p = (d_x, d_y)^T$

affine  $\mathbf{W}(\mathbf{x}; \mathbf{p}) = \mathbf{A}\mathbf{x} + \mathbf{d} = \begin{pmatrix} 1 + d_{xx} & d_{xy} & d_x \\ d_{yx} & 1 + d_{yy} & d_y \end{pmatrix} \begin{pmatrix} x \\ y \\ 1 \end{pmatrix}$

$$p = (d_{xx}, d_{xy}, d_{yx}, d_{yy}, d_x, d_y)^T$$

## Parametric model

$$\text{minimize } \sum_{\mathbf{x}} (I(\mathbf{W}(\mathbf{x}; \mathbf{p} + \Delta \mathbf{p})) - J(\mathbf{x}))^2$$

with respect to  $\Delta \mathbf{p}$

$$\mathbf{W}(\mathbf{x}; \mathbf{p} + \Delta \mathbf{p}) \approx \mathbf{W}(\mathbf{x}; \mathbf{p}) + \frac{\partial \mathbf{W}}{\partial \mathbf{p}} \Delta \mathbf{p}$$

$$I(\mathbf{W}(\mathbf{x}; \mathbf{p} + \Delta \mathbf{p})) \approx I(\mathbf{W}(\mathbf{x}; \mathbf{p})) + \frac{\partial I}{\partial \mathbf{p}} \Delta \mathbf{p}$$

$$\approx I(\mathbf{W}(\mathbf{x}; \mathbf{p})) + \frac{\partial I}{\partial \mathbf{x}} \frac{\partial \mathbf{W}}{\partial \mathbf{p}} \Delta \mathbf{p}$$

$$\rightarrow \text{minimize } \sum_{\mathbf{x}} \left( I(\mathbf{W}(\mathbf{x}; \mathbf{p})) + \nabla I \frac{\partial \mathbf{W}}{\partial \mathbf{p}} \Delta \mathbf{p} - J(\mathbf{x}) \right)^2$$

## Parametric model

warped image                      target image

$$\sum_{\mathbf{x}} \left( I(\mathbf{W}(\mathbf{x}; \mathbf{p})) + \nabla I \frac{\partial \mathbf{W}}{\partial \mathbf{p}} \Delta \mathbf{p} - J(\mathbf{x}) \right)^2$$

Jacobian of the warp

$$\frac{\partial \mathbf{W}}{\partial \mathbf{p}} = \begin{pmatrix} \frac{\partial \mathbf{W}_x}{\partial \mathbf{p}} \\ \frac{\partial \mathbf{W}_y}{\partial \mathbf{p}} \end{pmatrix} = \begin{pmatrix} \frac{\partial \mathbf{W}_x}{\partial \mathbf{p}_1} & \frac{\partial \mathbf{W}_x}{\partial \mathbf{p}_2} & \dots & \frac{\partial \mathbf{W}_x}{\partial \mathbf{p}_n} \\ \frac{\partial \mathbf{W}_y}{\partial \mathbf{p}_1} & \frac{\partial \mathbf{W}_y}{\partial \mathbf{p}_2} & \dots & \frac{\partial \mathbf{W}_y}{\partial \mathbf{p}_n} \end{pmatrix}$$

## Jacobian matrix

- The Jacobian matrix is the matrix of all first-order partial derivatives of a vector-valued function.

$$F(x_1, x_2, \dots, x_n) \quad F: \mathbf{R}^n \rightarrow \mathbf{R}^m$$

$$= (f_1(x_1, x_2, \dots, x_n), f_2(x_1, x_2, \dots, x_n), \dots, f_m(x_1, x_2, \dots, x_n))$$

$$J_F(x_1, x_2, \dots, x_n) = \begin{bmatrix} \frac{\partial f_1}{\partial x_1} & \dots & \frac{\partial f_1}{\partial x_n} \\ \vdots & \ddots & \vdots \\ \frac{\partial f_m}{\partial x_1} & \dots & \frac{\partial f_m}{\partial x_n} \end{bmatrix}$$

or

$$\frac{\partial (f_1, f_2, \dots, f_m)}{\partial (x_1, x_2, \dots, x_n)} = \begin{bmatrix} \frac{\partial f_1}{\partial x_1} & \dots & \frac{\partial f_1}{\partial x_n} \\ \vdots & \ddots & \vdots \\ \frac{\partial f_m}{\partial x_1} & \dots & \frac{\partial f_m}{\partial x_n} \end{bmatrix}$$

$$F(\mathbf{x} + \Delta \mathbf{x}) \approx F(\mathbf{x}) + J_F(\mathbf{x}) \Delta \mathbf{x}$$

## Jacobian matrix

$$F: \mathbf{R} \times [0, \pi] \times [0, 2\pi] \rightarrow \mathbf{R}^3 \quad t = r \sin \phi \cos \theta$$

$$F(r, \phi, \theta) = (t, u, v) \quad u = r \sin \phi \sin \theta$$

$$v = r \cos \phi$$

$$J_F(r, \phi, \theta) = \begin{bmatrix} \frac{\partial t}{\partial r} & \frac{\partial t}{\partial \phi} & \frac{\partial t}{\partial \theta} \\ \frac{\partial u}{\partial r} & \frac{\partial u}{\partial \phi} & \frac{\partial u}{\partial \theta} \\ \frac{\partial v}{\partial r} & \frac{\partial v}{\partial \phi} & \frac{\partial v}{\partial \theta} \end{bmatrix}$$

$$= \begin{bmatrix} \sin \phi \cos \theta & r \cos \phi \cos \theta & -r \sin \phi \sin \theta \\ \sin \phi \sin \theta & r \cos \phi \sin \theta & r \sin \phi \cos \theta \\ \cos \phi & -r \sin \phi & 0 \end{bmatrix}$$



## Parametric model

warped image                  target image

$$\sum_x \left( I(\mathbf{W}(\mathbf{x}; \mathbf{p})) + \nabla I \frac{\partial \mathbf{W}}{\partial \mathbf{p}} \Delta \mathbf{p} - J(\mathbf{x}) \right)^2$$

image gradient

Jacobian of the warp

$$\frac{\partial \mathbf{W}}{\partial \mathbf{p}} = \begin{pmatrix} \frac{\partial \mathbf{W}_x}{\partial \mathbf{p}} \\ \frac{\partial \mathbf{W}_y}{\partial \mathbf{p}} \end{pmatrix} = \begin{pmatrix} \frac{\partial \mathbf{W}_x}{\partial p_1} & \frac{\partial \mathbf{W}_x}{\partial p_2} & \dots & \frac{\partial \mathbf{W}_x}{\partial p_n} \\ \frac{\partial \mathbf{W}_y}{\partial p_1} & \frac{\partial \mathbf{W}_y}{\partial p_2} & \dots & \frac{\partial \mathbf{W}_y}{\partial p_n} \end{pmatrix}$$

## Jacobian of the warp

$$\frac{\partial \mathbf{W}}{\partial \mathbf{p}} = \begin{pmatrix} \frac{\partial \mathbf{W}_x}{\partial \mathbf{p}} \\ \frac{\partial \mathbf{W}_y}{\partial \mathbf{p}} \end{pmatrix} = \begin{pmatrix} \frac{\partial \mathbf{W}_x}{\partial p_1} & \frac{\partial \mathbf{W}_x}{\partial p_2} & \dots & \frac{\partial \mathbf{W}_x}{\partial p_n} \\ \frac{\partial \mathbf{W}_y}{\partial p_1} & \frac{\partial \mathbf{W}_y}{\partial p_2} & \dots & \frac{\partial \mathbf{W}_y}{\partial p_n} \end{pmatrix}$$

For example, for affine

$$\mathbf{W}(\mathbf{x}; \mathbf{p}) = \begin{pmatrix} 1+d_{xx} & d_{xy} & d_x \\ d_{yx} & 1+d_{yy} & d_y \end{pmatrix} \begin{pmatrix} x \\ y \\ 1 \end{pmatrix} = \begin{pmatrix} (1+d_{xx})x + d_{xy}y + d_x \\ d_{yx}x + (1+d_{yy})y + d_y \end{pmatrix}$$

$$\rightarrow \frac{\partial \mathbf{W}}{\partial \mathbf{p}} = \begin{pmatrix} x & 0 & y & 0 & 1 & 0 \\ 0 & x & 0 & y & 0 & 1 \end{pmatrix}$$

## Parametric model

$$\arg \min_{\Delta \mathbf{p}} \sum_x \left( I(\mathbf{W}(\mathbf{x}; \mathbf{p})) + \nabla I \frac{\partial \mathbf{W}}{\partial \mathbf{p}} \Delta \mathbf{p} - J(\mathbf{x}) \right)^2$$

$$\rightarrow 0 = \sum_x \left[ \nabla I \frac{\partial \mathbf{W}}{\partial \mathbf{p}} \right]^T \left[ I(\mathbf{W}(\mathbf{x}; \mathbf{p})) + \nabla I \frac{\partial \mathbf{W}}{\partial \mathbf{p}} \Delta \mathbf{p} - J(\mathbf{x}) \right]$$

$$\Delta \mathbf{p} = \mathbf{H}^{-1} \sum_x \left[ \nabla I \frac{\partial \mathbf{W}}{\partial \mathbf{p}} \right]^T [J(\mathbf{x}) - I(\mathbf{W}(\mathbf{x}; \mathbf{p}))]$$

$$\text{Hessian } \mathbf{H} = \sum_x \left[ \nabla I \frac{\partial \mathbf{W}}{\partial \mathbf{p}} \right]^T \left[ \nabla I \frac{\partial \mathbf{W}}{\partial \mathbf{p}} \right]$$

