Optimal trees and forests

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Todays lecture

- Trees and forests
- Optimal forests
  - Minimum spanning forests
  - Shortest path forests
- Applications in image segmentation

Part 1: Forests and trees

Forests and trees

In this lecture, we will consider two special types of graphs: *forests* and *trees*.

- A forest is a graph without simple cycles.
- A tree is a connected forest

(In other words, a forest is a collection of trees)

Recall: Cycles, connected graphs

- A *cycle* is a path where the start vertex is the same as the end vertex.
- A cycle is *simple* if it has no repeated vertices other than the endpoints.
- Two vertices $v, w \in V$ are *linked* if G contains a path from v to w.
- A graph is *connected* if every pair of vertices on the graph is linked.

Tree, example

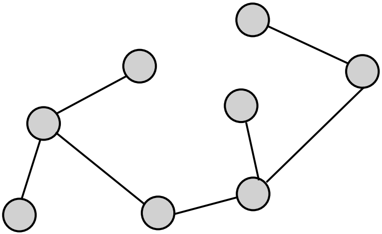

Figure 1: Left: A tree. Right: Not a tree.

Cuts

- Informally a *cut* is a set of edges that, when removed from the graph, separate the graph into two or more connected components. We can think of a cut as a boundary between regions.
- Let $S \subseteq E$, and $G' = (V, E \setminus S)$. If, for all $e_{v,w} \in S$, it holds that $v \underset{G'}{\not\sim} w$, then S is a *cut* on G.

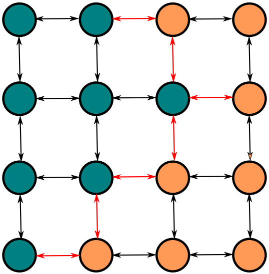

Figure 2: A set of edges (red) forming a cut.

Properties of trees and forests

- There is a *unique* path between each (linked) pair of vertices. *Why?*
- Any subset of the edges of a forest is a cut. *Why?*

Spanning trees

Definition, spanning tree

Let G be a connected, undirected graph. Let T be a subgraph of G such that

- T is a tree.
- $V(T) = V(G)$.

Then T is a *spanning tree* of G.

For any G, there exists at least one spanning tree. *Why?*

Edge weighted graphs

- We associate each edge $e \in E$ with a real valued, non-negative *weight*, $w(e)$.
- The weight of an edge represents the dissimilarity (or, alternatively, similarity) between the vertices connected by the edge.
- For example, we may define the edge weights as

$$w(e_{ij}) = |I(v) - I(j)| \,, \tag{1}$$

where $I(v)$ is the intensity of the image element corresponding to v.

Part 2: Minimum spanning trees

Minimum spanning trees

- A graph can have many different spanning trees. A *minimum spanning tree* (MST) is a spanning tree $T = (V, E')$ that (globally) minimizes

$$f(T) = \sum_{e \in E'} w(e) \; . \qquad (2)$$

- Although this is a global optimization problem, efficient algorithms for computing minimum spanning trees exist. We will now take a look at two such algorithms: Prim's algorithm [7] and Kruskal's algorithm [6].

Kruskal's algorithm

Kruskal's algorithm

Set $E_{new} = \emptyset$.
while *there exists an edge* $e_{p,q}$ *such that* $p \underset{(V,E_{new})}{\not\sim} g$ **do**
| Choose such an edge with minimal weight and add it to E_{new}.
end

- At the termination of the algorithm, (V, E_{new}) is a MST on G.

Kruskal's algorithm, example

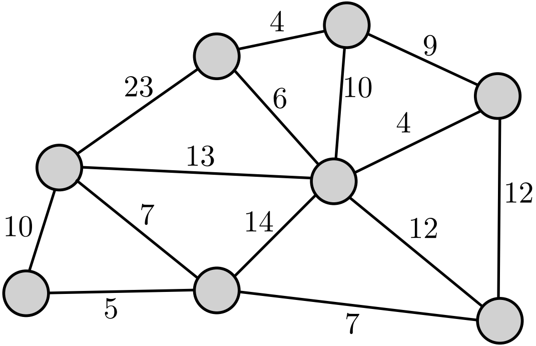

Figure 3: An edge weighted graph.

Kruskal's algorithm, example

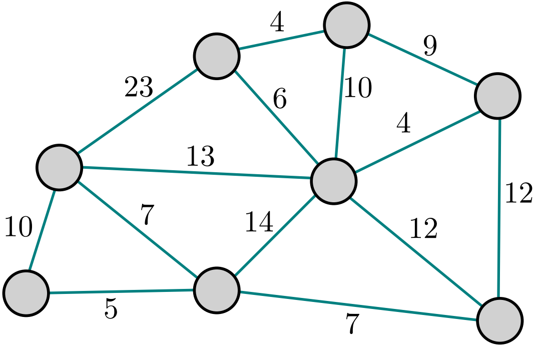

Figure 4: Choose an edge with minimal weight that does not form a cycle.

Kruskal's algorithm, example

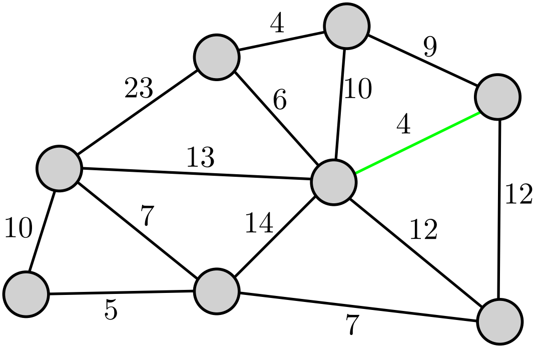

Figure 5: Add this edge to the tree.

