3D from Volume: Part III

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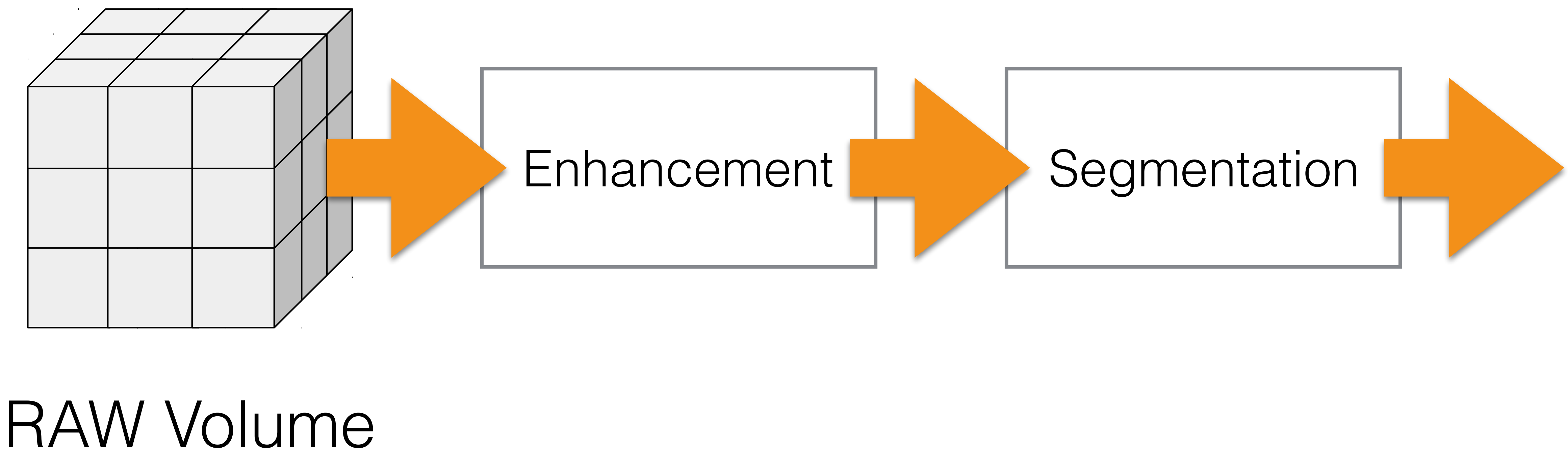
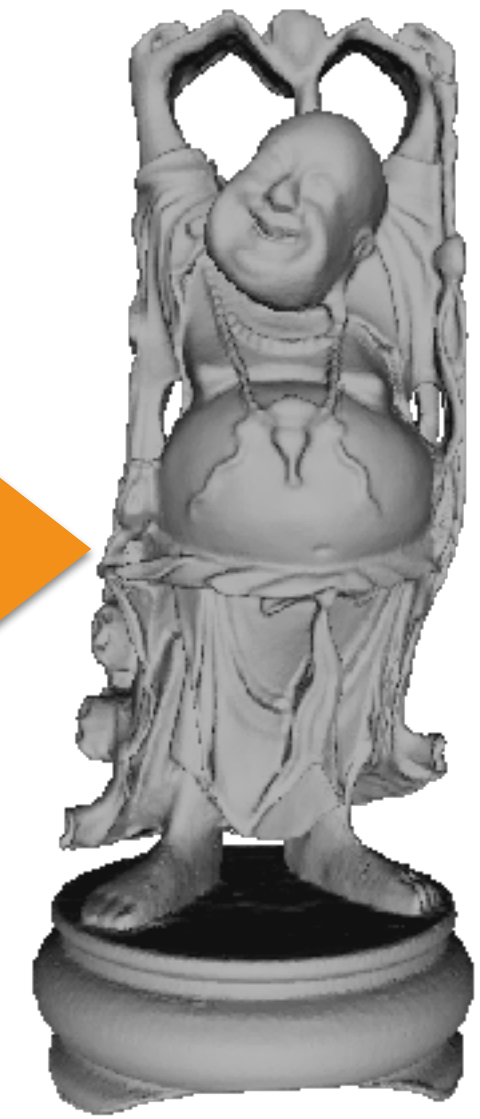
The Processing Pipeline



The Processing Pipeline

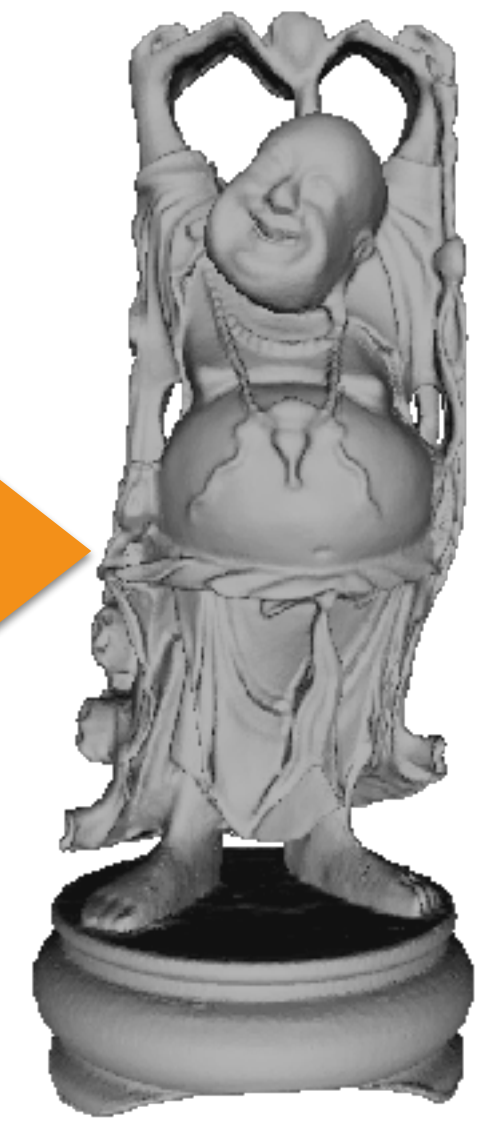
Points Extractions → Mesh Extraction →



3D Mesh

The Processing Pipeline

Points Extractions → Mesh Extraction →



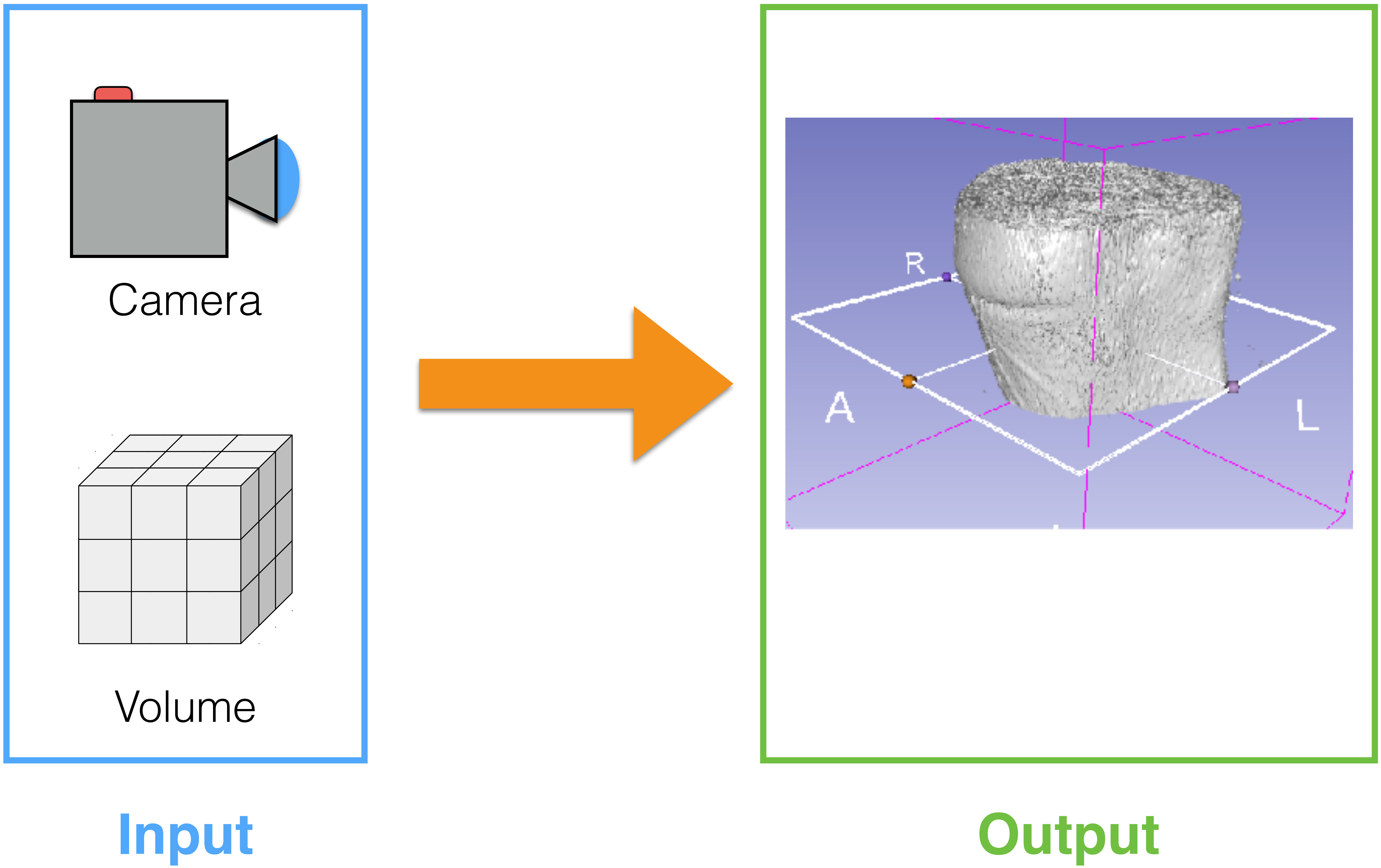
3D Mesh

3D Visualization

Volume Visualization

- We need to pre-visualize the 3D model that we are going to create. This process is called ***rendering***.
- Pre-visualization is:
  - fast: no need to create a 3D model
  - it helps the segmentation process

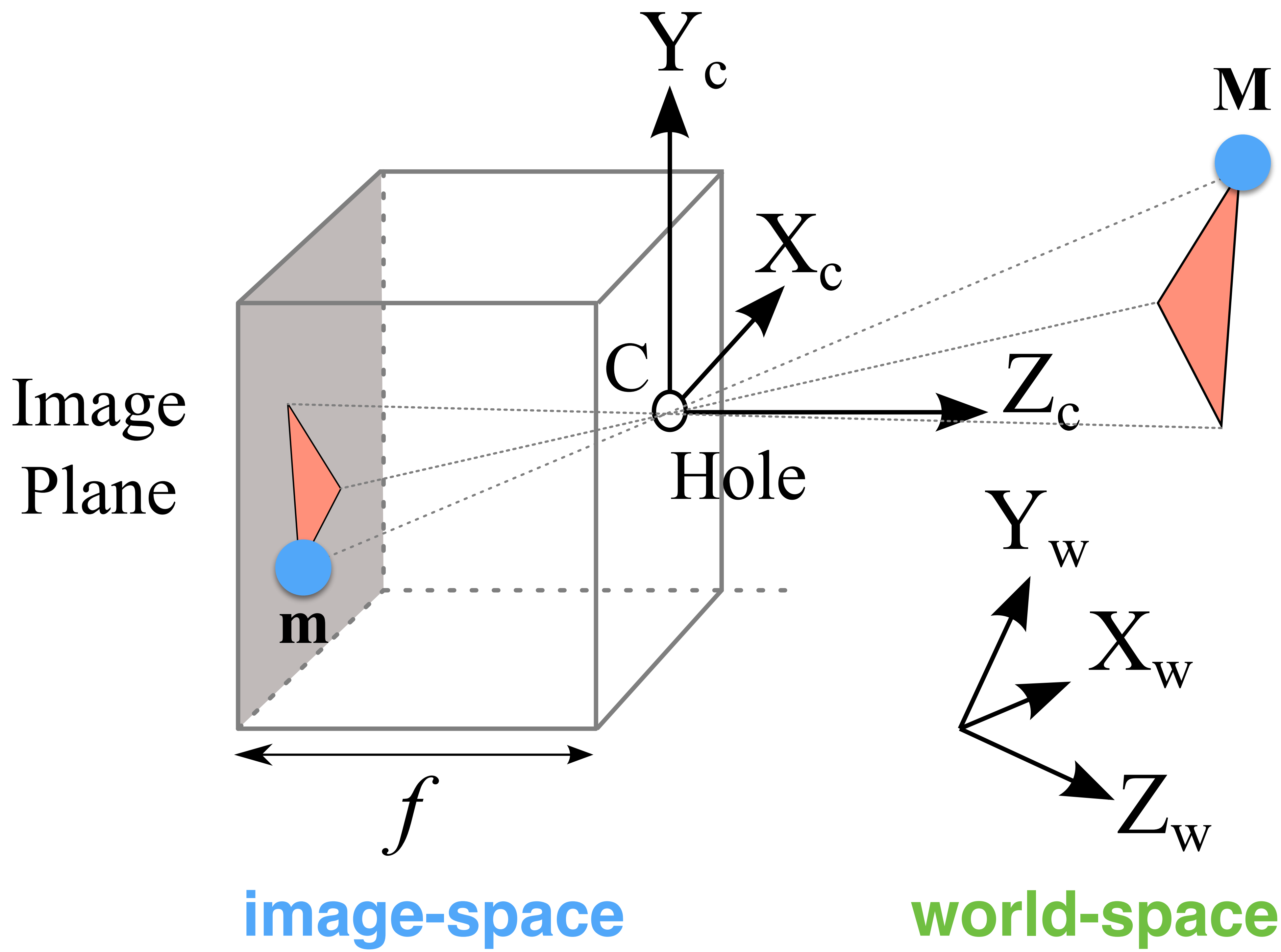
Volume Visualization



Volume Visualization

- Given a “virtual camera” and a 3D volume (e.g., from a CAT or MRI), we want to generate an image, i.e., called ***rendered image***.
- What do we need?
    - Define the “virtual camera” model
    - Define how to color pixels; i.e., rendering

Virtual Camera Model: Pinhole Camera

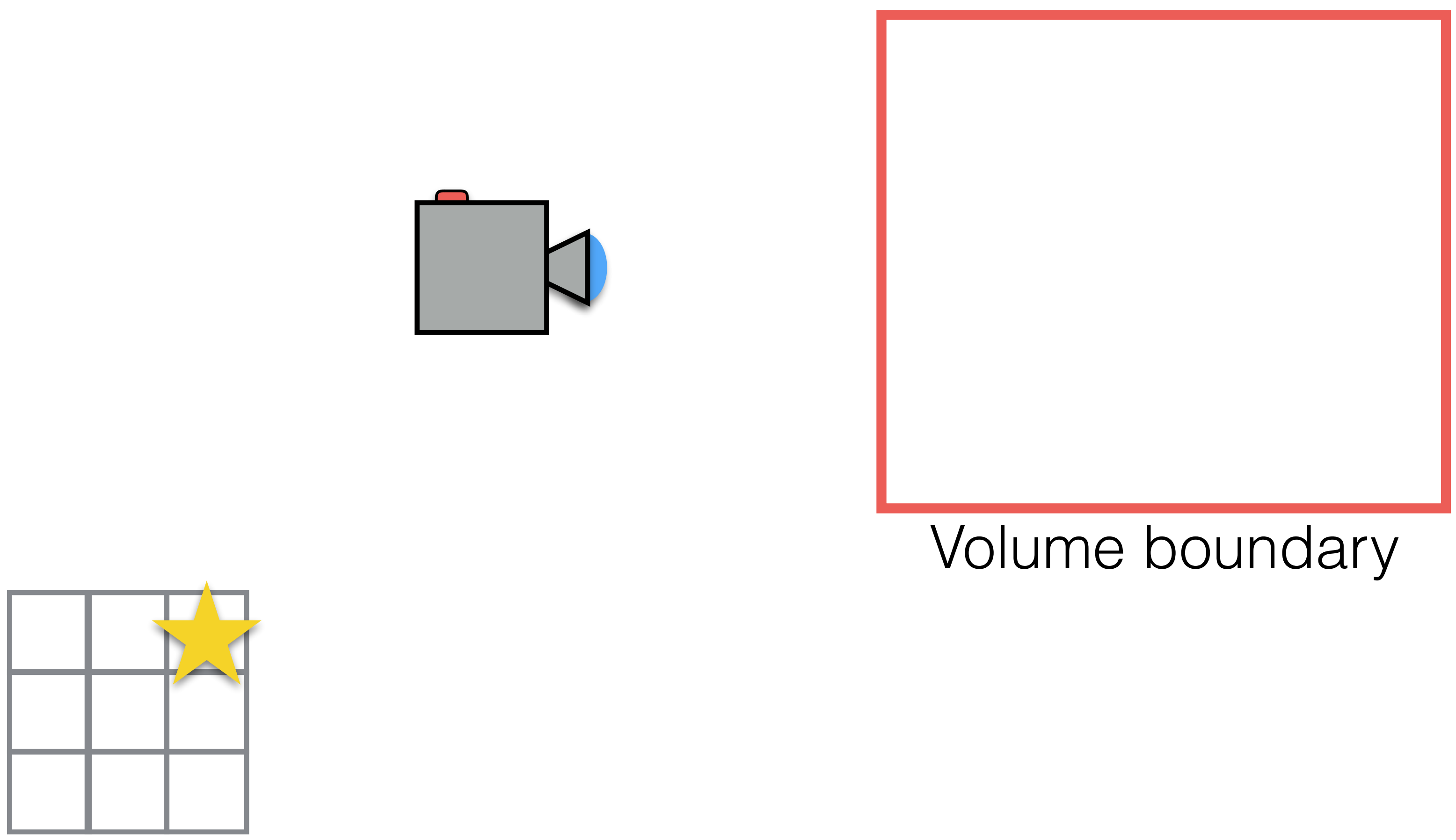


Rendering

- We need to color pixels (in the image plane) using the volume information; i.e., intensity values.
- For each pixel, we create a ray (i.e., a line):
  - If the ray intersects the volume, then we collect intensity values from it; i.e. we integrate it!
  - Otherwise the pixel will be set to zero or fully transparent!

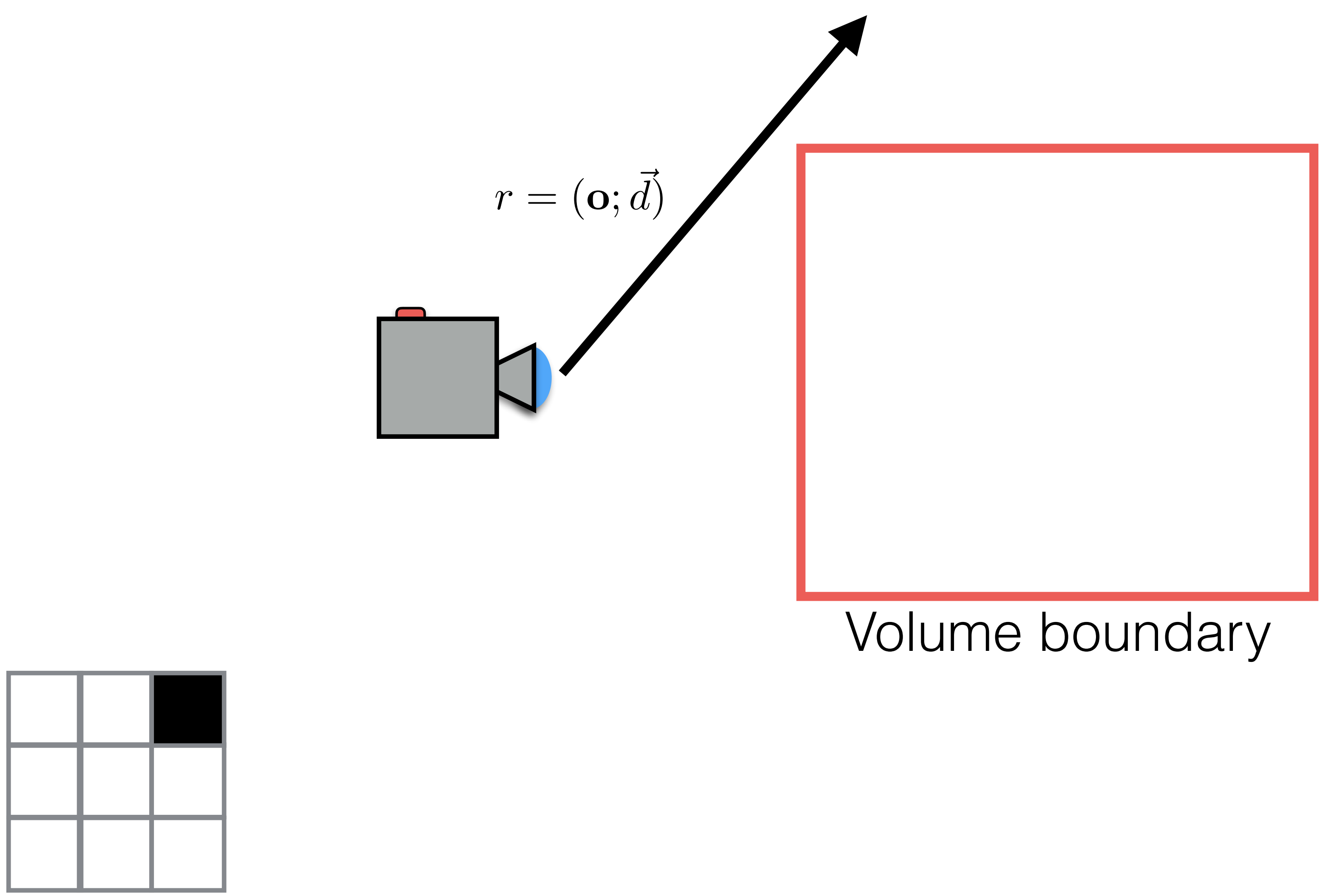
Volume Rendering: Ray-Marching

- Let's start our rendering at a given pixel (see the star):



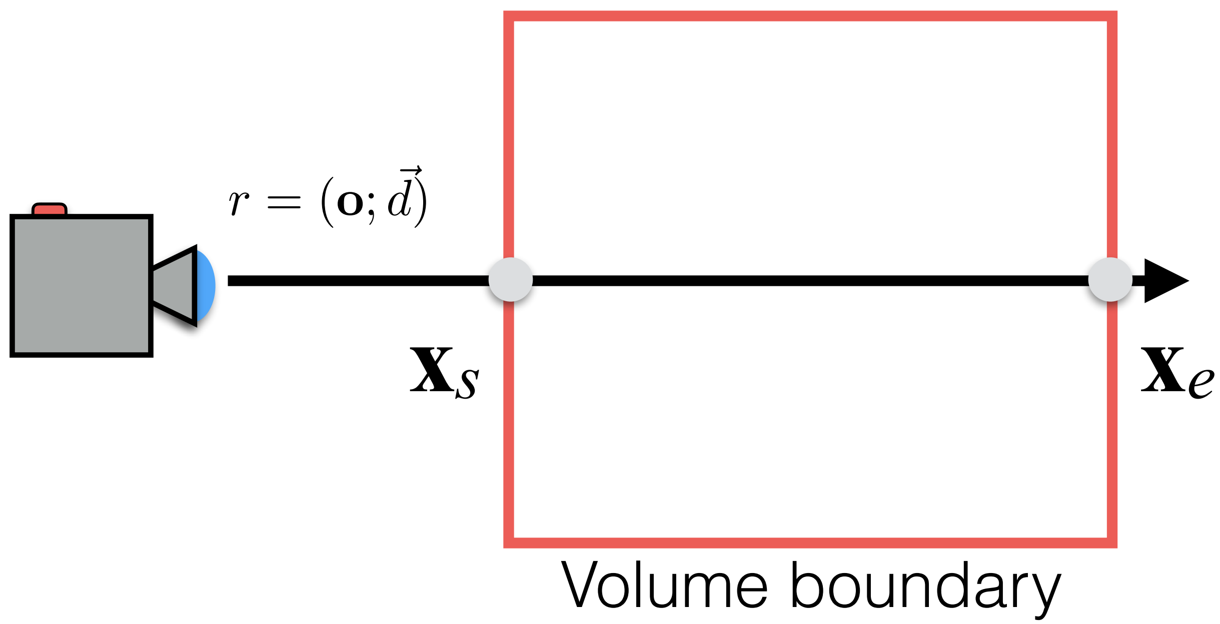
Volume Rendering: Ray-Marching

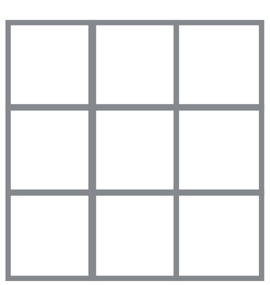
- If the ray misses the volume:



Volume Rendering: Ray-Marching

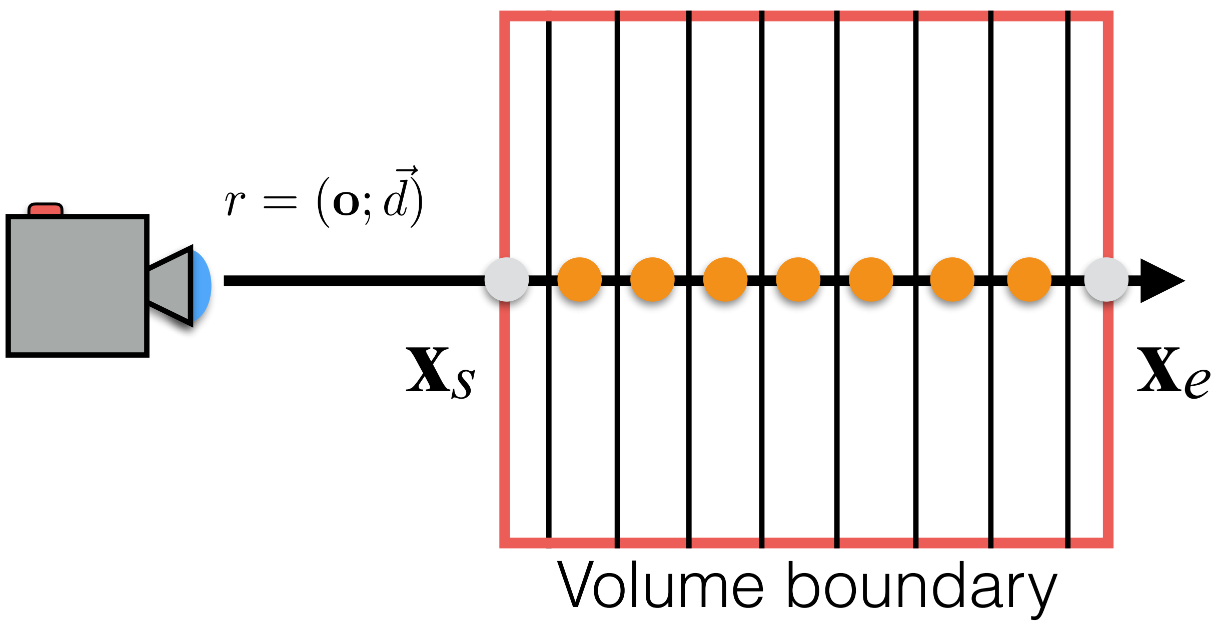
- If the ray hits the volume:

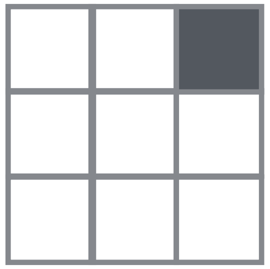




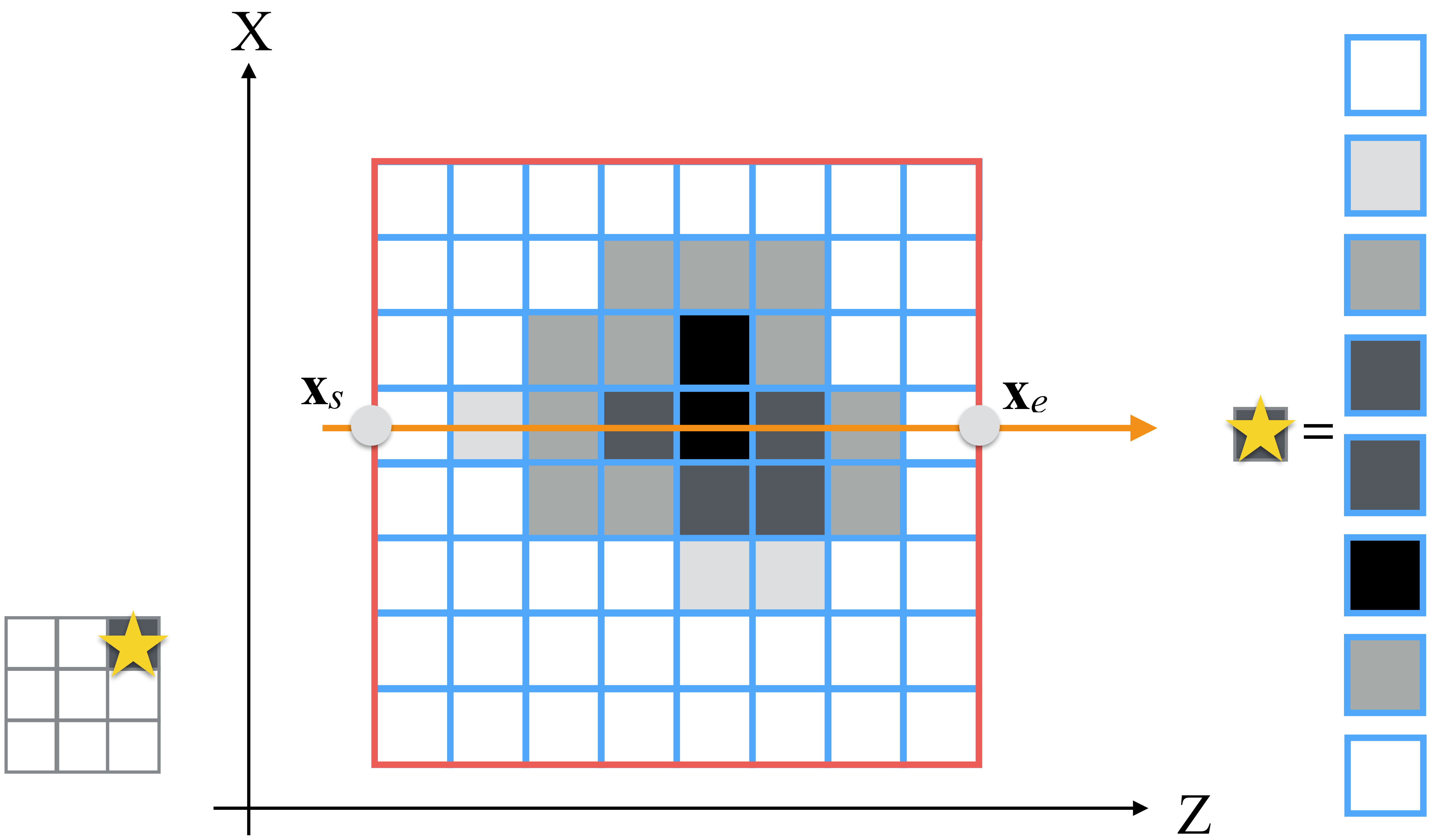
Volume Rendering: Ray-Marching

- Then, we integrate inside it with a step equal to the resolution of the volume:





Volume Rendering: Ray-Marching



Volume Rendering: Ray-Marching

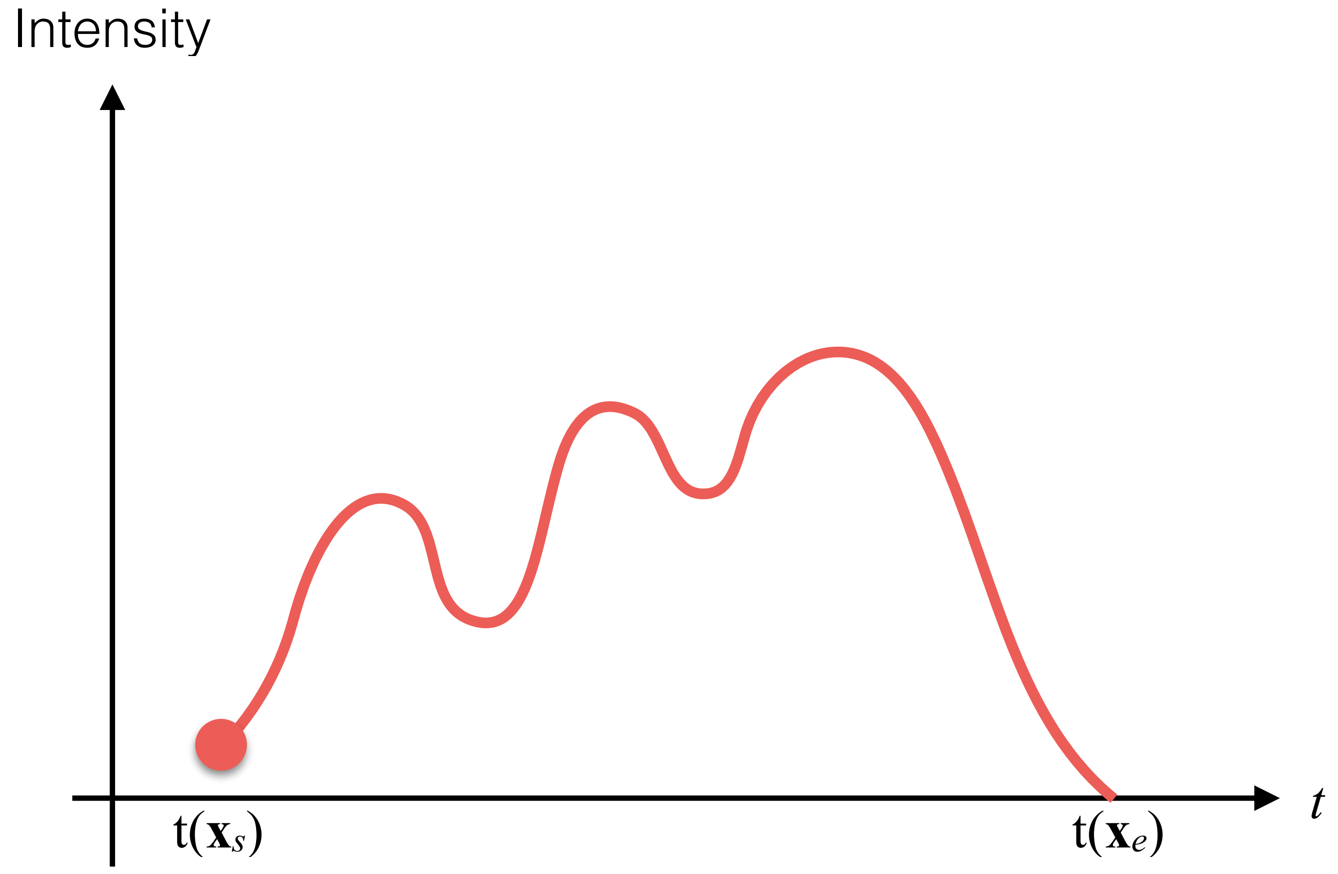
- In other words:

$$I[u,v] = \int_{t(\mathbf{x}_s)}^{t(\mathbf{x}_e)} T\Big(V\left[\mathbf{o} + \vec{d}[u,v]\cdot t\right]\Big)\,dt$$

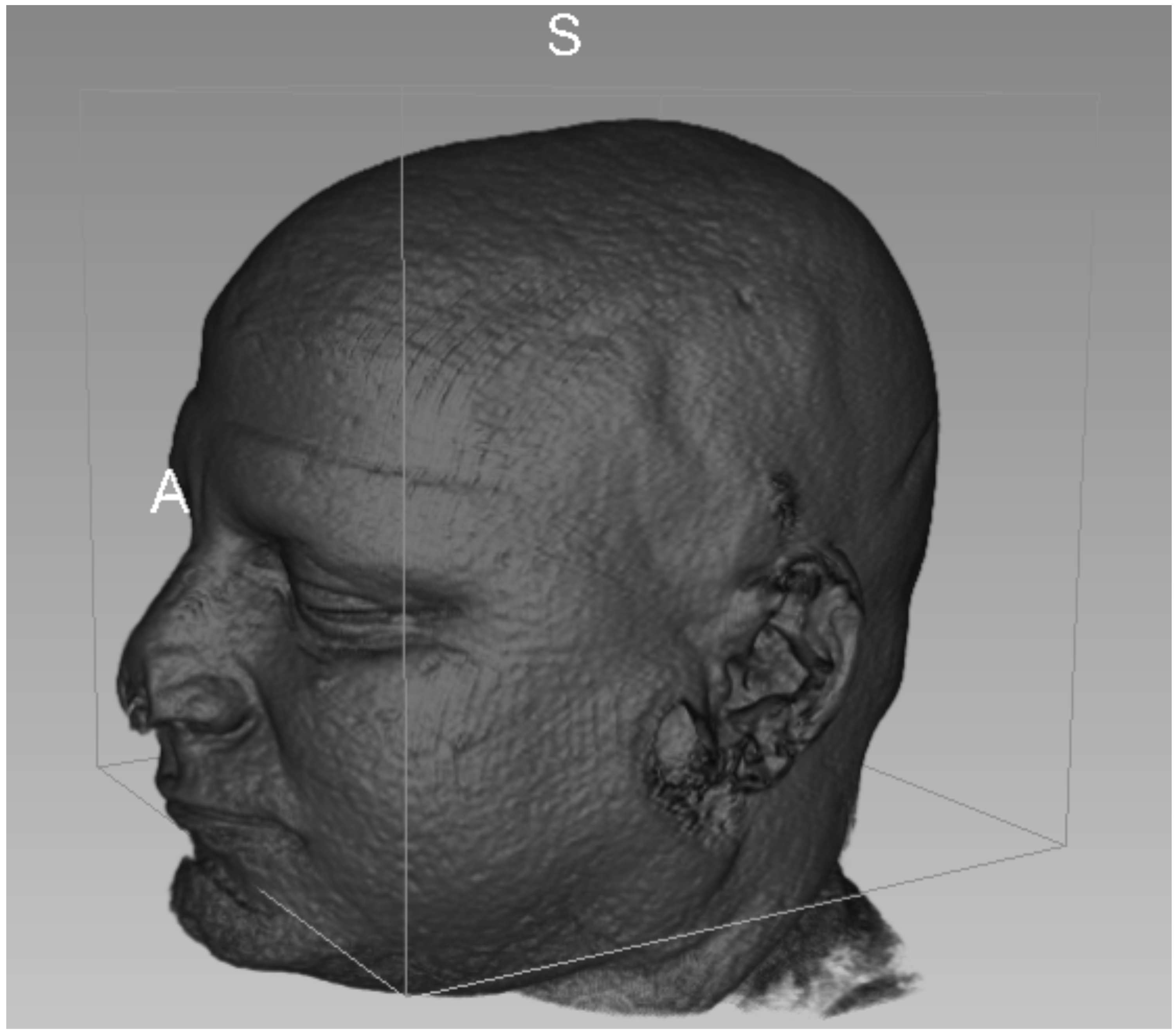
T is called the ***transfer function***
to highlights volume features.