## Lucas-Kanade algorithm

iterate

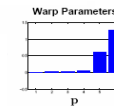
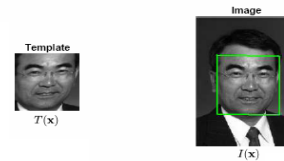
- 1) warp I with  $W(\mathbf{x}; \mathbf{p})$
- 2) compute error image  $J(\mathbf{x}, y) - I(\mathbf{W}(\mathbf{x}, \mathbf{p}))$
- 3) compute gradient image  $\nabla I$  with  $W(\mathbf{x}, \mathbf{p})$
- 4) evaluate Jacobian  $\frac{\partial \mathbf{W}}{\partial \mathbf{p}}$  at  $(\mathbf{x}; \mathbf{p})$
- 5) compute  $\nabla I \frac{\partial \mathbf{W}}{\partial \mathbf{p}}$
- 6) compute Hessian
- 7) compute  $\sum_x \left[ \nabla I \frac{\partial \mathbf{W}}{\partial \mathbf{p}} \right]^T [J(\mathbf{x}) - I(\mathbf{W}(\mathbf{x}; \mathbf{p}))]$
- 8) solve  $\Delta \mathbf{p}$
- 9) update  $\mathbf{p}$  by  $\mathbf{p} + \Delta \mathbf{p}$

until converge

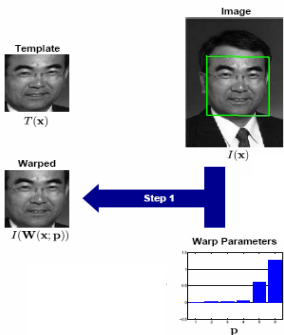
$$\Delta \mathbf{p} = \mathbf{H}^{-1} \sum_x \left[ \nabla I \frac{\partial \mathbf{W}}{\partial \mathbf{p}} \right]^T [J(\mathbf{x}) - I(\mathbf{W}(\mathbf{x}; \mathbf{p}))]$$



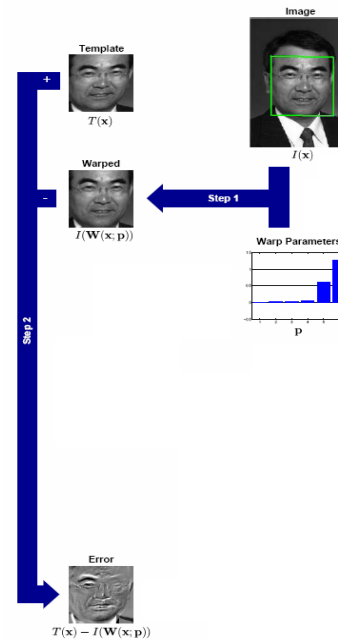
$$\Delta \mathbf{p} = \mathbf{H}^{-1} \sum_{\mathbf{x}} \left[ \nabla I \frac{\partial \mathbf{W}}{\partial \mathbf{p}} \right]^T [J(\mathbf{x}) - I(\mathbf{W}(\mathbf{x}; \mathbf{p}))]$$



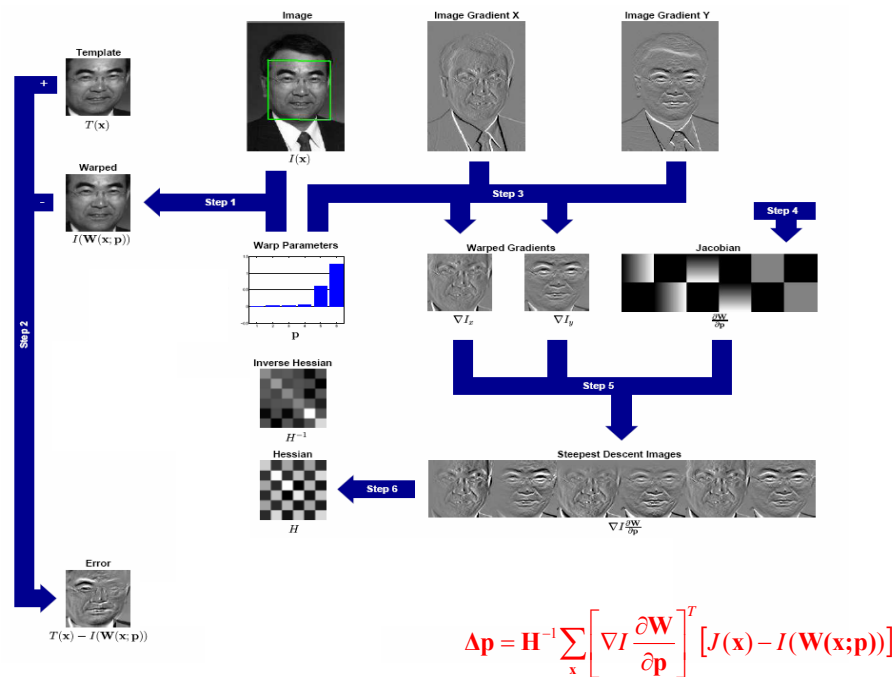
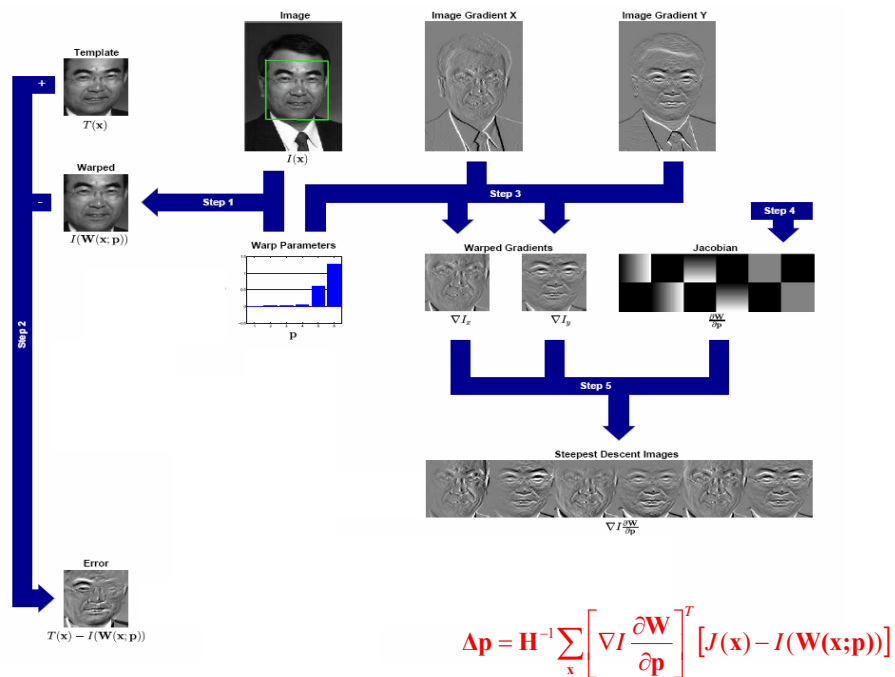
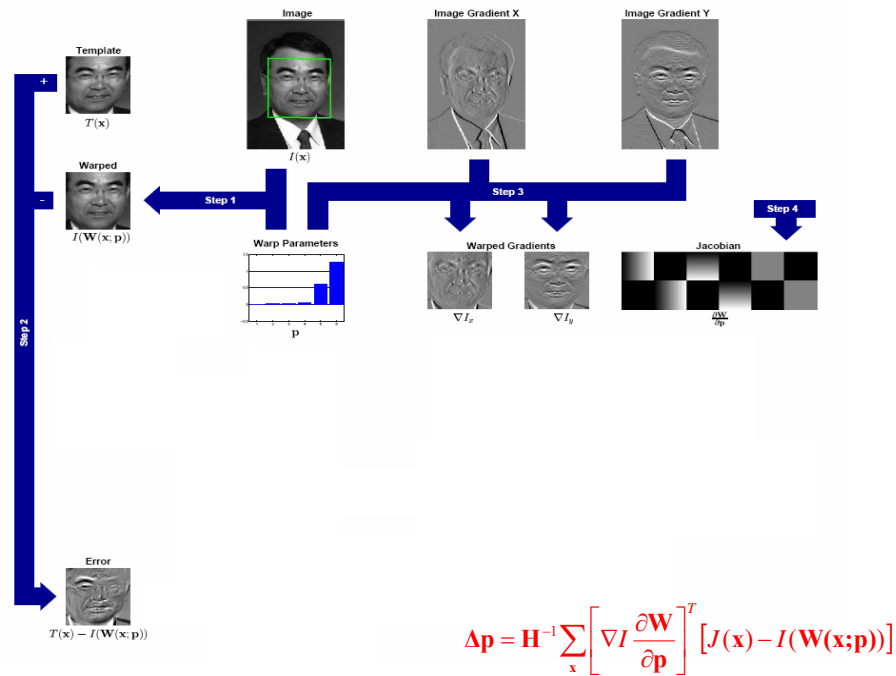
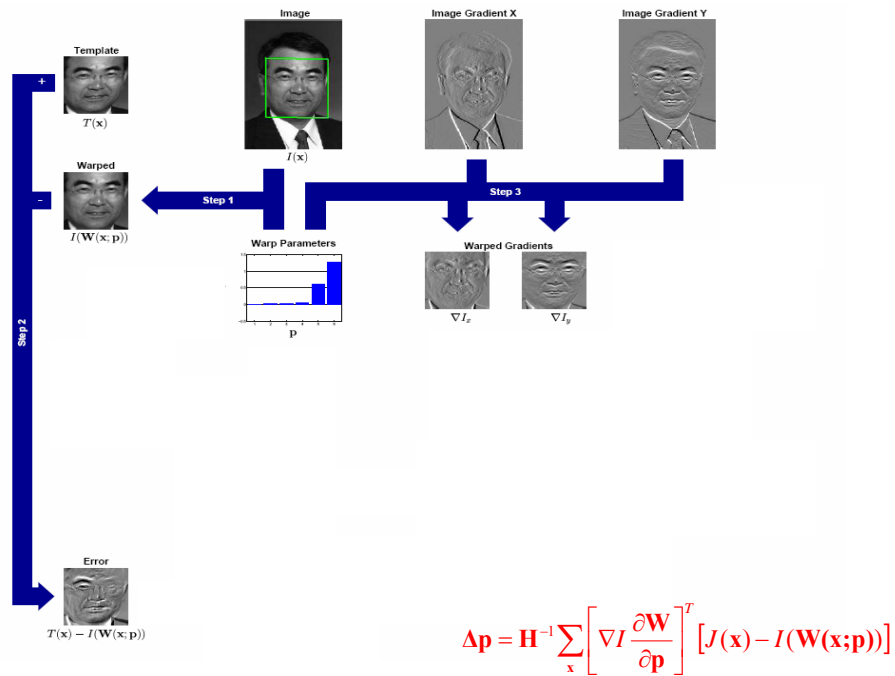
$$\Delta \mathbf{p} = \mathbf{H}^{-1} \sum_{\mathbf{x}} \left[ \nabla I \frac{\partial \mathbf{W}}{\partial \mathbf{p}} \right]^T [J(\mathbf{x}) - I(\mathbf{W}(\mathbf{x}; \mathbf{p}))]$$