Kruskal's algorithm, example

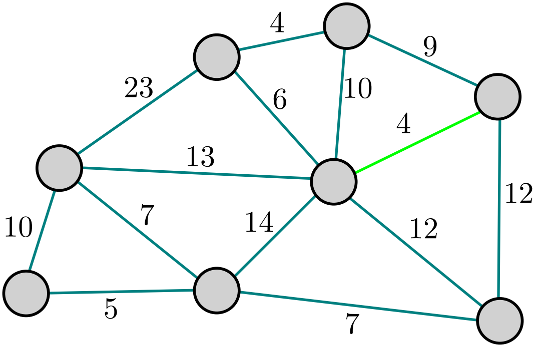

Figure 6: Choose an edge with minimal weight that does not form a cycle.

Kruskal's algorithm, example

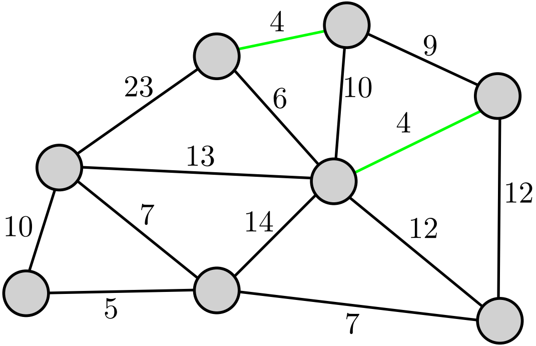

Figure 7: Add this edge to the tree.

Kruskal's algorithm, example

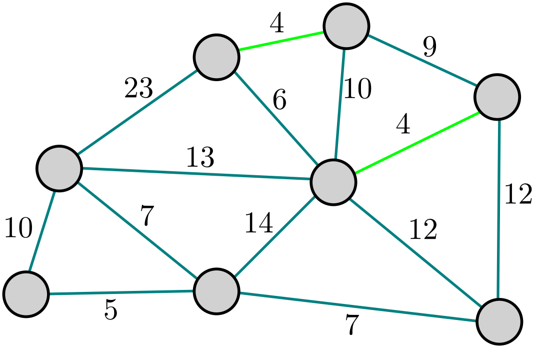

Figure 8: Choose an edge with minimal weight that does not form a cycle.

Kruskal's algorithm, example

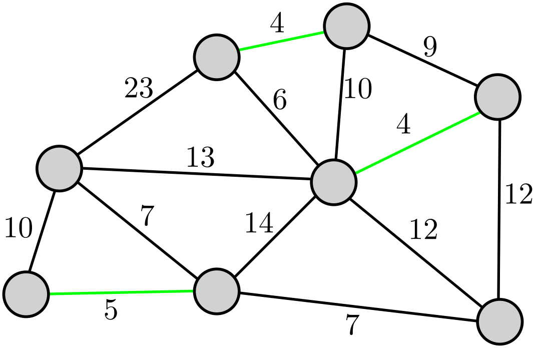

Figure 9: Add this edge to the tree.

Kruskal's algorithm, example

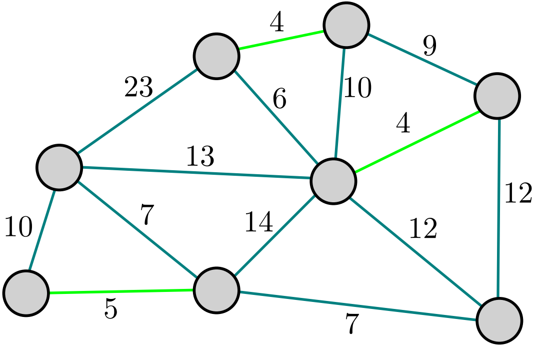

Figure 10: Choose an edge with minimal weight that does not form a cycle.

Kruskal's algorithm, example

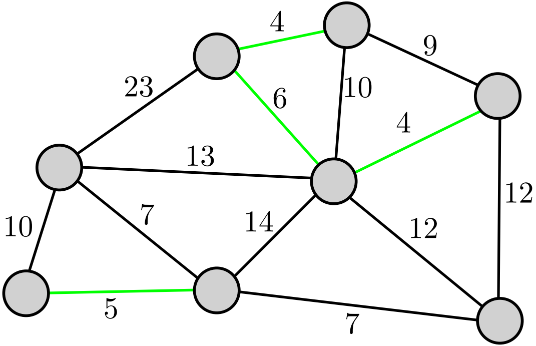

Figure 11: Add this edge to the tree.

Kruskal's algorithm, example

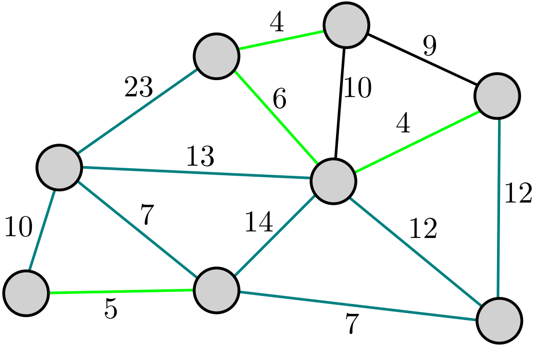

Figure 12: Choose an edge with minimal weight that does not form a cycle.

Kruskal's algorithm, example

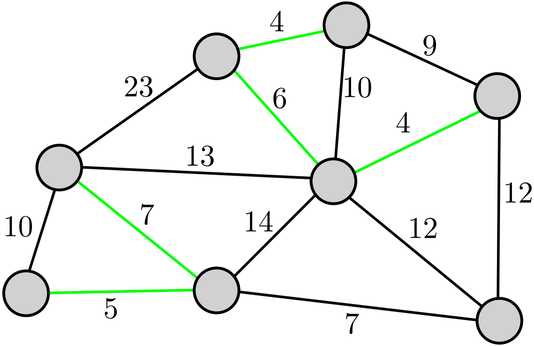

Figure 13: Add this edge to the tree.