Volume Rendering: Ray-Marching

- To determine the outside surface, we stop the integration at the first non zero value (over a threshold):

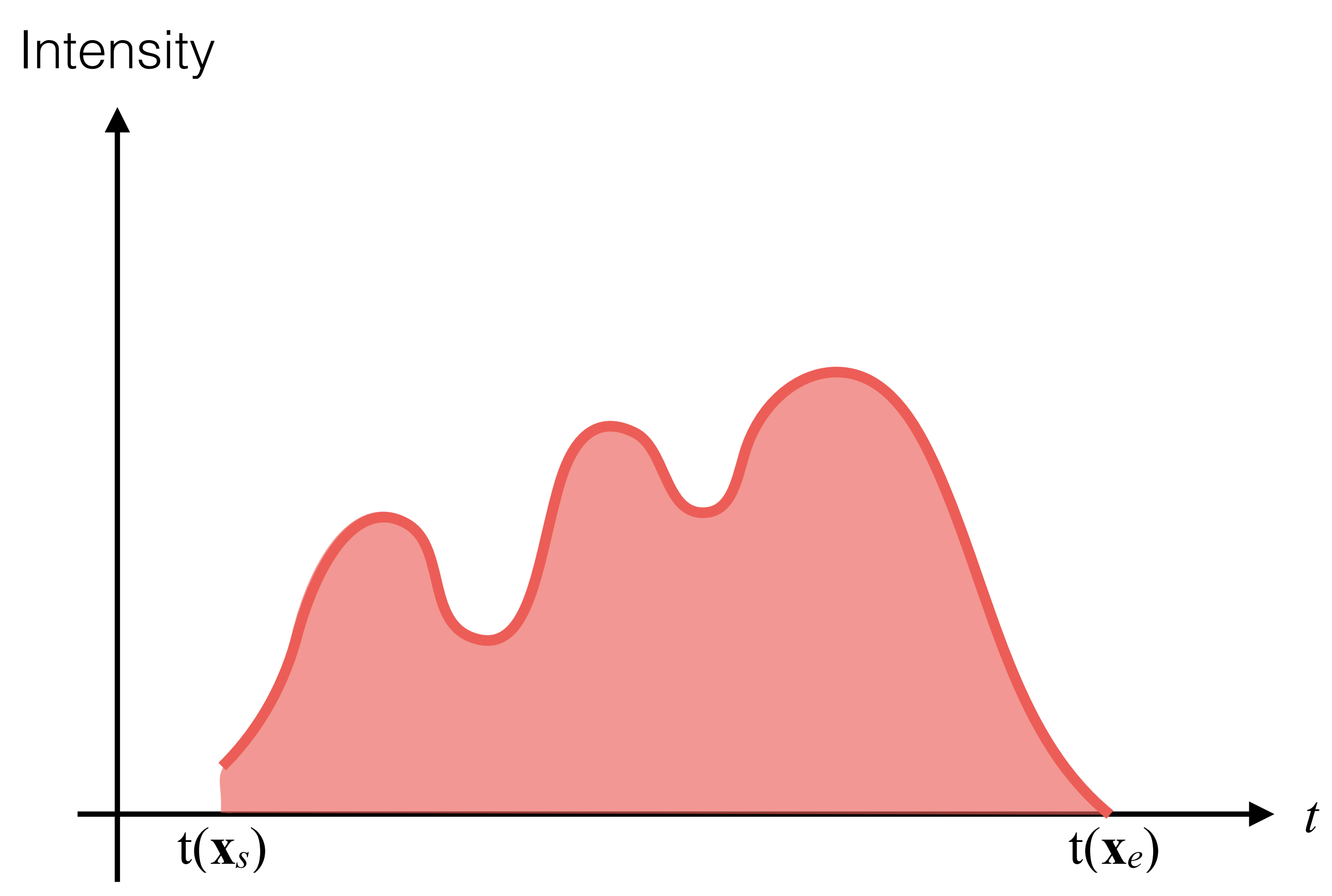


Volume Rendering: Ray-Marching Example

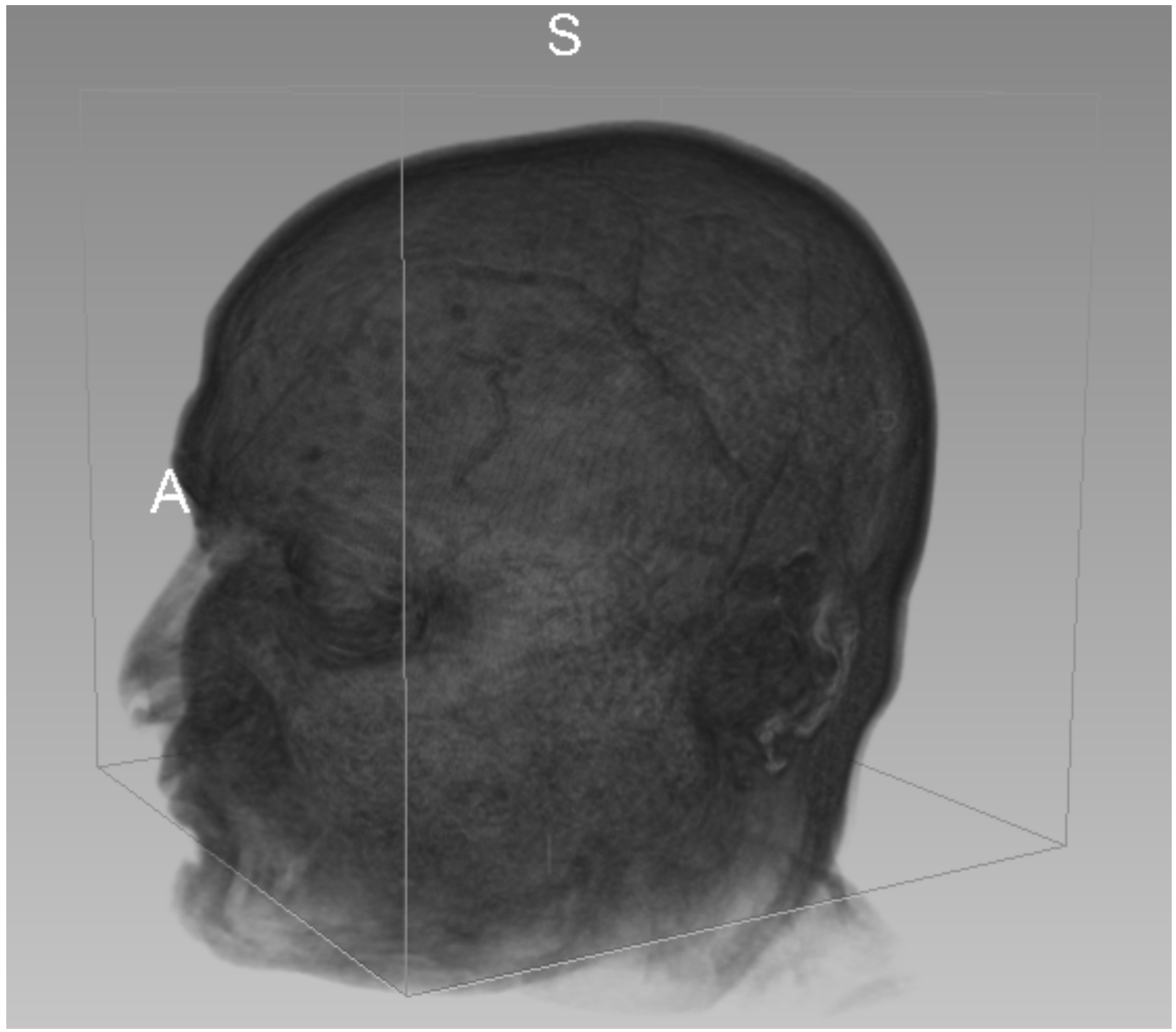


Volume Rendering: Ray-Marching

- To see all features inside the volume, we integrate along the ray:

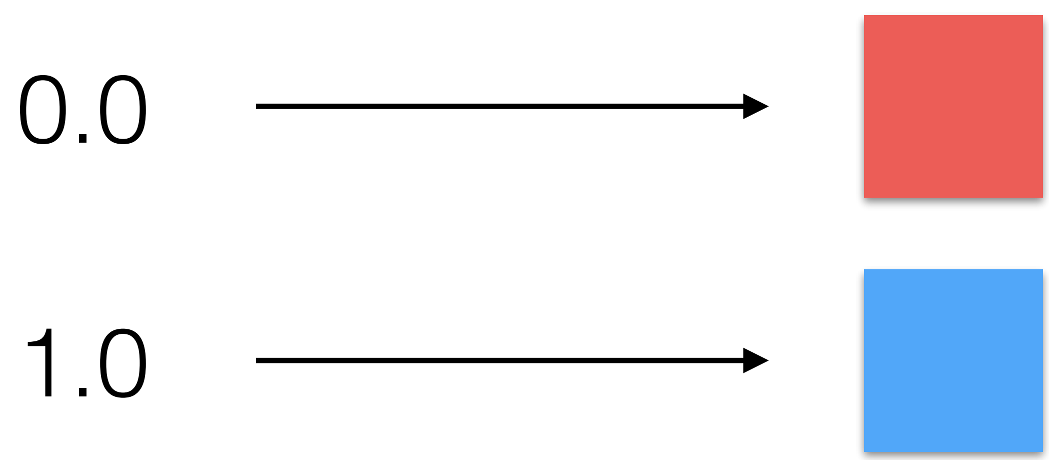


Volume Rendering: Ray-Marching Example



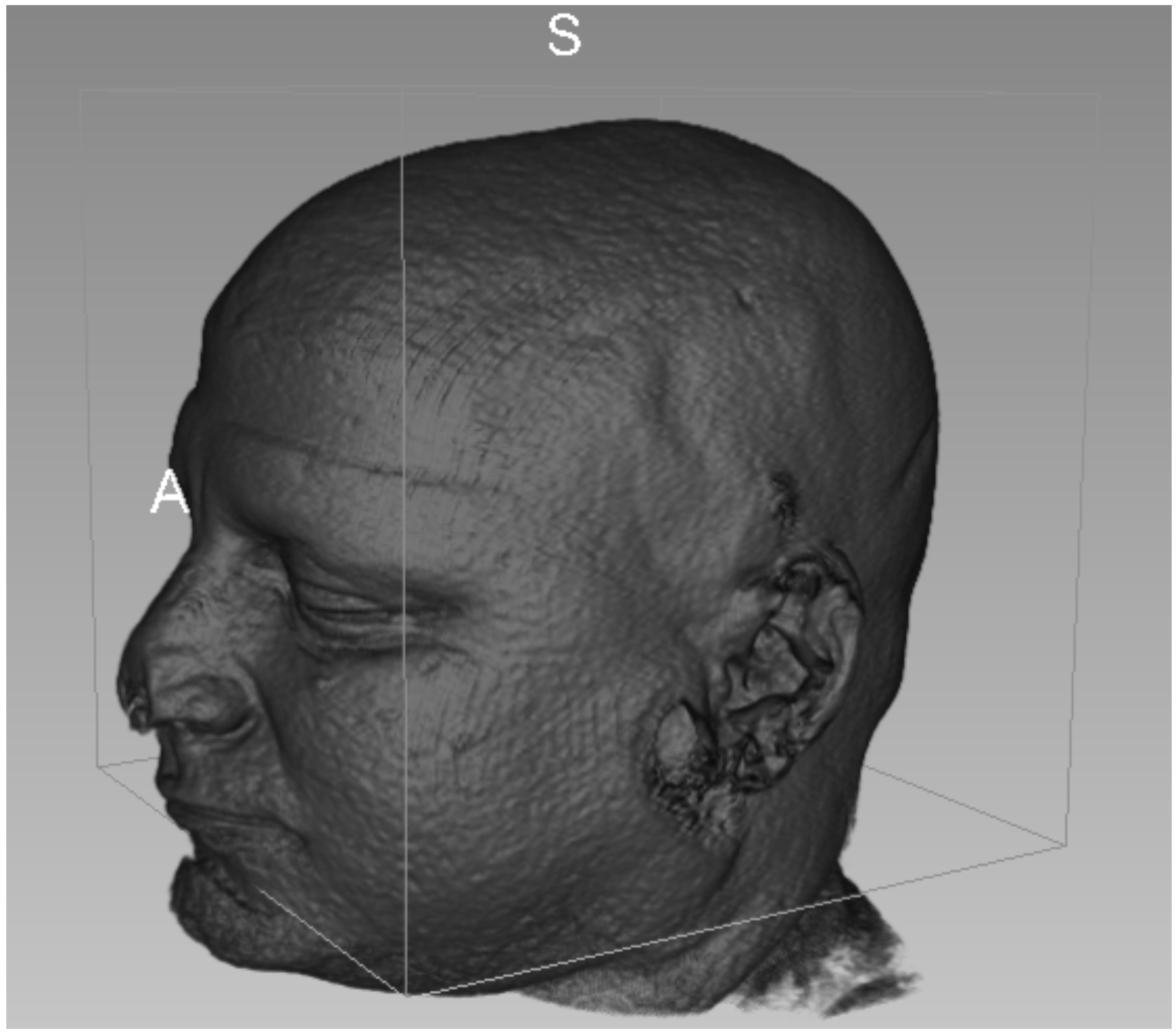
Volume Rendering: Color Mapping

- To improve visualization intensity values are mapped to colors:

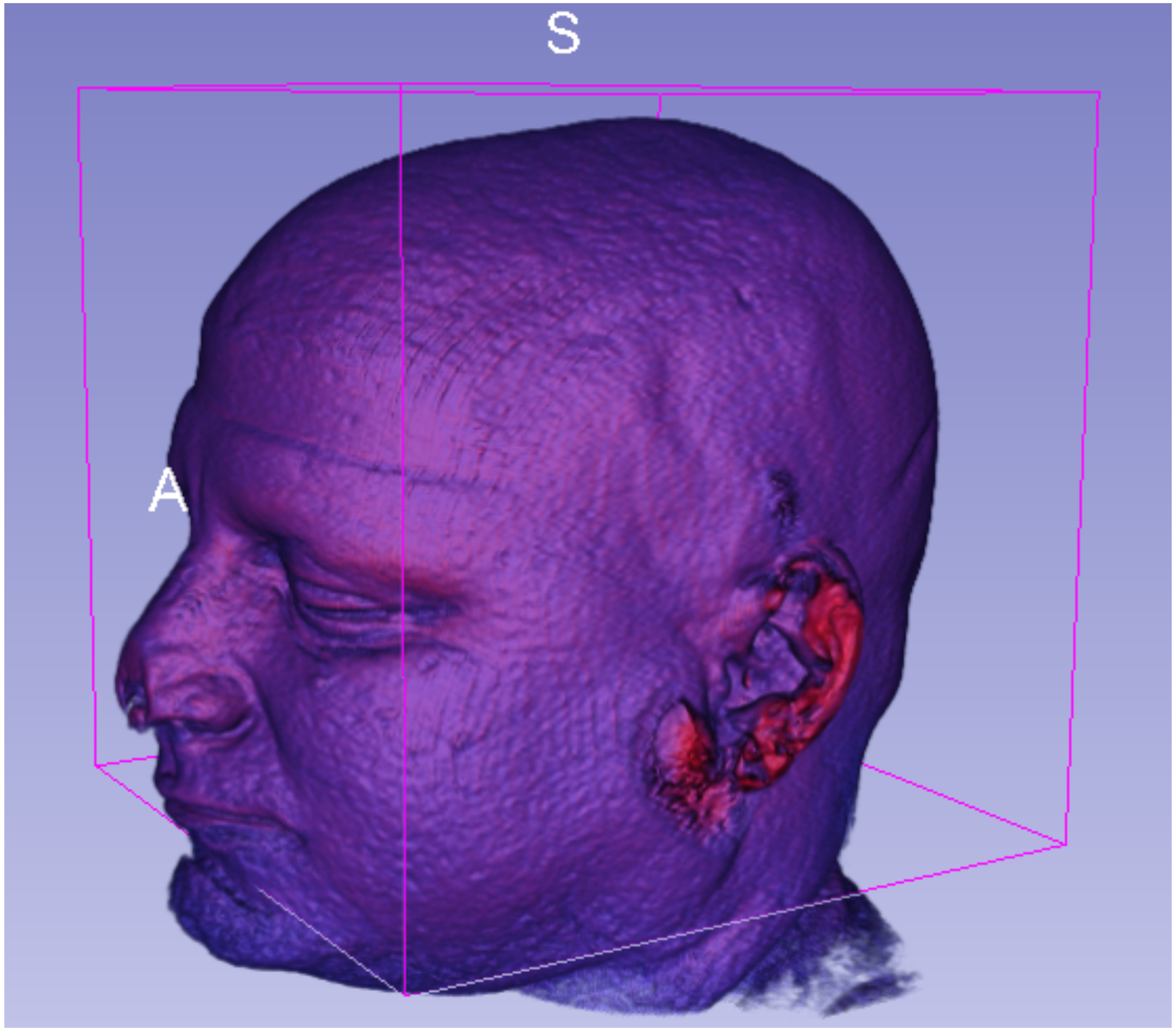


- In between values are linearly interpolated:

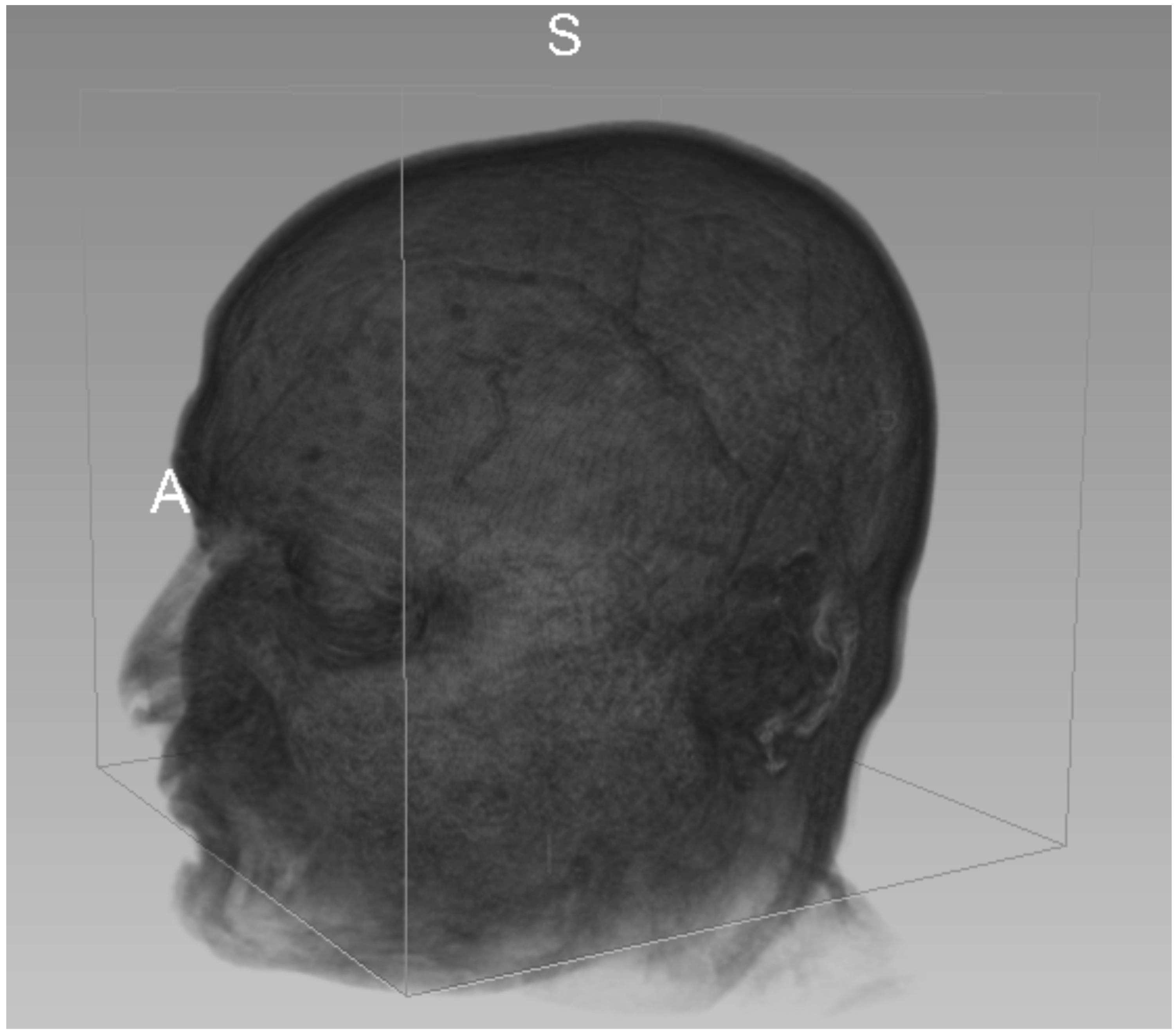
Volume Rendering: Color Mapping



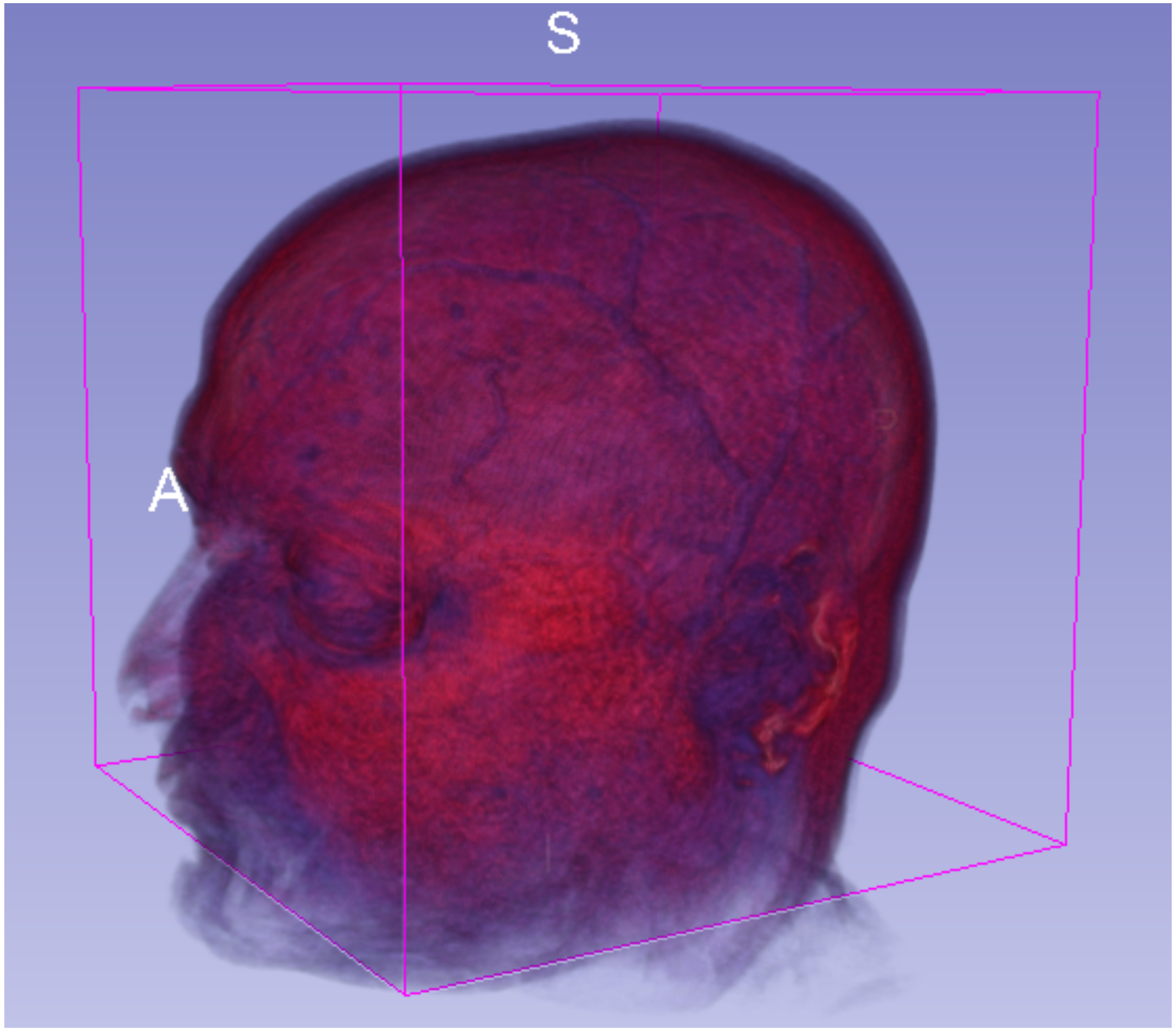
Volume Rendering: Color Mapping



Volume Rendering: Color Mapping



Volume Rendering: Color Mapping



Volume Rendering: Let there be light

- We can improve quality by adding light sources.
- There are local (taking into account that light bounces around) and global models.
- For the sake of simplicity, we are interested in local models only!

Volume Rendering: Let there be light

- A local model is a function computing radiance (L); i.e., the value for coloring the pixel using only local geometry information:

  - Point's position.

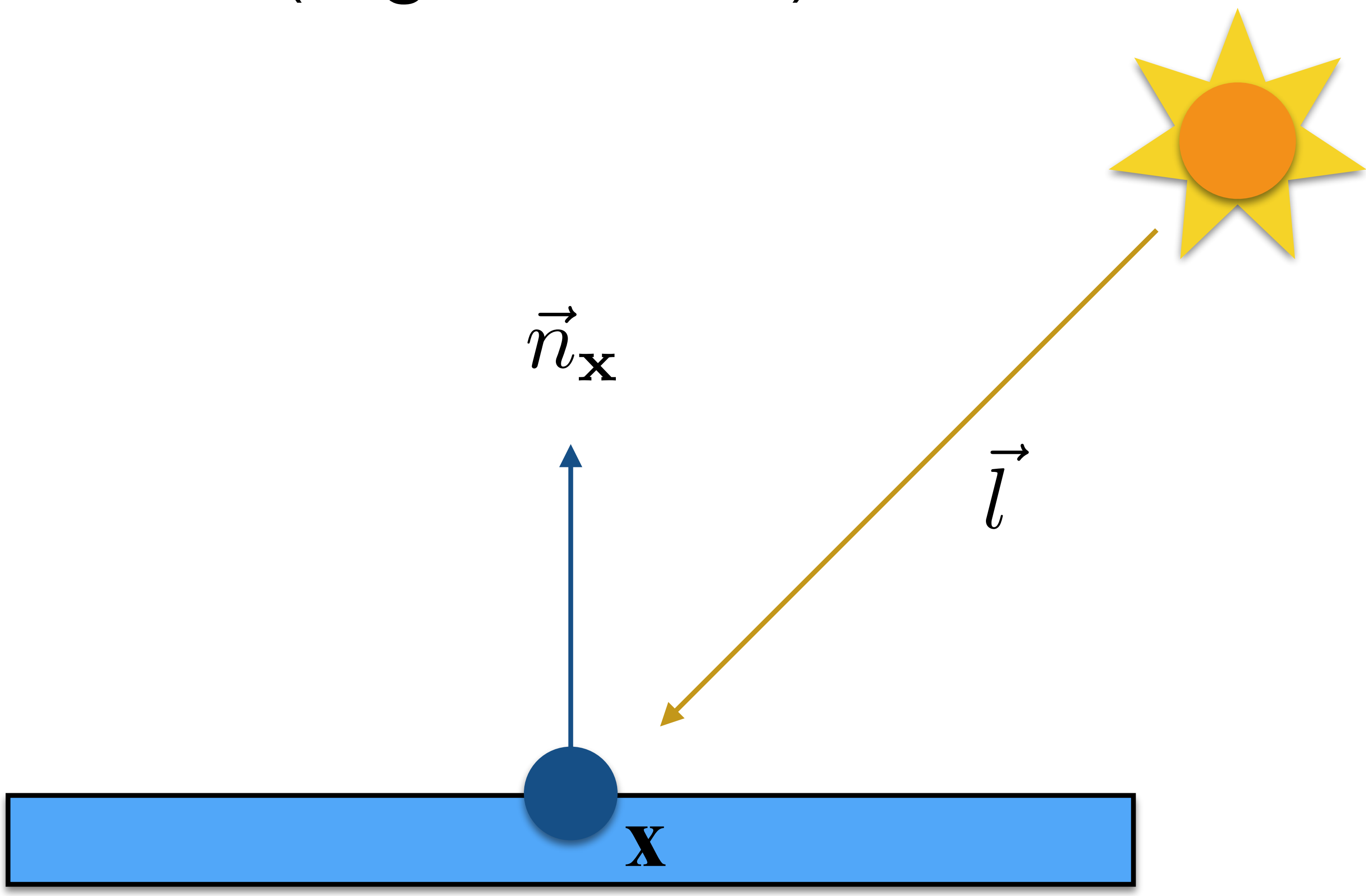
  - Point's normal.

  - Optical properties of the material at its position. The intensity value of the volume (or its color encoding) in our case.

  - Light source's position.