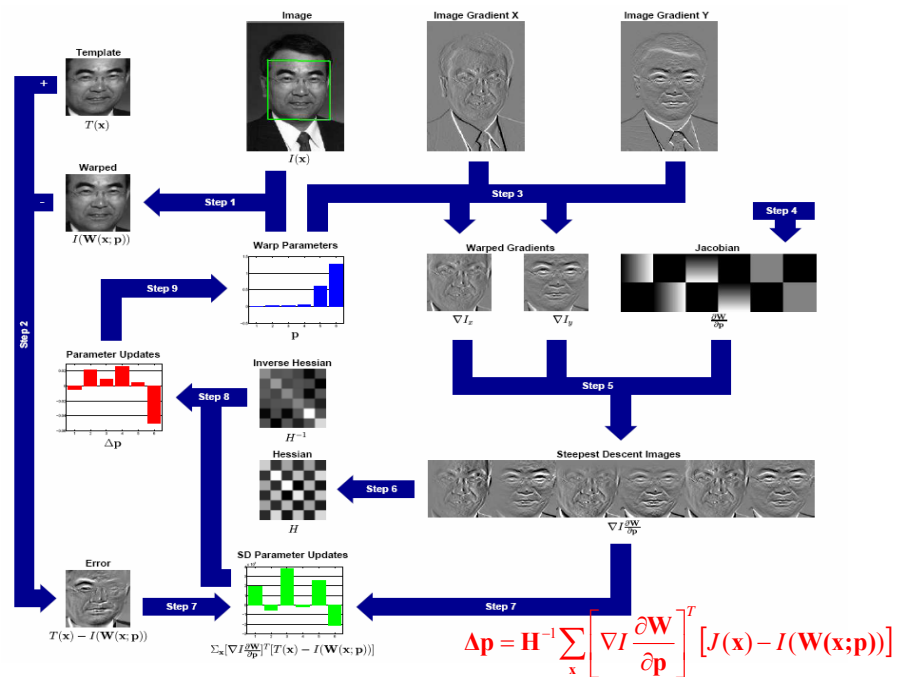
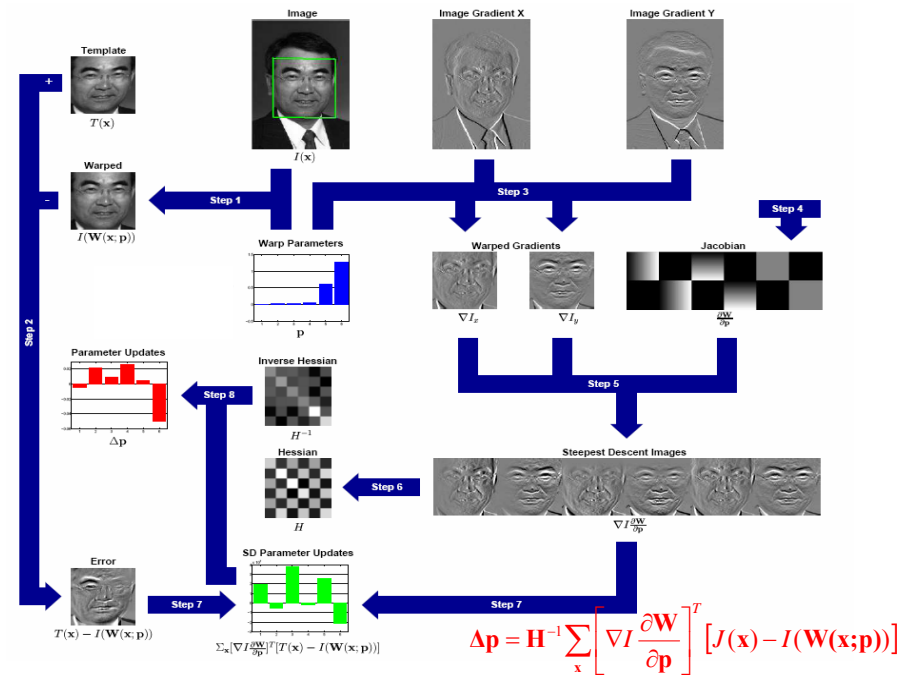
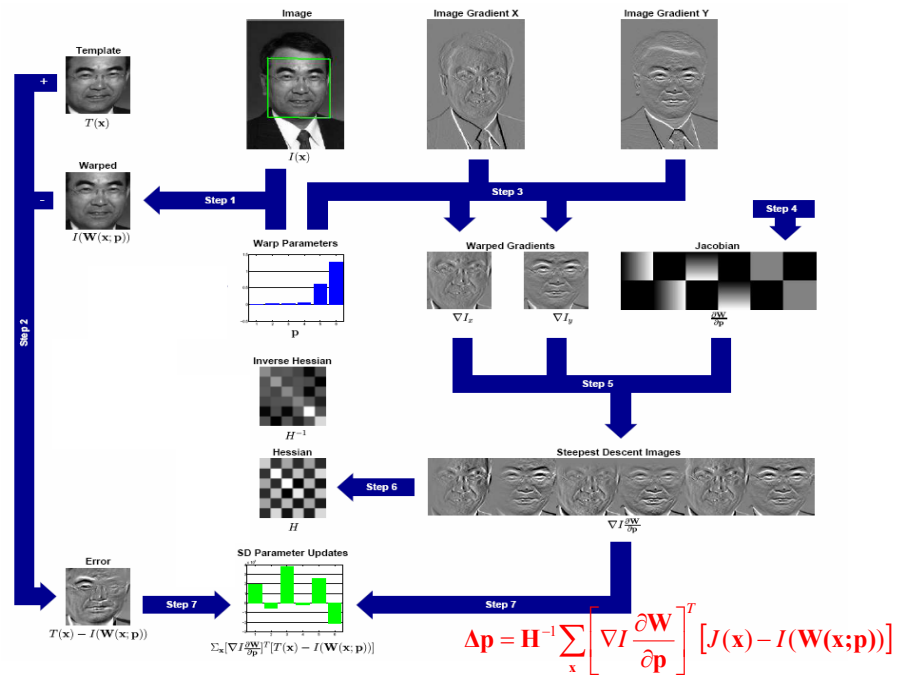


$$\Delta \mathbf{p} = \mathbf{H}^{-1} \sum_{\mathbf{x}} \left[ \nabla I \frac{\partial \mathbf{W}}{\partial \mathbf{p}} \right]^T [J(\mathbf{x}) - I(\mathbf{W}(\mathbf{x}; \mathbf{p}))]$$