Kruskal's algorithm, example

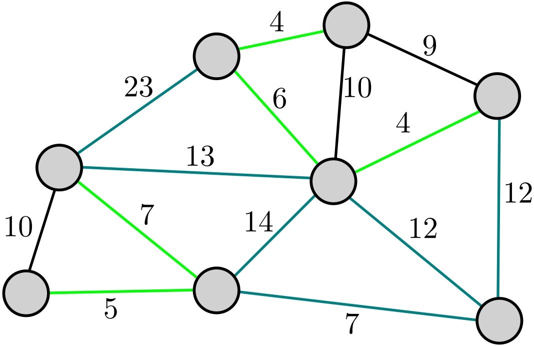

Figure 14: Choose an edge with minimal weight that does not form a cycle.

Kruskal's algorithm, example

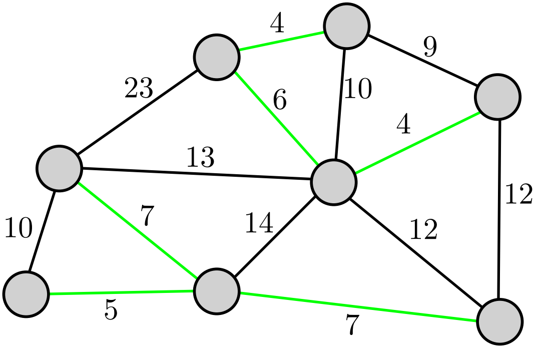

Figure 15: Add this edge to the tree.

Kruskal's algorithm, example

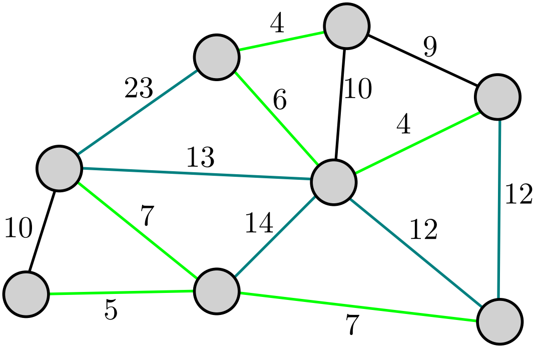

Figure 16: Choose an edge with minimal weight that does not form a cycle.

Kruskal's algorithm, example

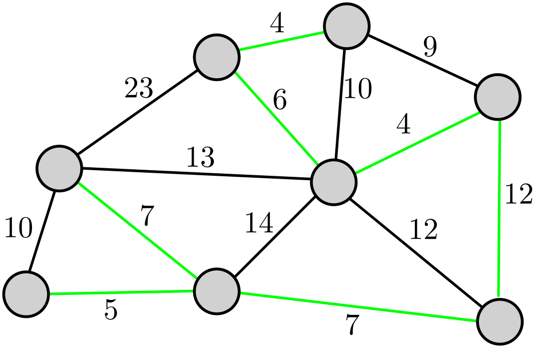

Figure 17: Add this edge to the tree.

Kruskal's algorithm, example

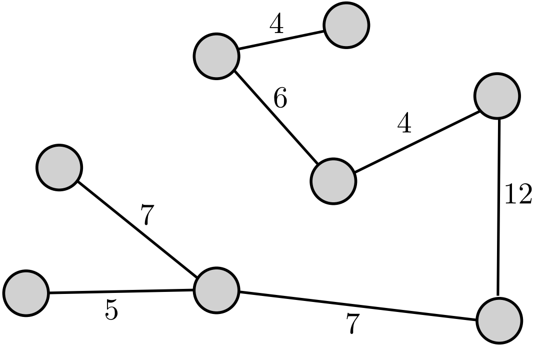

Figure 18: The tree is spanning. The algorithm terminates.

Implementing Kruskal's algorithm

- Kruskal's algorithm can be shown to run in $O(E \log V)$ time.
- By pre-sorting the edges by weight, the step "Choose such an edge with minimal weight" can be performed in constant time.
- To keep track of which vertices are in which components, a *disjoint-set data structure* can be used. This data structure allows efficient implementation of the following operations:
  - *Find:* Determine which subset a particular element is in. (Or determining if two elements are in the same subset).
  - *Union:* Merge two subsets into a single subset.

Prim's algorithm

Prim's algorithm

Set $V_{new} = \{v\}$, where v is an arbitrary vertex in V.
Set $E_{new} = \emptyset$.
while $V_{new} \neq V$ **do**
  Choose an edge $e_{p,q}$ *with minimal weight such that* p *is in* V_{new} *and* q *is not.*
  Add q *to* V_{new} *and* $e_{p,q}$ *to* E_{new}.
end

- At the termination of the algorithm, (V, E_{new}) is a MST on G.

Prim's algorithm, example

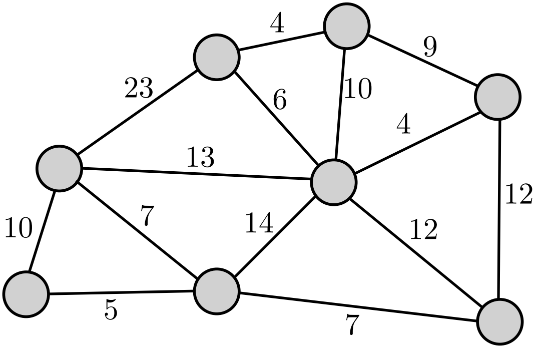

Figure 19: An edge weighted graph.

Prim's algorithm, example

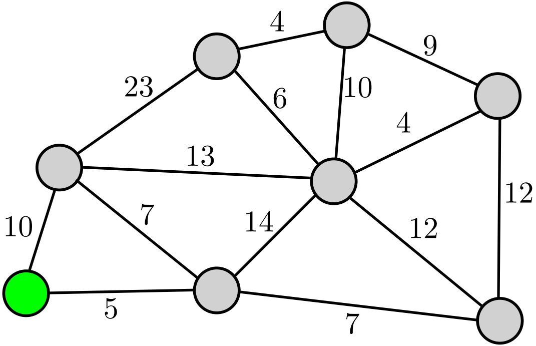

Figure 20: Start by adding an arbitrary vertex to V_{new}.