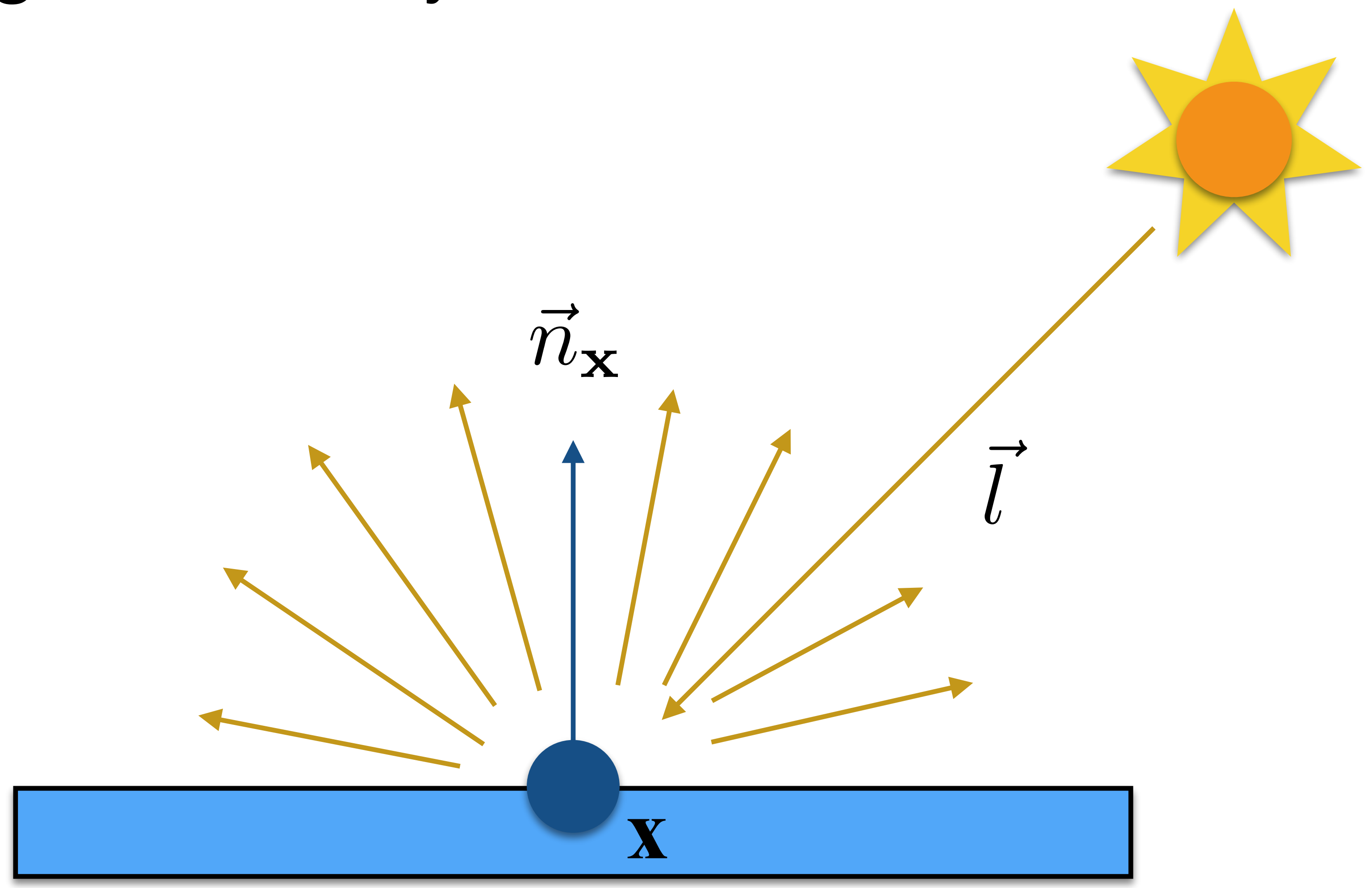
Volume Rendering: Let there be light

- A simple model assumes that the light source is placed at infinite (e.g., the sun):



Volume Rendering: Let there be light

- A simple local model is the diffuse model that assume light is locally reflected in all directions:



Volume Rendering: Let there be light

- The model is defined as

$$L(\mathbf{x}) = \frac{\lambda}{\pi} \cdot \max(-\vec{n}_{\mathbf{x}} \cdot \vec{l}, 0)$$

- Note that:
  - $\vec{n}_{\mathbf{x}}$ needs to be normalized.
  - $\vec{l}$ needs to be normalized.

Volume Rendering: Let there be light

- The model is defined as

Radiance

$$\boxed{L(\mathbf{x})} = \frac{\lambda}{\pi} \cdot \max(-\vec{n}_{\mathbf{x}} \cdot \vec{l}, 0)$$

- Note that:
  - $\vec{n}_{\mathbf{x}}$ needs to be normalized.
  - $\vec{l}$ needs to be normalized.

Volume Rendering: Let there be light

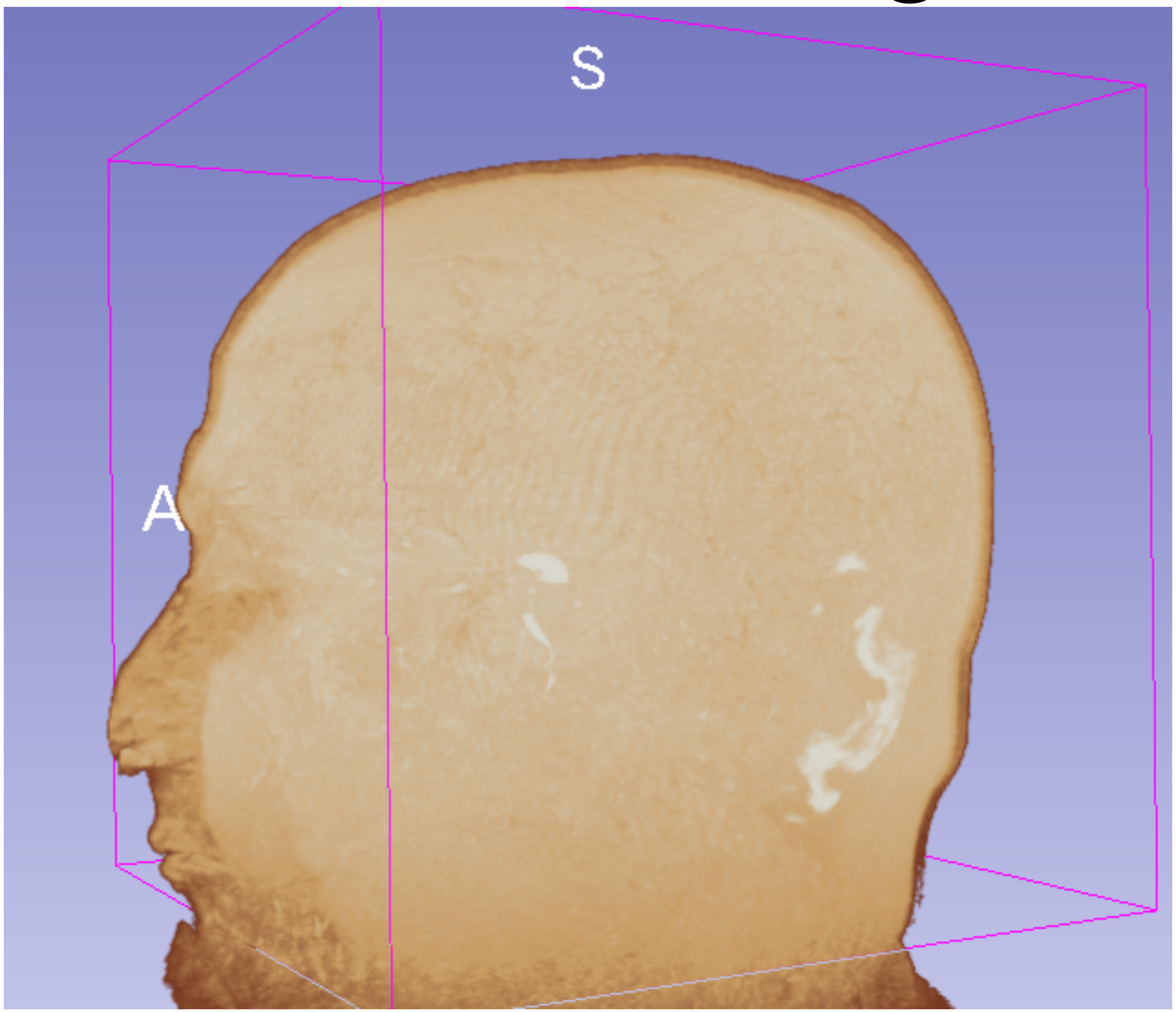
- The model is defined as

Radiance Albedo/Intensity

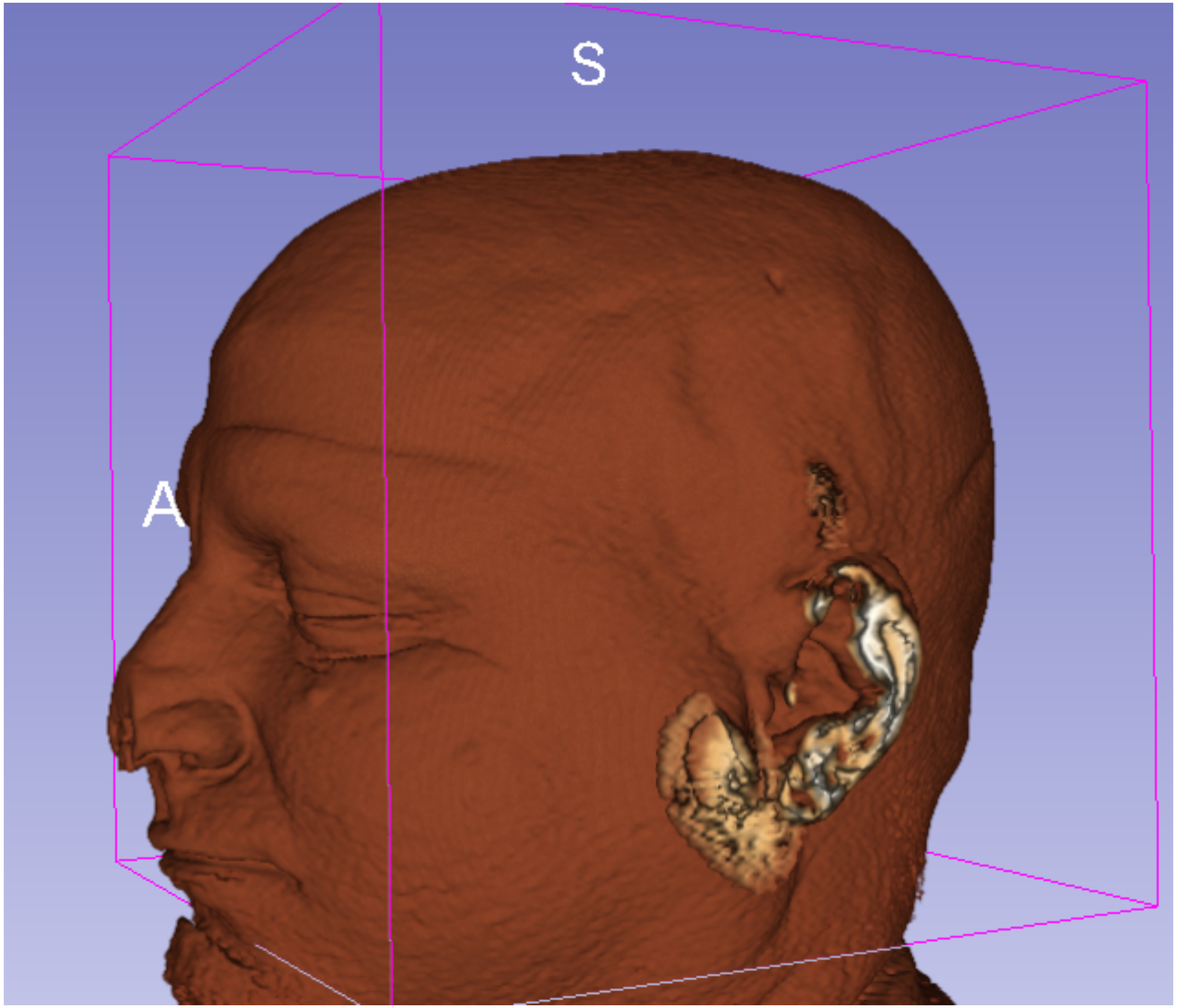
$$L(\mathbf{x}) = \frac{\lambda}{\pi} \cdot \max(-\vec{n}_{\mathbf{x}} \cdot \vec{l}, 0)$$

- Note that:
  - $\vec{n}_{\mathbf{x}}$ needs to be normalized.
  - $\vec{l}$ needs to be normalized.

Volume Rendering: Let there be light



Volume Rendering: Let there be light



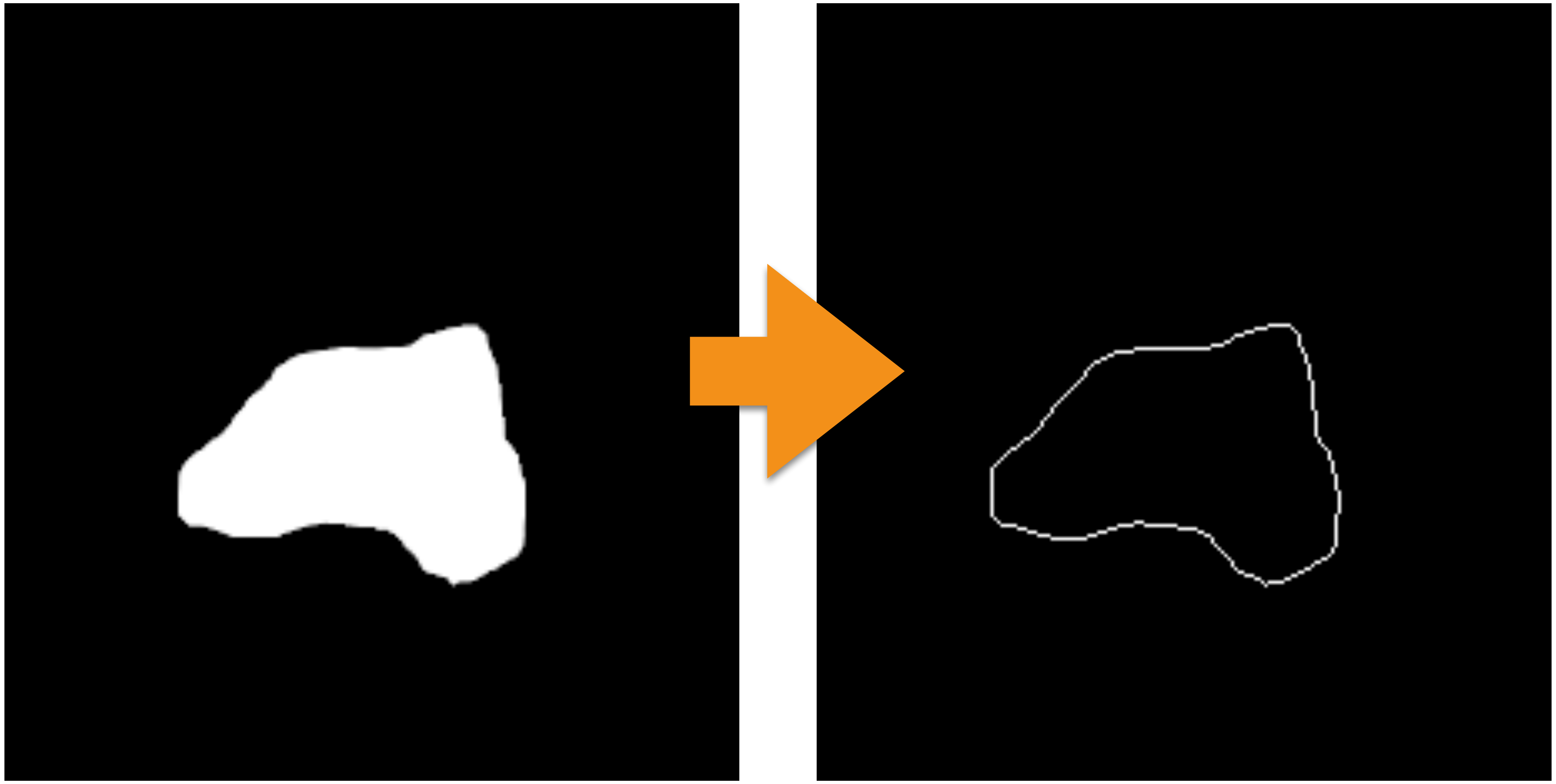
Volume Rendering

- It is a very simple and easy to implement method.
- It is computationally expensive.
  - It works in real-time using a GPU!

3D Points Extraction

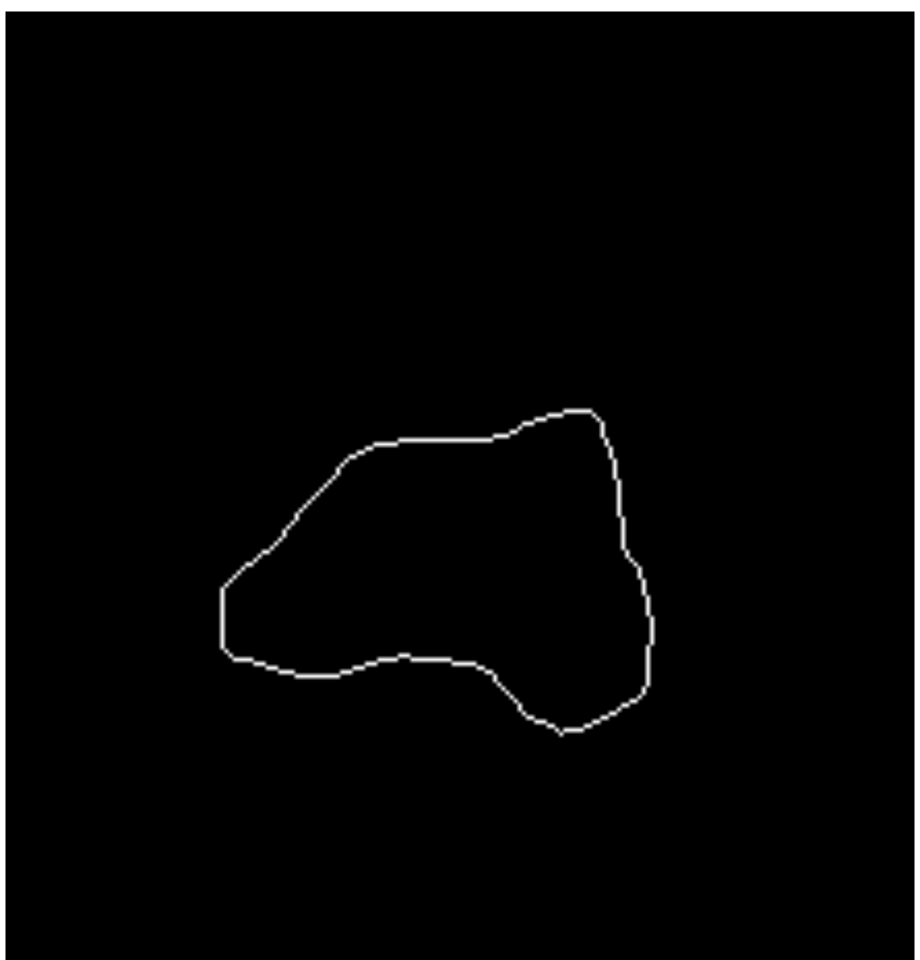
3D Points Extraction

- For each slice of the volume, we compute the edges of the segmented region:



3D Points Extraction

- For each white pixel in the edge with coordinates (u, v) at the i-th slice, we compute its 3D position as



$$m = \begin{bmatrix} x \\ y \\ z \end{bmatrix} = \begin{bmatrix} u \cdot k_u \\ v \cdot k_v \\ i \cdot k_w \end{bmatrix}$$

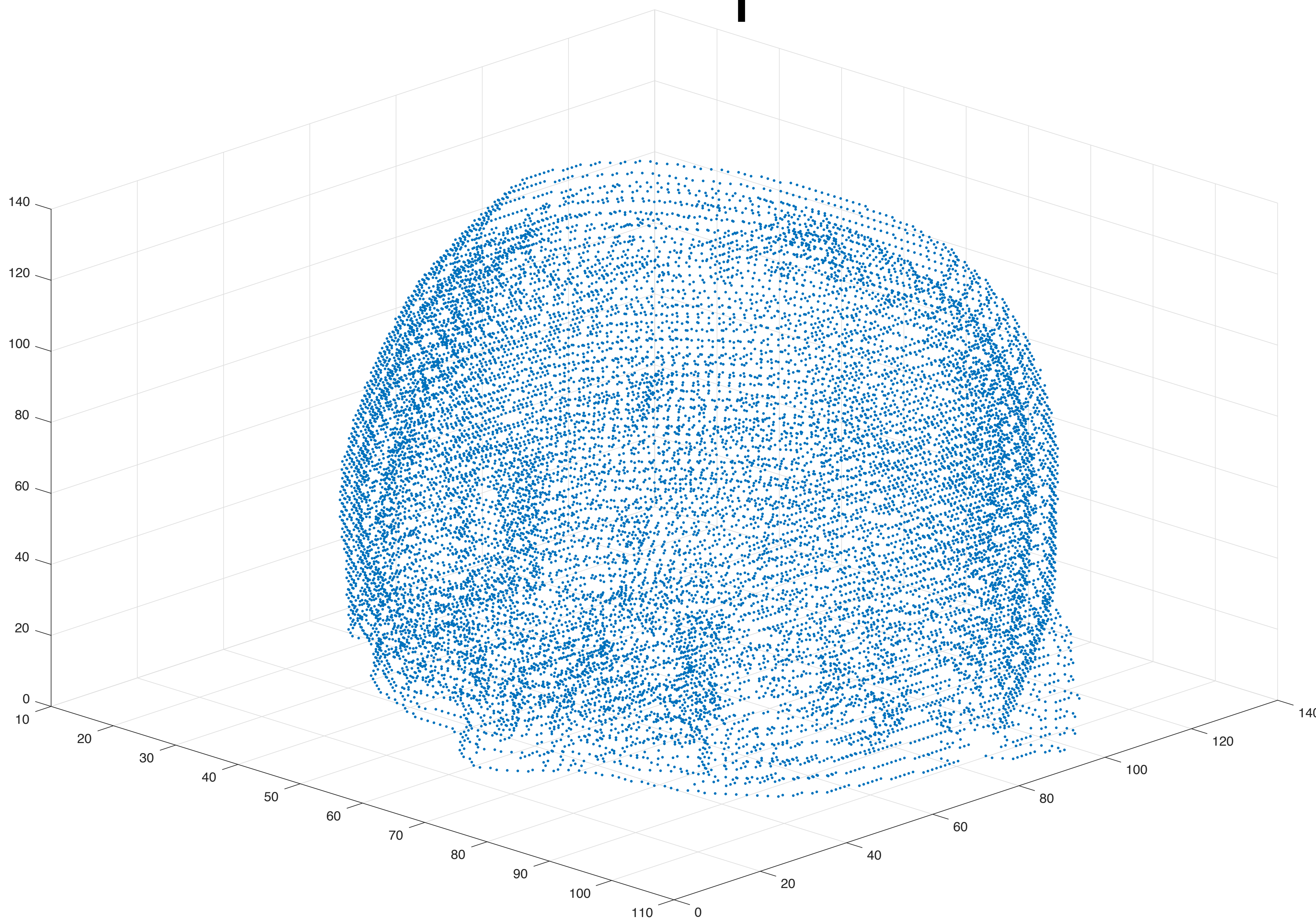
k_u is the pixel's width in mm
k_v is the pixel's height in mm
k_w is the distance between slices in mm

3D Points Extraction

- How do we compute the normal at the point?
- It is simply the negative value of the gradient of the volume in that point:

$$\vec{n} = -\frac{\vec{\nabla} V}{\|\vec{\nabla} V\|}$$

3D Points Extraction Example



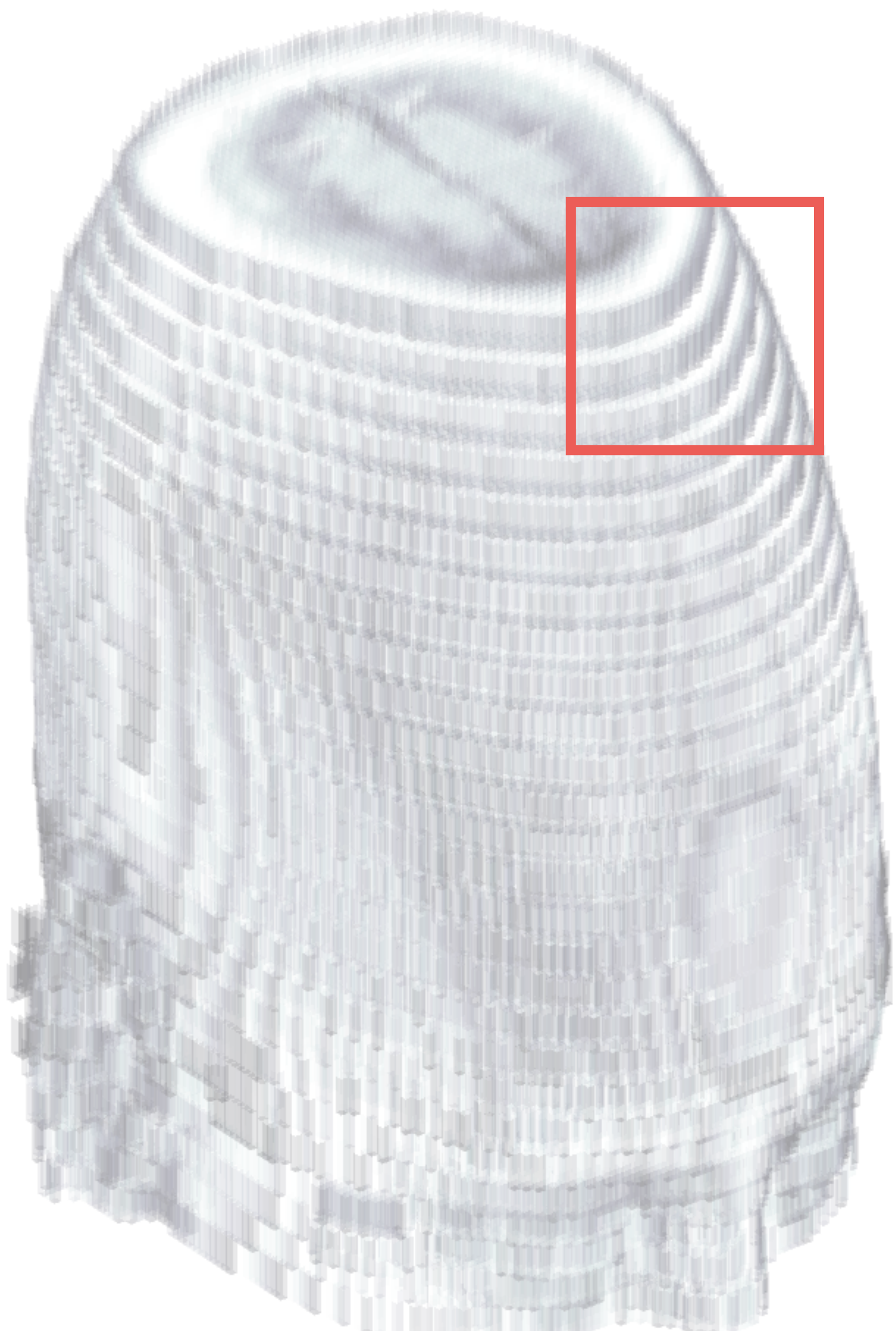
3D Mesh Extraction

A Very Stupid Algorithm:

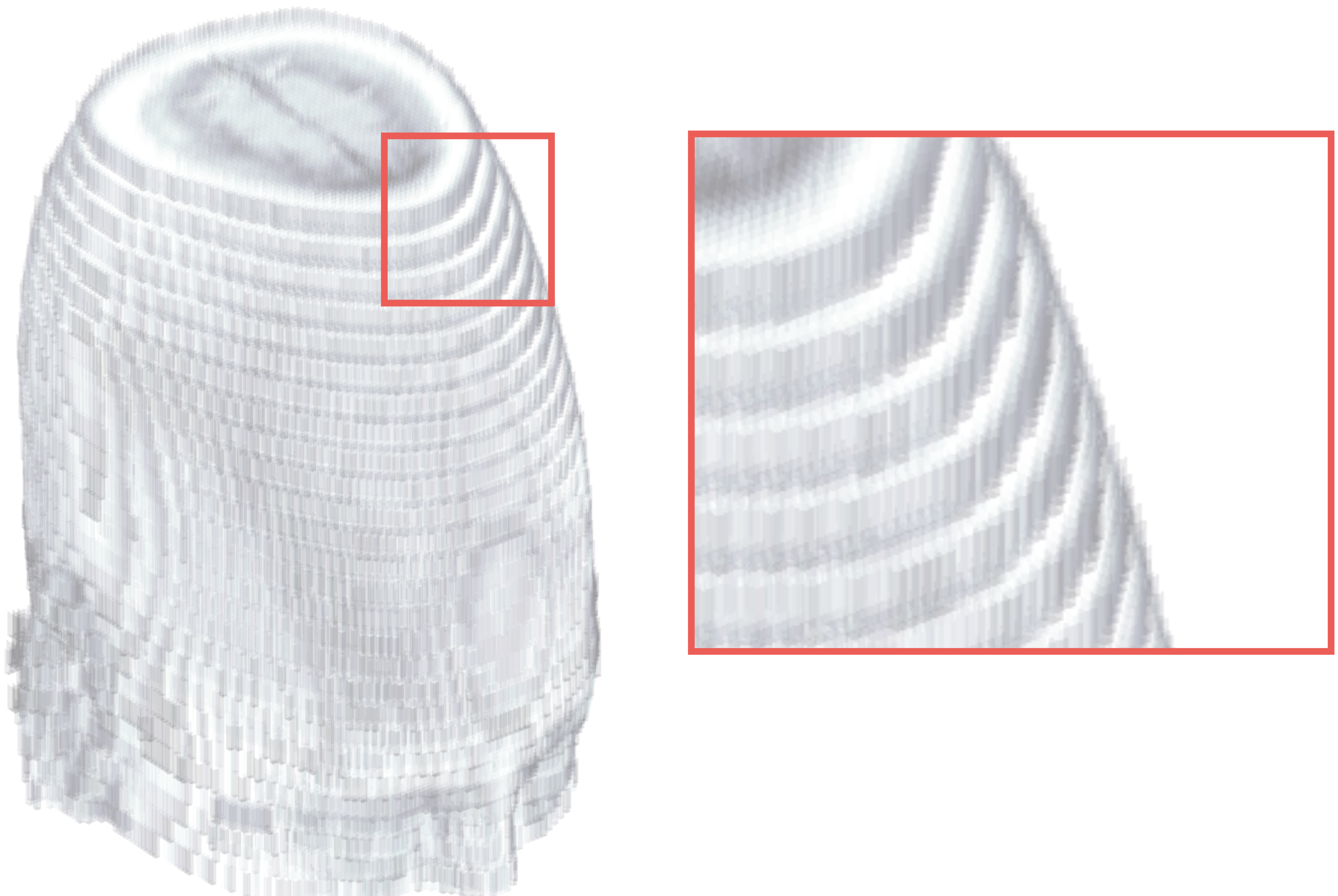
For each extracted point, create a cube…

A Very Stupid Algorithm Example

A Very Stupid Algorithm Example



A Very Stupid Algorithm Example



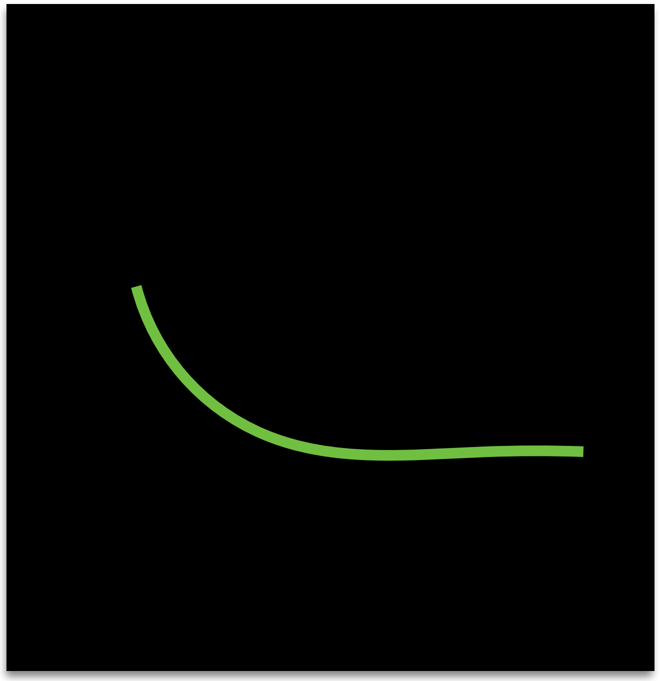
I guess, we can do better than this!

Connecting the dots…

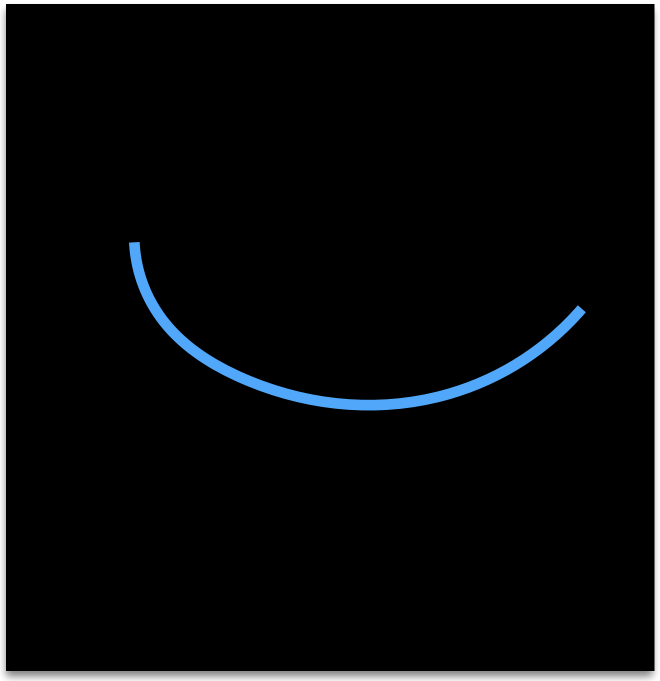
Edges Triangulation

- As the first step, we extract the edges from each slice in the volume.
- We save the connectivity of points belonging to the same edge —> “parametric curve”
    - We may have more curves per slice!

