Image Mosaicing Method by Using Sift and Grid Based

Manoj Kumar Ramaiya[1], Nirupma Tiwari[2], Naveen Hemrajani[3], Priya Bhatnagar[4]
Suresh Gyanvihar University, Jaipur, India [12]
JECRC University ,Jaipur , India[3]
Shriram College of Engineering & Management, Gwalior, India[4]
manojramaiya@gmail.com,girishniru@gmail.com,Naveen_h@yahoo.com, priya2406@gmail.com

***Abstract* - Image Mosaicing is The Stitching of Multiple Correlated Images to Generate a Large Wide Angle Image of a Scene. Image Mosaicing Has Become An Active Area of Research in the Fields of Photogrammetry, Computer Vision, Image Processing, and Computer Graphics. Application Includes The Construction of Aerial and Satellite Photographs, Photo Editing and The Creation of Virtual Environments Mosaicing Could Be Regarded as a Special Case of Scene Reconstruction Where The Images are Related by Planar Holography only. Image Mosaicing has been Collecting Widespread Attention Because It Can Automatically Construct a Panoramic Image from Multiple Images. Various Image Mosaicing Algorithms Have Been Developed To Solve Problems Like Misregistration Of Image. In This Paper, We Proposed And Implemented A Grid Based Approach For Image Mosaicing Which Not Only Includes More Features But Also Improves Accuracy Over Previous Methods. Previously, Image Mosaicing Algorithms Developed Includes Less Features Hence, Not Able To Produce Better Quality Of Images. Geometry, Object, Homograph And Texture Based Features Are Extracted Which Is Termed As Feature Extraction Firstly We Divide Image Into Grid Or Matrix Form.**

Keywords: Feature Extraction, Grid, Homographic images, Image Mosaicing , Image Stitching, Matcher, Panoramic, RANSAC algorithm, SIFT Feature Extraction ,Texture, VERIFIER algorithm.

I. INTRODUCTION

An Image mosaic is a synthetic composition generated from a sequence of images and it can be obtained by understanding geometric relationships between images. The geometric relations are coordinate transformations that relate the different image coordinate systems. By applying the appropriate transformations via a warping operation and merging the overlapping regions of warped images, it is possible to construct a single image indistinguishable from a single large image of the same object, covering the entire visible area of the scene.

Several image mosaicing algorithms have been proposed over the last decade. Some novelties include feature based image mosaicing proposed by Hu [1] which was the first method which tells about feature extraction.

Secondly ,expectation maximization algorithm for removing inconsistent overlaid regions in mosaicing proposed by Liyoshi[5] or the distortion calibration and the registration algorithm proposed by Tong[10].

This paper proposes a Grid Based multiple features (GBMF) approach which is a combination of various methods includes an image mosaicing algorithm. These deals with six major steps:

1. Image framing 2. Feature Extraction 3. Matching 4. Verification of features 5. Redrawing 6. Image Stitching.

Image framing includes image division based on frames. Grid based multiple features (GBMF) to assess the performance of previous mosaicing algorithms. For image mosaicing the system, the work starts with pre-processing phase, which consist of two important steps. First, framing or grid formation on the basis of calculation of global intensity difference. Second, feature extraction after image intensity is calculated. The mathematical formulas and calculation required in global intensity difference consist of intensity difference, image gradient and grayscale conversion are used for image registration. Many filters are used like Gaussian and average filters which results in less distortion of image. After the framing phase, here five basic features are considered for mosaicing as geometrical, object oriented, homographic, S.I.F.T (Scale Invariant Feature Transform) and Texture Based methods of feature extraction is done.

II. PROPOSED METHODOLOGY

Grid Based Multiple Features Based On Image Mosaicing:-- In this paper, Grid based Multiple features algorithm proposed which not only includes more features of images on the basis of texture, object oriented , homographic based, And SIFT based thus large data set can be obtained and Homographic approach for image registration including framing reduces problems of previous approaches. The methodology adopted is as follows: First, the image is divided into frames. Secondly, frames are then used in feature selection and feature extraction. Multiple

Feature extraction is done. After, this images are matched, verified and redrawn. After, those images are stitched. The various stages in this approach are explained in below sections.