Prim's algorithm, example

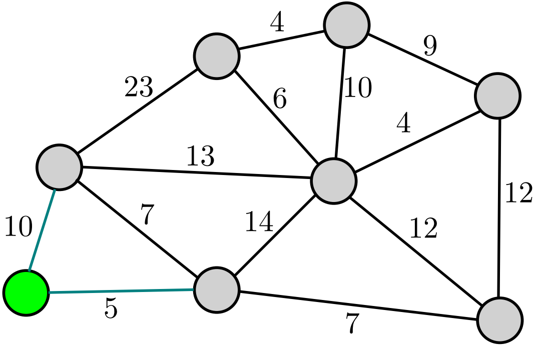

Figure 21: Choose a minimal edge $e_{p,q}$ with such that p is in V_{new} and q is not.

Prim's algorithm, example

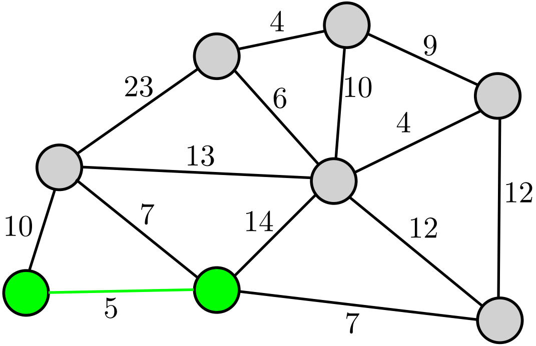

Figure 22: Add q to V_{new} and $e_{p,q}$ to E_{new}.

Prim's algorithm, example

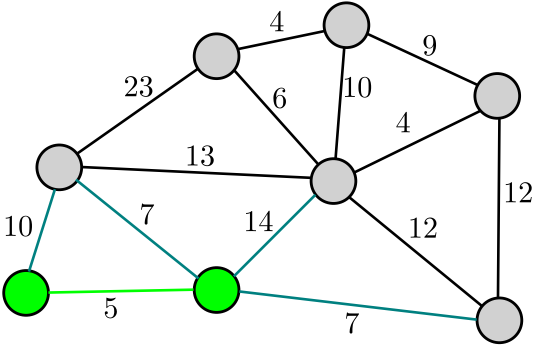

Figure 23: Choose a minimal edge $e_{p,q}$ with such that p is in V_{new} and q is not.

Prim's algorithm, example

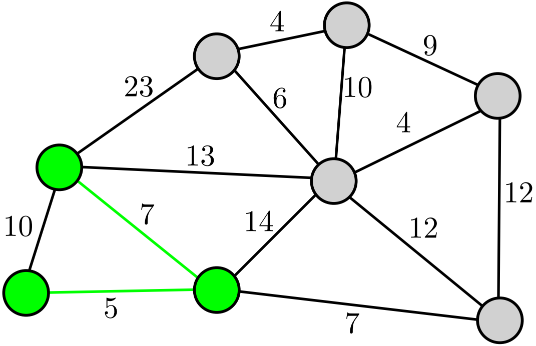

Figure 24: Add q to V_{new} and $e_{p,q}$ to E_{new}.

Prim's algorithm, example

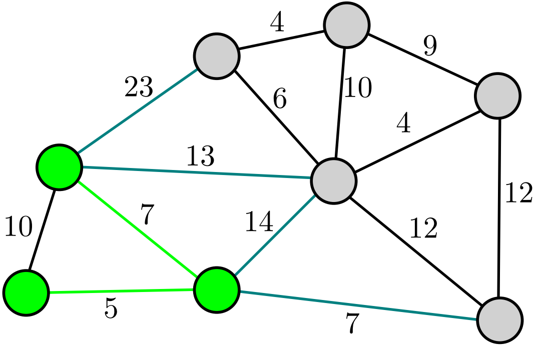

Figure 25: Choose a minimal edge $e_{p,q}$ with such that p is in V_{new} and q is not.

Prim's algorithm, example

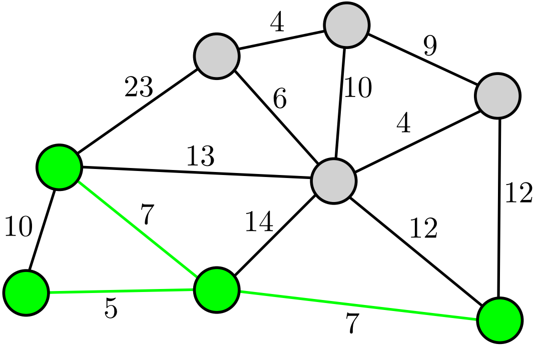

Figure 26: Add q to V_{new} and $e_{p,q}$ to E_{new}.

Prim's algorithm, example

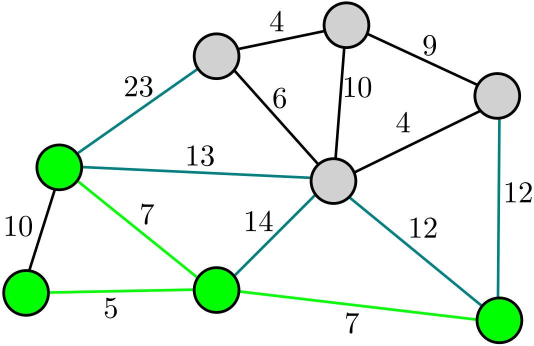

Figure 27: Choose a minimal edge $e_{p,q}$ with such that p is in V_{new} and q is not.

Prim's algorithm, example

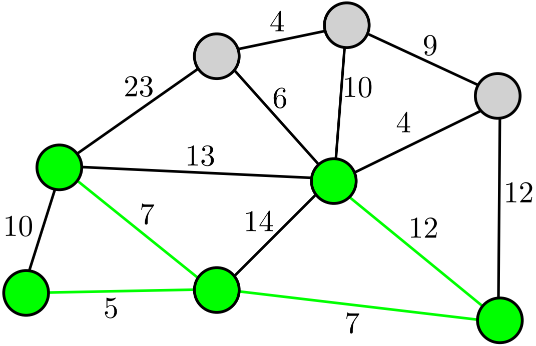

Figure 28: Add q to V_{new} and $e_{p,q}$ to E_{new}.