Edges Triangulation

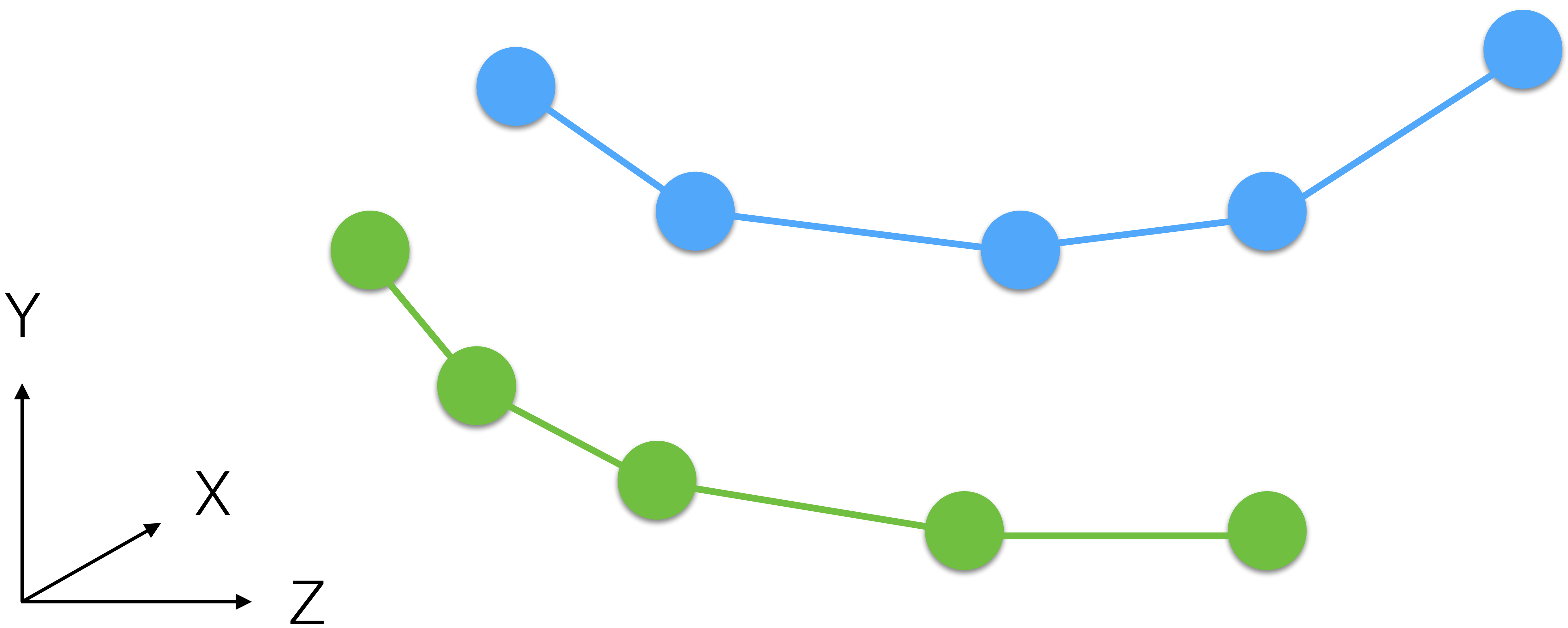


Slice 1

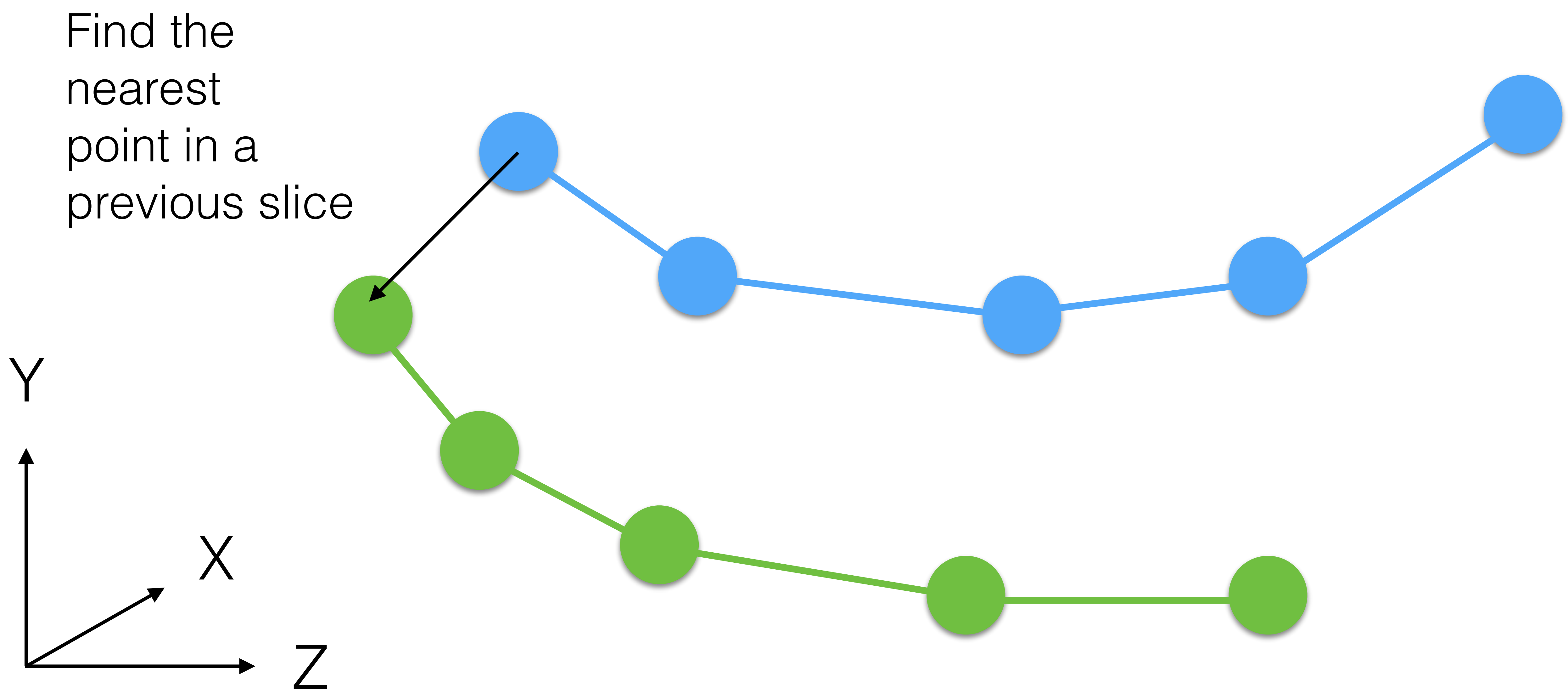


Slice 2

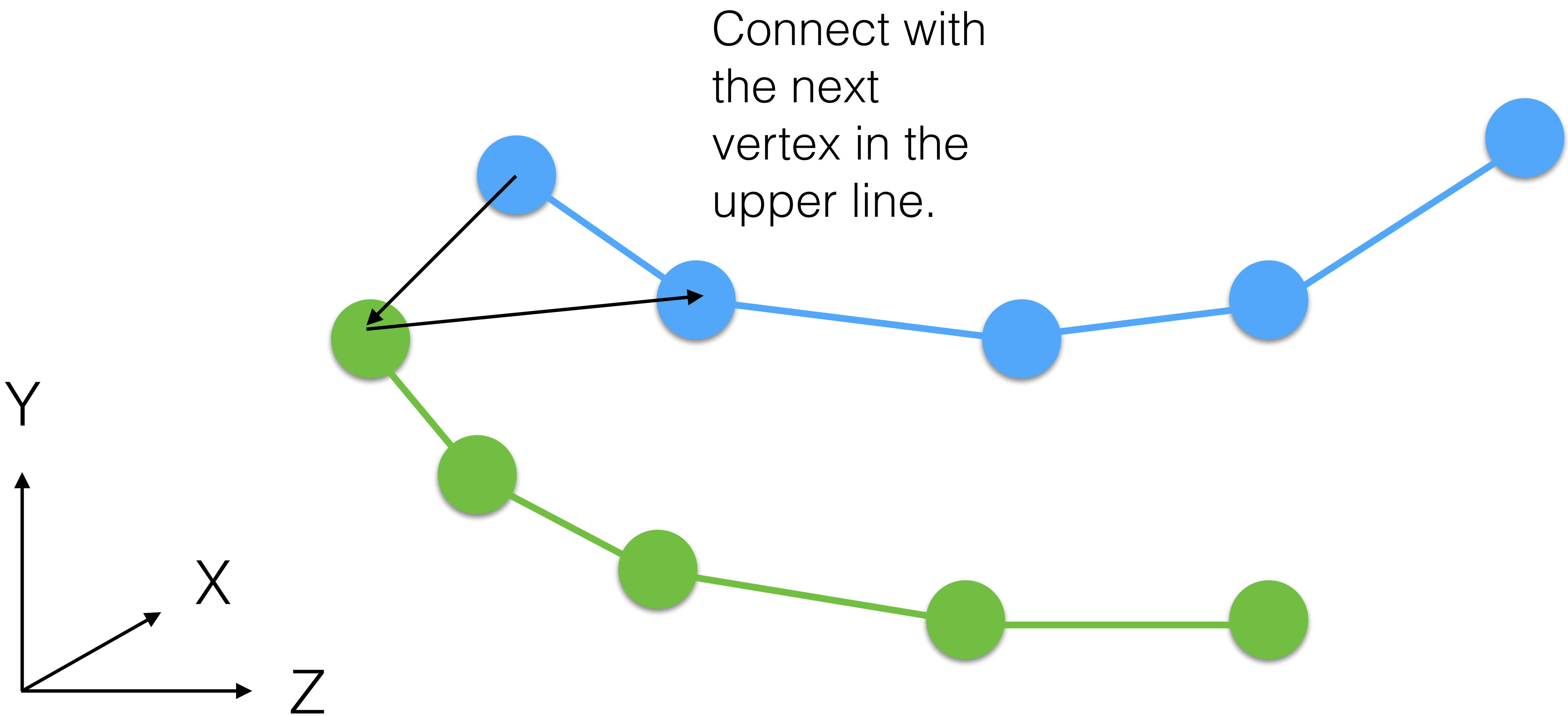
Edges Triangulation



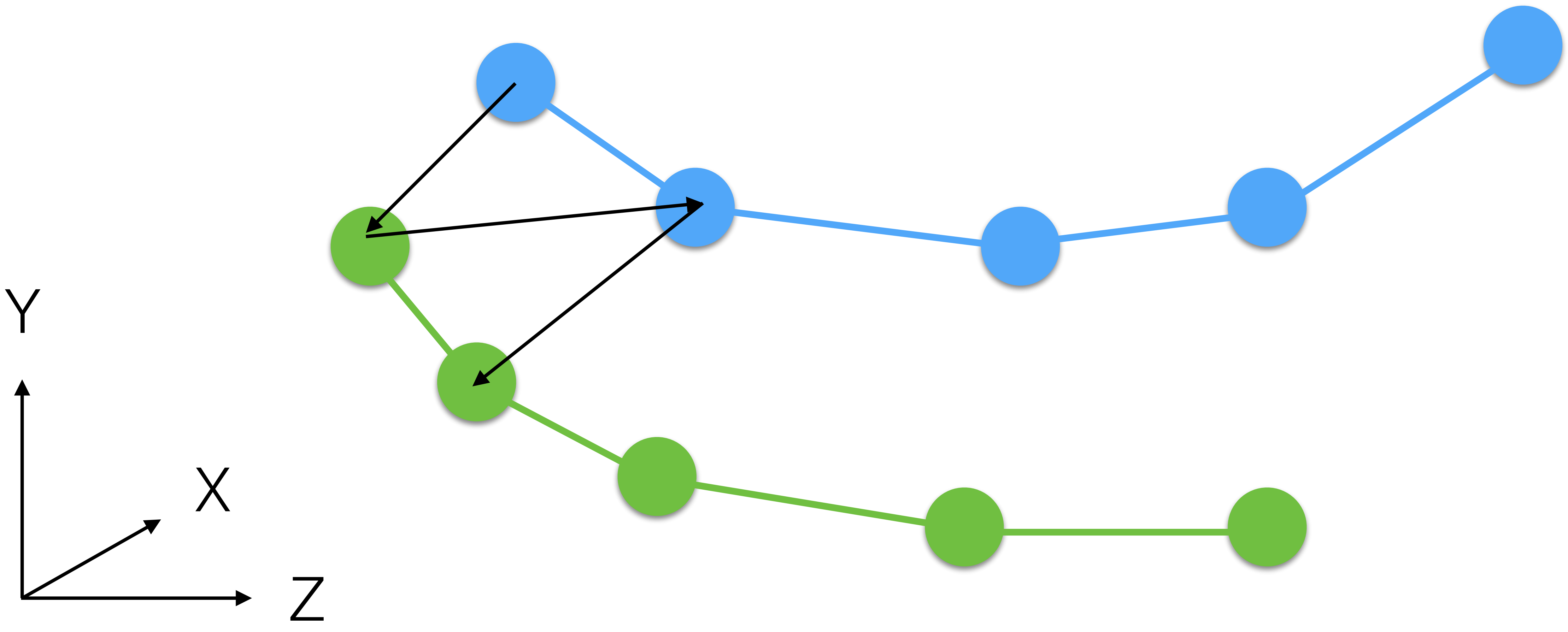
Edges Triangulation



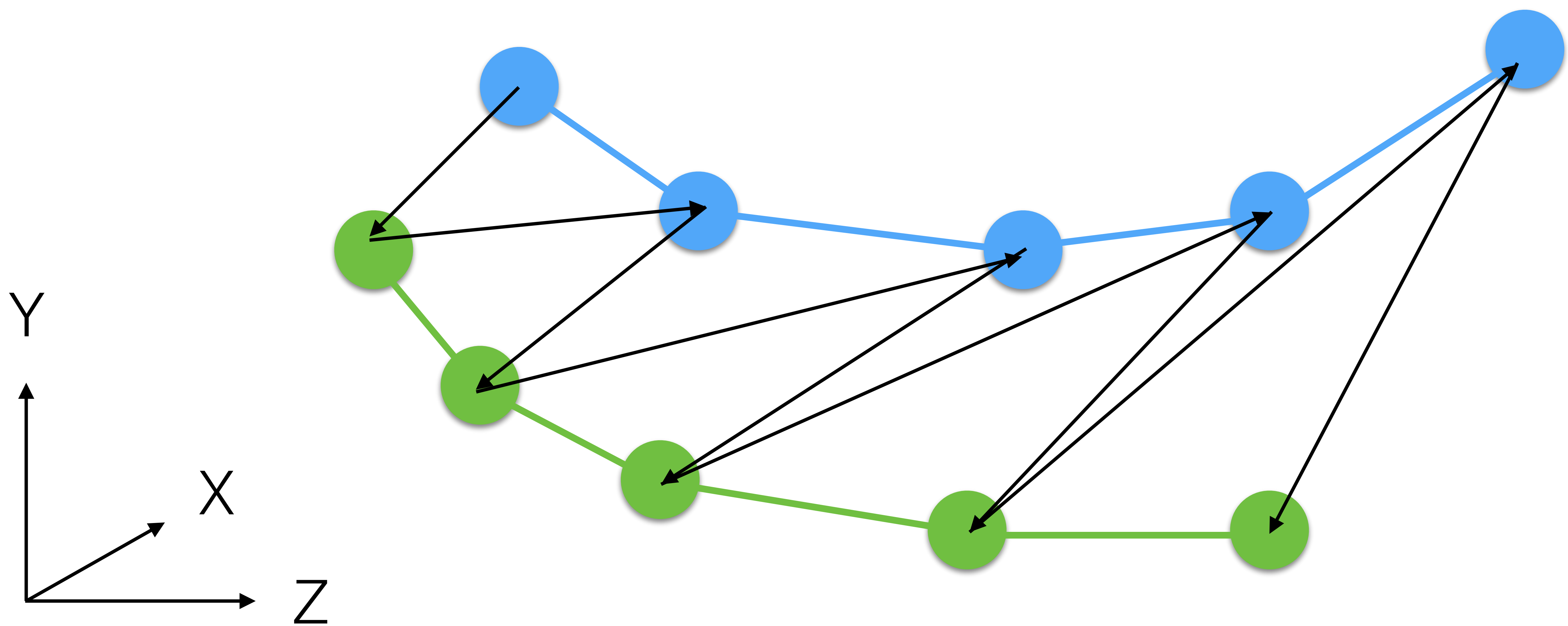
Edges Triangulation



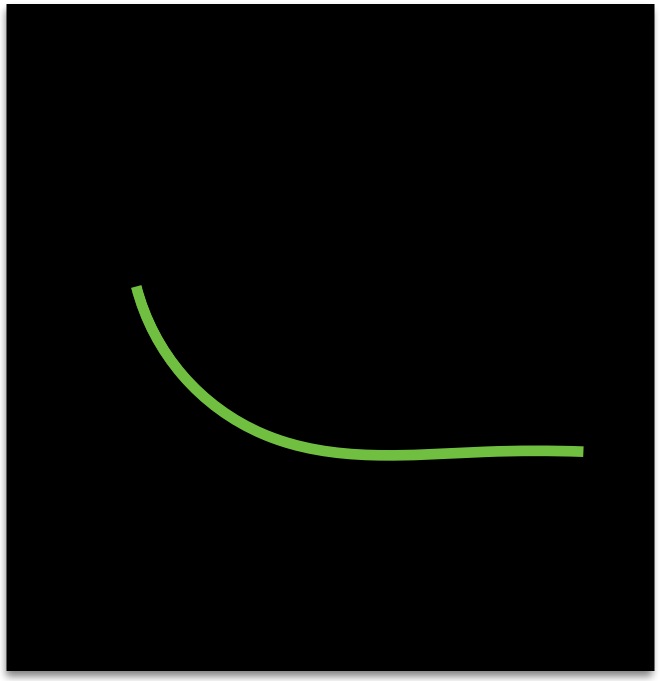
Edges Triangulation



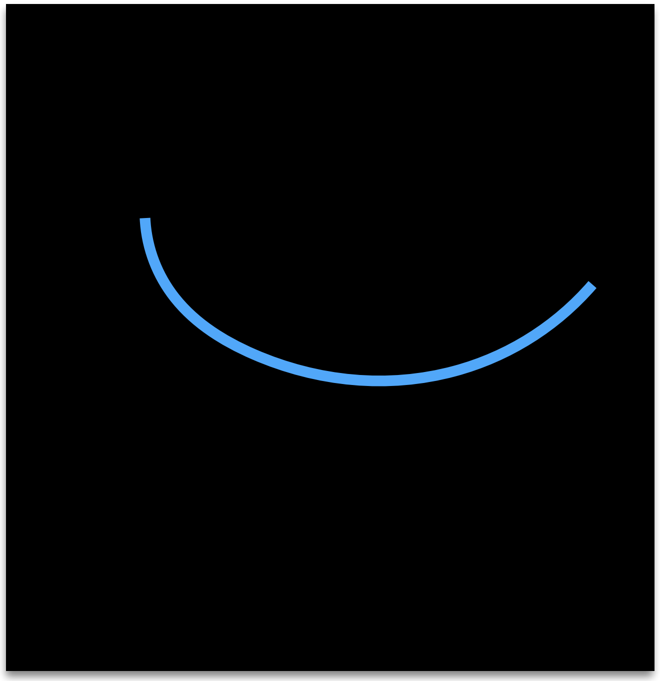
Edges Triangulation



Edges Triangulation: Fail Case

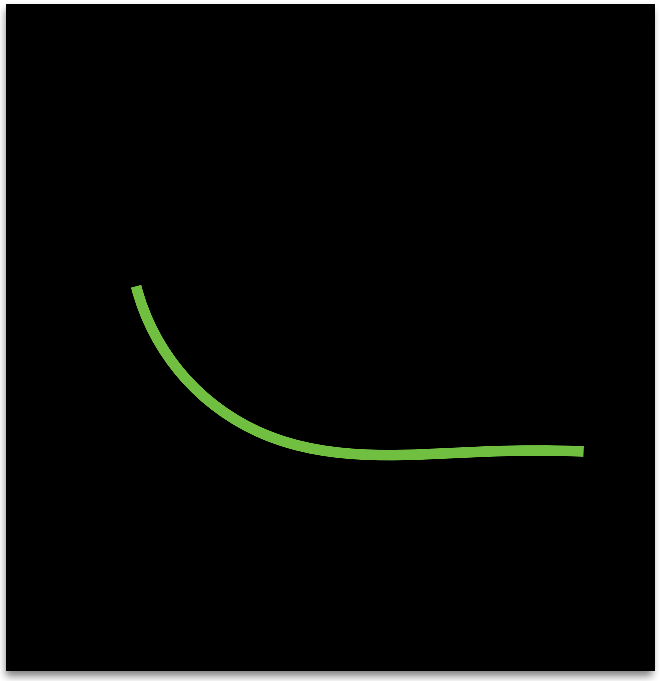


Slice 1

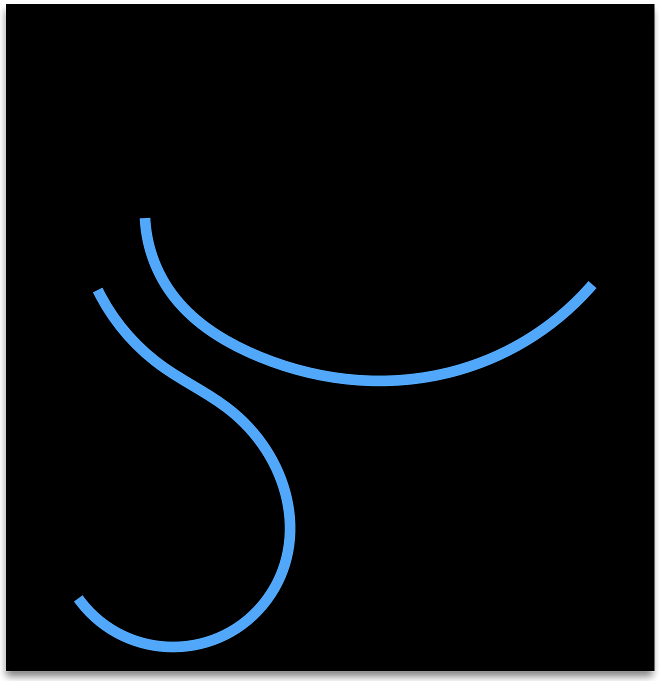


Slice 2

Edges Triangulation: Fail Case

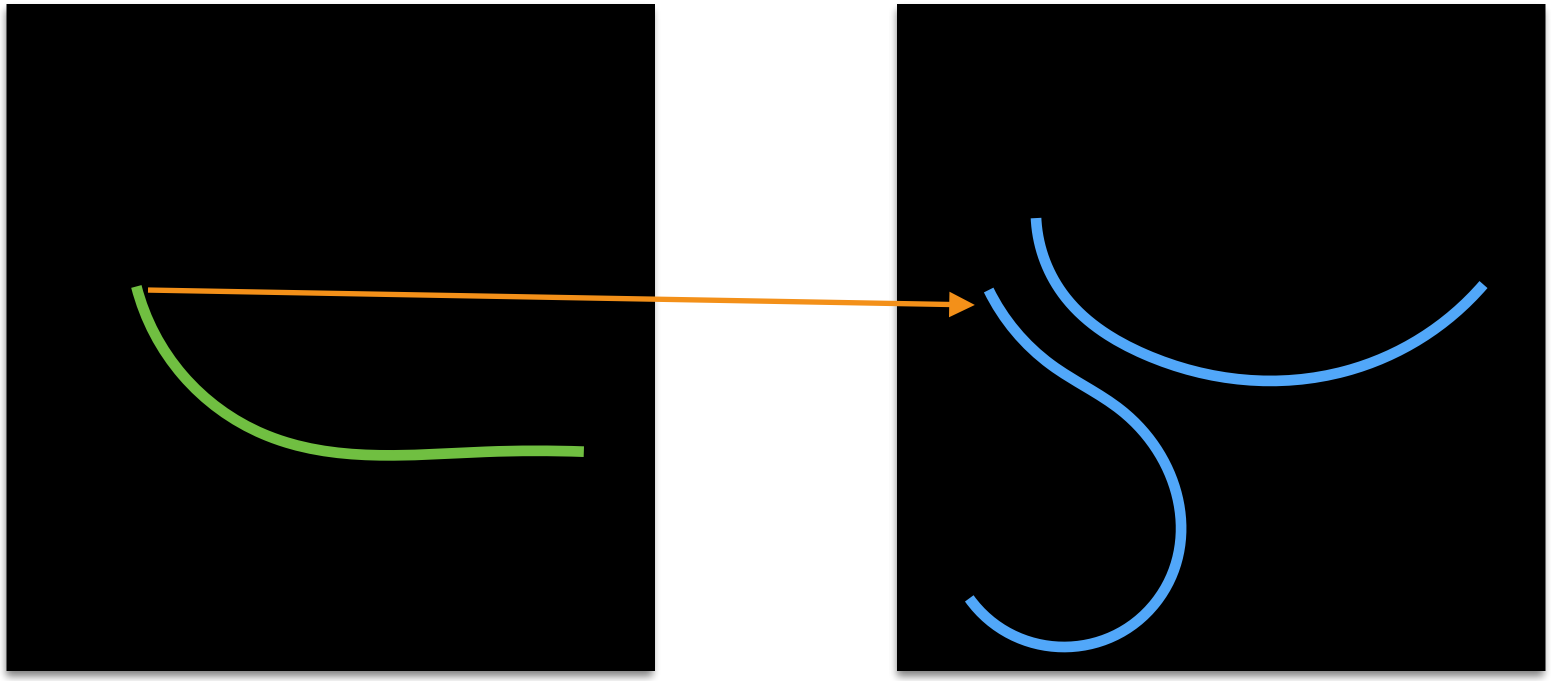


Slice 1



Slice 2

Edges Triangulation: Fail Case



Slice 1 | Slice 2

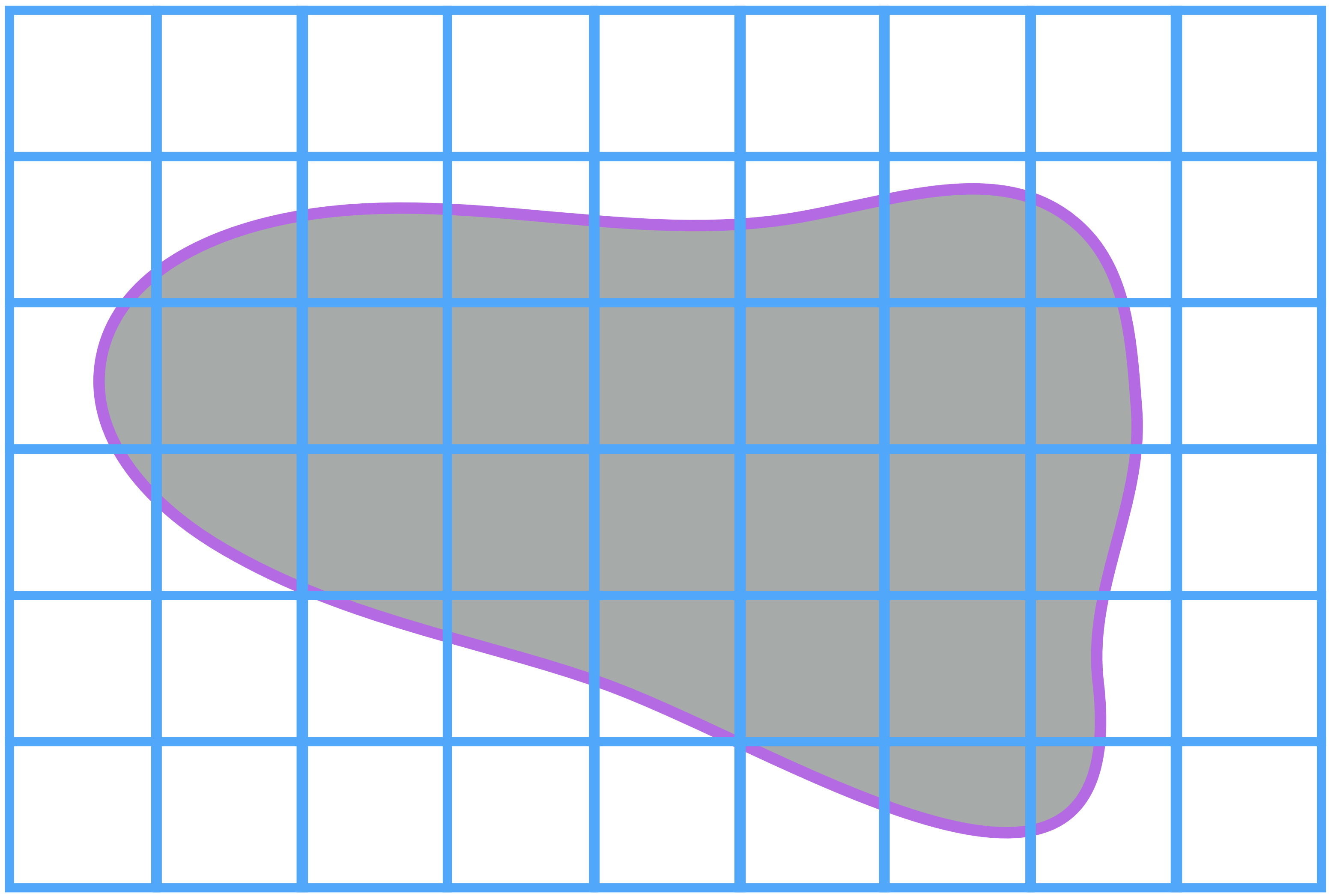
Edges Triangulation

- It works because we have a previously known connectivity.
- It works only for a binary segmentation mask:
  - No multiple objects!
- Quality of triangles is pretty poor!
- We cannot close the mesh; i.e., it is not watertight!