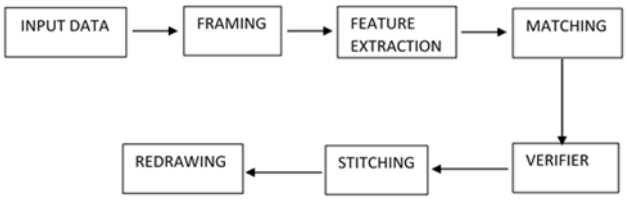


Figure 1: Work flow Diagram

III. ALGORITHMS

A. Image Framing and Feature Extraction:

Texture Based Approach for Framing

To overcome the complexity of using texture features on entire image the proposed method divides the image into four Parts of different size and evaluates the texture features in each part separately. This is called framing. The texture features are derived from co-occurrence Parameters. They are given in the following equations.

Input: Full image

Output: The final image is the output image.

ANGULAR SECOND MOMENT

(ASM) = Σp (Ǿ, d) (a, b)

MAXIMUM PROBABILITY=MAX P (Ǿ,d)(a,b)

Entropy, (ET)=Σa,bp(Ǿ,d)(a,b)log2p(Ǿ,d)(a,b)

Inverse Difference

(ID)= Σ P(Ǿ,d)(a,b)/(1+ | a-b |)

Inverse Difference Moment

(IDM) = Σ p(Ǿ,d)(a,b)/(1+ | a-b | 2)

Mean (M) = Σa*p (Ǿ,d)(a,b)

Where p(Ǿ,d)(a,b) is the frequency of occurrences of two where Pixels, with grey-levels a, b appearing in the window separated by a distance d in direction 'Ǿ'. The texture features are evaluated for each part individually in all orientations. The average value of each texture feature s taken as final value. Texture Based Approach depends on shape, colour composition of an image.

B. Feature extraction Based On Homography :

Input Images of a scenery or hall are taken from various point of view and features are extracted. Homographs estimation is done by calculating energy functions:

Calculation of energy Function is as follows:

$$Eng(L) = \Sigma DP(lp) + \gamma \Sigma Vp,q(lp, lq), \{p,q\} \in N$$

where $Dp(lp)$ denotes the *data term*, and $Vp,q(lp, lq)$ denotes the *smoothness term*. The data term $Dp(lp)$ defines the cost of assigning the label lp to pixel p.

Feature extraction using SIFTS: SIFT FEATURE using homographic approach includes:

-Scale space construction

-Extrema detection

-Orientation Assignment

-Key point Localization

-Key point descriptors.

Feature Extraction based on geometry:

Various geometrical features like shape, size, width, height are considered in this feature extraction. Oriented Algorithm is used for this purpose:

Feature extraction Based on Object Oriented:.

Object Oriented includes tree, car, buildings, fan etc. are matched and common points are derived .This concept of object oriented is used.

Image Registration

For each grid with respect to source image:

Step 1.Compute the common points of grid of target images and source images common points are found.

Step 2.Both common points are correlated.

Step 3.Find the homographic using STITCHER Algorithm. Call STITCHER

Step 4.Best matching points are obtained and call MATCHER and VERIFIER.

STITCHER ALGORITHM:

1: Select randomly the minimum number of points and determine the model parameters and solve parameter. 2: Determine how many points from the set of all points fit with a predefined tolerance €.

3: If the fraction of the number of inliers over the total number points in the set exceeds a predefined threshold re-estimate the model parameters using all the identified inliers and terminate.

4: Otherwise, repeat steps 1 through 4 (N times).

C. Image Matching and Verification:

MATCHER ALGORITHM:

Method: w1 (P1, Error1) > w2 (P2, Error2)

If P1>P2

Return True

Else

If P1<P2

Return False

Else

If δ1>δ2

Return False

Else return true

GMST of G will reduce here, image matching is done by taking P1 and P2 which means P1 means probability of far common points and P2 means probability of near points. Δ1 and δ2 are function values of different points.

