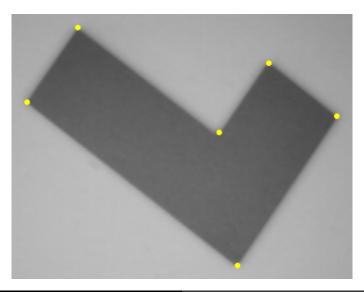
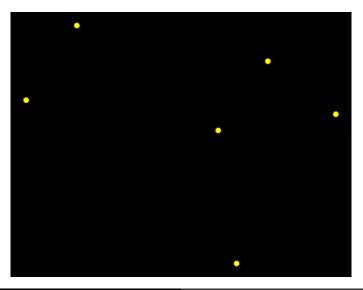
### **Points and Pointillism**

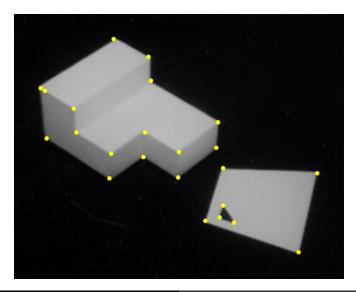
A Computational Perspective

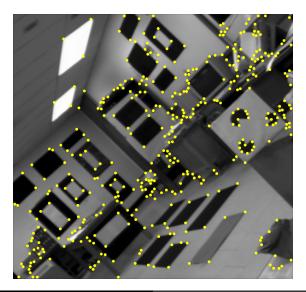
#### Partha Bhowmick

Associate Professor CSE Department IIT Kharagpur







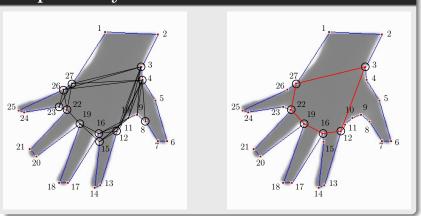


#### Applications

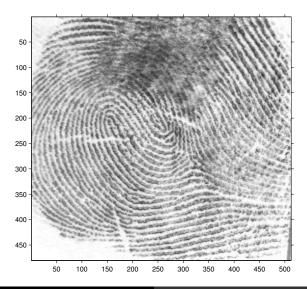
- shape analysis
- **2** tracking and classification of moving vehicles
- optical flow computation
- 3D scene analysis and reconstruction from stereo image pairs
- face tracking and face recognition
- retrieval of images and videos

etc.

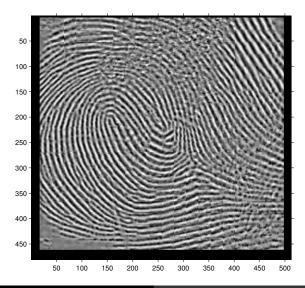
#### Shape Analysis



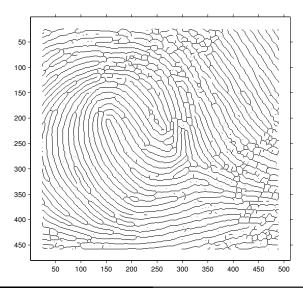
#### Minutiae as Points



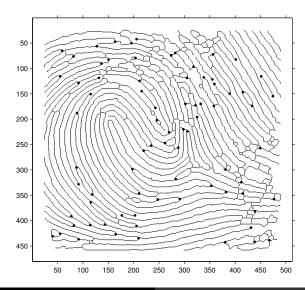
#### Minutiae as Points



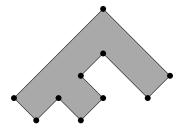
#### Minutiae as Points



#### Minutiae as Points

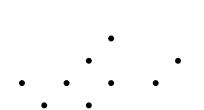


### Point Set Pattern Matching



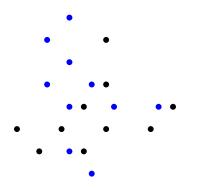
#### Object corners

#### Point Set Pattern Matching



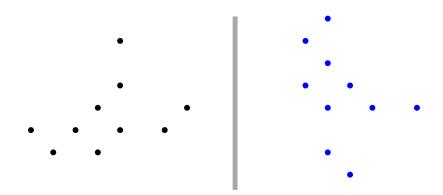
Point set

#### Point Set Pattern Matching



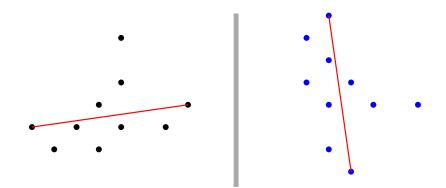
**Q**: Does the blue point set match the black one? What's the transformation?