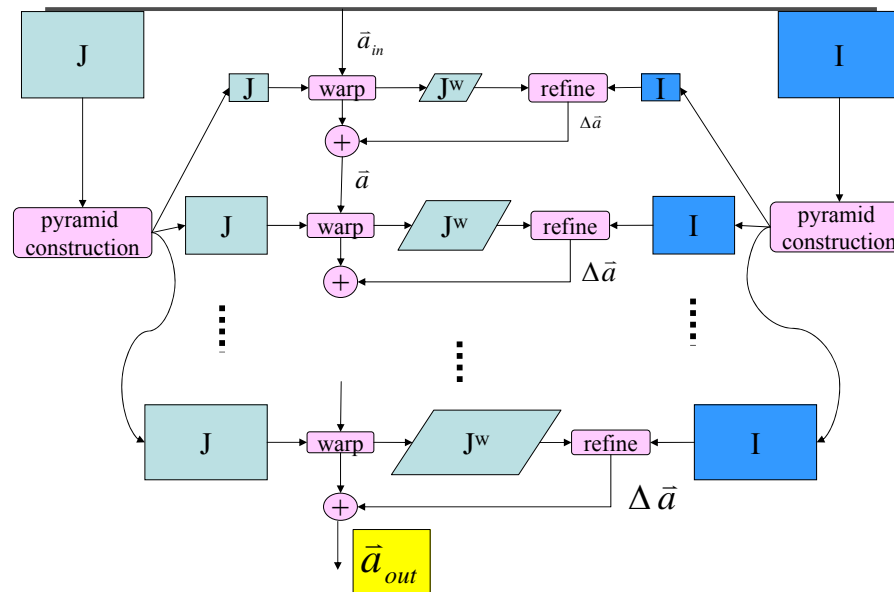
$$\Delta \mathbf{p} = \mathbf{H}^{-1} \sum_{\mathbf{x}} \left[ \nabla I \frac{\partial \mathbf{W}}{\partial \mathbf{p}} \right]^T [J(\mathbf{x}) - I(\mathbf{W}(\mathbf{x}; \mathbf{p}))]$$





### Coarse-to-fine strategy

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## Application of image alignment

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## Direct vs feature-based

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- Direct methods use all information and can be very accurate, but they depend on the fragile “brightness constancy” assumption
- Iterative approaches require **initialization**
- Not robust to illumination change and noise images
- In early days, direct method is better.
  
- Feature based methods are now more robust and potentially faster
- Even better, it can recognize panorama without initialization

## Tracking

## Tracking

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$I(x,y,t)$

$I(x,y,t+1)$



## Tracking

brightness constancy  $I(x+u, y+v, t+1) - I(x, y, t) = 0$

$$I(x, y, t) + uI_x(x, y, t) + vI_y(x, y, t) + I_t(x, y, t) - I(x, y, t) \approx 0$$

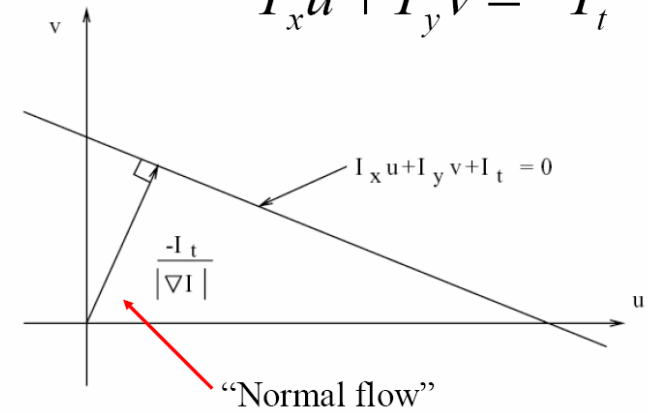
$$uI_x(x, y, t) + vI_y(x, y, t) + I_t(x, y, t) = 0$$

$$I_x u + I_y v + I_t = 0 \quad \text{optical flow constraint equation}$$

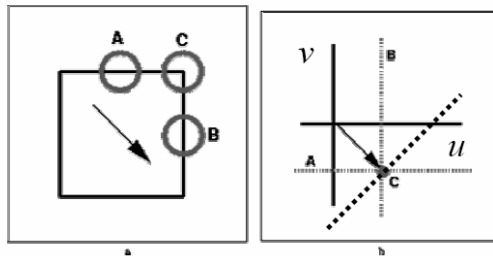
## Optical flow constraint equation

At a single image pixel, we get a line:

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



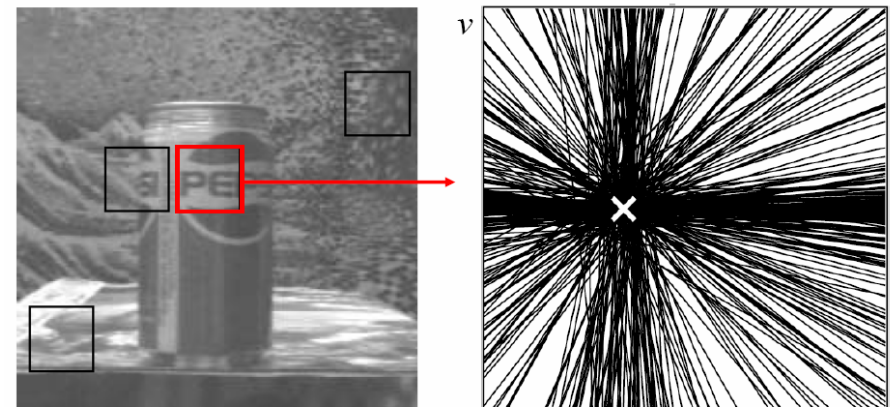
## Multiple constraints



Combine constraints to get an estimate of velocity.

## Area-based method

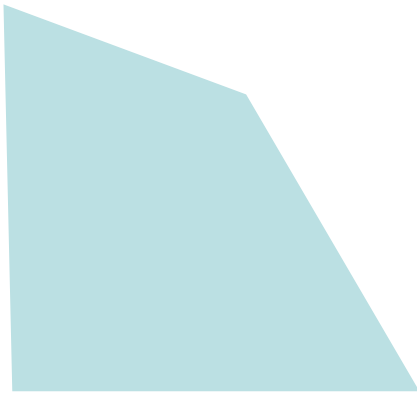
- Assume spatial smoothness



## Aperture problem

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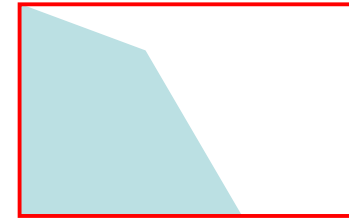
DigiVFX



## Aperture problem

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DigiVFX



## Aperture problem

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DigiVFX



## Demo for aperture problem

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- [http://www.sandlotscience.com/Distortions/Breathing\\_Square.htm](http://www.sandlotscience.com/Distortions/Breathing_Square.htm)
- [http://www.sandlotscience.com/Ambiguous/Barberpole\\_Illusion.htm](http://www.sandlotscience.com/Ambiguous/Barberpole_Illusion.htm)

## Aperture problem

- Larger window reduces ambiguity, but easily violates spatial smoothness assumption

## Area-based method

- Assume spatial smoothness

$$E(u, v) = \sum_{x,y} (I_x u + I_y v + I_t)^2$$

$$\frac{\partial E}{\partial u} = \sum_R (I_x u + I_y v + I_t) I_x = 0$$

$$\frac{\partial E}{\partial v} = \sum_R (I_x u + I_y v + I_t) I_y = 0$$

## Area-based method

$$\left[ \sum_R I_x^2 \right] u + \left[ \sum_R I_x I_y \right] v = - \sum_R I_x I_t$$

$$\left[ \sum_R I_x I_y \right] u + \left[ \sum_R I_y^2 \right] v = - \sum_R I_y I_t$$

$$\begin{bmatrix} \sum I_x^2 & \sum I_x I_y \\ \sum I_y I_x & \sum I_y^2 \end{bmatrix} \begin{bmatrix} u \\ v \end{bmatrix} = \begin{bmatrix} - \sum I_x I_t \\ - \sum I_y I_t \end{bmatrix}$$

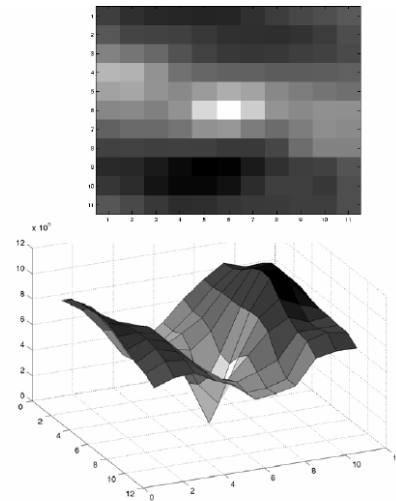
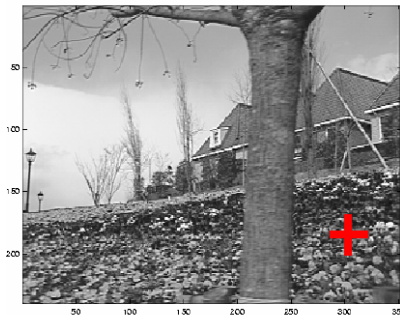
must be invertible

## Area-based method

- The eigenvalues tell us about the local image structure.
- They also tell us how well we can estimate the flow in both directions
- Link to Harris corner detector



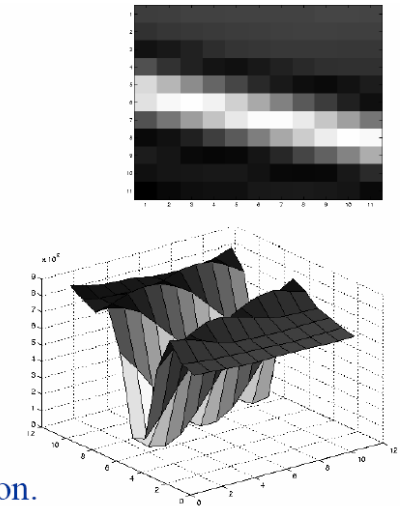
## Textured area



$$\begin{bmatrix} \sum I_x^2 & \sum I_x I_y \\ \sum I_y I_x & \sum I_y^2 \end{bmatrix}$$

Gradients in x and y.