Prim's algorithm, example

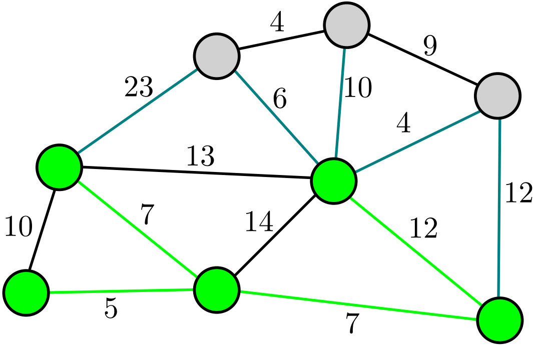

Figure 29: Choose a minimal edge $e_{p,q}$ with such that p is in V_{new} and q is not.

Prim's algorithm, example

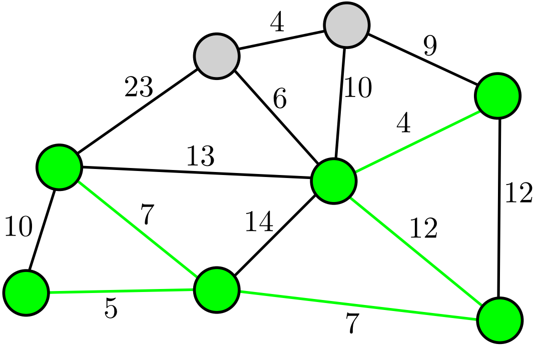

Figure 30: Add q to V_{new} and $e_{p,q}$ to E_{new}.

Prim's algorithm, example

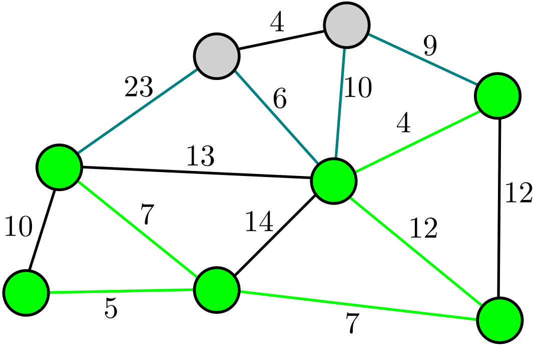

Figure 31: Choose a minimal edge $e_{p,q}$ with such that p is in V_{new} and q is not.

Prim's algorithm, example

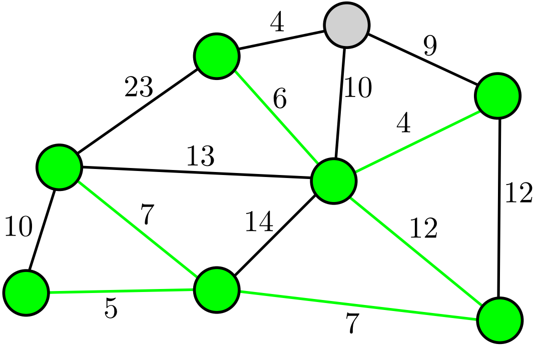

Figure 32: Add q to V_{new} and $e_{p,q}$ to E_{new}.

Prim's algorithm, example

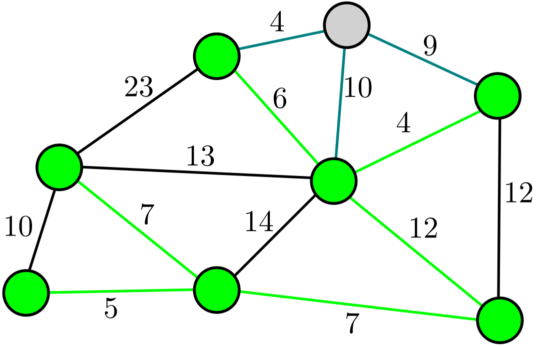

Figure 33: Choose a minimal edge $e_{p,q}$ with such that p is in V_{new} and q is not.

Prim's algorithm, example

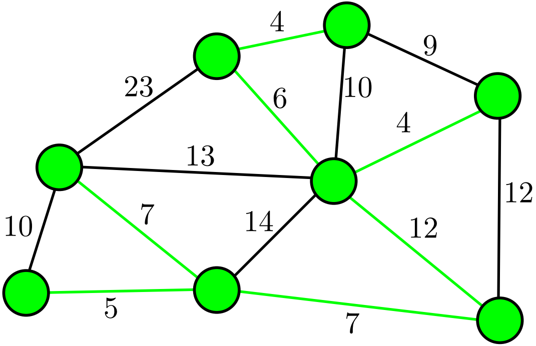

Figure 34: Add q to V_{new} and $e_{p,q}$ to E_{new}.

Prim's algorithm, example

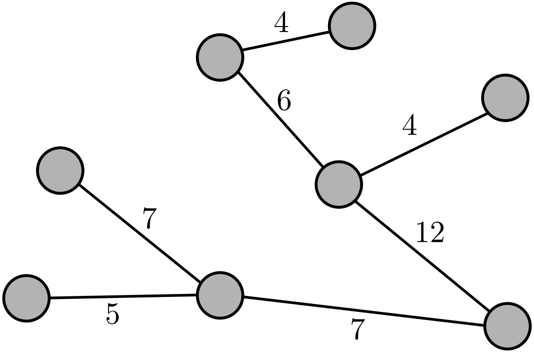

Figure 35: $V_{new} = V$. The algorithm terminates.

Implementing Prim's algorithm

- The edges are not neccesarily visited in increasing order, so we can't pre-sort the edges.
- Instead, we can use some variant of a *priority queue* to efficiently find the next edge with minimum weight.
- With such an implementation, Prim's algorithm can be shown to run in $O(E \log V)$.

Spanning forests relative to seeds

Definition, spanning forest

Let G be a connected, undirected graph, and let $S \subseteq V$ be a set of *seedpoints*. Let T be a subgraph of G such that

- T is a forest.
- $V(T) = V(G)$.
- Each connected component of T contains exactly one seedpoint.