3.4 VERIFIER ALGORITHM:

VERIFIER is a new proposed algorithm which discards false matches

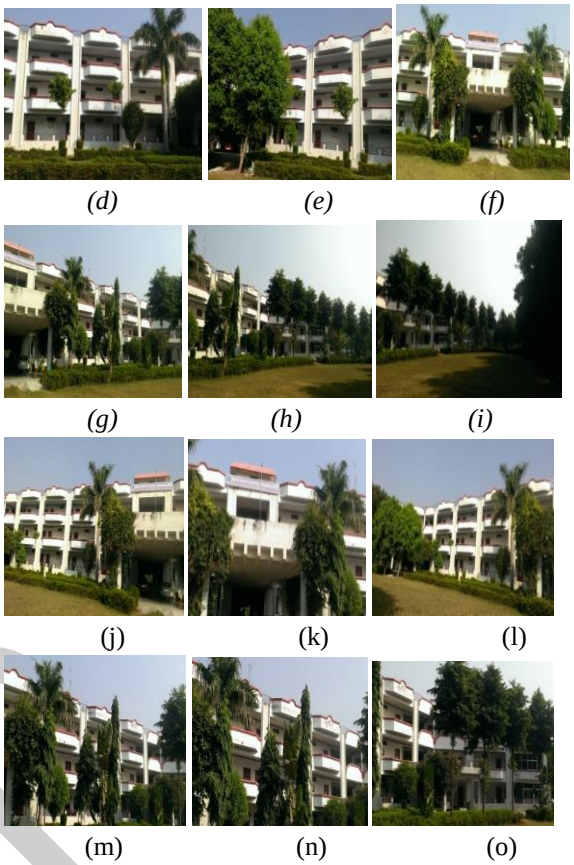
1. Estimates an optimum Homographic matrix based on homographic constraints.

2. Geometric distance error is calculated and maximum no of inliers are derived for constructing homographic matrix .Then using this matrix image is warped into a common coordinate frame.

IV. EXPERIMENTAL RESULTS AND DISCUSSION

A. Collection of Data Sets

(a) *(b)* *(c)*



(d) *(e)* *(f)*

(g) *(h)* *(i)*

(j) (k) (l)

(m) (n) (o)

Fig 2 Collection of Data Set

B. SIFT feature based image mosaicing: SIFT stands for Scale Invariant Feature Transforms. This is already developed module in MATLAB 2012 version. It uses the invariant features extracted from images is used to perform reliable matching. Scale Invariant method was one of the most effective method of feature extraction which was extended to form mosaiced image and the comparison is done .In Scale Invariant Feature Transform method first image is applied as input of Figure 2.

Keypoint Localization It is the second step performed on input images

Methamatical Formula: The first stage is to construct a Gaussian "scale space" function from the input image [1]. The difference of Gaussian (DoG), D(x, y, σ), is calculated as the difference between two filtered images, one with k multiplied by scale of the other.

$$D(x, y, \sigma) = L(x, y, k\sigma) - L(x, y, \sigma) \quad \text{(1)}$$

$$L(x, y, \sigma) = G(x, y, \sigma) * I(x, y) \quad \text{(2)}$$

$$G(x, y, \sigma) = 2\pi\sigma^* \exp\{- x2*y2/\sigma2\} \quad \text{(3)}$$

Image matching and verification: Image Matching is performed by finding Key points on the basis of common features indicated by blue lines between image G,H in Fig.

3.Data output is found by localization. Later, verification is performed

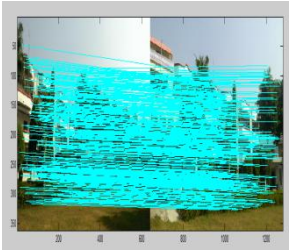


Fig 3-Common Points b/t G&H

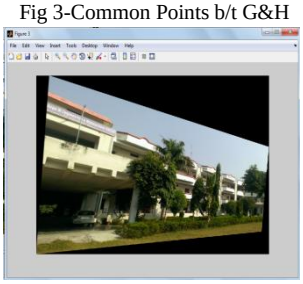


Fig 4 - Rotated Image

Fig 5 - Mosaiced Image Using SIFT

Orientation assignment:

In this, images are rotated by application of scaling and rotation on data set. Final Mosaiced image is generated.

C. Grid Based Image Mosaicing:

A new technique is developed by us in which more comparison is done on the basis of multiple features extraction. The image is divided into grid or frames. Data Set is taken as input. After that image matching is done and common points are found.

First of all both images are combined with each other. After that key points matched are matched and more features are included.