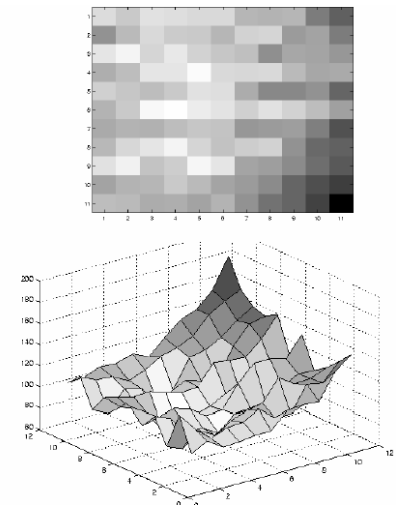
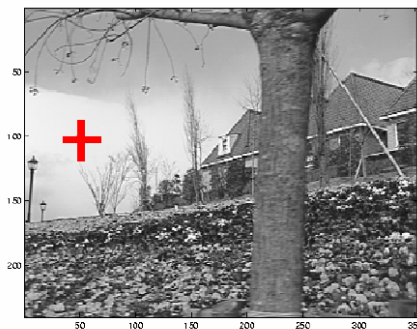
## Edge



$$\begin{bmatrix} \sum I_x^2 & \sum I_x I_y \\ \sum I_y I_x & \sum I_y^2 \end{bmatrix}$$

Gradients oriented in one direction.

## Homogenous area

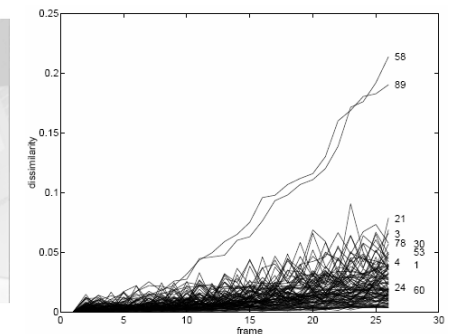
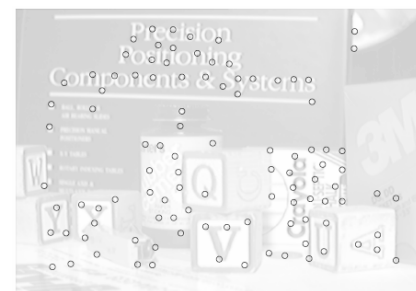


$$\begin{bmatrix} \sum I_x^2 & \sum I_x I_y \\ \sum I_y I_x & \sum I_y^2 \end{bmatrix}$$

Weak gradients everywhere.

## KLT tracking

- Select feature by  $\min(\lambda_1, \lambda_2) > \lambda$
- Monitor features by measuring dissimilarity



## Translational Model



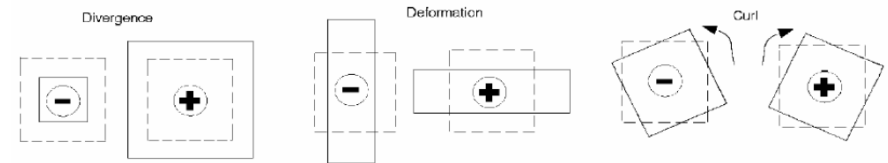
What's wrong with the translational assumption (ie constant motion within a region R)?

How can we generalize it?

## Affine Flow

$$E(\mathbf{a}) = \sum_{x,y \in R} (\nabla I^T \mathbf{u}(x; \mathbf{a}) + I_t)^2$$

$$\mathbf{u}(x; \mathbf{a}) = \begin{bmatrix} u(x; \mathbf{a}) \\ v(x; \mathbf{a}) \end{bmatrix} = \begin{bmatrix} a_1 + a_2x + a_3y \\ a_4 + a_5x + a_6y \end{bmatrix}$$



## Optimization

$$E(\mathbf{a}) = \sum_{x,y \in R} (I_x a_1 + I_x a_2 x + I_x a_3 y + I_y a_4 + I_y a_5 x + I_y a_6 y + I_t)^2$$

Differentiate wrt the  $a_i$  and set equal to zero.

$$\begin{bmatrix} \Sigma I_x^2 & \Sigma I_x^2 x & \Sigma I_x^2 y & \Sigma I_x I_y & \Sigma I_x I_y x & \Sigma I_x I_y y \\ \Sigma I_x^2 x & \Sigma I_x^2 x^2 & \Sigma I_x^2 xy & \Sigma I_x I_y x & \Sigma I_x I_y x^2 & \Sigma I_x I_y xy \\ & & & \vdots & & \\ \Sigma I_y^2 & \Sigma I_y^2 x & \Sigma I_y^2 y & \Sigma I_x I_y & \Sigma I_x I_y x & \Sigma I_x I_y y \\ \Sigma I_y^2 x & \Sigma I_y^2 x^2 & \Sigma I_y^2 xy & \Sigma I_x I_y x & \Sigma I_x I_y x^2 & \Sigma I_x I_y xy \\ & & & \vdots & & \\ \Sigma I_y^2 y & \Sigma I_y^2 xy & \Sigma I_y^2 y^2 & \Sigma I_x I_y y & \Sigma I_x I_y xy & \Sigma I_x I_y y^2 \end{bmatrix} \begin{bmatrix} a_1 \\ a_2 \\ a_3 \\ a_4 \\ a_5 \\ a_6 \end{bmatrix} = \begin{bmatrix} -\Sigma I_x I_t \\ -\Sigma I_x I_t x \\ -\Sigma I_x I_t y \\ -\Sigma I_y I_t \\ -\Sigma I_y I_t x \\ -\Sigma I_y I_t y \end{bmatrix}$$

## KLT tracking

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<http://www.ces.clemson.edu/~stb/klt/>

## KLT tracking

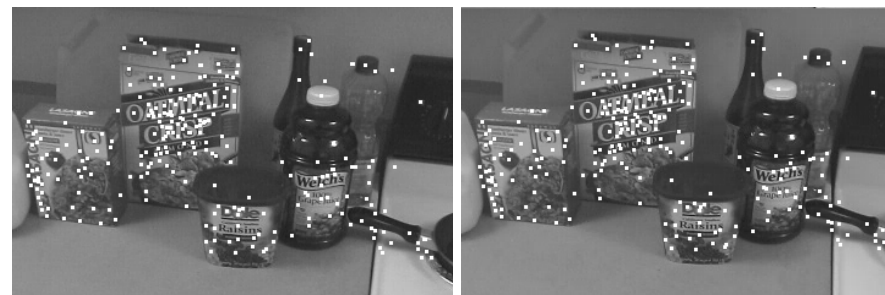
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<http://www.ces.clemson.edu/~stb/kl/>

## SIFT tracking (matching actually)

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Frame 0 → Frame 10

## SIFT tracking

DigiVFX



Frame 0 → Frame 100

## SIFT tracking

DigiVFX



Frame 0 → Frame 200

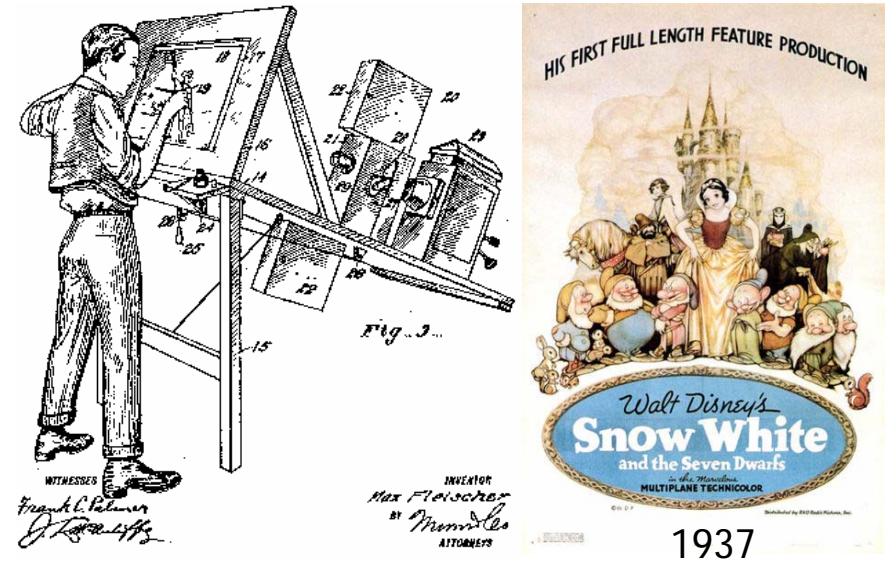
## KLT vs SIFT tracking

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- KLT has larger accumulating error; partly because our KLT implementation doesn't have affine transformation?
- SIFT is surprisingly robust
- Combination of SIFT and KLT ([example](#))  
<http://www.frc.ri.cmu.edu/projects/buzzard/smalls/>