Then T is a *spanning forest* of G, relative to S.

Minimum spanning forests

- A spanning forest T of G is a *minimum spanning forest* (MSF) if the sum of the edge weights is smaller than for any other spanning forest relative to S.
- We can use Prim's or Kruskal's algorithms, with slight modifications, to compute MSFs.

Minimum spanning forests and segmentation

- A MSF partitions a graph into a number of components, each containing exactly one seed-point.
- We will now examine how this can be used for seeded segmentation.

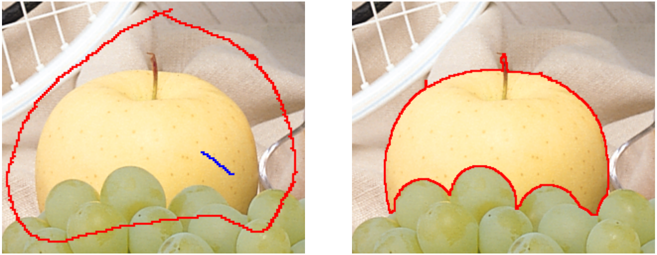

Figure 36: Left: Seed-points representing background (red) and object (blue). Right: Segmentation by MSFs.

But each seedpoint defines a connected component?

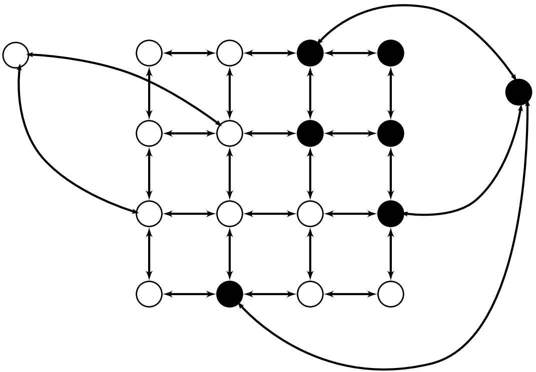

Figure 37: A pixel adjacency graph with “extra” vertices, corresponding to label categories.

MSF cuts, global optimality

- For any spanning forest T on G, we define a *induced cut* C as follows:

$$C(T) = \{e_{p,q} \in E \ \mid p \underset{T}{\not\sim} q\} \ . \tag{3}$$

- For any cut C, we define the *weight* of a cut as

$$\min_{e \in S}(W(e)) \ . \tag{4}$$

- If S is a cut induced by a MSF, then the weight of S is greater than or equal to the cost of *any* other cut that separates the seedpoints [1].

Properties of MSF cuts

Contrast invariance

- The MSF computations depend on the relative ordering of the edge weights, but not on the absolute weight values.
- Thus, the segmentation result is invariant under strictly monotonic transformations of the edge weights. (A transformation that preserves the order)

Properties of MSF cuts

Seed-relative robustness.

- The *core*, or *robustness region*, of a seedpoint is the region (set of vertices) where the seed can be moved without altering the segmentation result.
- For MSF-cuts, the core of each seedpoint can be determined exactly, and is usually large. [2]

MSF cuts and Watersheds

There is a strong relation between segmentation by MSFs and the Watershed approach to segmentation:

- J. Cousty et al., *Watershed cuts: minimum spanning forests, and the drop of water principle*. IEEE PAMI, 31(8), 2009.
- J. Cousty et al., *Watershed cuts: Thinnings, shortest path forests, and topological watersheds*. IEEE PAMI, 32(5), 2010.

Part 3: Shortest path forests

Shortest paths on graphs

- Let G be a connected, undirected,edge weighted graph. We define the *length* $f(\pi)$ of a path π on G as

$$f(\pi) = \sum_{i=1}^{k-1} w(e_{v_i, v_{i+1}}) \ . \tag{5}$$

- For each pair of vertices v, w, there exists one or more paths in G that start at v and end at w. Among these paths, there is at least one path for which the length is minimal.
- Formally, a path π is a *shortest path* if $f(\pi) \leq f(\tau)$ for any other path τ with $org(\tau) = org(\pi)$ and $dst(\tau) = dst(\pi)$.

Shortest paths on graphs

- The length of the shortest path between two vertices provides a notion of *distance*, or *degree of connectedness*, between pairs of vertices in the graph.
- Again, we have a global optimization problem: Among all paths between a pair of vertices, we seek one that has minimum length. Fortunately, there are efficient algorithms that solve this problem.
- Given a set $S \subseteq V$ of seed-points, it is in fact possible to simultaneously compute minimal cost paths from S to all other vertices in V. The output of this computation is a *shortest path forest*.

Shortest paths on graphs

- In general, the shortest path between two vertices is not unique. The set of shortest paths between two image elements p and q is denoted $\pi_{min}(p, q)$.
- For two sets $A \subseteq V$ and $B \subseteq V$, π is a path between A and B if $org(\pi) \in A$ and $dst(\pi) \in B$. If $f(\pi) \leq f(\tau)$ for any other path τ between A and B, then π is a shortest path between A and B. The set of shortest paths between A and B is denoted $\pi_{min}(A, B)$.

Predecessor maps

Predecessor maps, definition

A *predecessor map* is a mapping P that assigns to each vertex $v \in V$ either an element $w \in \mathcal{N}(v)$, or $\emptyset$.

For any $v \in V$, a predecessor map P defines a path $P^*(p)$ recursively. We denote by $P^0(v)$ the first element of $P^*(v)$.

Spanning forests as predecessor maps

Spanning, definition

A *spanning forest* is a predecessor map that contains no cycles, i.e., $|P^*(v)|$ is finite for all $v \in V$. If $P^*(v) = \emptyset$, then v is a *root* of P.

Shortest path forests

Let $S \subseteq V$. If P is a spanning forest such that $P^*(v) \in \pi_{min}(v, S)$ for all vertices $v \in V$, then we say that P is an *shortest path forest* with respect to S.