#### Point Set Pattern Matching



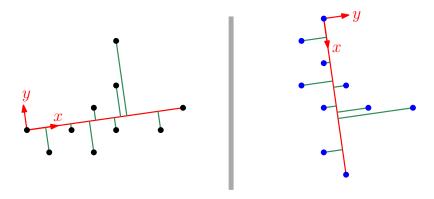
Treat them separately in proper local coordinate system.

#### Point Set Pattern Matching



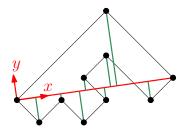
Consider the longest vectors (red lines).

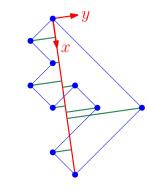
#### Point Set Pattern Matching



Define the local coordinate systems and compare the recomputed point coordinates.

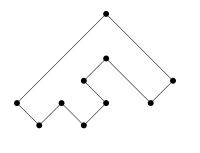
### Point Set Pattern Matching

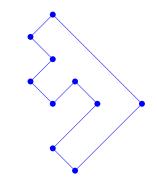




#### Report the match.

#### Point Set Pattern Matching





#### Redraw the objects if needed.

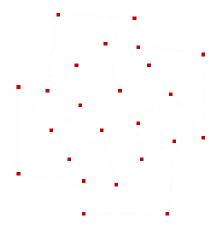
#### Pointillism



----Our algorithmic artwork (in progress)---

Ensemble

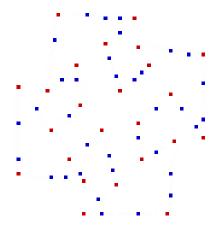
#### Unordered Point Set



#### Object corners — Too few to reconstruct

Ensemble

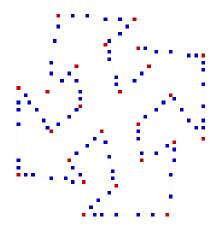
### Unordered Point Set



#### Sufficient?

Ensemble

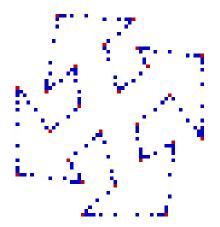
### Unordered Point Set



#### Sufficient???

Ensemble

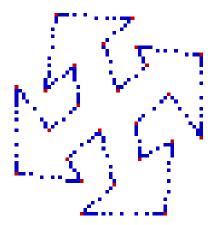
#### Unordered Point Set



#### Yes, sufficient! (Pointillist factor $\phi = 1$ )

Ensemble

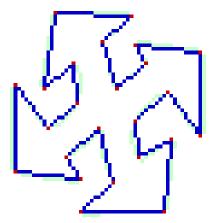
#### Unordered Point Set



#### More than sufficient (Pointillist factor $\phi = 2$ )

Ensemble

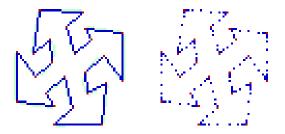
### Unordered Point Set



#### Reconstruction

# The idea

- Use the nearest neighbor (NN) rule.
- NN mimics our psycho-visual mechanism.
- Pick an optimal or suboptimal set of points so that reconstruction is possible.

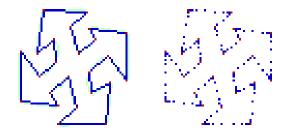


#### Ensemble

# Edge processing

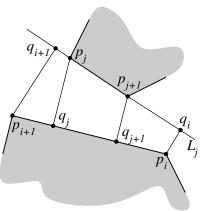
#### Procedure

Find the minimum distance between two edges  $e_i$ and  $e_j$  of (same or different) polygon(s).



# Edge processing

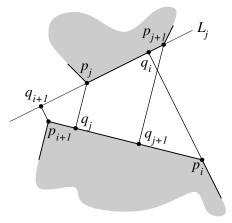
Case 1



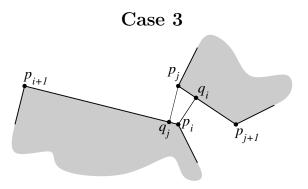
Ensemble

### Edge processing

Case 2



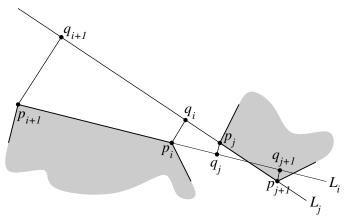
# Edge processing



Ensemble

### Edge processing

Case 4



### Reconstruction idea

Facts about **Delaunay triangulation** DT(S) of any point set S:

• Each pair of nearest neighbors in S are neighbors in DT(S).