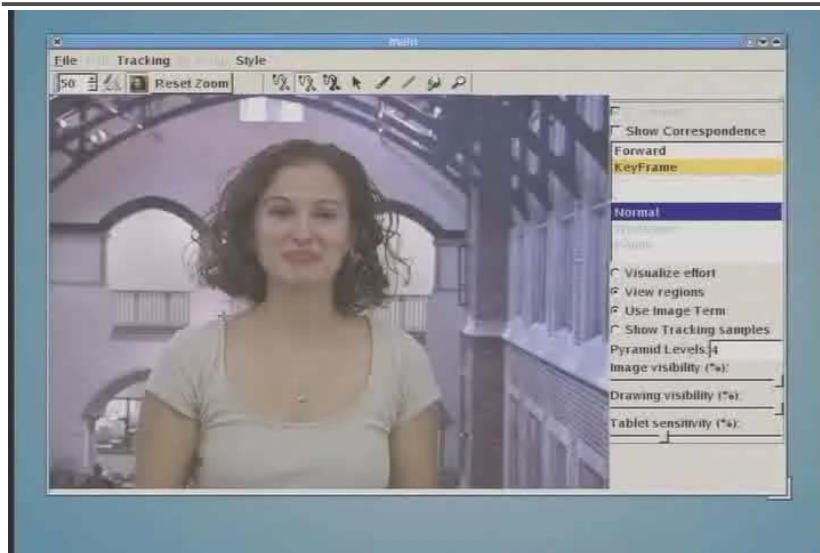
## Rotoscoping (Max Fleischer 1914)

DigiVFX



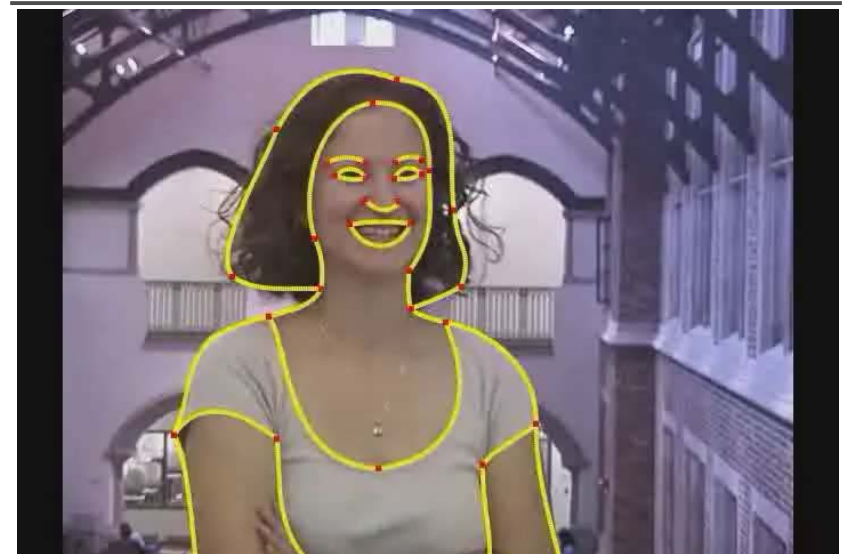
## Tracking for rotoscoping

DigiVFX



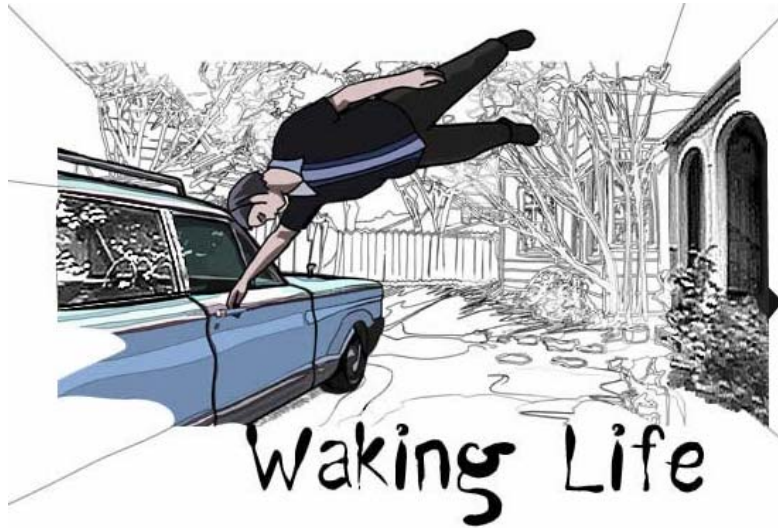
## Tracking for rotoscoping

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## Waking life (2001)

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**Optical flow**

## A Scanner Darkly (2006)

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- Rotoshop, a proprietary software. Each minute of animation required 500 hours of work.



## Single-motion assumption

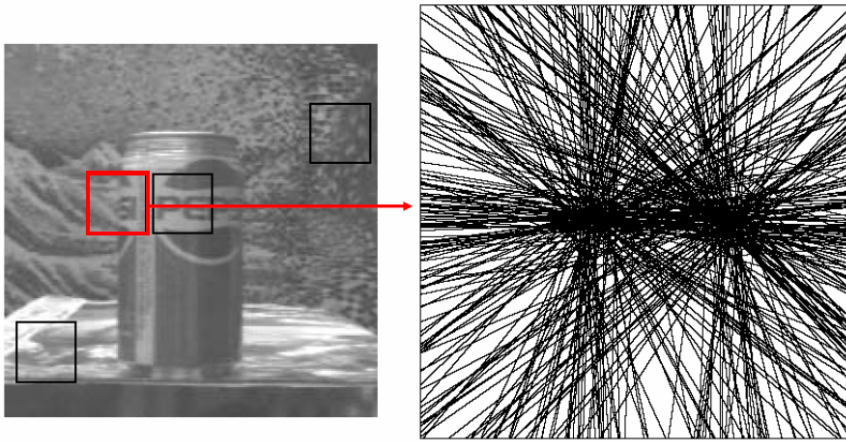
DigiVFX

Violated by

- Motion discontinuity
- Shadows
- Transparency
- Specular reflection
- ...

## Multiple motion

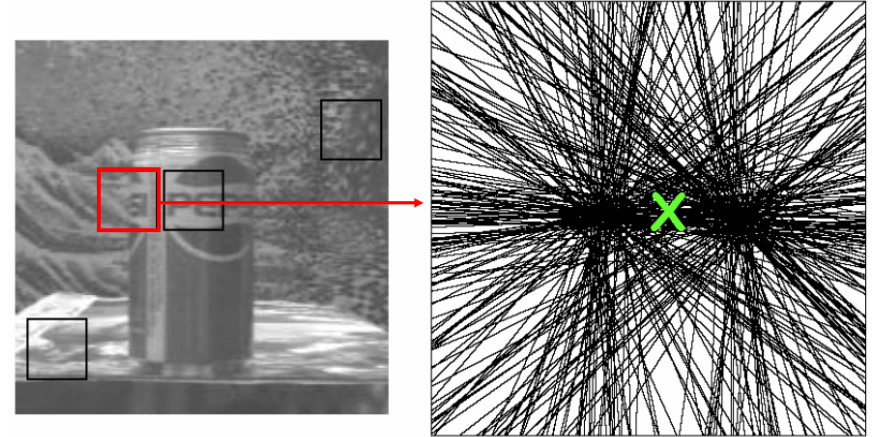
DigiVFX



What is the “best” fitting translational motion?

## Multiple motion

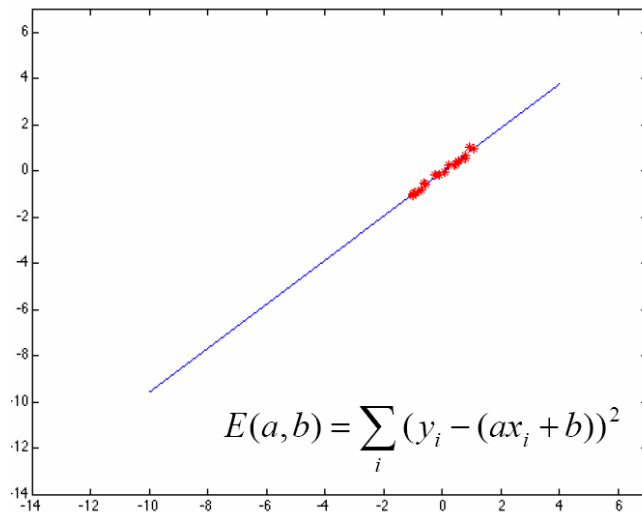
DigiVFX



Least squares fit.