Computing shortest path forests

- In 1956, Dijkstra [4] proposed an algorithm for computing shortest path forests.
- The algorithm is based on the observation that if $\pi = \pi_1 \cdot \pi_2$ is a shortest path between $org(\pi)$ and $dst(\pi)$, then π_1 and π_2 must also be shortest paths between their respective endpoints.
- Thus, we can recursively reduce the problem to a set of "smaller" subproblems.

Dijkstra's algorithm

Input: A graph $G = (V, E)$ and a set $S \subseteq V$ of seed-points.
Auxillary: Two set of vertices $\mathcal{F}$ and $\mathcal{Q}$ whose union is V.
Set F$\leftarrow \emptyset$,Q$\leftarrow V$.
For all $v \in V$, set $P(v) + leftarrow\emptyset$.

while $\mathcal{Q} \neq \emptyset$ **do**

  Remove from Q a vertex v such that $f(P * (v))$ is minimum, and add it to $\mathcal{F}$.

  foreach $w \in \mathcal{N}(w)$ **do**

    If $f(P^*(w) \cdot \langle w, v \rangle < f(P^*(v)))$, then set $P(w) \leftarrow v$.

  end

end

Dijkstra's algorithm, example

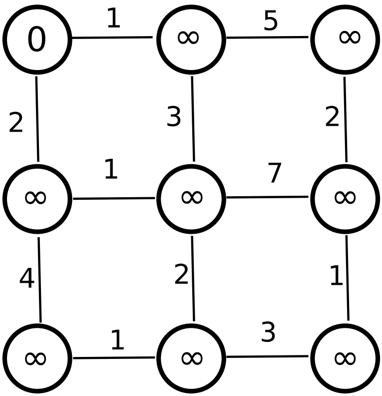

Figure 38: Dijkstra's algorithm.

Dijkstra's algorithm, example

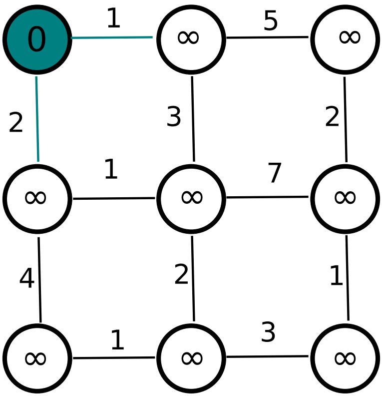

Figure 39: Dijkstra's algorithm.

Dijkstra's algorithm, example

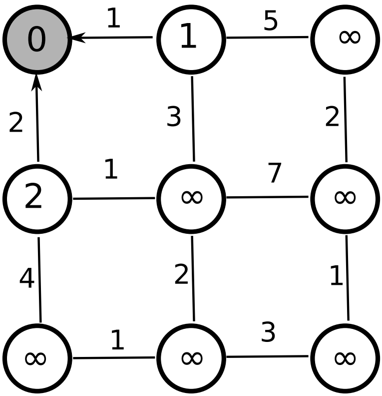

Figure 40: Dijkstra's algorithm.

Dijkstra's algorithm, example

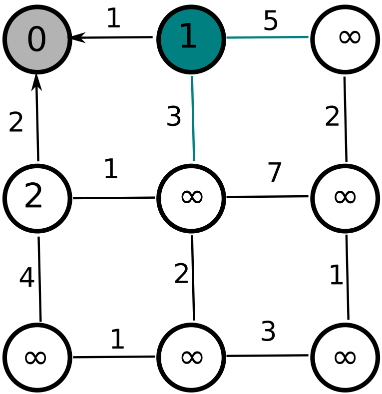

Figure 41: Dijkstra's algorithm.

Dijkstra's algorithm, example

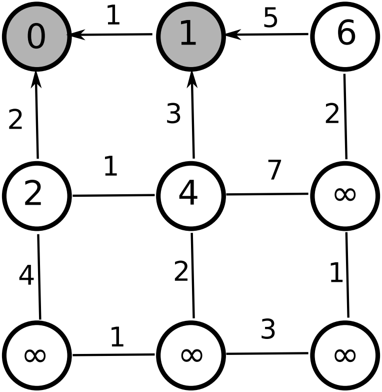

Figure 42: Dijkstra's algorithm.

Dijkstra's algorithm, example

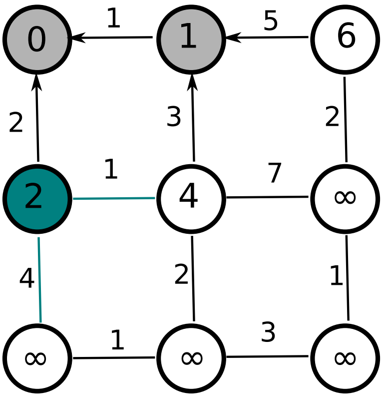

Figure 43: Dijkstra's algorithm.

Dijkstra's algorithm, example

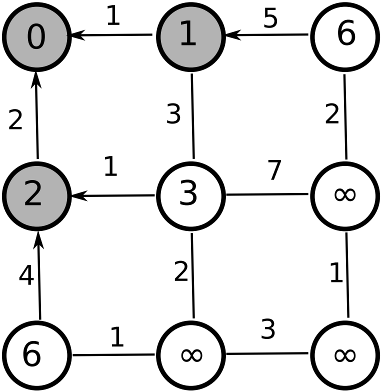

Figure 44: Dijkstra's algorithm.

Dijkstra's algorithm, example

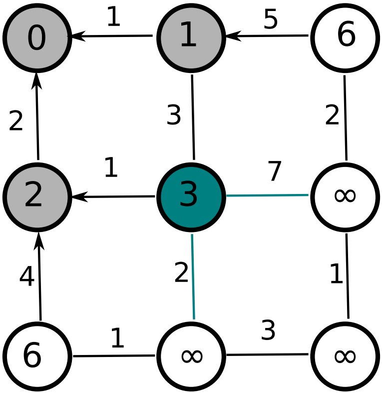

Figure 45: Dijkstra's algorithm.