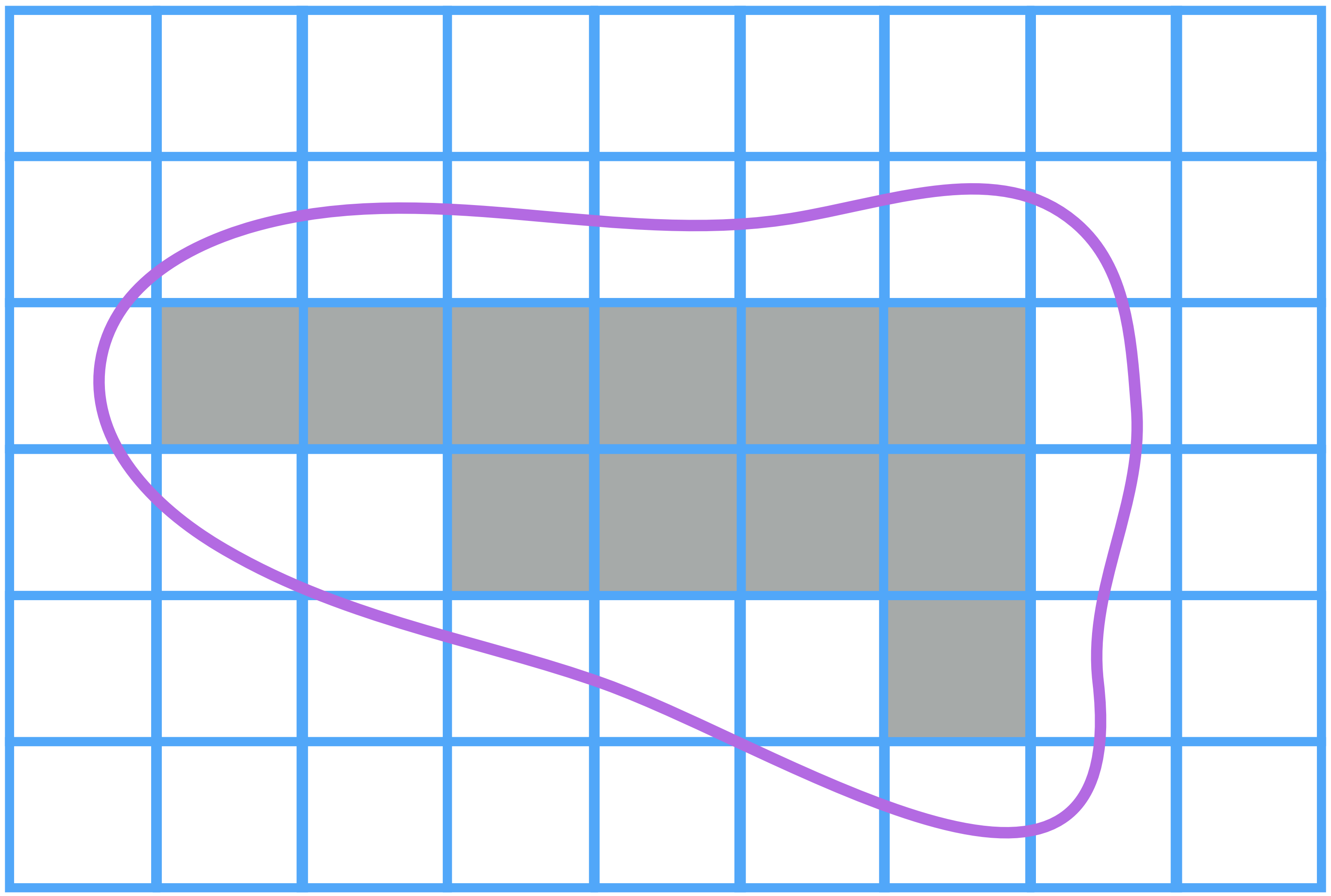
Marching Cubes

Let's start in 2D

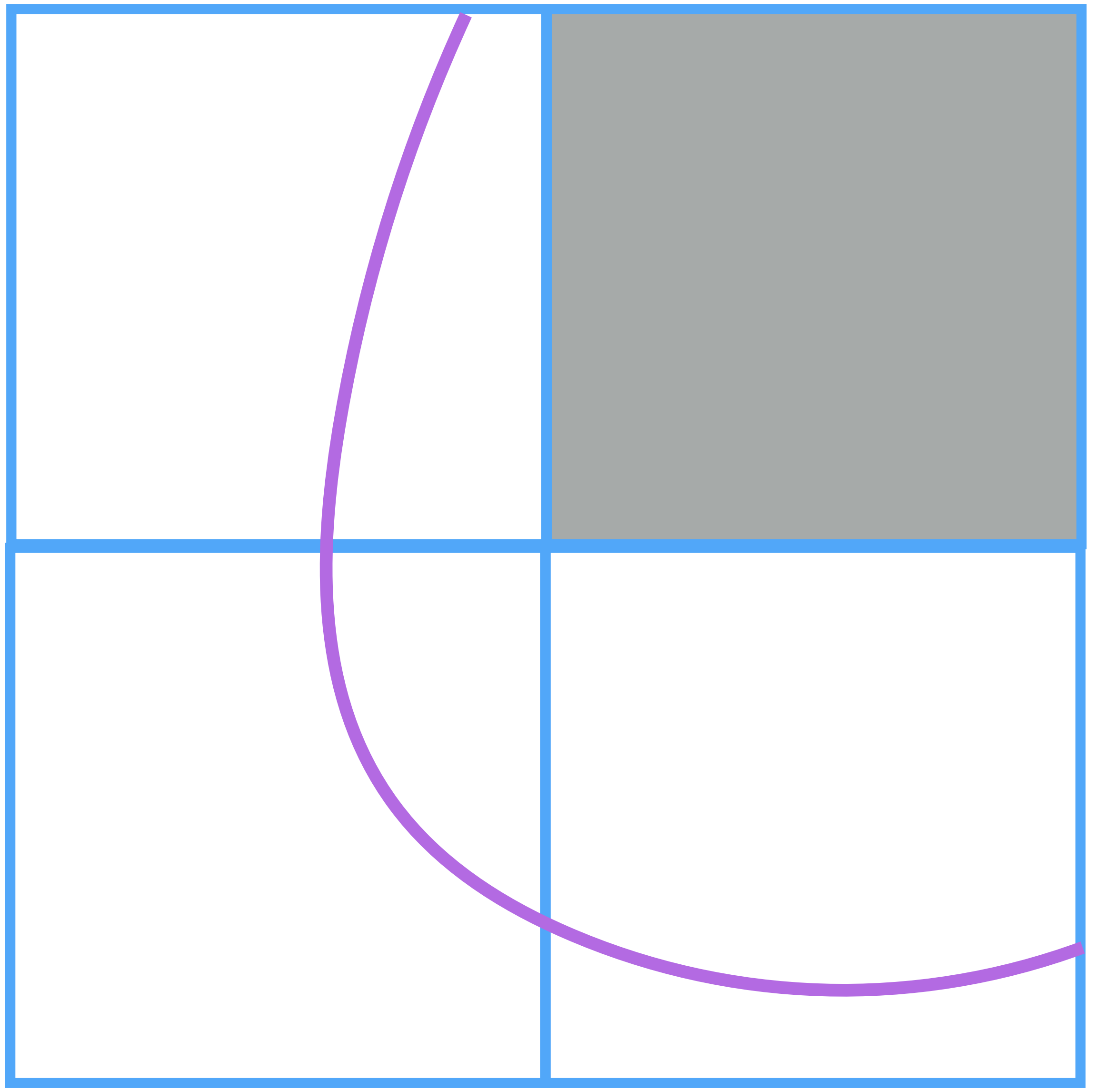
Marching Squares



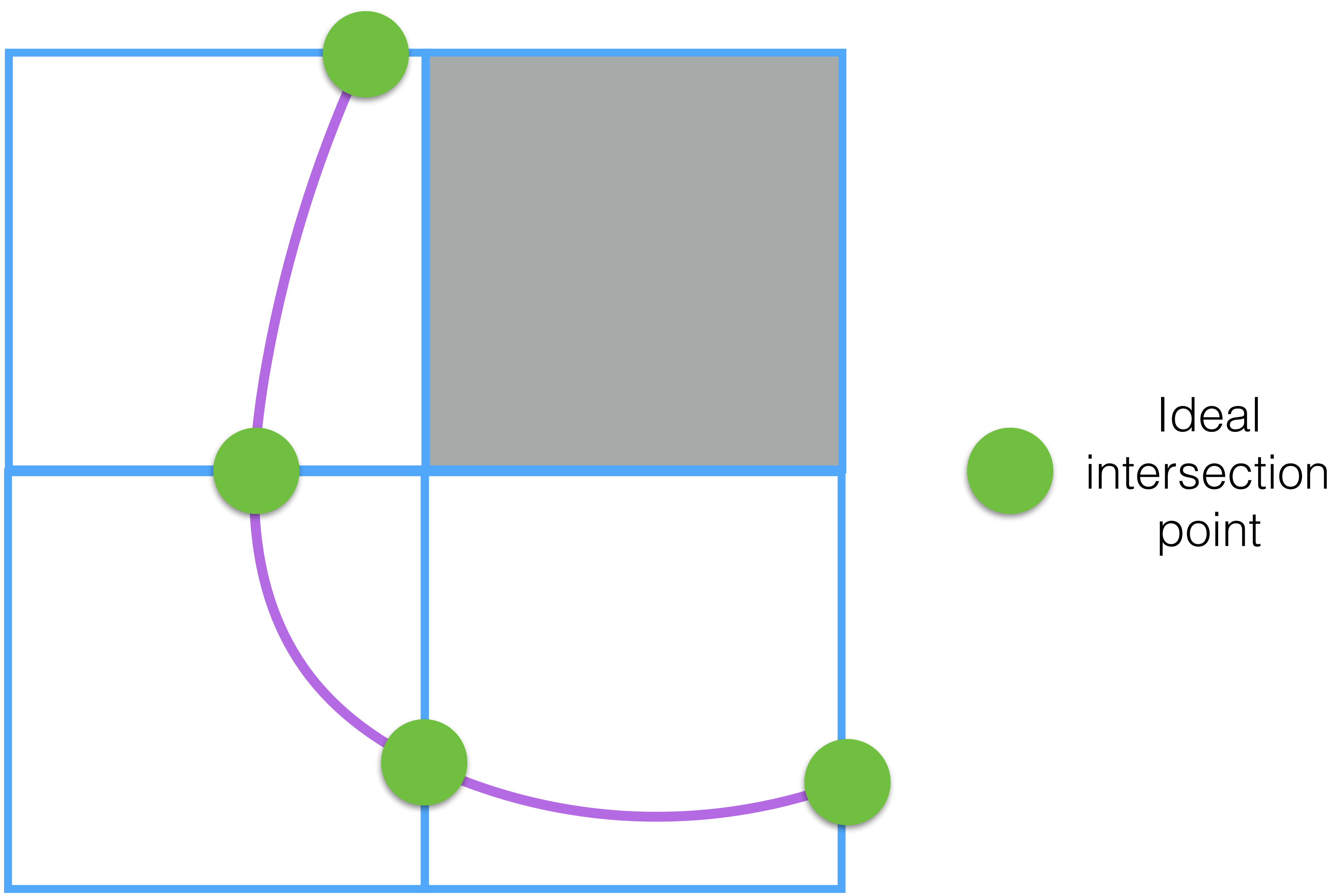
Marching Squares



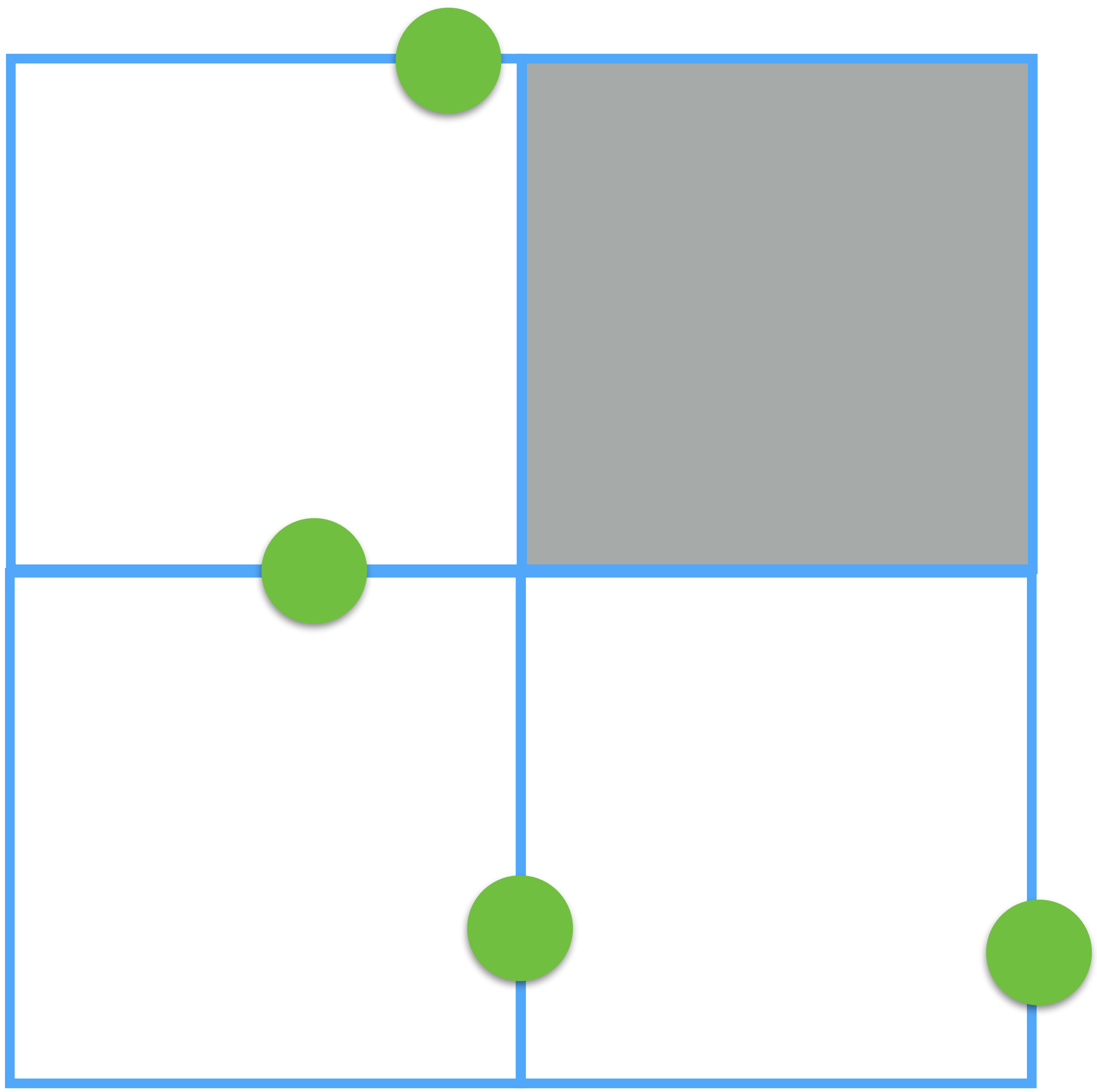
Marching Squares



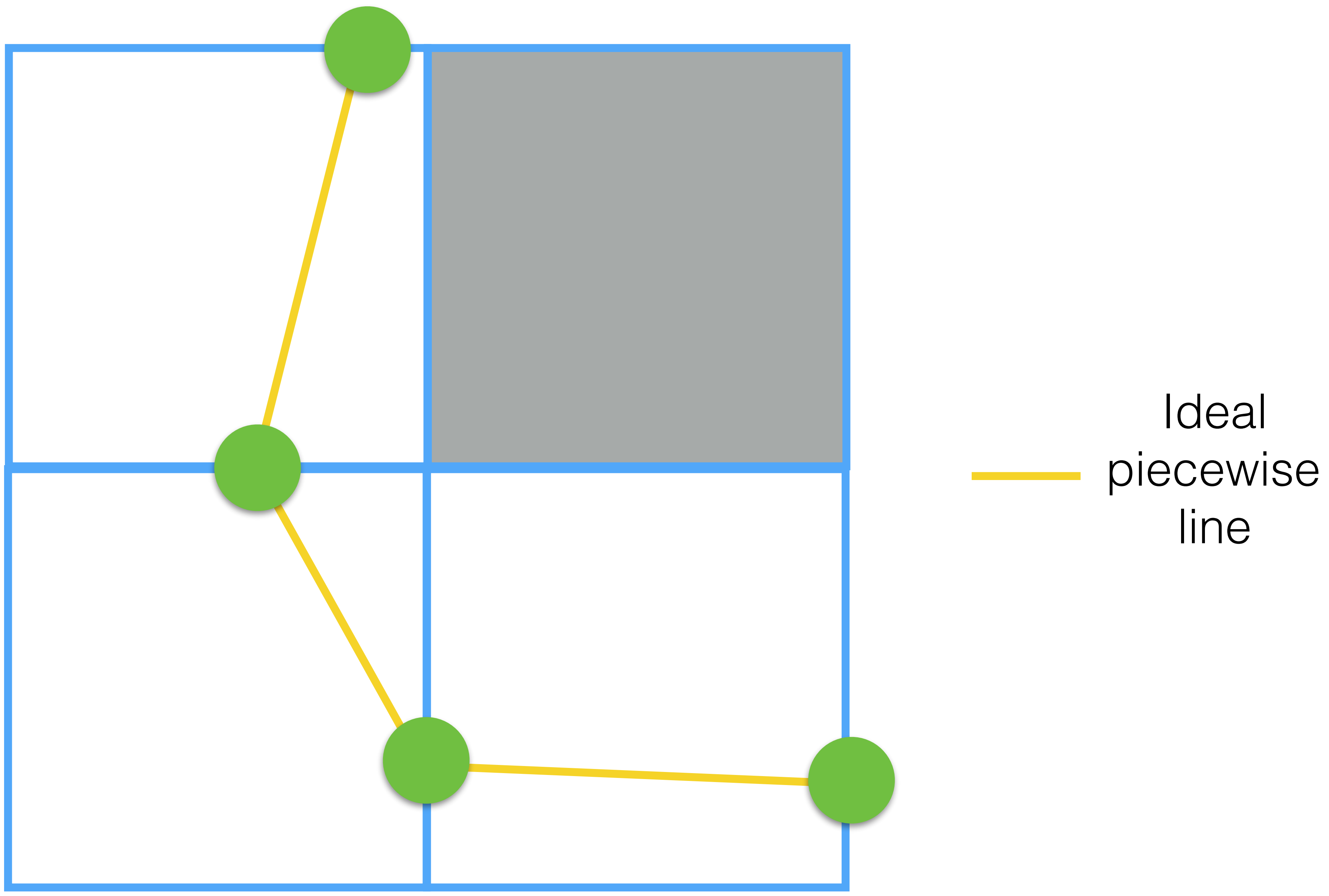
Marching Squares



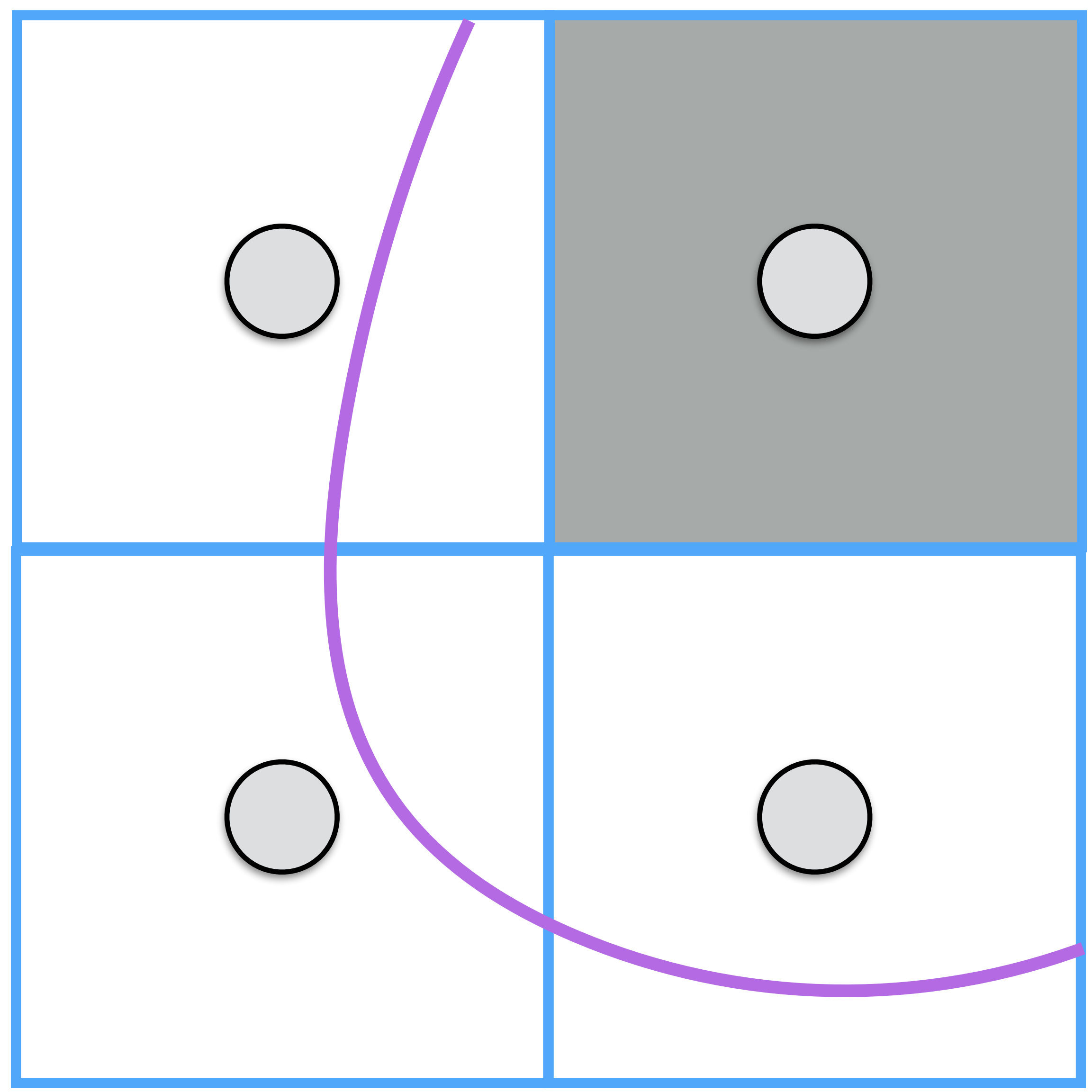
Marching Squares



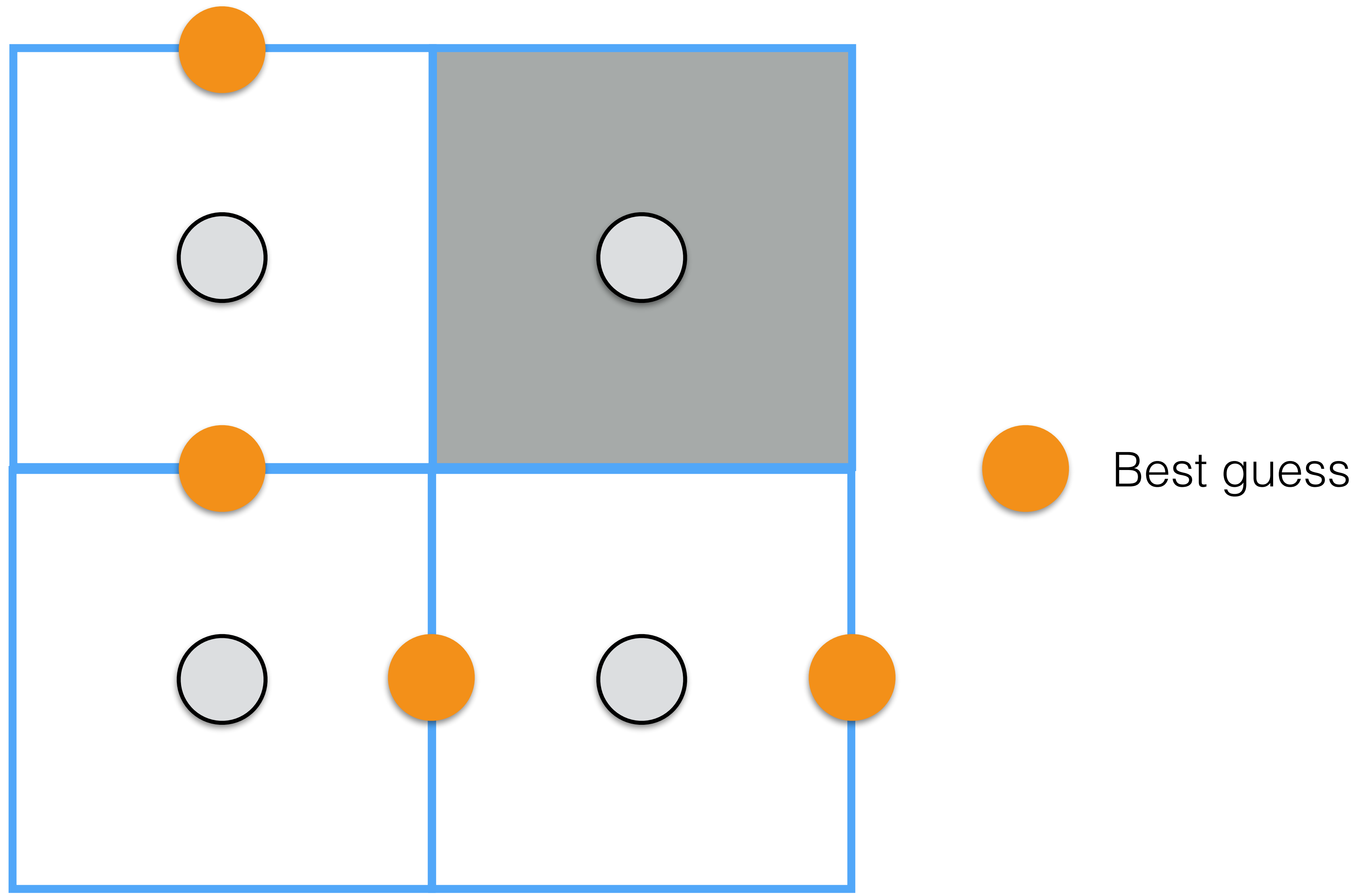
Marching Squares



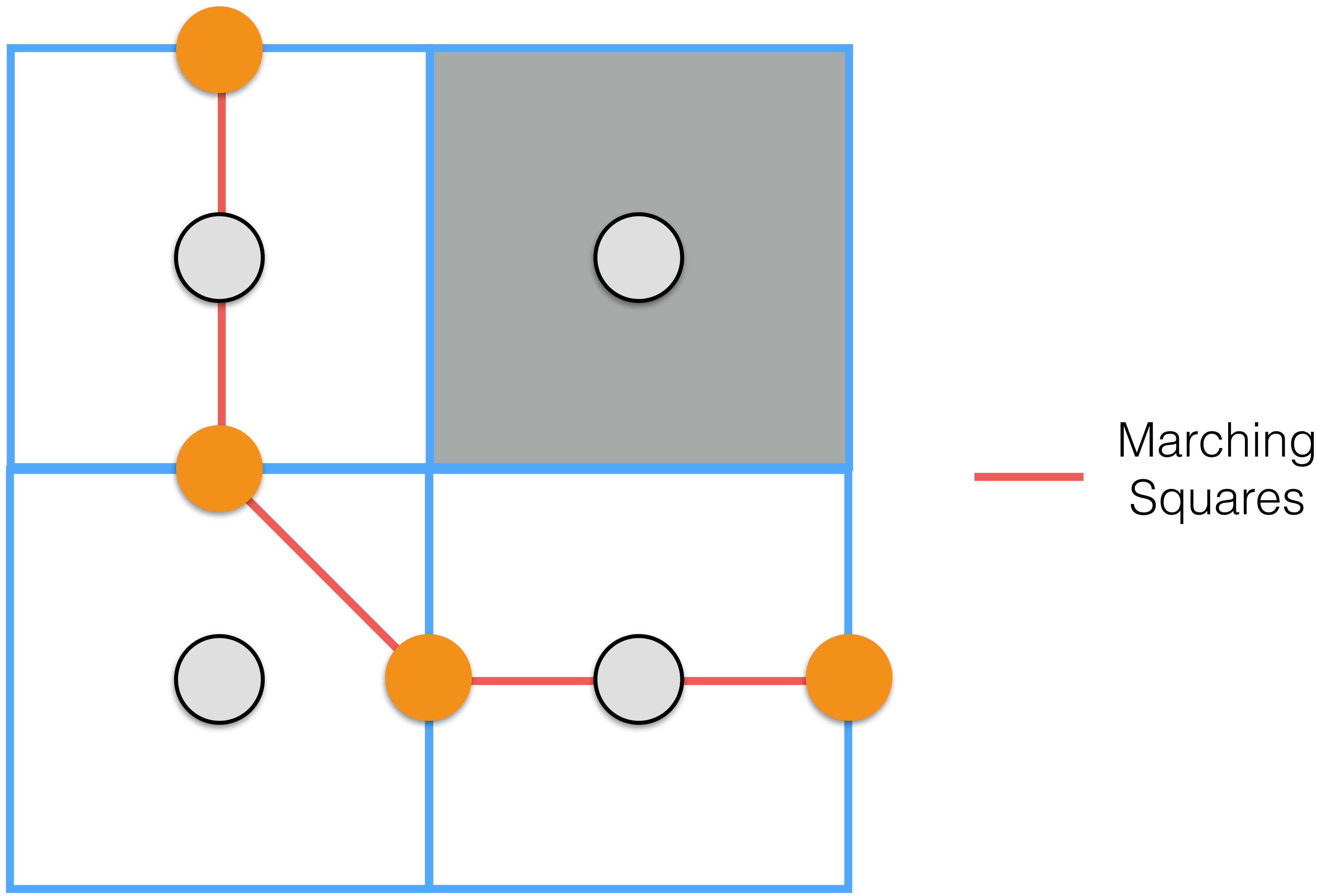
Marching Squares



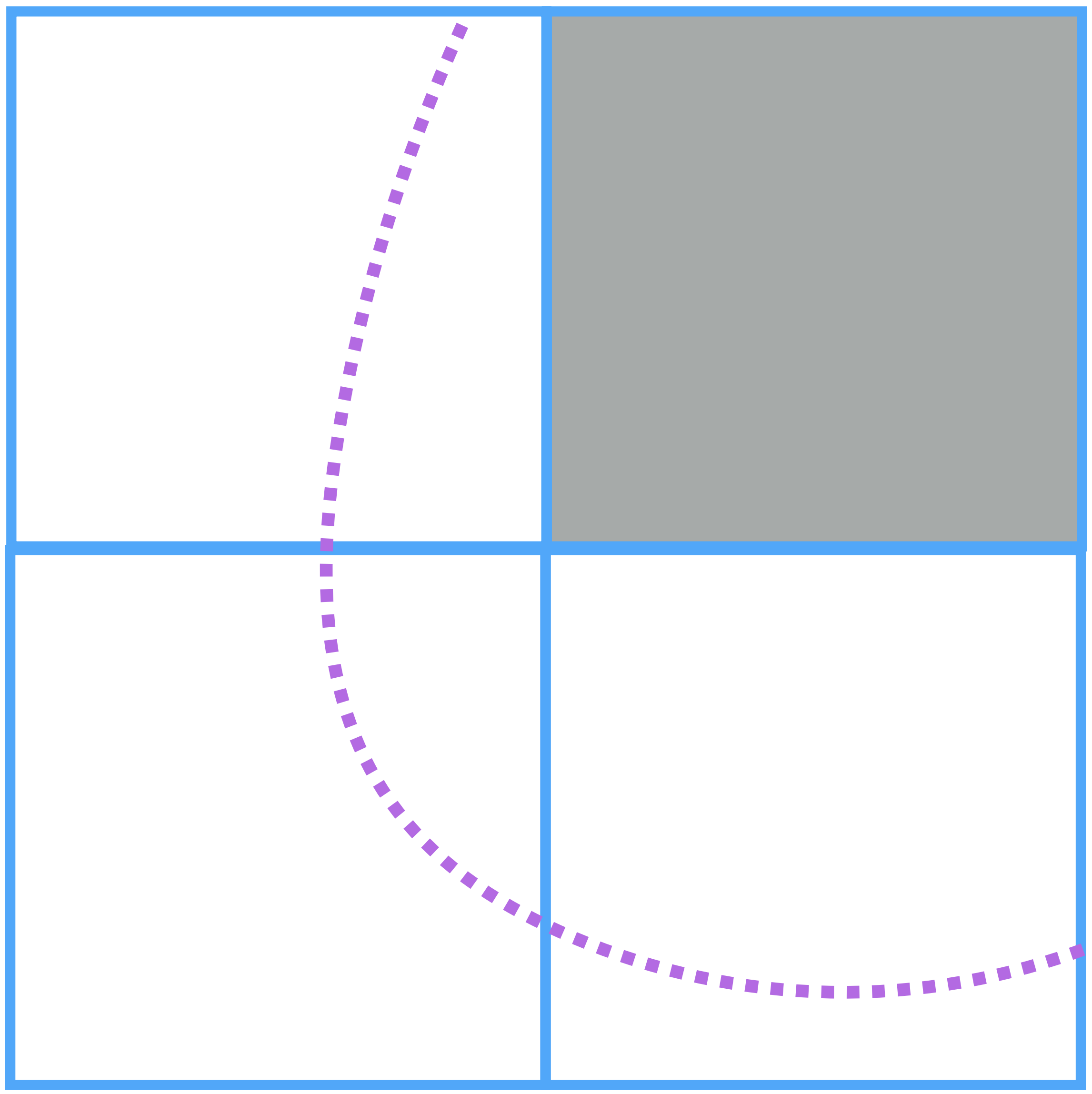
Marching Squares



Marching Squares

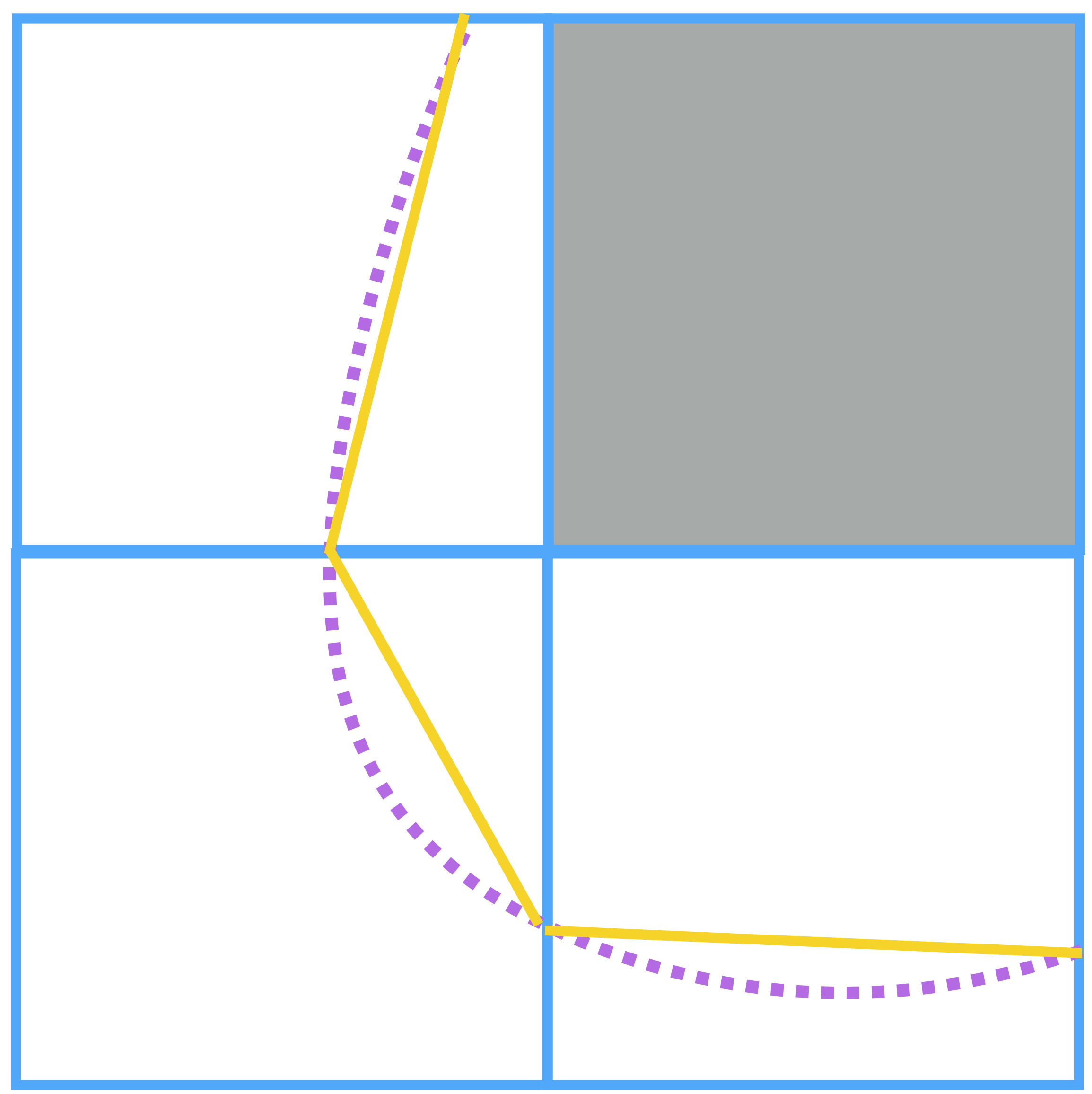


Marching Squares



Real boundary
Ideal piece-wise line
Marching squares

Marching Squares



Real boundary
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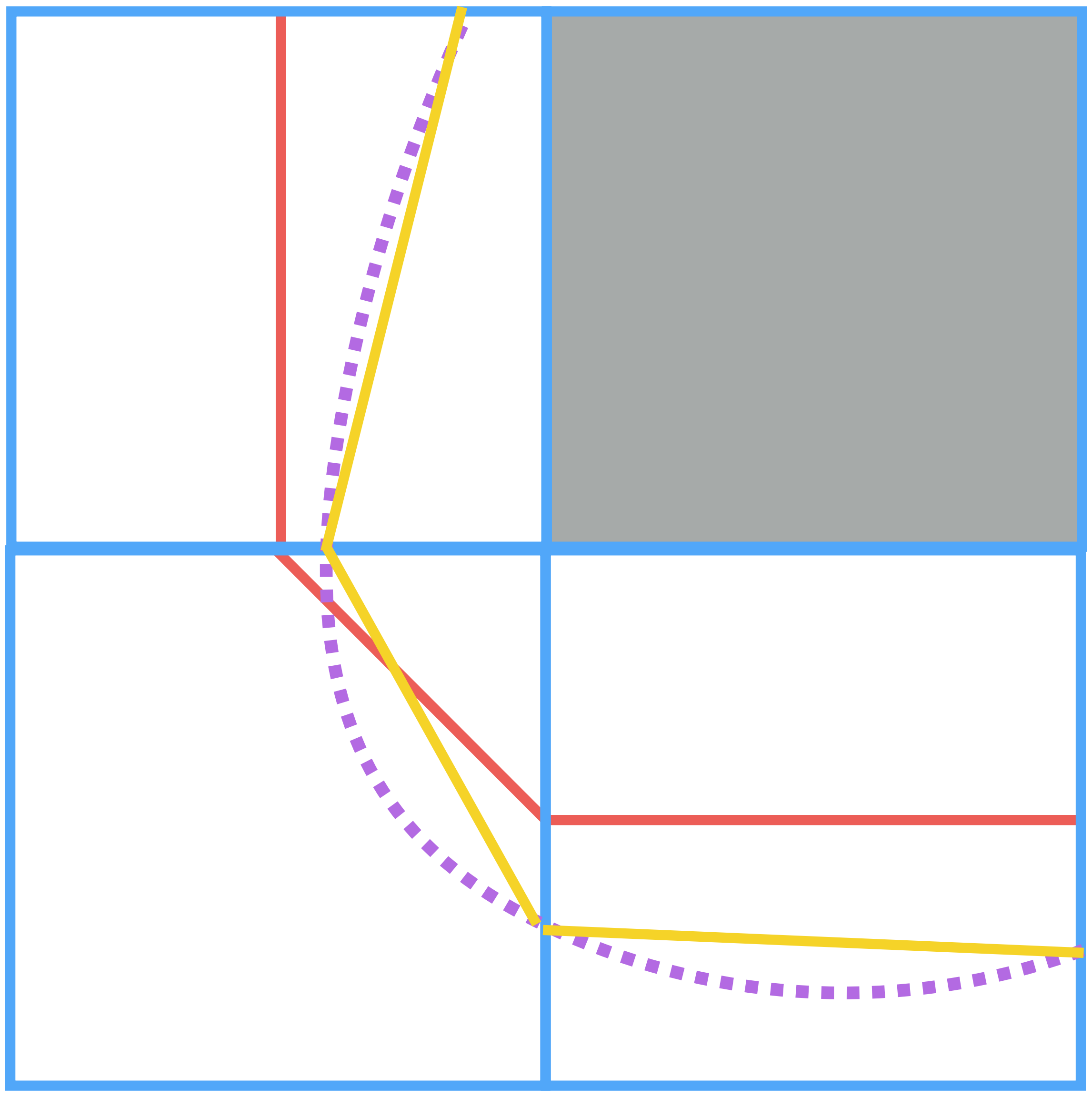
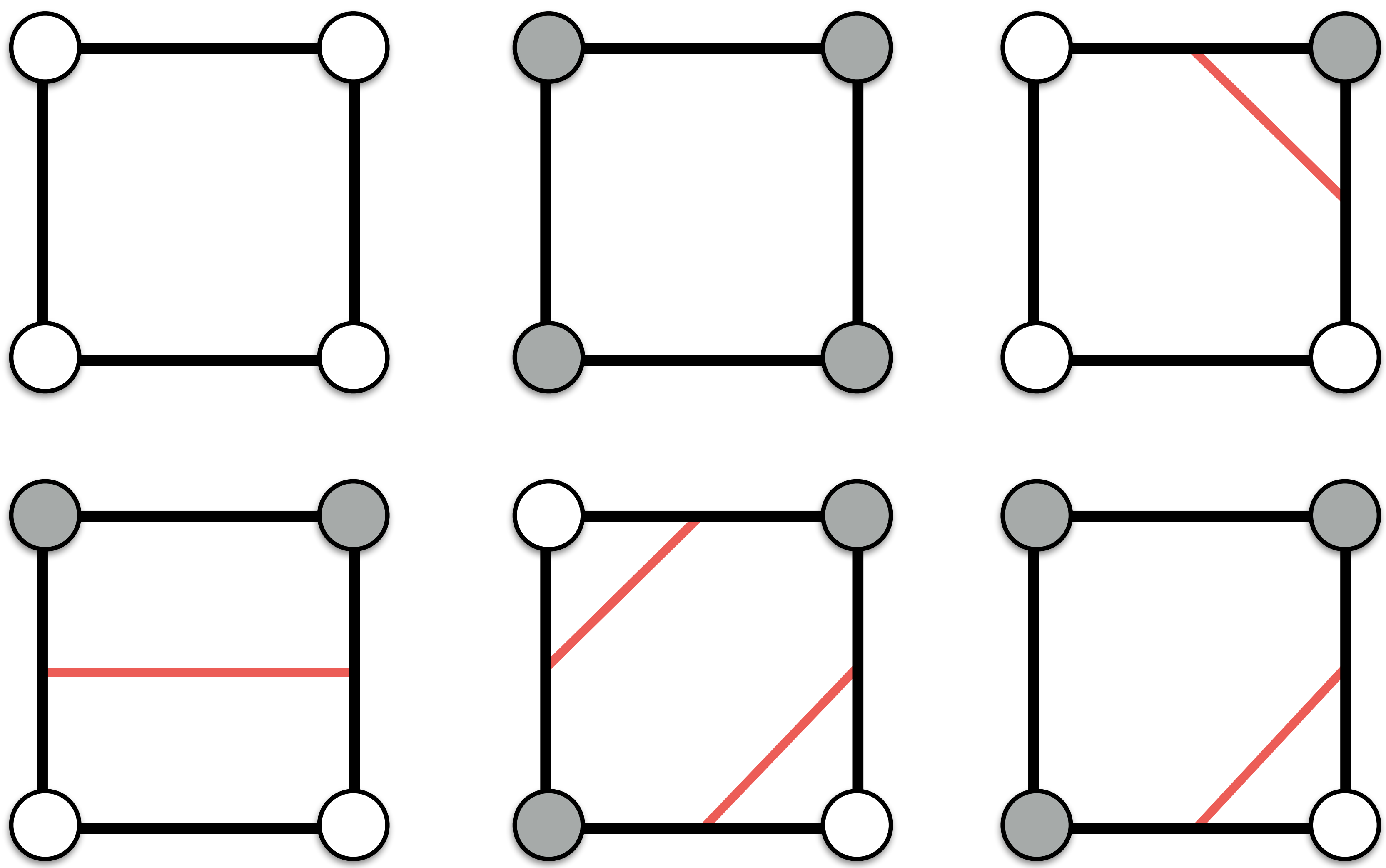
Marching Squares