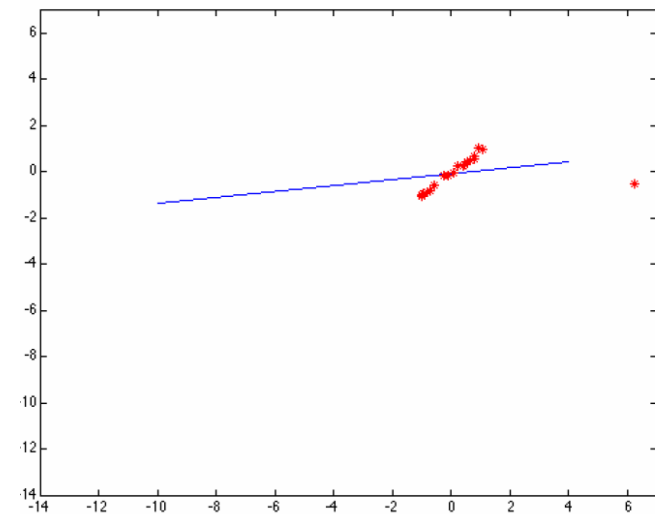
## Simple problem: fit a line

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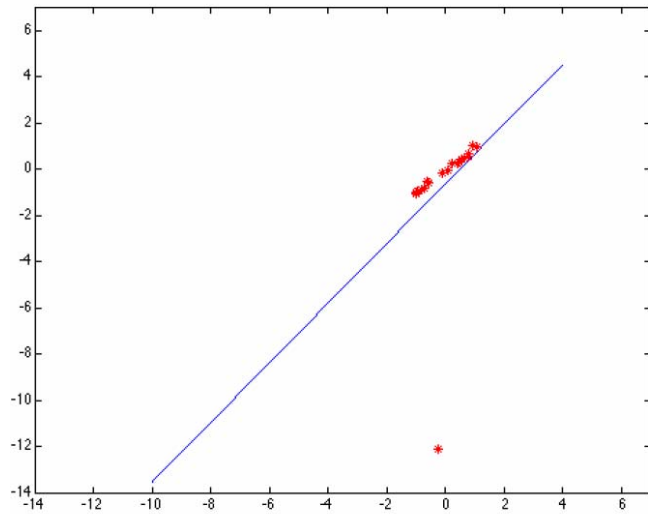


## Least-square fit

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## Least-square fit

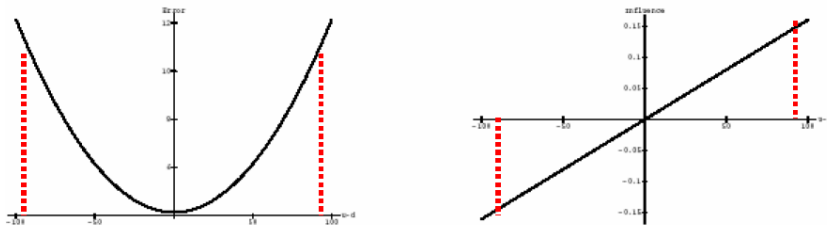


## Robust statistics

- Recover the best fit for the **majority** of the data
- Detect and reject **outliers**

## Approach

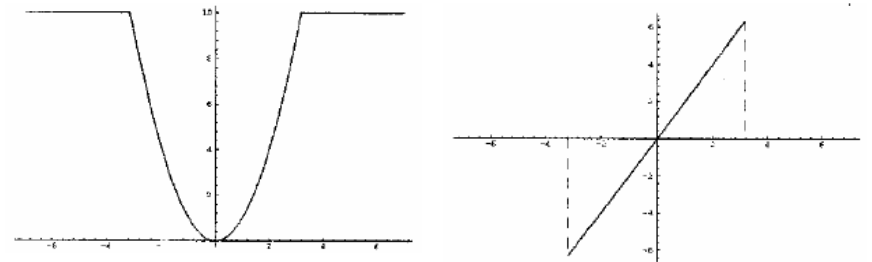
Influence is proportional to the derivative of the  $\rho$  function.



Want to give less influence to points beyond some value.

## Robust weighting

$$\rho(x, \alpha, \lambda) = \begin{cases} \lambda x^2 & \text{if } |x| < \frac{\sqrt{\alpha}}{\sqrt{\lambda}}, \\ \alpha & \text{otherwise.} \end{cases} \quad \psi(x, \alpha, \lambda) = \begin{cases} 2\lambda x & \text{if } |x| < \frac{\sqrt{\alpha}}{\sqrt{\lambda}}, \\ 0 & \text{otherwise.} \end{cases}$$

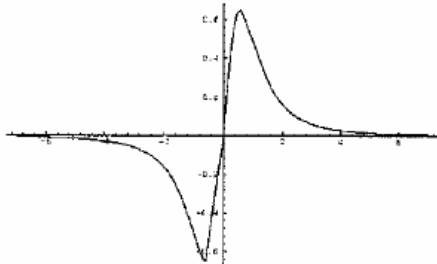
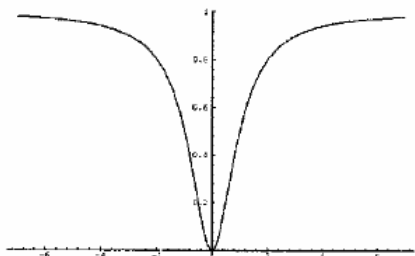


Truncated quadratic

## Robust weighting

$$\rho(x, \sigma) = \frac{x^2}{\sigma + x^2}$$

$$\psi(x, \sigma) = \frac{2x\sigma}{(\sigma + x^2)^2}$$



Geman & McClure

## Robust estimation

$$E(\mathbf{a}) = \sum_{x,y \in R} \rho(I_x u + I_y v + I_t, \sigma)$$

Minimize: differentiate and set equal to zero:

$$\frac{\partial E}{\partial u} = \sum_{x,y \in R} \psi(I_x u + I_y v + I_t, \sigma) I_x = 0$$

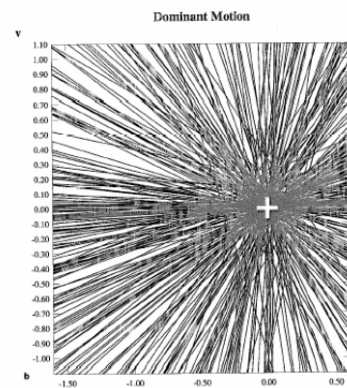
$$\frac{\partial E}{\partial v} = \sum_{x,y \in R} \psi(I_x u + I_y v + I_t, \sigma) I_y = 0$$

*No closed form solution!*

## Fragmented occlusion

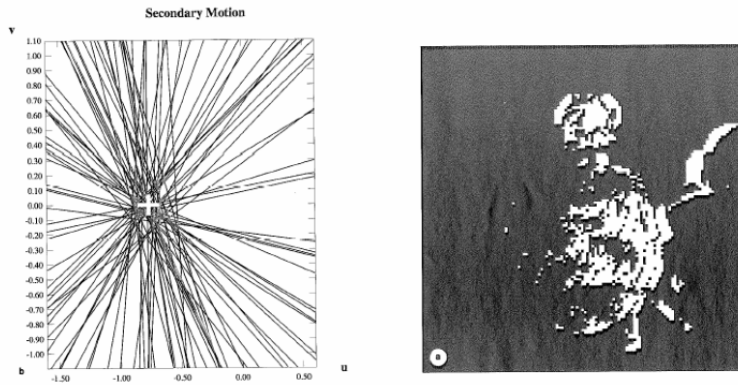


## Results

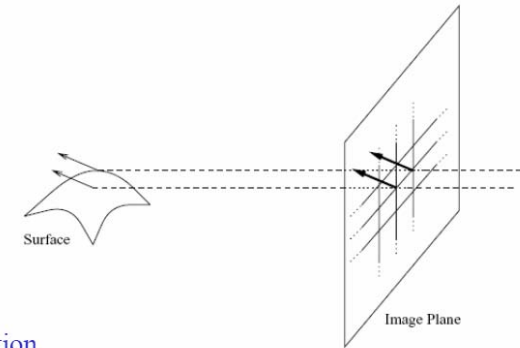




# Results



# Regularization and dense optical flow

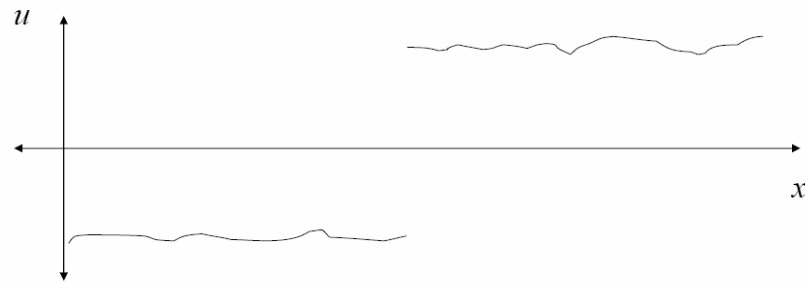


## Assumption

- \* Neighboring points in the scene typically belong to the same surface and hence typically have similar motions.
- \* Since they also project to nearby points in the image, we expect spatial coherence in image flow.