• For the **Euclidean graph**<sup>1</sup> EG(S) of S, the **minimum spanning tree** MST(EG(S)) is a subgraph of DT(S).

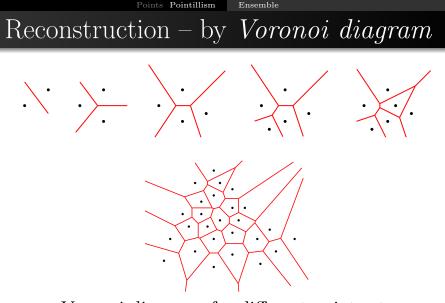
<sup>&</sup>lt;sup>1</sup>If S consists of m points, then the vertices of EG(S) are the points in S and the edges are all  $\binom{n}{2}$  undirected pairs of distinct points, the weight of each edge being given by the Euclidean distance between the corresponding points.

### Reconstruction idea

Facts about **Delaunay triangulation** DT(S) of any point set S:

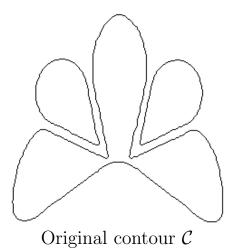
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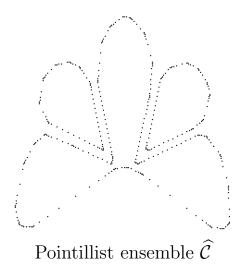


Voronoi diagrams for different point sets

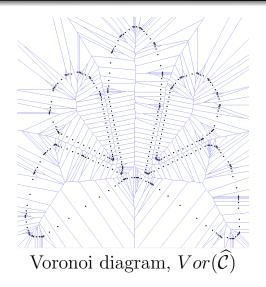






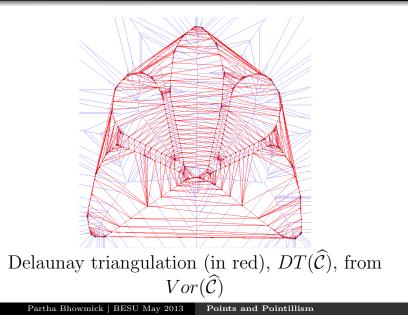


Reconstruction – by Voronoi diagram

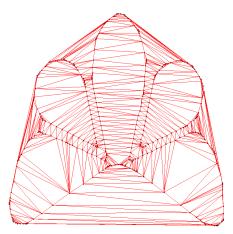


Ensemble

# Reconstruction – by Voronoi diagram

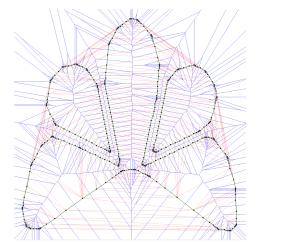




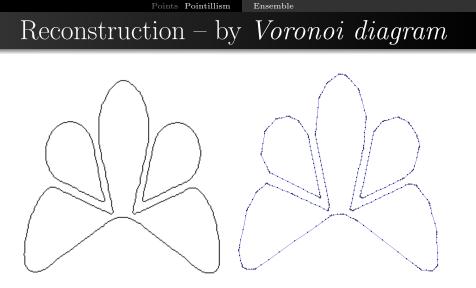


 $DT(\widehat{\mathcal{C}}) =$  subgraph of Euclidean graph  $EG(\widehat{\mathcal{C}})$ 

Reconstruction – by Voronoi diagram

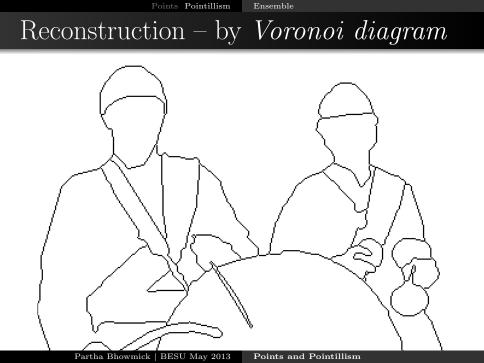


Reconstructed curve (in green) =  $MST(DT(\widehat{C}))$ 



#### Original

#### Reconstruction



Ensemble

### Reconstruction – by Voronoi diagram