Real boundary
Ideal piece-wise line
Marching squares

Marching Squares: Cases

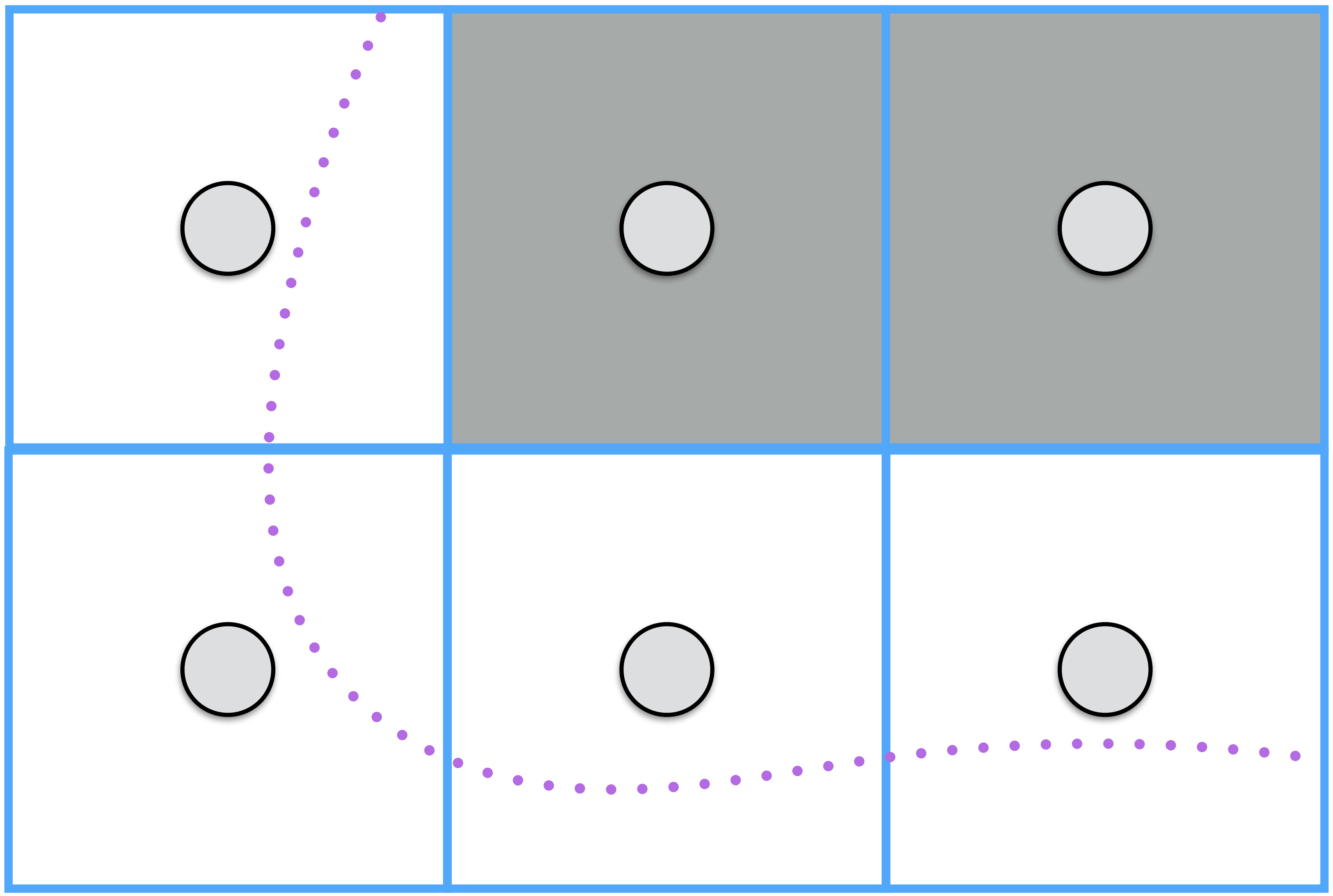


There are in total 16 (2^4) configurations, the other ones can be computed by rotating or reflecting these.

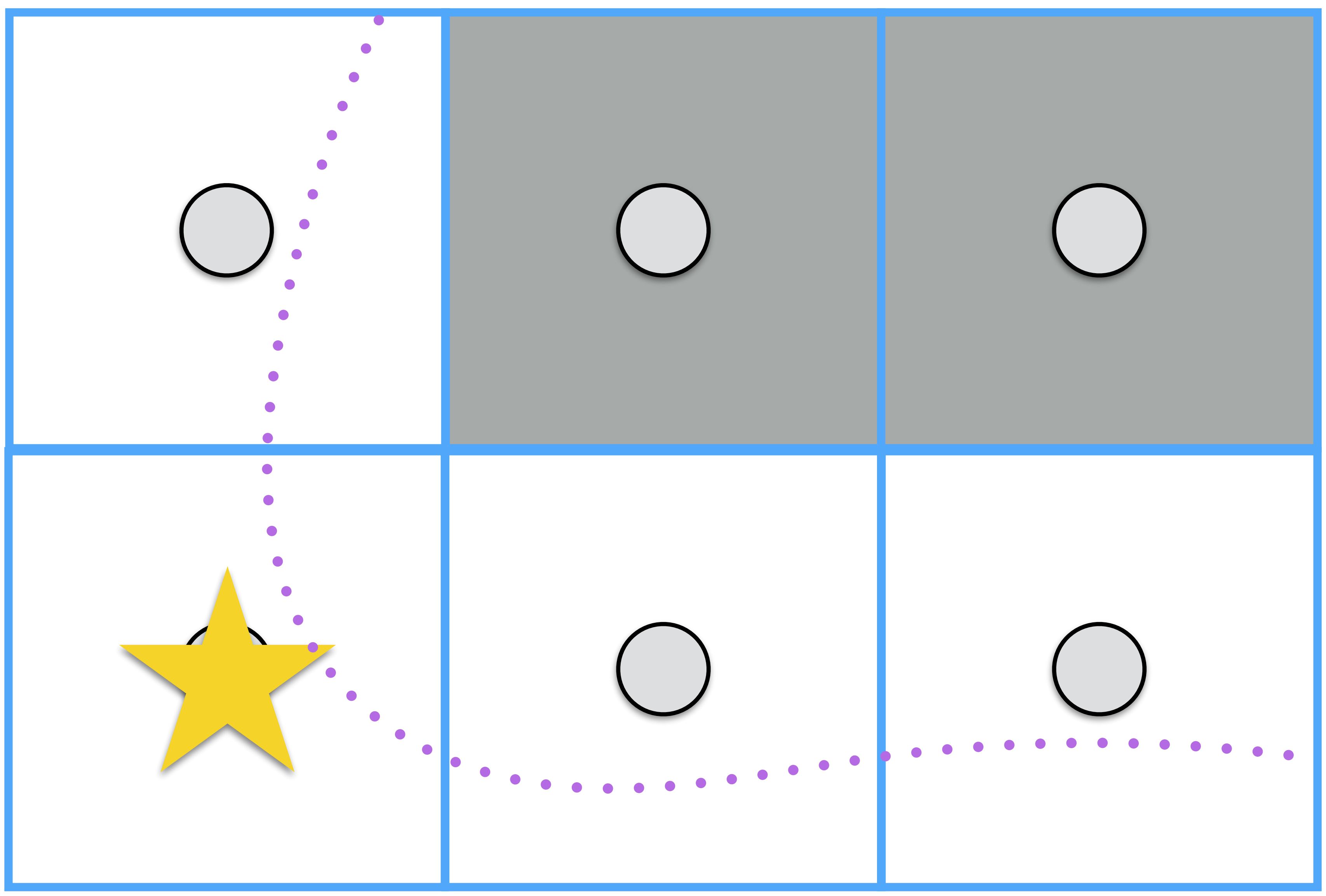
Marching Squares

- For each square:
  - We compute the configuration of the current square.
  - We fetch from the table of configurations our case.
  - We place the line for that case in the current square.