# Formalize this Idea

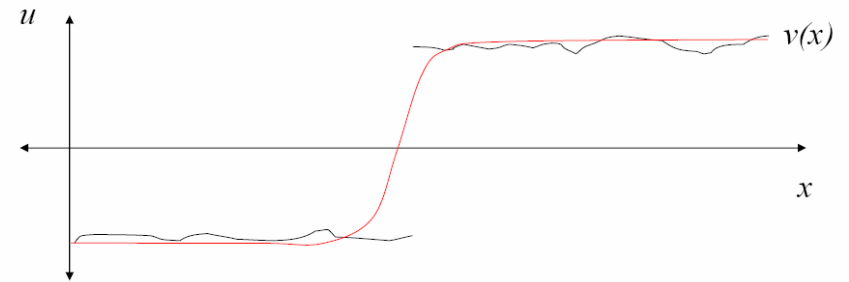
Noisy 1D signal:



Noisy measurements  $u(x)$

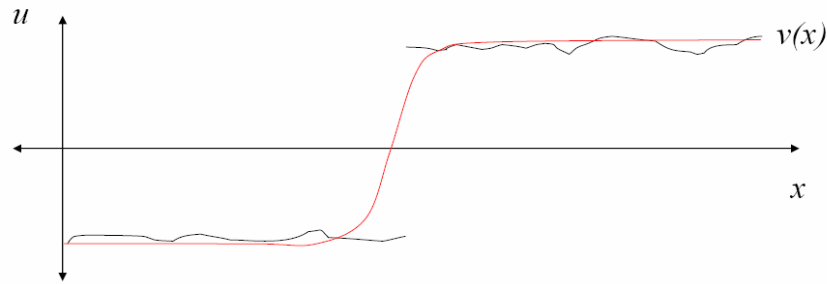
# Regularization

Find the “best fitting” smoothed function  $v(x)$



Noisy measurements  $u(x)$

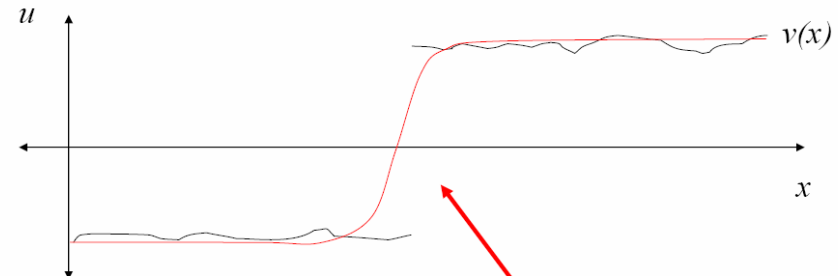
# Regularization



Minimize: Faithful to the data Spatial smoothness assumption

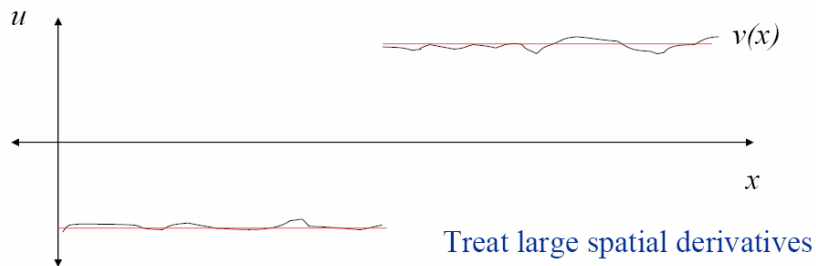
$$E(v) = \sum_{x=1}^N (v(x) - u(x))^2 + \lambda \sum_{x=1}^{N-1} (v(x+1) - v(x))^2$$

# Discontinuities



What about this discontinuity?  
 What is happening here?  
 What can we do?

# Robust Regularization



Minimize: Treat large spatial derivatives as outliers.

$$E(v) = \sum_{x=1}^N \rho(v(x) - u(x), \sigma_1) + \lambda \sum_{x=1}^{N-1} \rho(v(x+1) - v(x), \sigma_2)$$

# “Dense” Optical Flow

$$E_D(\mathbf{u}(\mathbf{x})) = \rho(I_x(\mathbf{x})u(\mathbf{x}) + I_y(\mathbf{x})v(\mathbf{x}) + I_t(\mathbf{x}), \sigma_D)$$

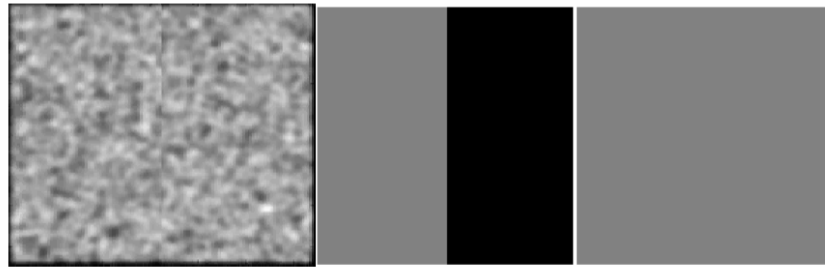
$$E_S(u, v) = \sum_{\mathbf{y} \in G(\mathbf{x})} [\rho(u(\mathbf{x}) - u(\mathbf{y}), \sigma_S) + \rho(v(\mathbf{x}) - v(\mathbf{y}), \sigma_S)]$$

Objective function:

$$E(\mathbf{u}) = \sum_{\mathbf{x}} E_D(\mathbf{u}(\mathbf{x})) + \lambda E_S(\mathbf{u}(\mathbf{x}))$$

When  $\rho$  is quadratic = “Horn and Schunck”

## Example

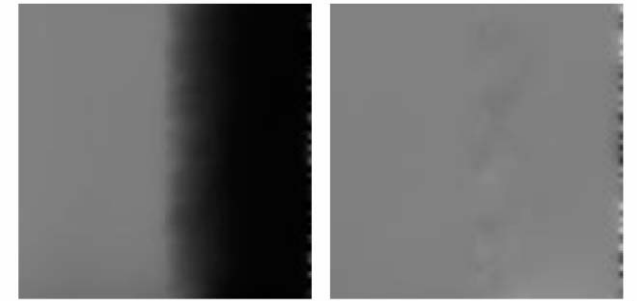


Input image

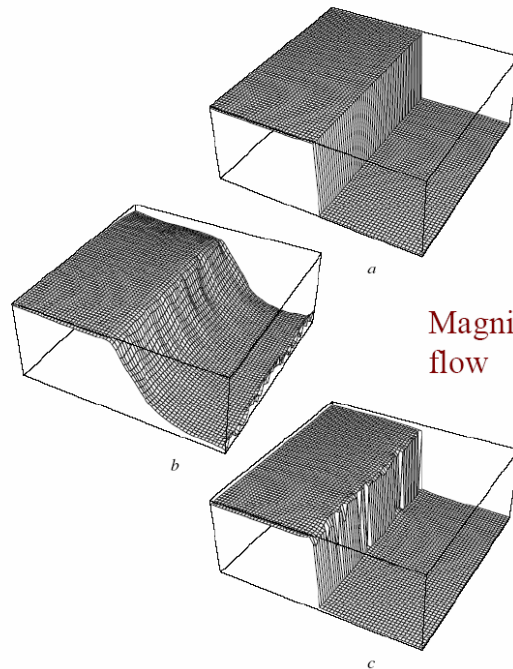
Horizontal motion

Vertical motion

Quadratic:



Robust:



Magnitude of horizontal flow

## Applications of Optical Flow



Impressionist effect.  
Transfer motion of real world to a painting

## Input for the NPR algorithm

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## Brushes

DigiVFX



## Edge clipping

DigiVFX



## Gradient

DigiVFX



## Smooth gradient

DigiVFX



## Textured brush

DigiVFX



## Edge clipping

DigiVFX



## Temporal artifacts

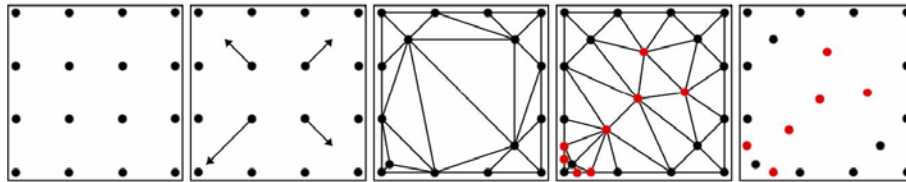
DigiVFX



Frame-by-frame application of the NPR algorithm

## Temporal coherence

DigiVFX



## RE:Vision

DigiVFX



## What dreams may come

DigiVFX



## Reference

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