Fig 6 Combined Images of Data Set

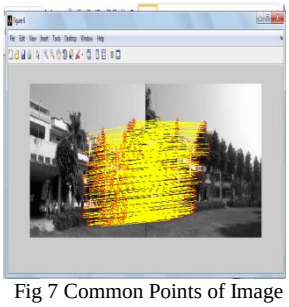


Fig 7 Common Points of Image

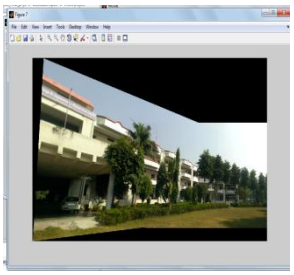


Fig 8 Final Mosaiced Image Using GBMF

V. COMPARISON BETWEEN GRID BASED APPROACH AND SIFT APPROACH

A. On The Basis of Graphical Analysis

Matching points for S.I.F.T method and G.B.M.F method.

Table 1 Matching Points Of S.I.F.T Method

H	H1	H2	H3
	2.1153	-0.1694	-543.1269
	0.4435	1.7718	-224.7017
	0.0017	0.0000	1.0000

H1 indicates source image points, H2 indicates target image points and H3 indicates common points of mosaiced image.

Table 2 Matching Points Of G.B.M.F Method.

H	H1	H2	H3
	2.1087	-0.1688	-541.3257
	0.4445	1.7600	-223.6330
	0.0017	0.0000	1.0000

H1 indicates source image points, H2 indicates target image points and H3 indicates common points of mosaiced image. When the modules of our project is executed ,then

these outputs are produced and give a clear picture about difference in number of common points and better quality achieved.

B. On the basis of P.S.N.R values

The red line explains the peak signal ratio values for S.I.F.T approach whereas blue line indicates grid based approach. In the graph below, X axis indicates images and Y-axis indicates peak -signal –noise-ratio of mosaiced image. The values plotted in above graph are given below in the table 4.3.

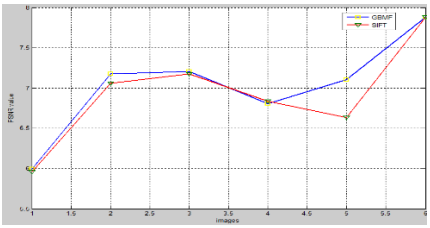


Fig 9 Comparison Of S.I.F.T P.S.N.R Values And G.B.M.F Based P.S.N.R Values.

Table 3 Representation of P.S.N.R Original Values and G.B.M.F Based Values.

S.No	Images	S.I.F.T. PSNR values	G.B.M.F. PSNR value
1	a,b	5.9576	5.9933
2	b,c	7.0604	7.1755
3	d,e	7.1772	7.2048
4	f,g	6.8377	6.8062
5	m,o	6.6322	7.1061
6	j,l	7.8810	7.8784

Higher the PSNR, better is algorithm.

C. On The Basis Of M.S.E Values

The blue line explains the Mean square error values for G.B.M.F. approach and red line indicates MSE values for S.I.F.T approach.

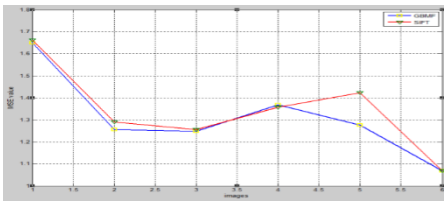


Fig 10 Comparison of Original M.S.E Values with G.B.M.F Based M.S.E Values.

Table 3 Representation Of M.S.E Original Values And G.B.M.F Based M.S.E Values .

S.No	Images	S.I.F.T M.S.E Values	G.B.M.F. M.S.E values
1	a,b	1.6623	1.6487
2	b,c	1.2896	1.2558
3	d,e	1.2553	1.2474
4	f,g	1.3574	1.3673
5	m,o	1.4232	1.2761
6	j,l	1.0675	1.0682

Lower the M.S.E, better is algorithm.

The Table and figures indicated above give a clear picture of the less distortion of images of G.B.M.F approach which produces better quality as comparison to original image mosaicing approach. The graphs plotted indicates that our present algorithm ensures more accuracy by calculation of correlation and covariance method and normalization.

VI. CONCLUSION

In this paper, Grid based approach focuses on frame based method which includes a lot of features. Features are extracted on the basis of texture, geometrical, object oriented, homographic and SIFTS features. Later image mosaicing is performed. This method solves accuracy, PSNR problem, better cost and computation. Therefore, enhances the performance of previous methods. VERIFIER Algorithm is proposed which removes the flaws of matching But, since in this method more features are included therefore, it has resulted in more execution time. In future, this algorithm can be improved by reducing execution time and applying it in very small and very large

images. In medical apparatus and digital cameras this algorithm can be further applied.

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