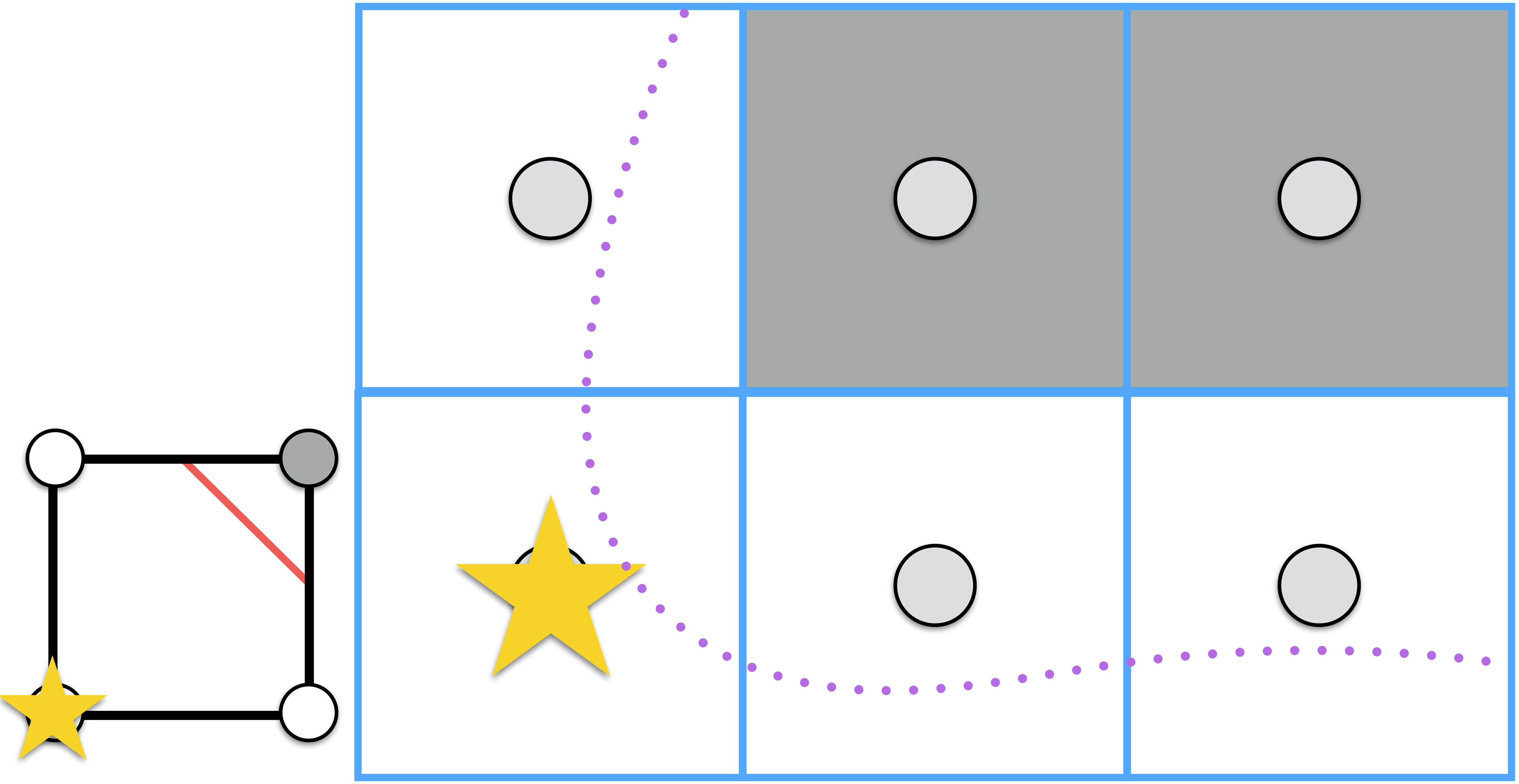
Marching Squares Example



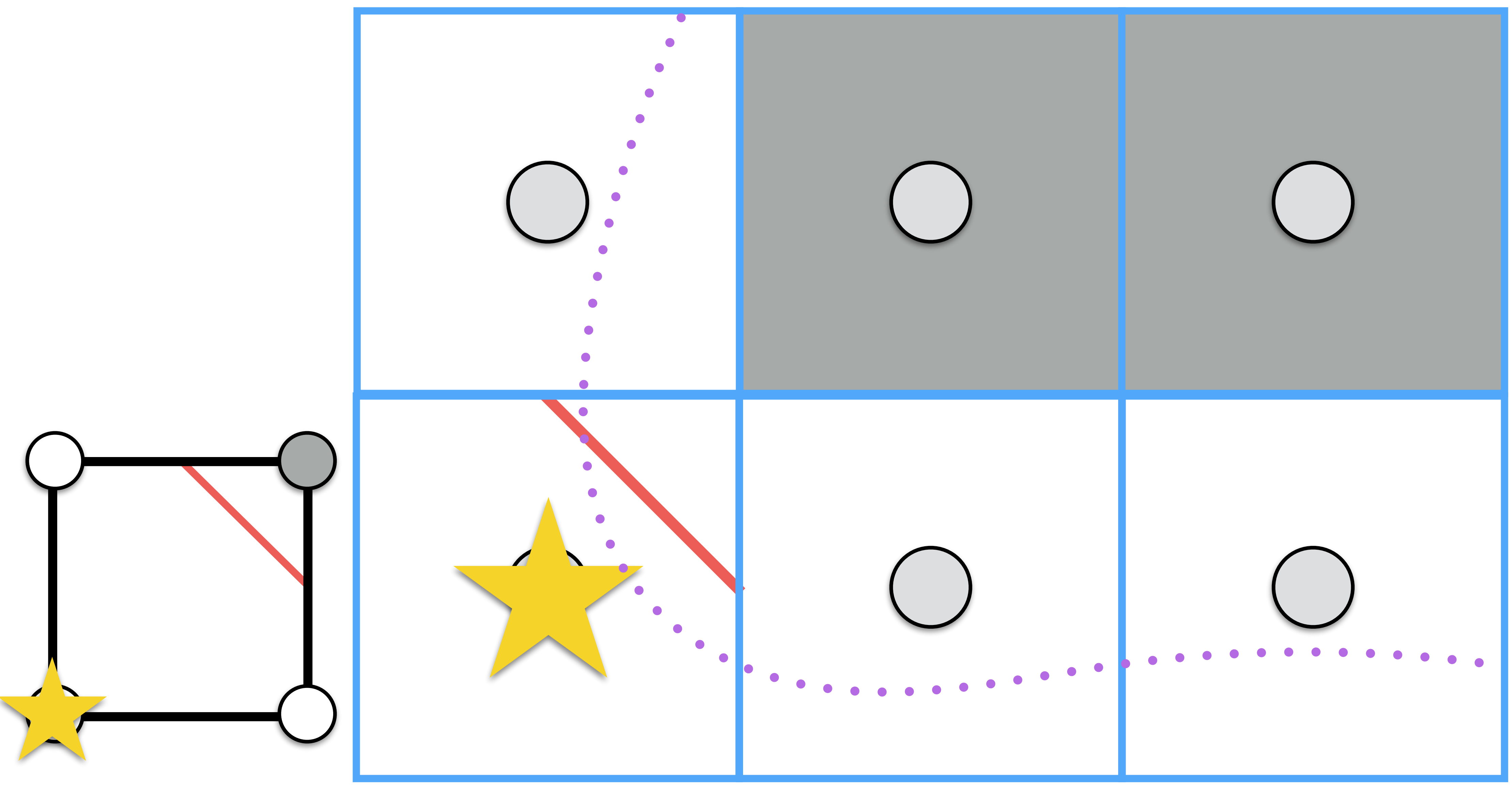
Marching Squares Example



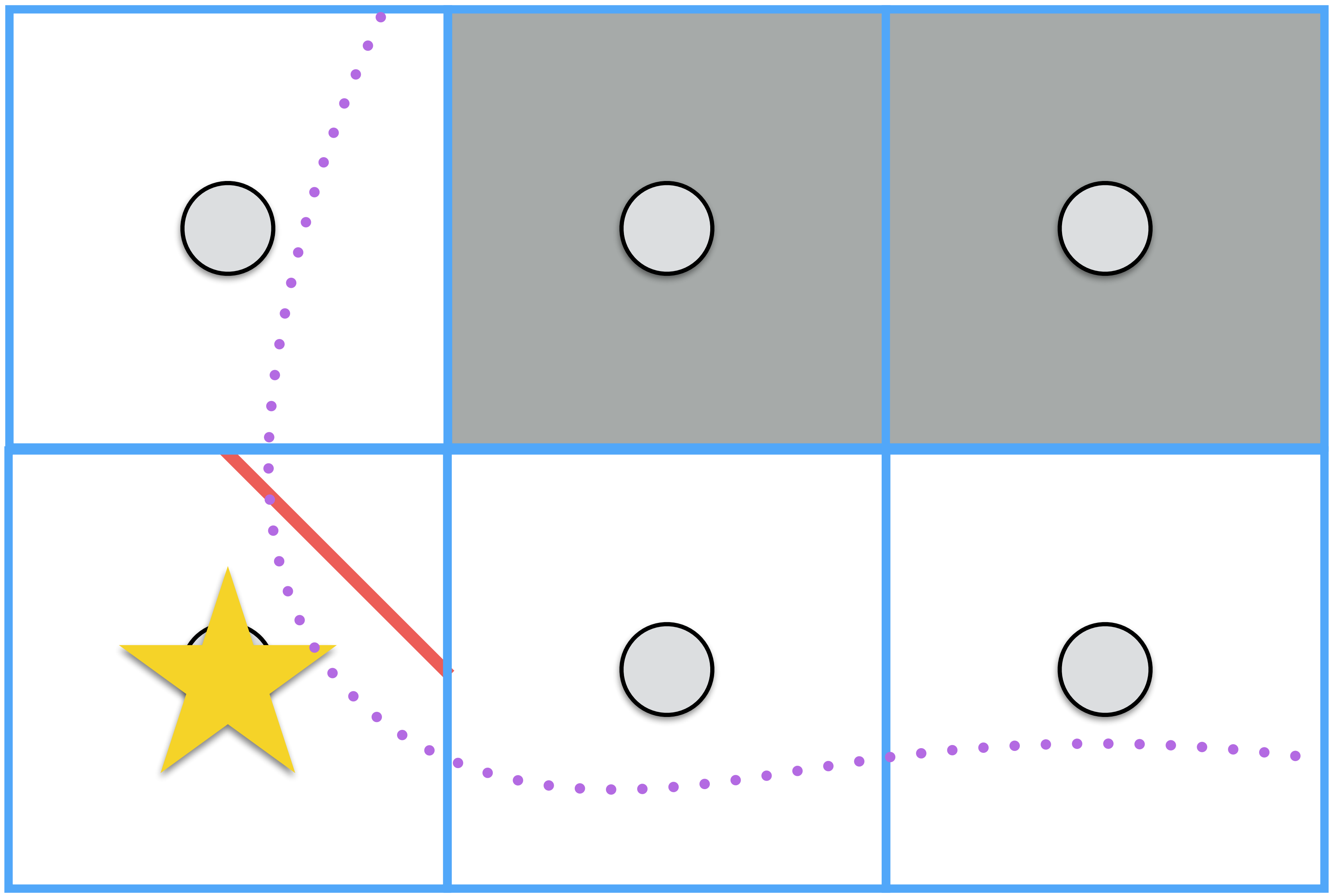
Marching Squares Example



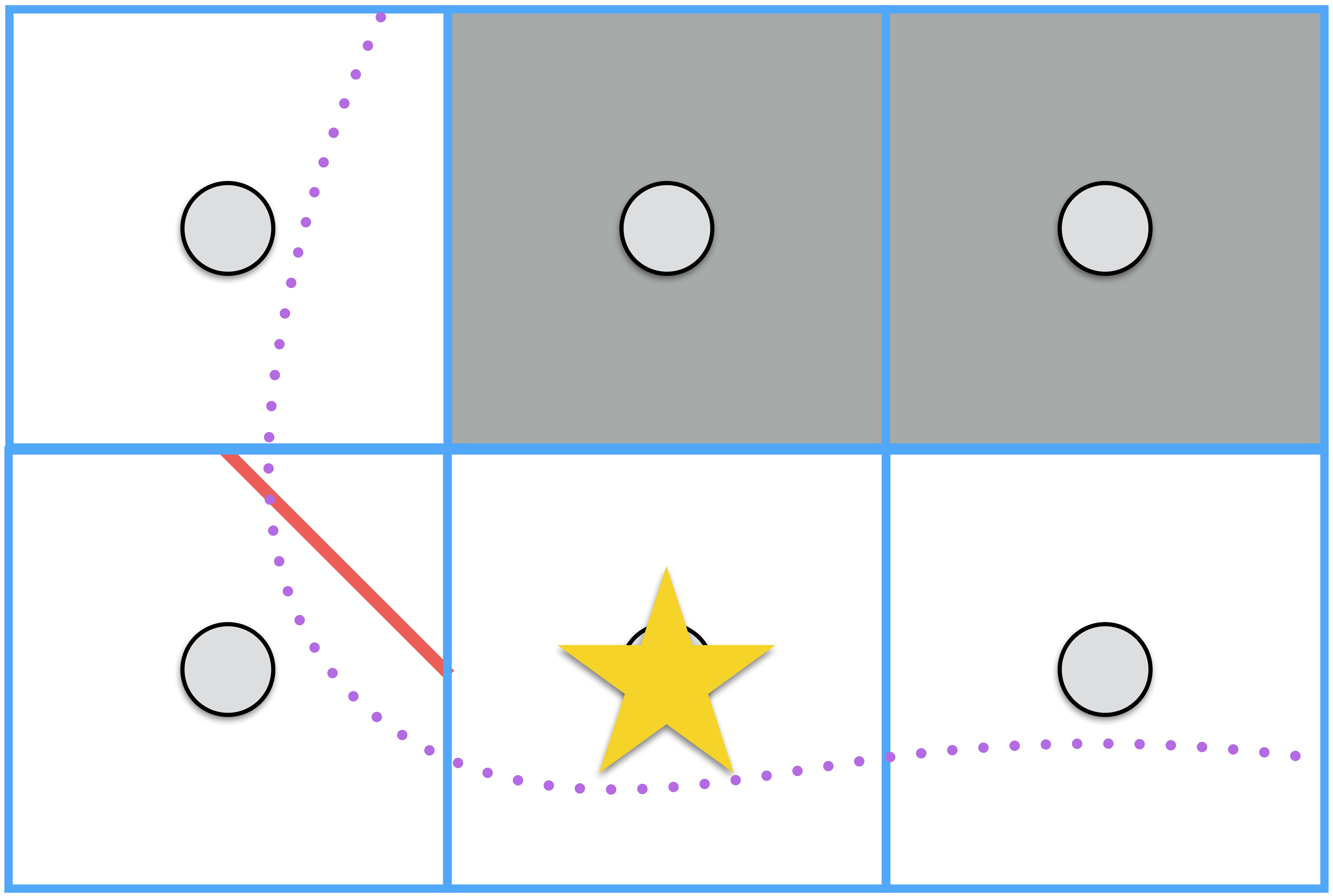
Marching Squares Example



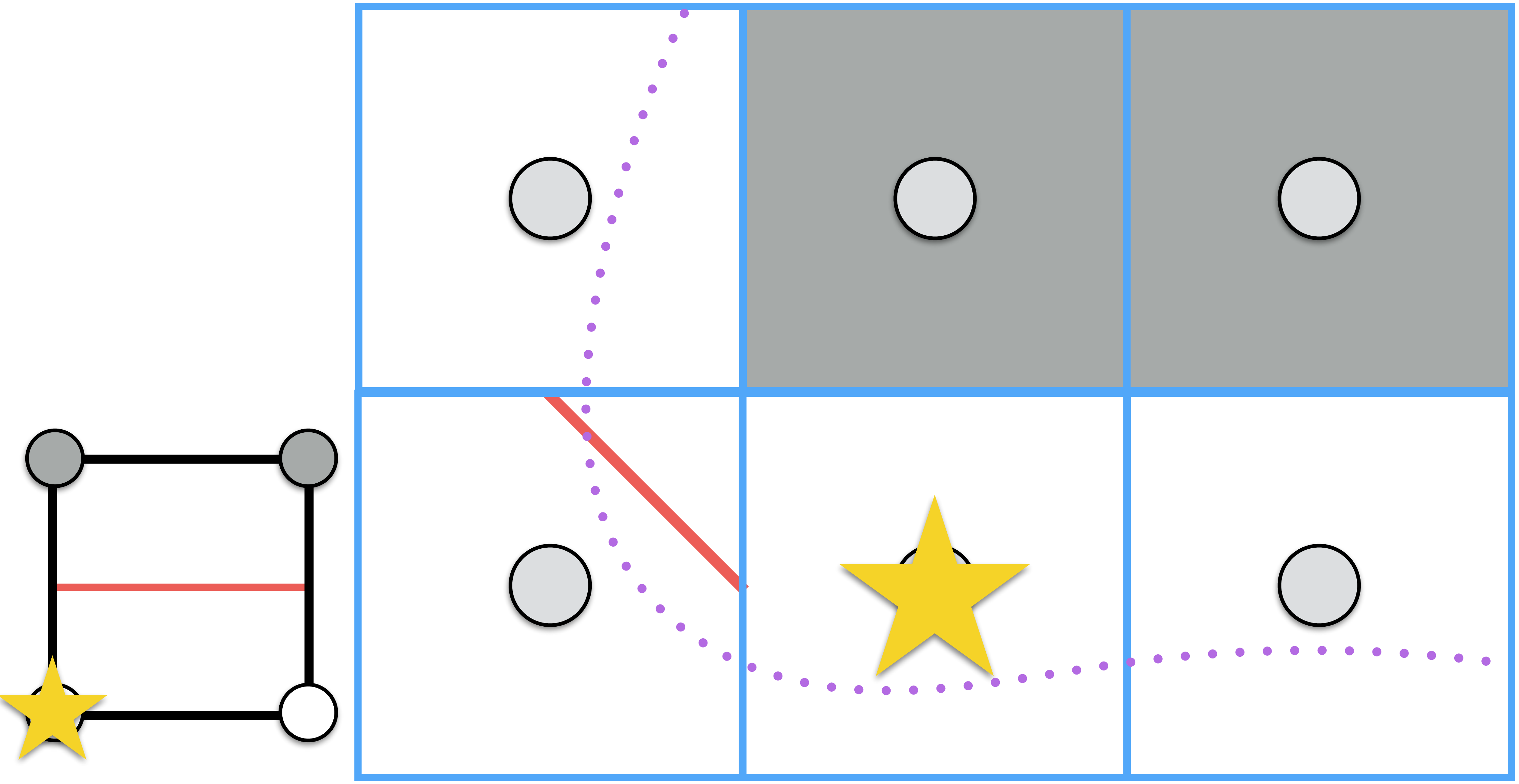
Marching Squares Example



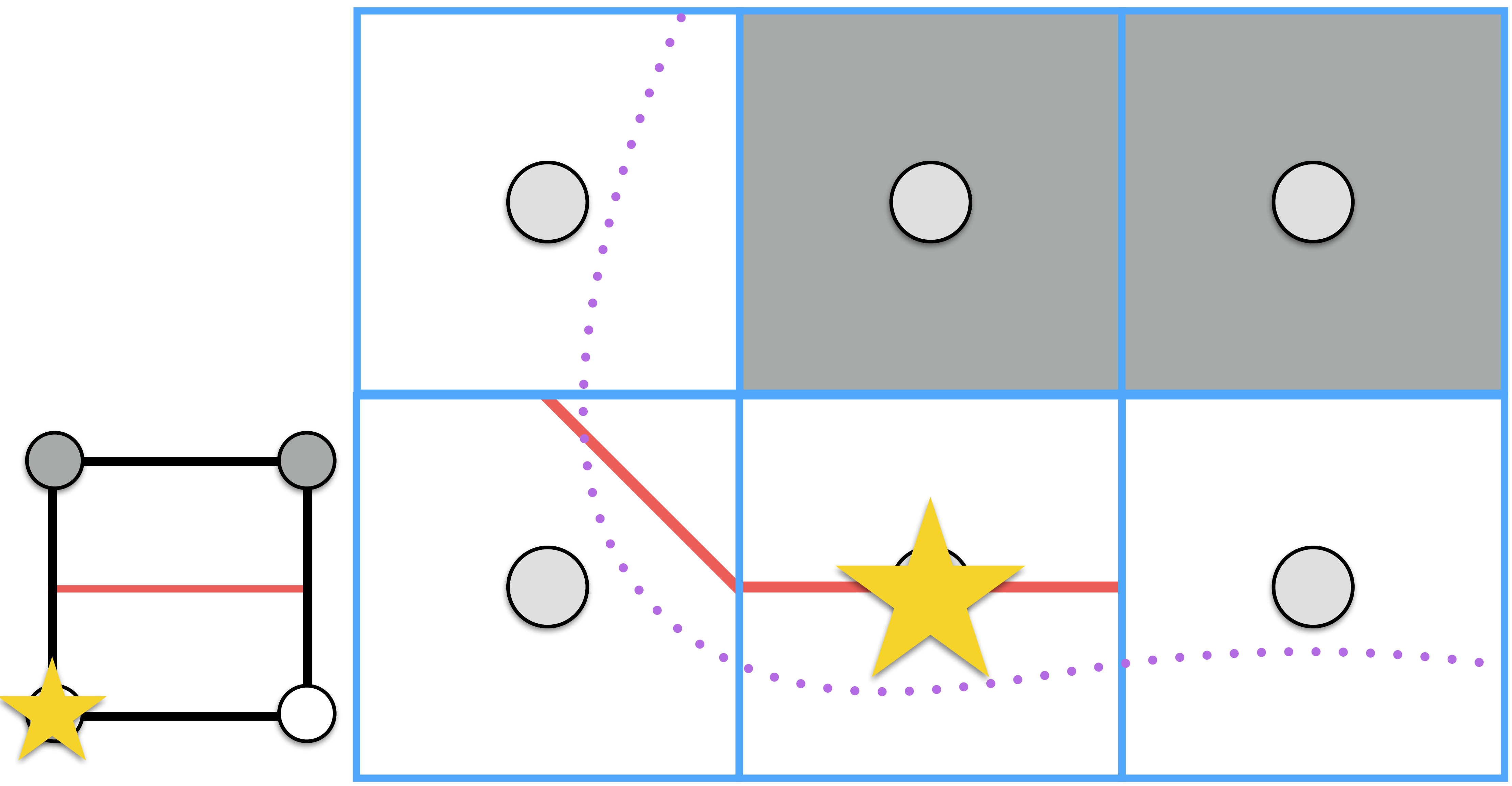
Marching Squares Example



Marching Squares Example



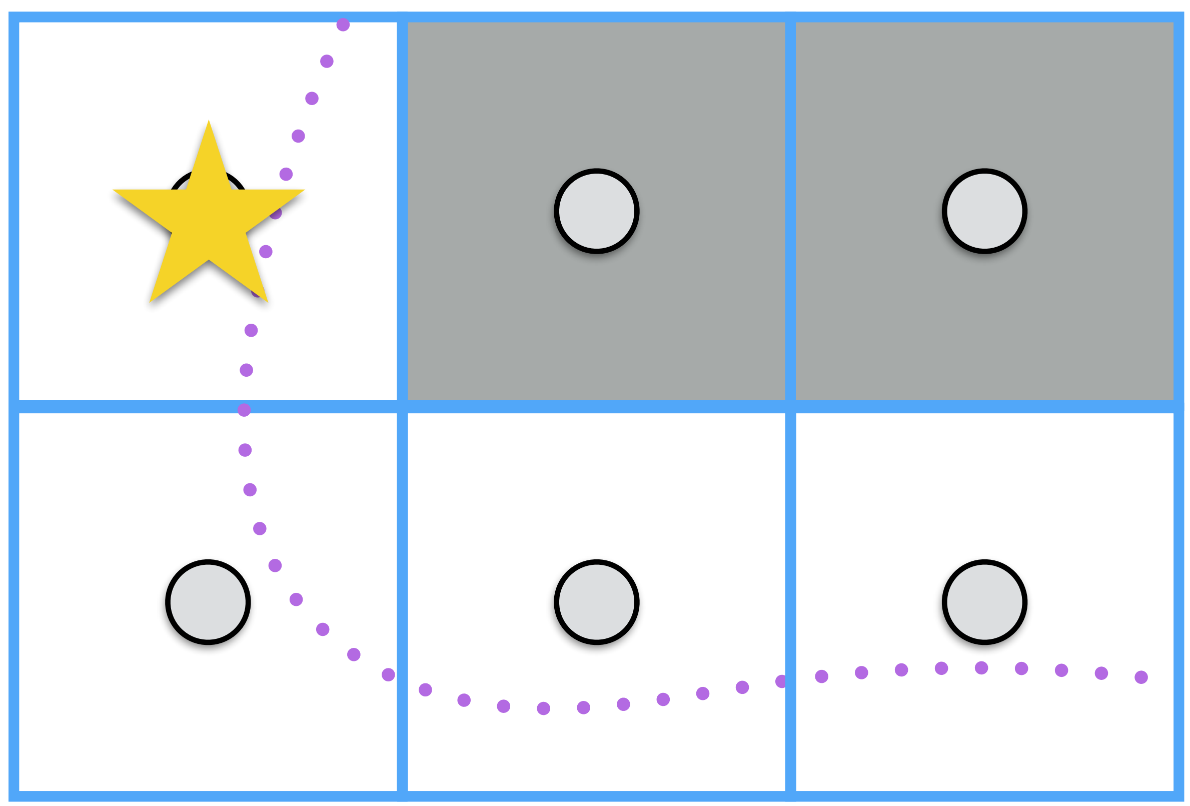
Marching Squares Example



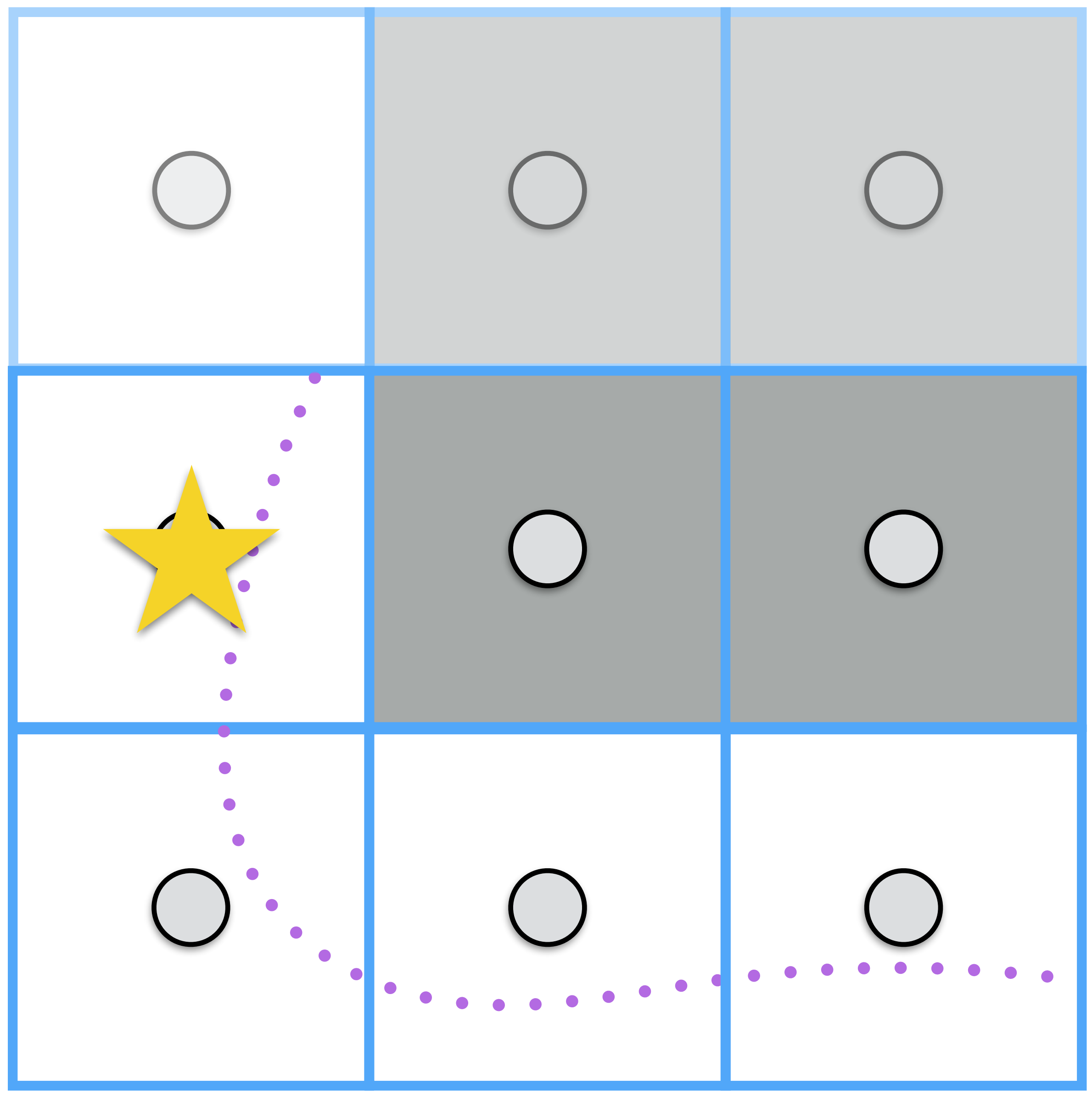
Marching Squares: Boundaries

- In theory, the object of our interest should be inside the volume without touching boundaries.
- However, we can have cases where the segmentation is touching boundaries!

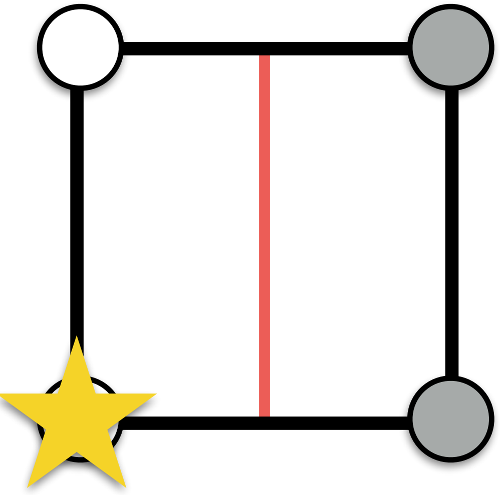
Marching Squares Boundaries Example

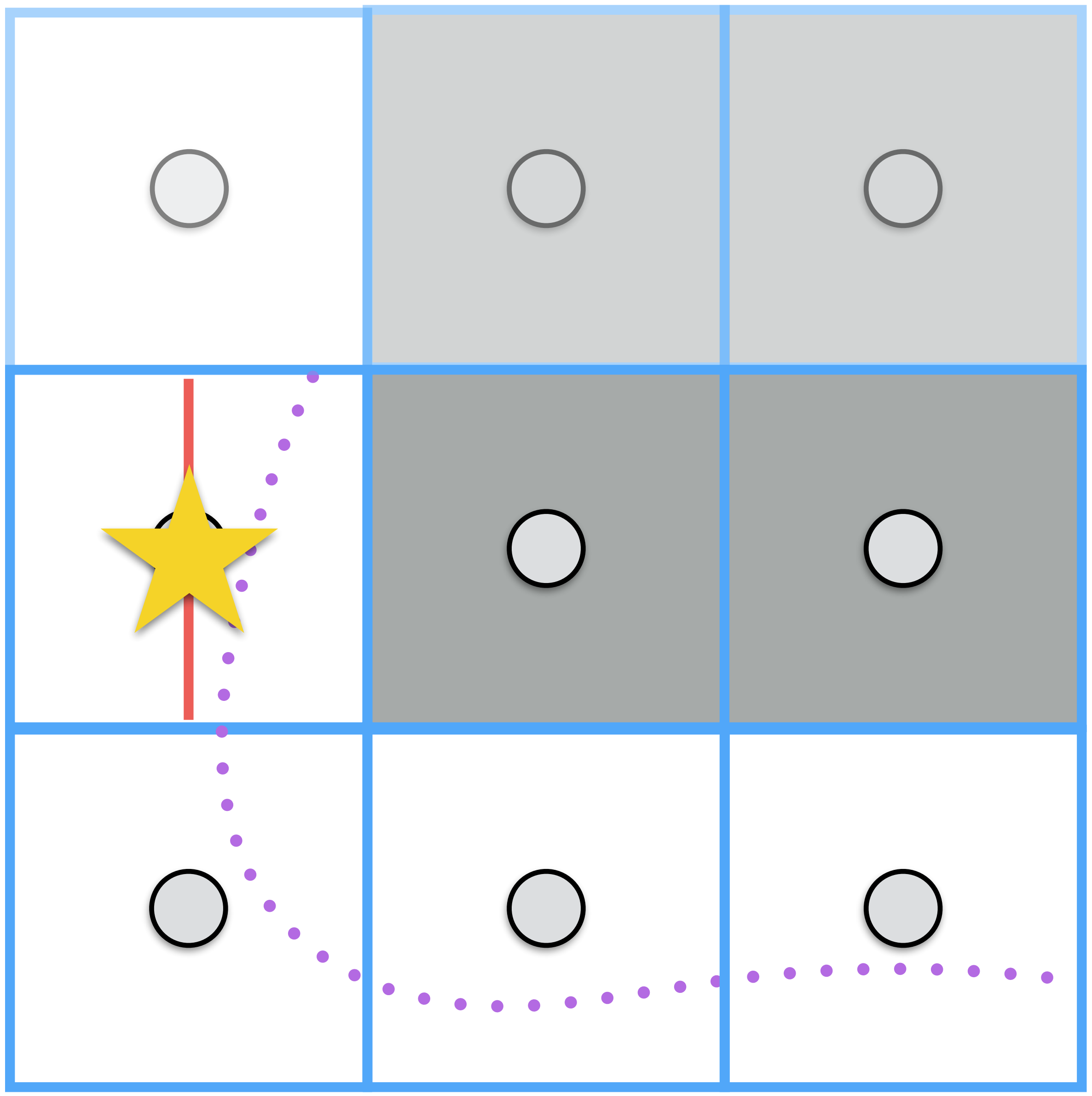


Marching Squares Boundaries Example

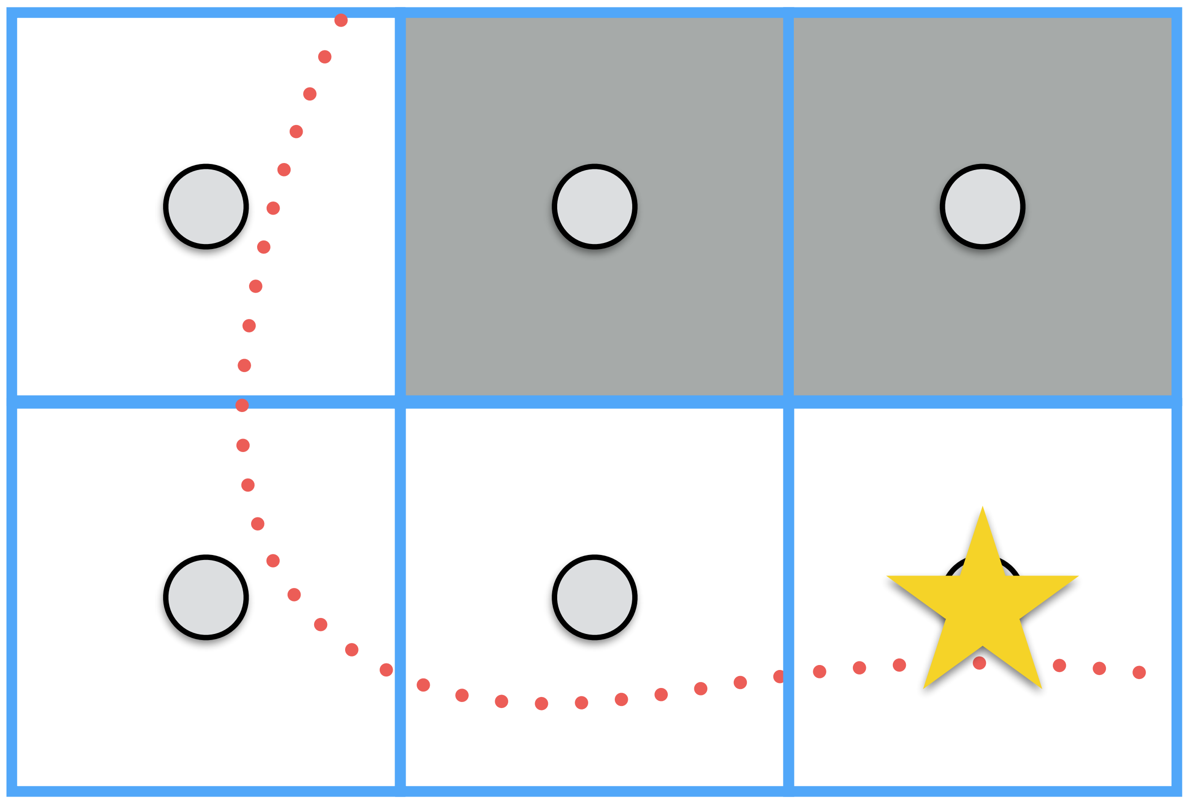


Marching Squares Boundaries Example

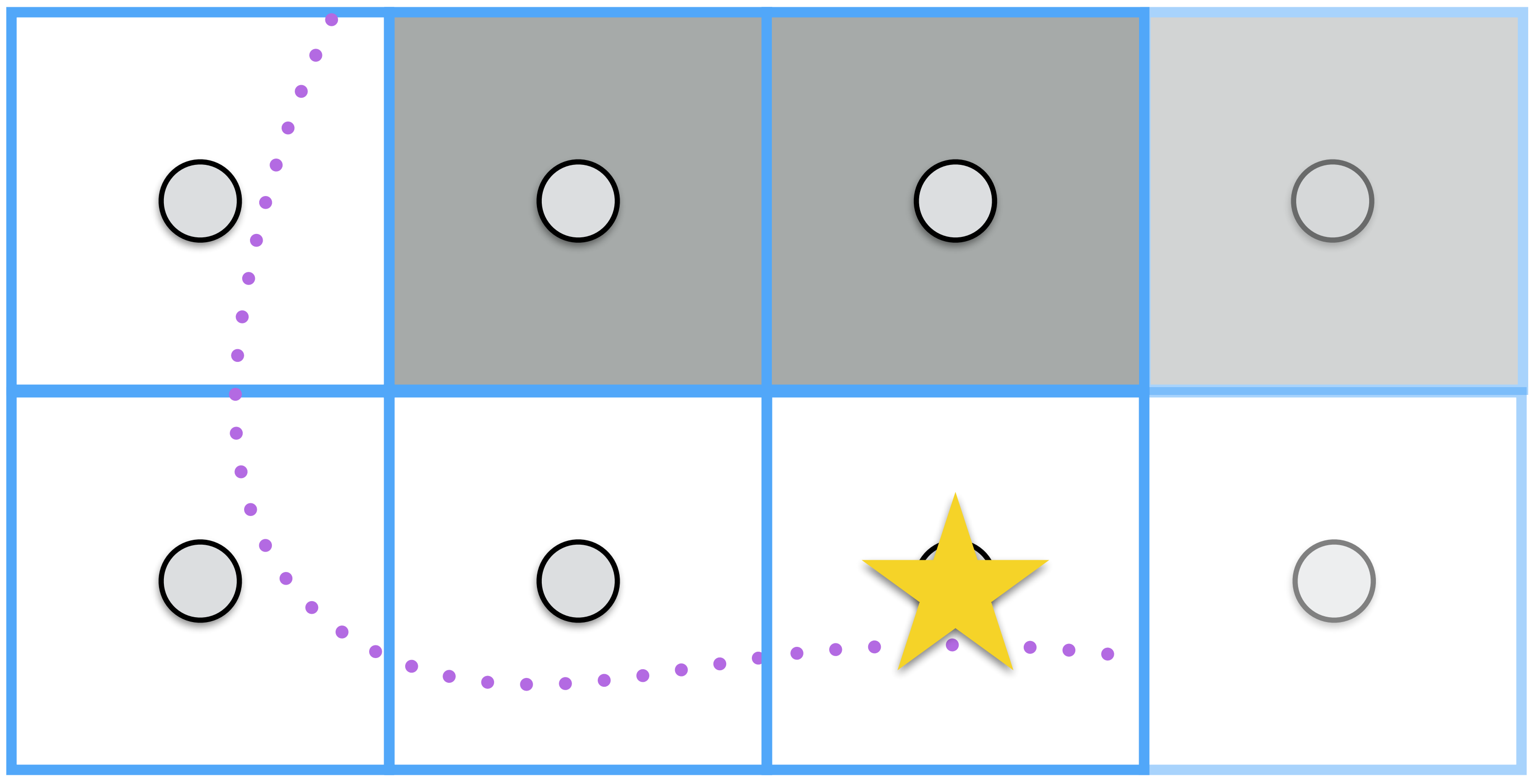




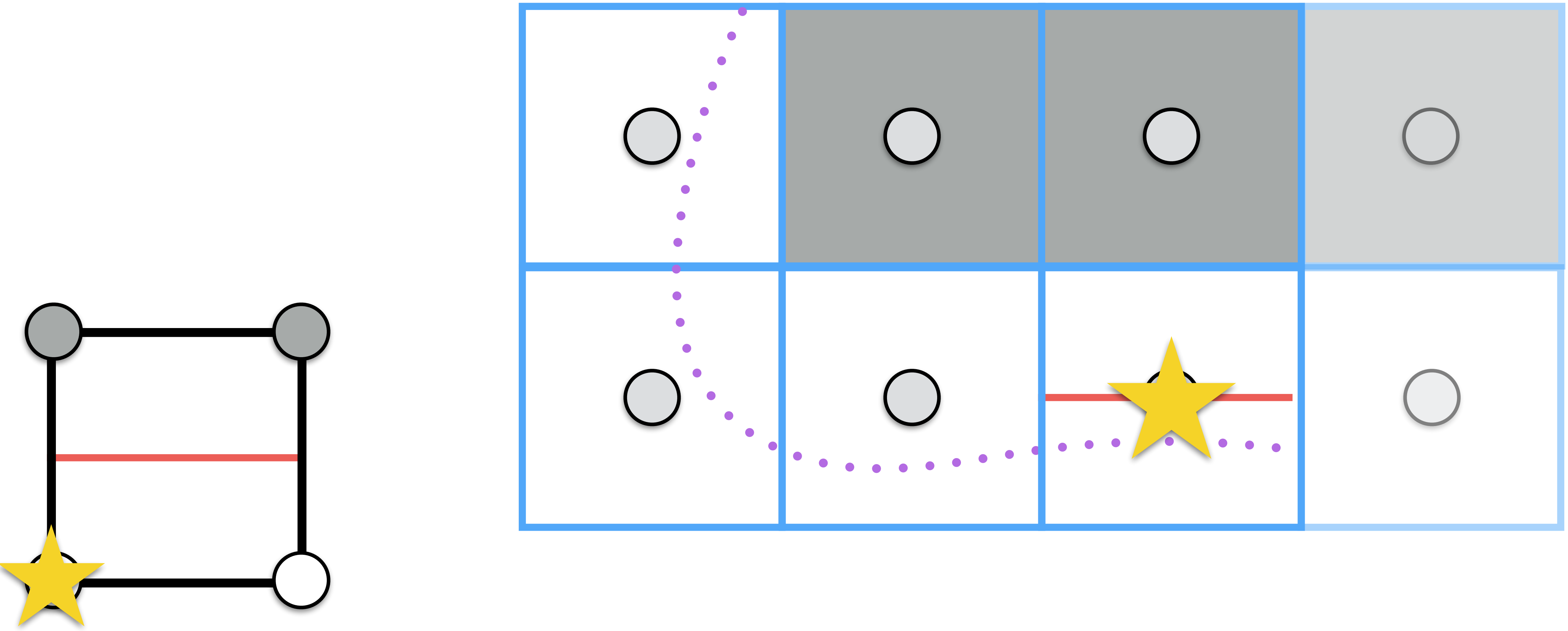
Marching Squares Boundaries Example



Marching Squares Boundaries Example



Marching Squares Boundaries Example



Marching Squares: Boundaries

- For these cases, we can set different politics:
  - We do not process boundaries, so we cut out part of the information
  - We replicate information from previous scan

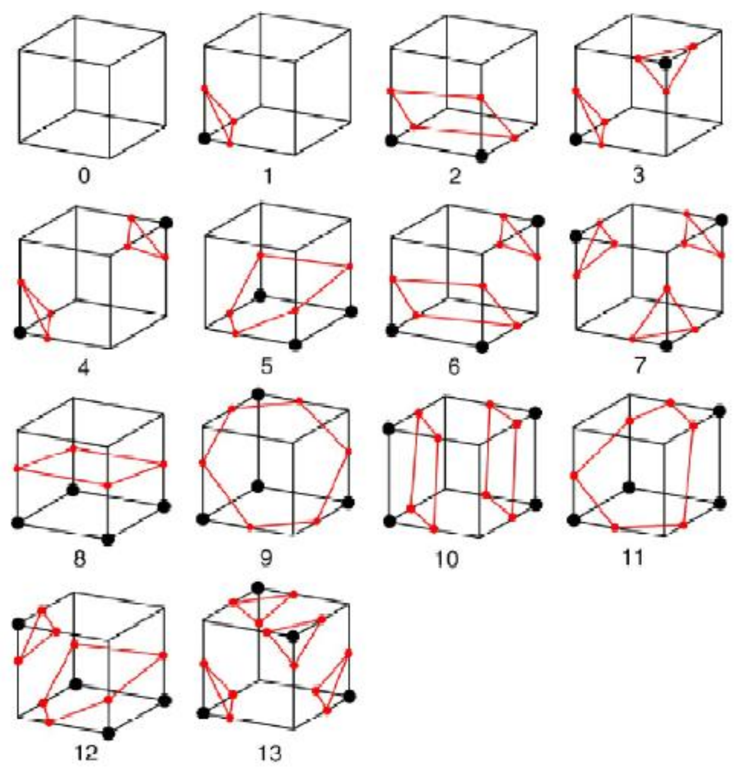
Let's move into the 3D world

Marching Cubes

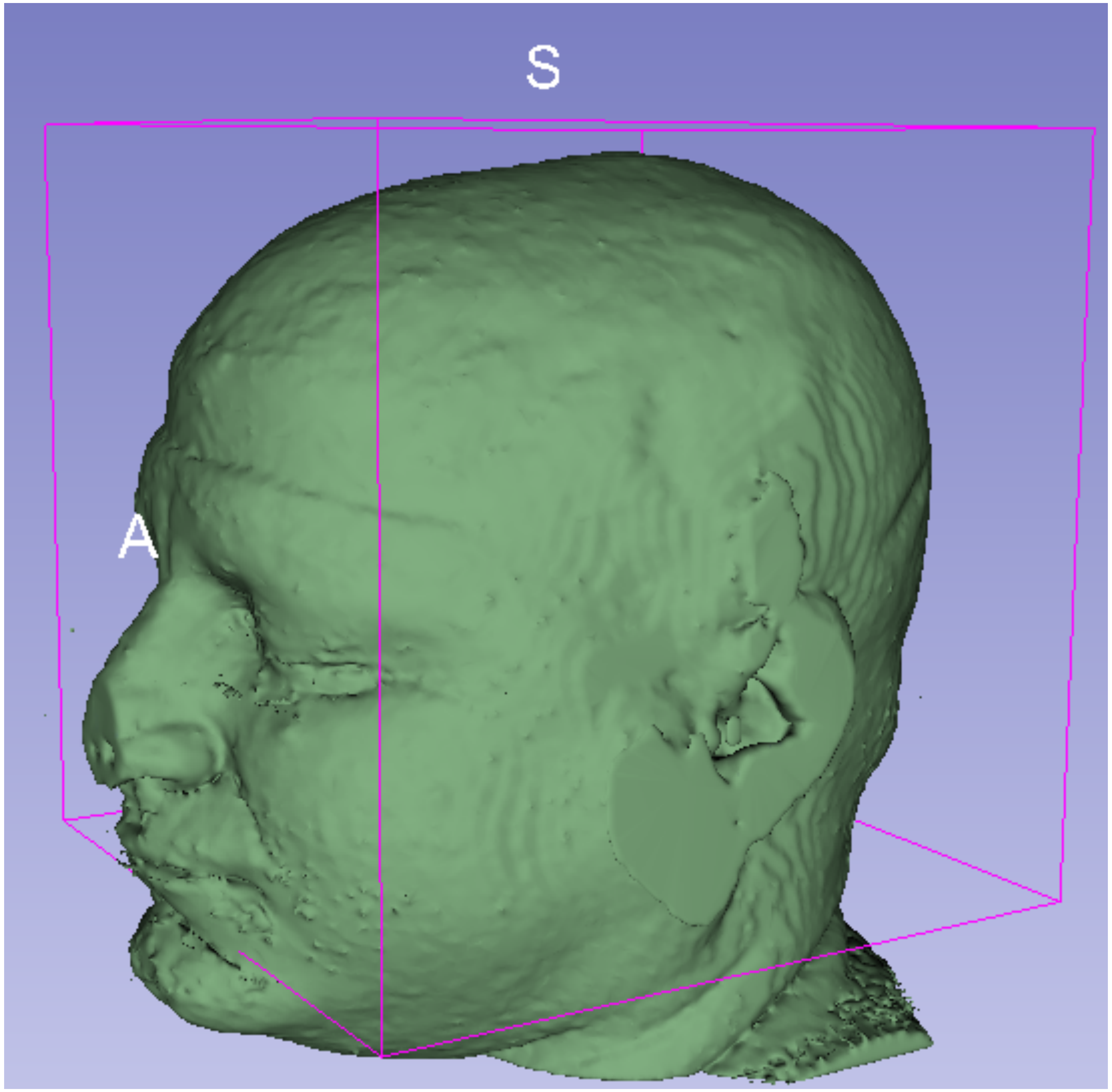
- 1st pass: as in the 2D cases, we need to mark which part of the volume is the inside (1) or the outside (0).
- 2nd pass: for each voxel, we need to find out the current configuration and to look up into a table to place ***triangles***!

Marching Cubes

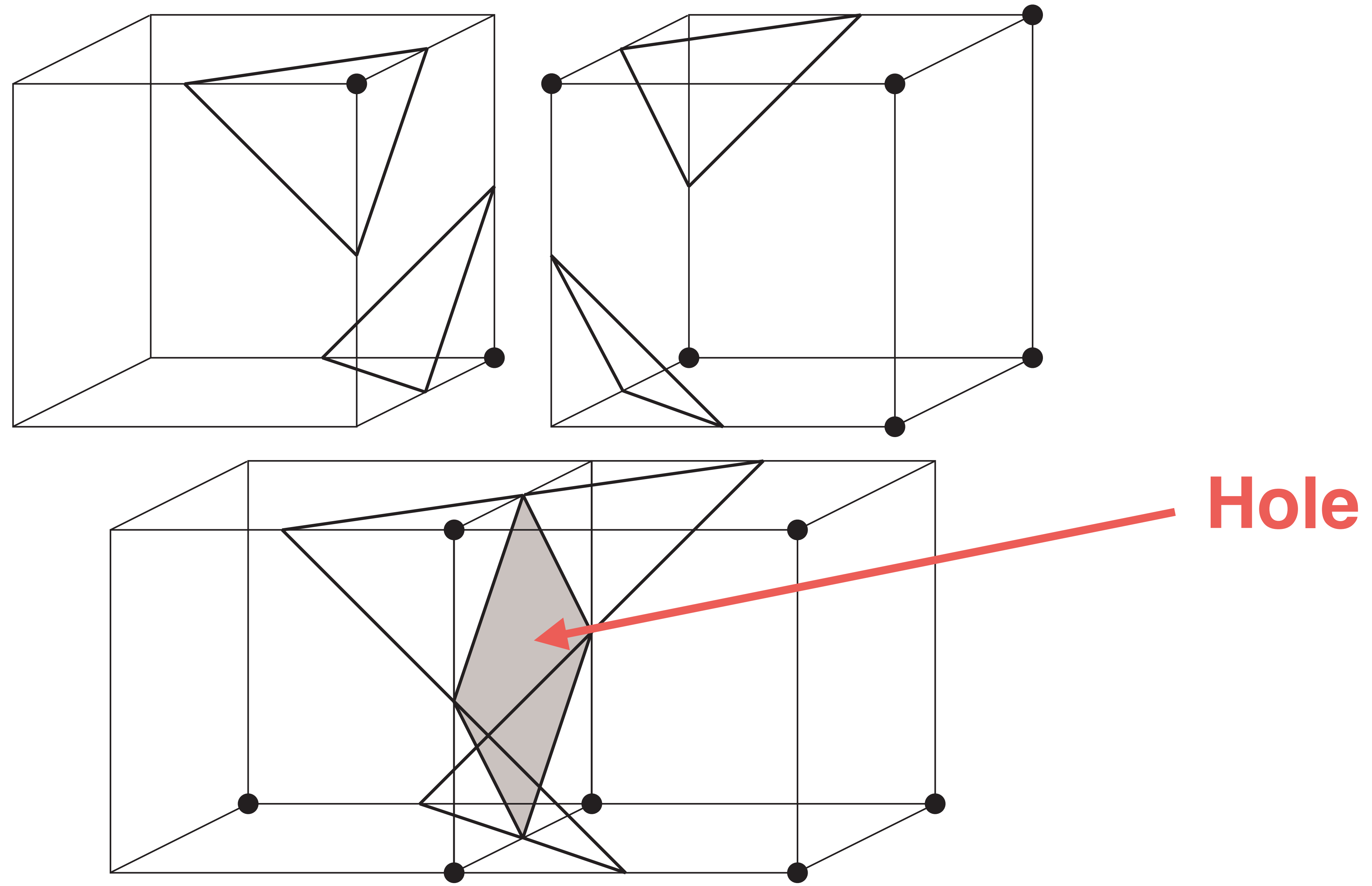
- In 3D the look up table has 256 entries (2^8).
- However, there are only 14 main cases (others are computed by reflecting and/or rotating these):



Marching Cubes



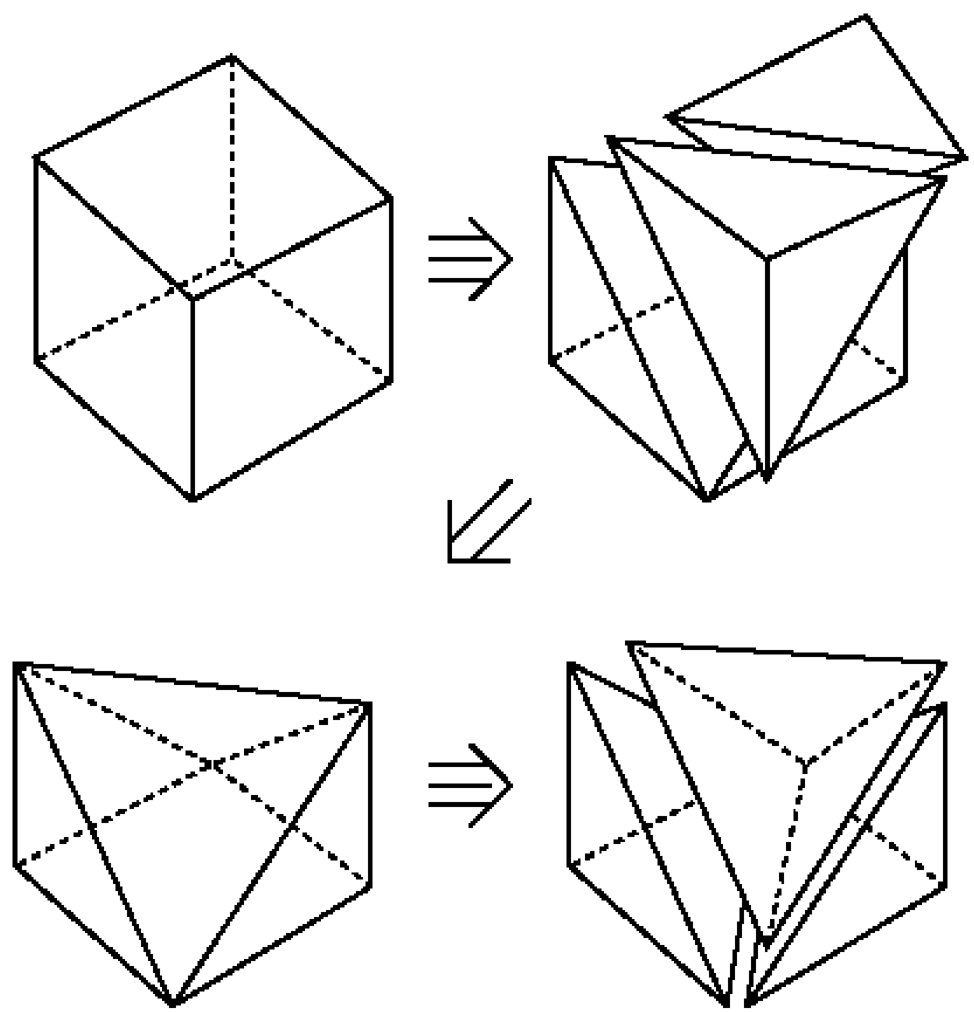
Marching Cubes: Ambiguous Cases



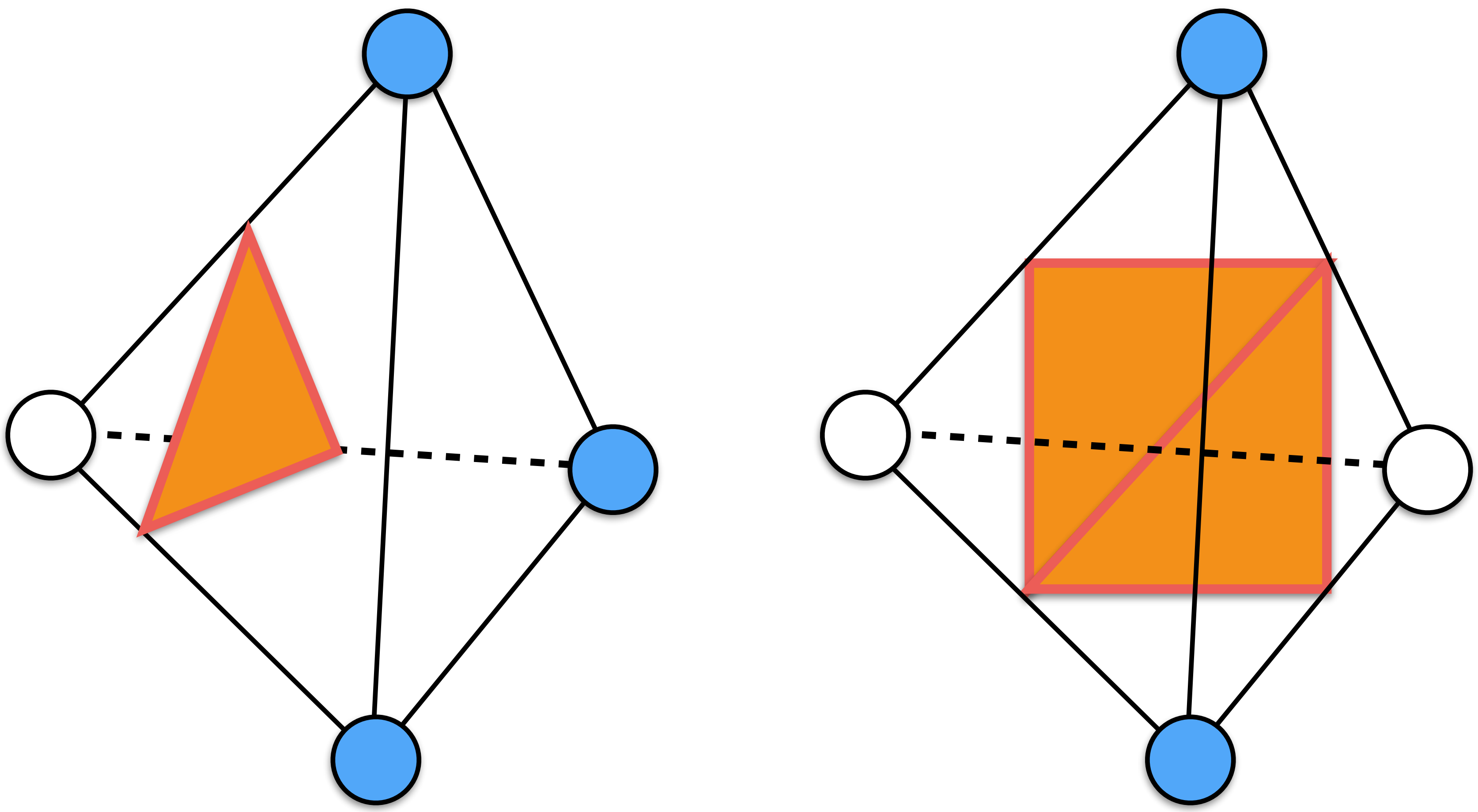
[Cignoni et al. 1999]

Marching Cubes: Ambiguous Cases

- A solution, which avoids ambiguous cases, is to partition each voxel/cell into tetrahedra; e.g. 5 or 6 of them.



Marching Cubes: Ambiguous Cases



Marching Cubes

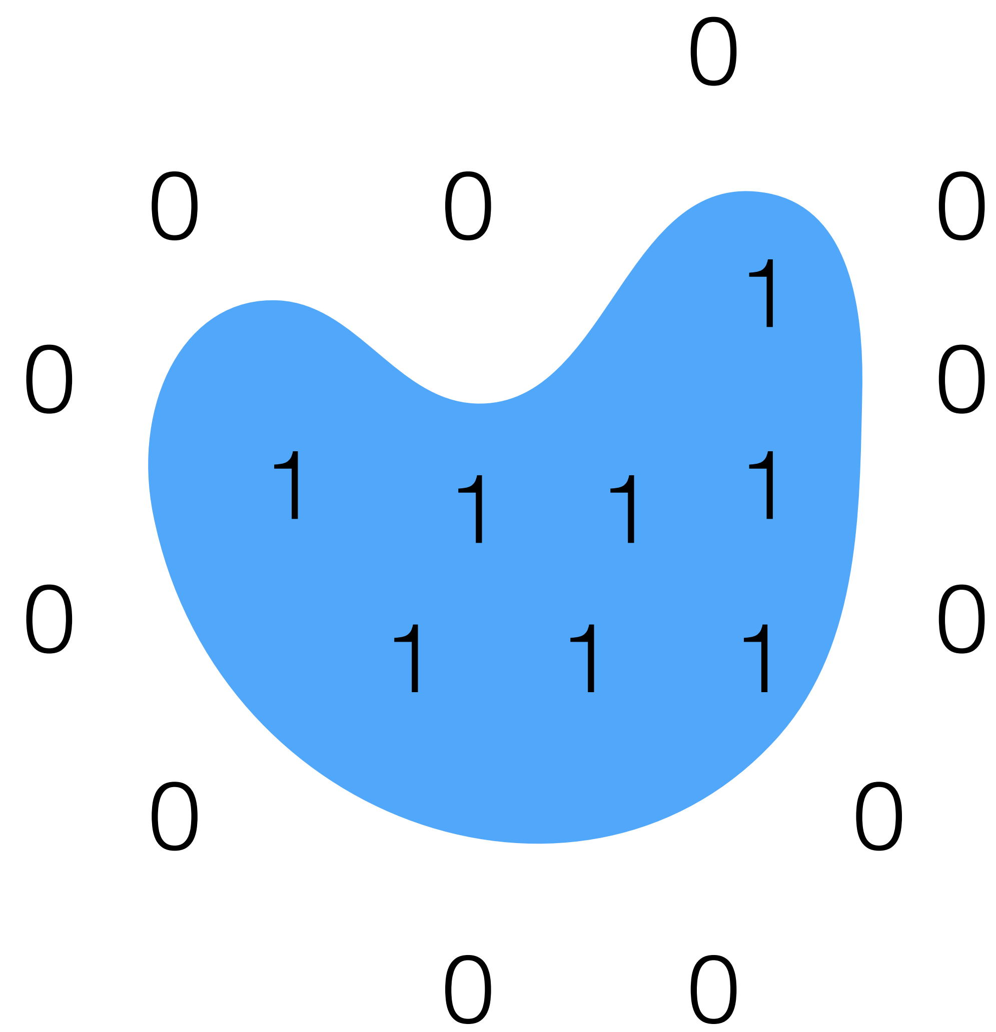
- Advantages:
  - Easy to understand and to implement
  - Fast and non memory consuming
- Disadvantages:
  - Consistency: C_0 and manifold result?
    - Ambiguous cases!
  - Mesh complexity: the number of triangles does not depend on the shape but on the discretization, i.e., number of voxels!
  - Mesh quality: arbitrarily ugly triangles

Poisson Reconstruction

Poisson Reconstruction

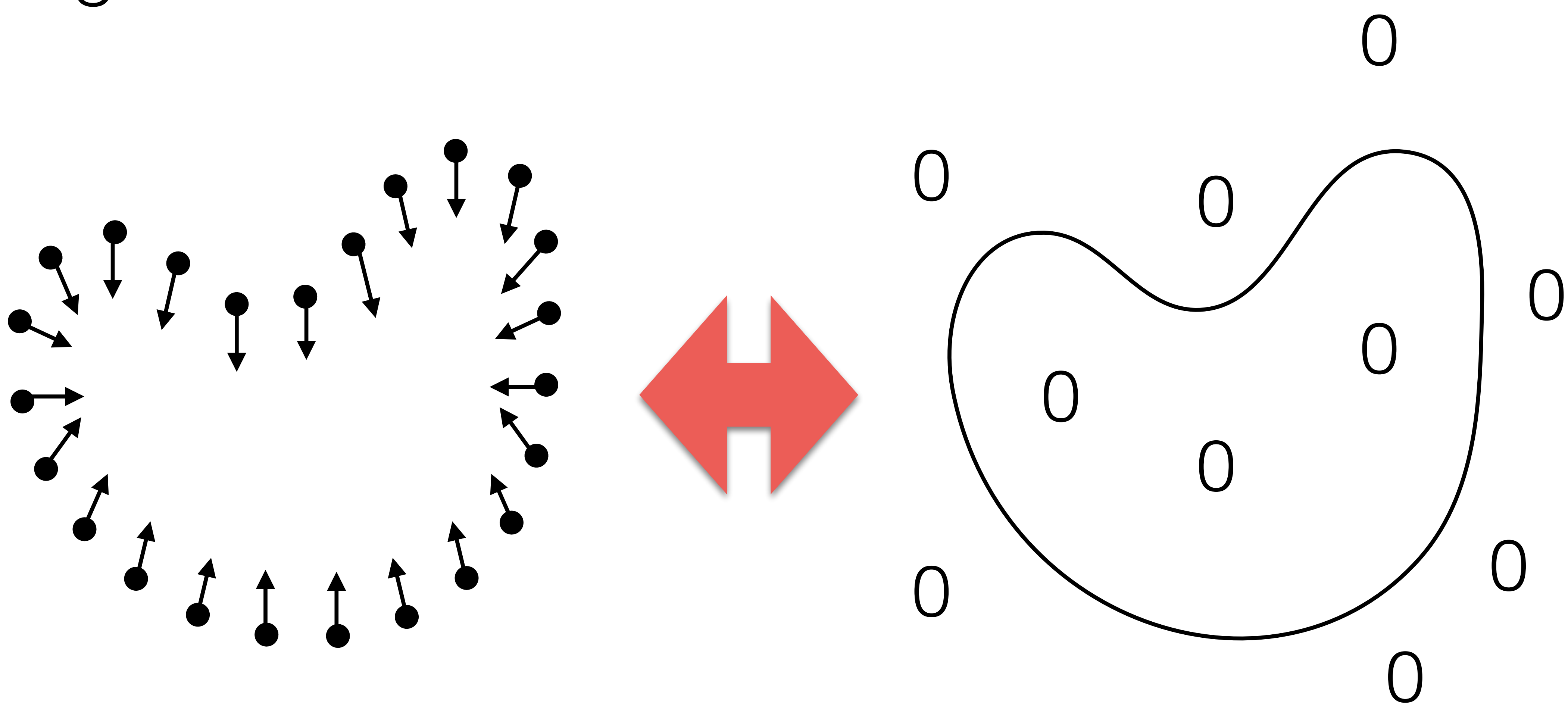
- The idea of this method is to reconstruct the surface of a 3D model by solving for the indicator function of the shape:

$$\chi(\mathbf{p}) = \begin{cases} 1 & \text{if } \mathbf{p} \in M, \\ 0 & \text{otherwise.} \end{cases}$$



Poisson Reconstruction: Gradient Relationship

- There is a relationship between the normal field and gradient of indicator function:



Oriented Points

Indicator function gradient

Poisson Reconstruction: Integration as a Poisson Problem

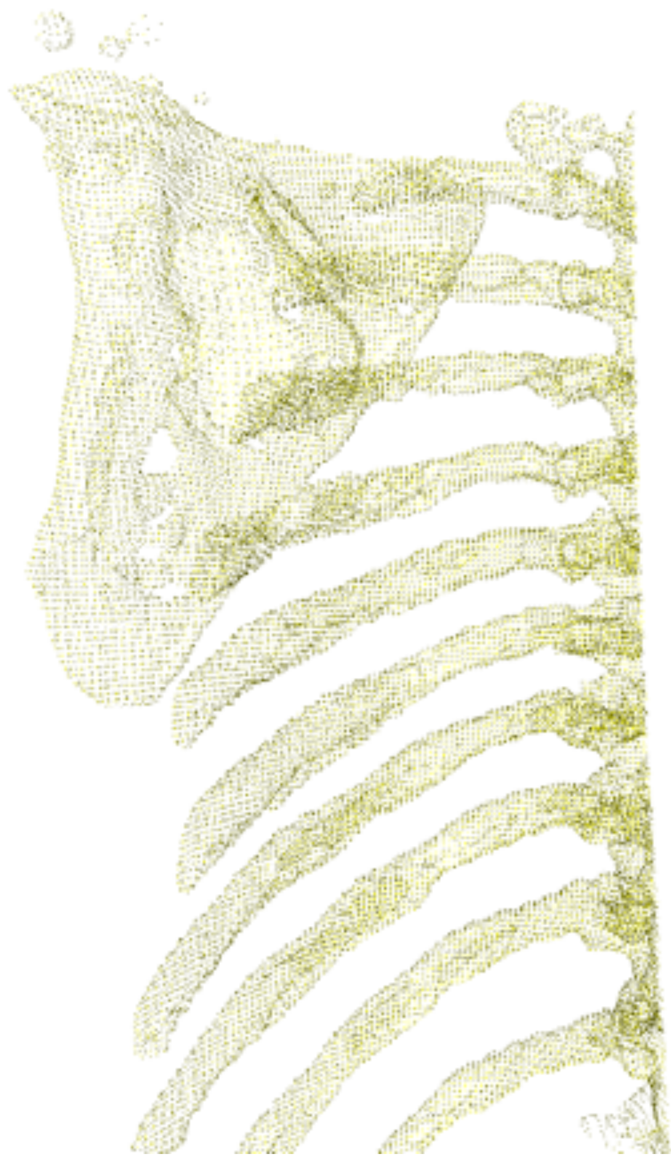
- Let's represent the points with a normal by a vector field $\vec{V}$.
- We need to find a function χ whose gradients best approximates $\vec{V}$:

$$\min_{\chi} \|\nabla \chi - \vec{V}\|$$

- If we apply the divergence operator, this becomes a Poisson problem:

$$\nabla \cdot (\nabla \chi) = \nabla \cdot \vec{V} \leftrightarrow \Delta \chi = \nabla \cdot \vec{V}$$

Poisson Reconstruction Example



3D Points

3D Surface

Poisson Reconstruction

- Advantages:
  - Precise
  - Robust
- Disadvantages:
  - Computationally slow, it depends on the resolution; i.e., it can take hours!
  - The Poisson solution needs to close the surface. If points density is not enough weird things may happen!

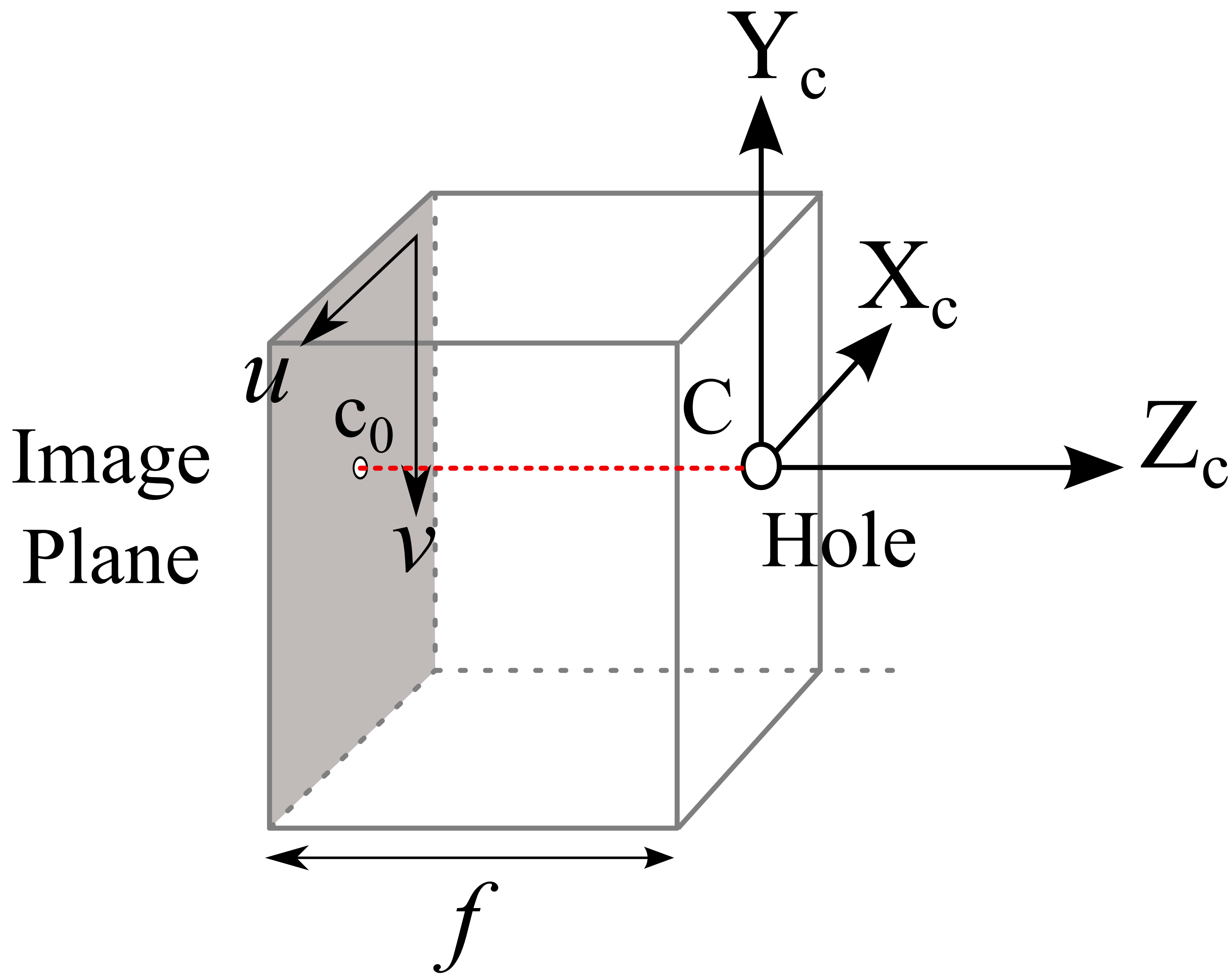
that’s all folks!

Acknowledgements

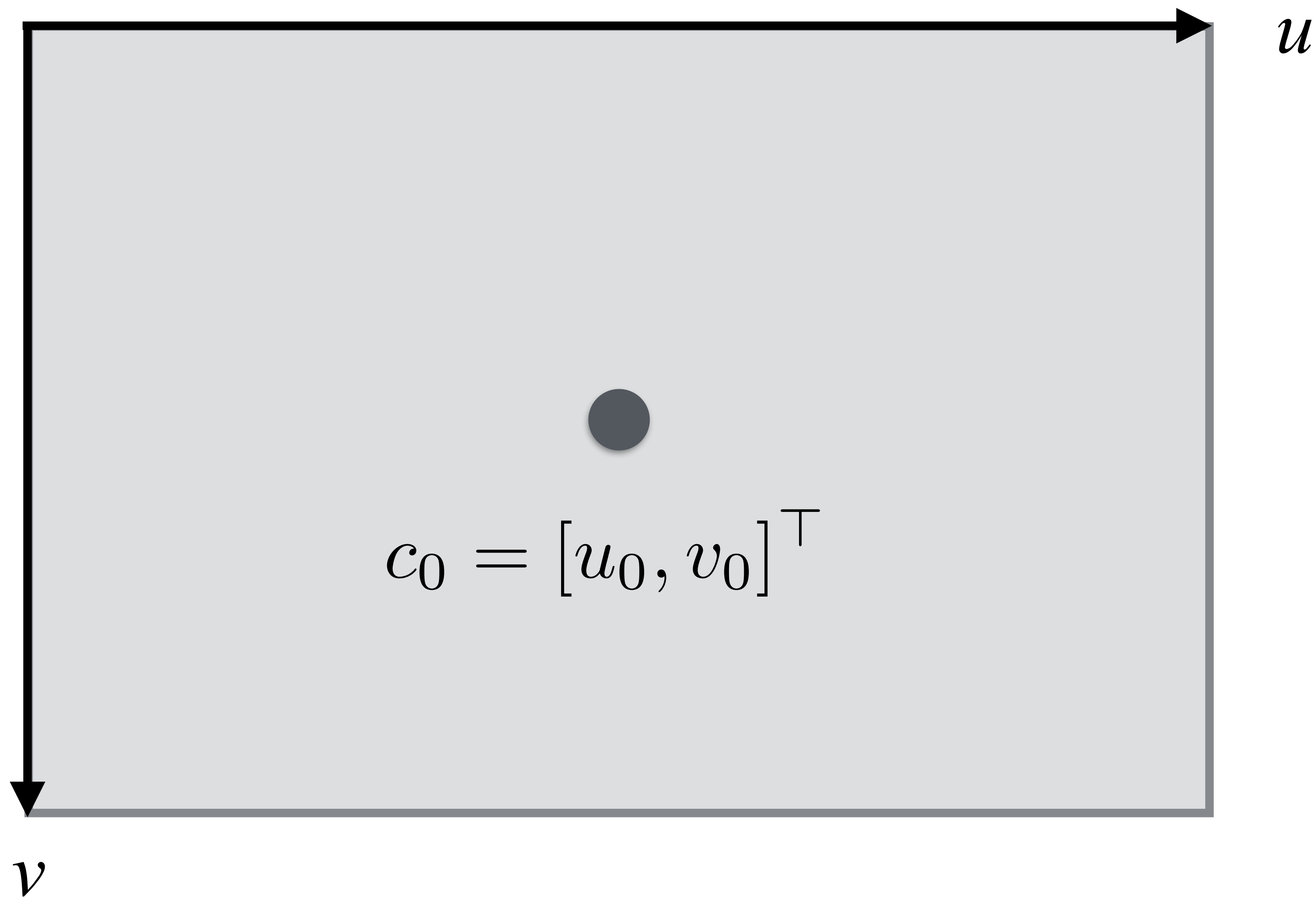
- Some images on work by:
  - Dr. Fabio Ganovelli:
    - http://vcg.isti.cnr.it/~ganovell/
  - Dr. Paolo Cignoni:
    - http://vcg.isti.cnr.it/~cignoni/

Appendix A: The Pin-hole Camera Model

Camera Model: Pinhole Camera

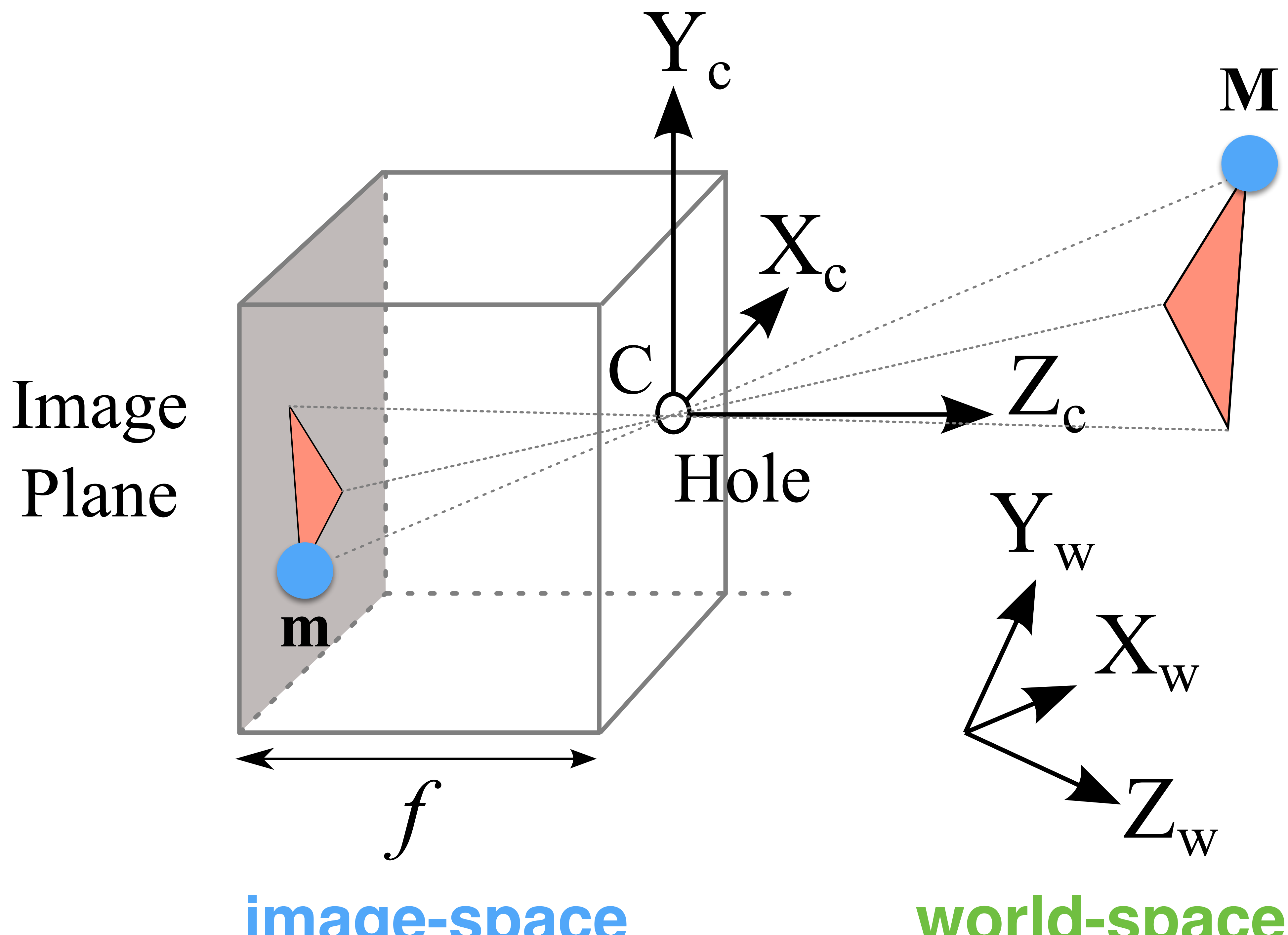


Camera Model: Image Plane



- Pixels are not square: height and width; i.e., (k_u, k_v).
- c_0 is the projection of C (the optical center) and its is called the principal point.

Camera Model: Pinhole Camera



Camera Model

- $\mathbf{M}$ is a point in the 3D world, and it is defined as:

$$\mathbf{M} = \begin{bmatrix} x \\ y \\ z \\ 1 \end{bmatrix}$$

- $\mathbf{m}$ is a 2D point, the projection of $\mathbf{M}$. $\mathbf{m}$ lives in the image plane UV:

$$\mathbf{m} = \begin{bmatrix} u \\ v \\ 1 \end{bmatrix}$$

Camera Model

- By analyzing the two triangles (real-world and projected one), the following relationship emerges:

$$\frac{f}{z} = -\frac{u}{x} = -\frac{v}{y}$$

- This means that:

$$\begin{cases} u = -\frac{f}{z} \cdot x \\ v = -\frac{f}{z} \cdot y \end{cases}$$

Camera Model: Intrinsic Parameters

- If we take all into account of the optical center, and pixel size we obtain:

$$\begin{cases} u = -\frac{f}{z} \cdot x \cdot k_u + u_0 \\ v = -\frac{f}{z} \cdot y \cdot k_v + v_0 \end{cases}$$

- If we put this in matrix form, we obtain:

$$P = \begin{bmatrix} -fk_u & 0 & u_0 & 0 \\ 0 & -fk_v & v_0 & 0 \\ 0 & 0 & 1 & 0 \end{bmatrix} = K[I|\mathbf{0}] \qquad K = \begin{bmatrix} -fk_u & 0 & u_0 \\ 0 & -fk_v & v_0 \\ 0 & 0 & 1 \end{bmatrix}$$

$$\mathbf{m}z = P \cdot \mathbf{M}$$

Camera Model: Extrinsic Parameters

- Note that K is called ***intrinsic matrix*** and has all projective properties of the camera.

- We need to define how the camera is placed (i.e., rotation and translation). This is described by the ***extrinsic matrix*** G:

$$G = \begin{bmatrix} R & \mathbf{t} \\ 0 & 1 \end{bmatrix} \qquad \mathbf{t} = \begin{bmatrix} t_1 \\ t_2 \\ t_3 \end{bmatrix} \quad R = \begin{bmatrix} \mathbf{r}_1^\top \\ \mathbf{r}_2^\top \\ \mathbf{r}_3^\top \end{bmatrix}$$

- R is a 3x3 rotation matrix, which is an orthogonal matrix with determinant 1.

- $\mathbf{t}$ is translation vector with three components.

Camera Model

- The full camera model including the camera pose is defined as:

$$P = K[I|\mathbf{0}]G = K[R|\mathbf{t}]$$

- P is 3x4 matrix with 11 independent parameters!

Appendix B:
From Pixels to Rays

Rendering: Ray Creation

- We need to create a ray r with an origin and a direction:
    - Origin is set to C; the center of the virtual camera:

$$\mathbf{o} = \mathrm{C}$$

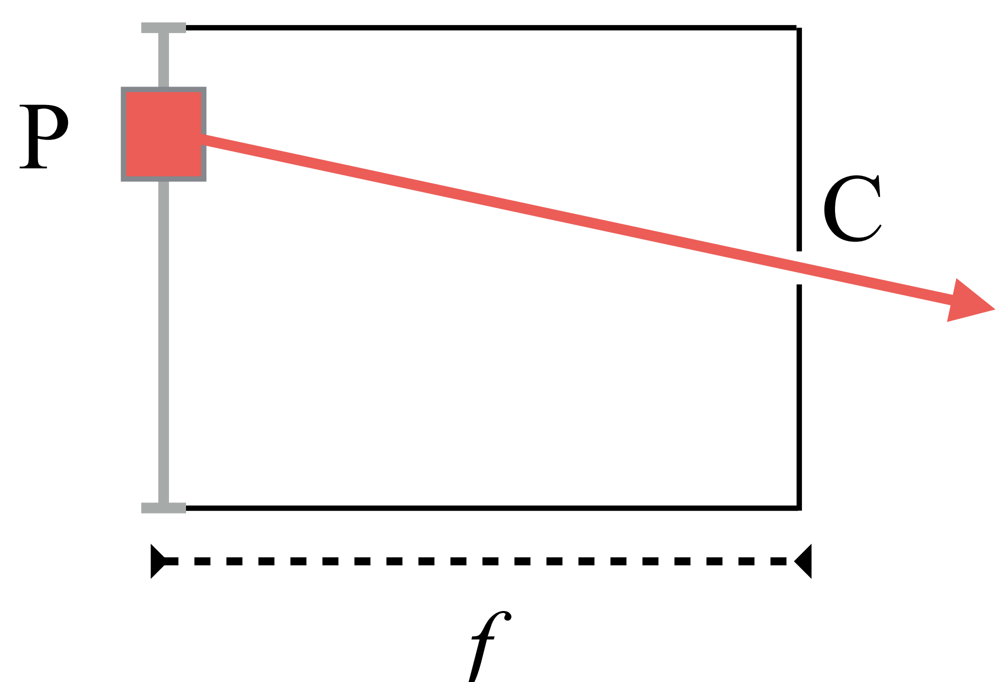
    - This is because the ray has to pass through it!

Rendering: Ray Creation

- Given a pixel coordinates (u, v), we need to compute the 3D point P inside the camera by inverting:

$$\begin{cases} u = -\frac{f}{z} \cdot x \cdot k_u + u_0 \\ v = -\frac{f}{z} \cdot y \cdot k_v + v_0 \end{cases}$$

- knowing z is set to f.



Rendering: Ray Creation

- Therefore, the point P is:

$$P = \begin{bmatrix} x \\ y \\ z \\ 1 \end{bmatrix} = \begin{bmatrix} \frac{(u-u_0)}{k_u} \\ \frac{(v-v_0)}{k_v} \\ -f \\ 1 \end{bmatrix}$$

- and, the ray direction is simply computed as:

$$\vec{d} = \frac{C - P}{\|C - P\|}$$

Appendix C:
Ray-Volume Boundary Intersection

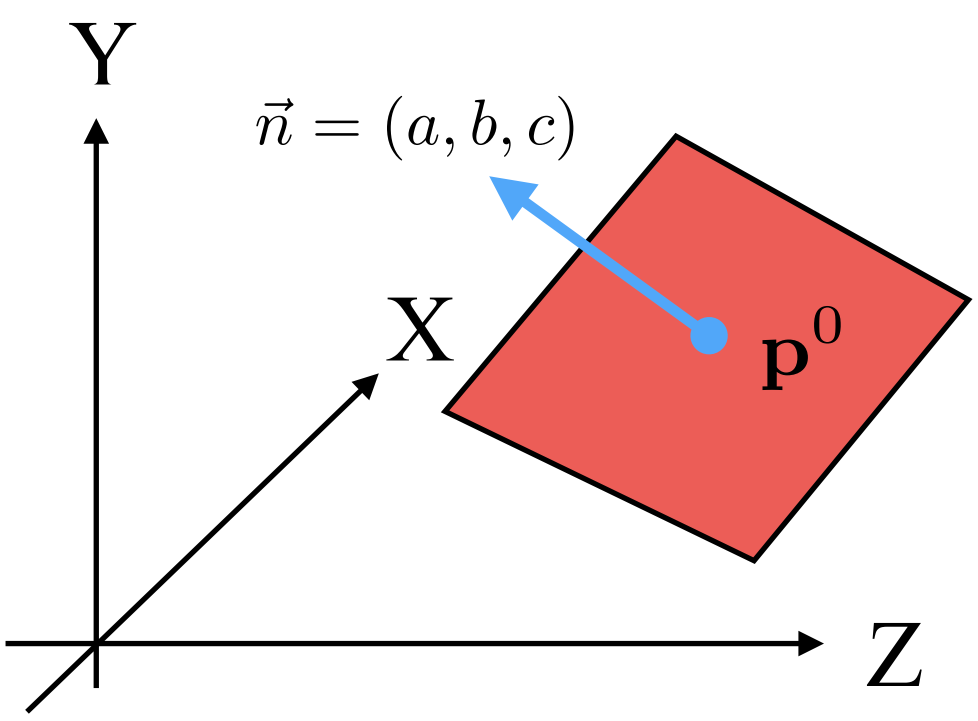
Ray-Box Intersection

- As the first step, we need to find the intersection ray-box. The volume boundary is just a box!
- We know that a box has six faces; i.e., planes:
  - We need to check intersection against six planes

Rendering: Ray-Plane Intersection

- A plane is defined by its normal (a, b, c) and a shift parameter (D):

$$a \cdot x + b \cdot y + c \cdot z + D = 0$$



$$D = -a \cdot p^0_x - b \cdot p^0_y - c \cdot p^0_z$$

Rendering: Ray-Plane Intersection

- We need to solve the system:

$$\begin{cases} \mathbf{p}(t) = \mathbf{o} + \vec{d} \cdot t \qquad t > 0 \\ a \cdot p_x + b \cdot p_y + c \cdot p_z + D = 0 \end{cases}$$

Its solution is

$$\vec{v} = \mathbf{p}^0 - \mathbf{o}$$

$$t = \frac{\vec{v} \cdot \vec{n}}{\vec{n} \cdot \vec{d}} \qquad (\vec{n} \cdot \vec{d}) > 0$$