Dijkstra's algorithm, example

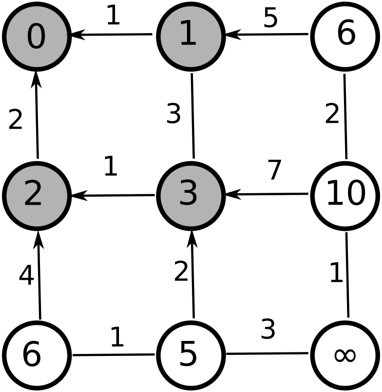

Figure 46: Dijkstra's algorithm.

Dijkstra's algorithm, example

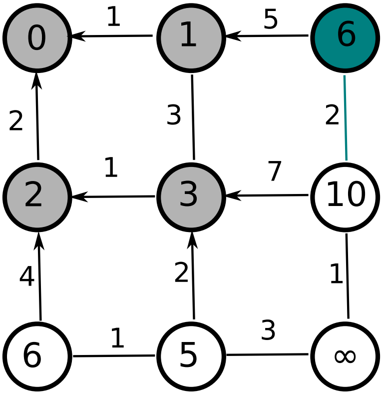

Figure 47: Dijkstra's algorithm.

Dijkstra's algorithm, example

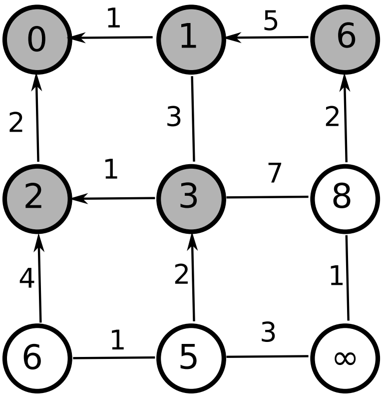

Figure 48: Dijkstra's algorithm.

Dijkstra's algorithm, example

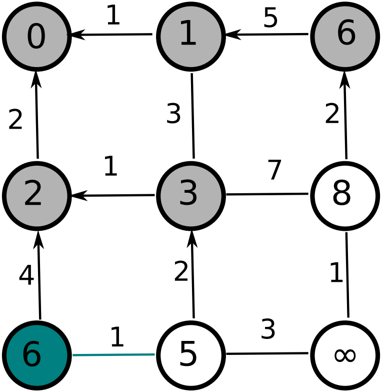

Figure 49: Dijkstra's algorithm.

Dijkstra's algorithm, example

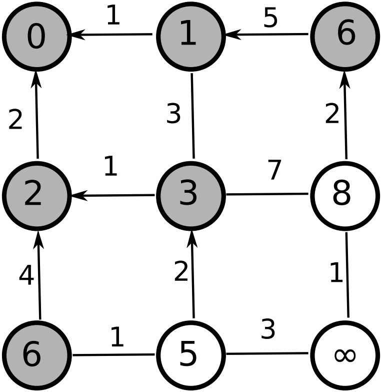

Figure 50: Dijkstra's algorithm.

Dijkstra's algorithm, example

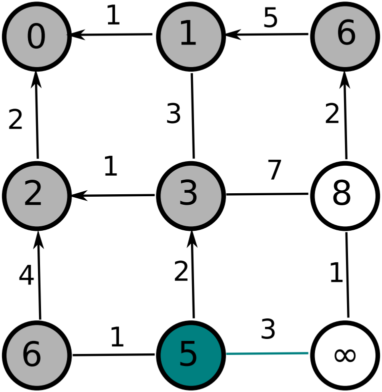

Figure 51: Dijkstra's algorithm.

Dijkstra's algorithm, example

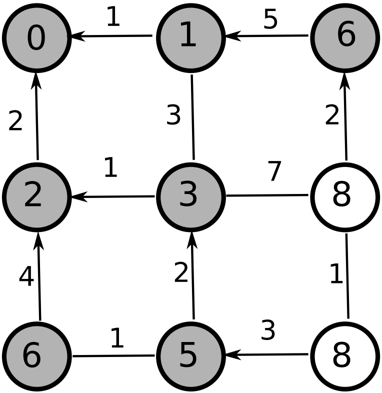

Figure 52: Dijkstra's algorithm.

Dijkstra's algorithm, example

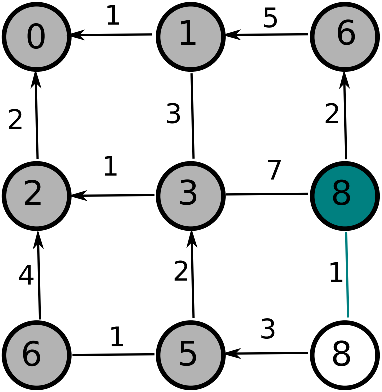

Figure 53: Dijkstra's algorithm.

Dijkstra's algorithm, example

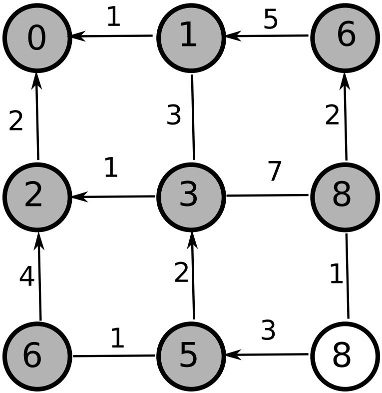

Figure 54: Dijkstra's algorithm.

Dijkstra's algorithm, example

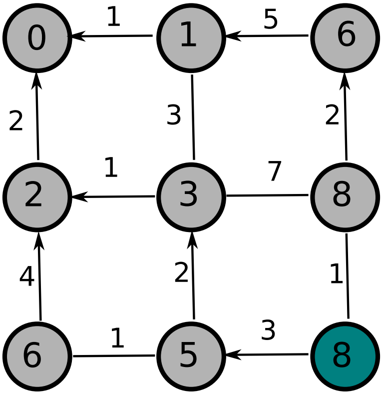

Figure 55: Dijkstra's algorithm.

Dijkstra's algorithm, example

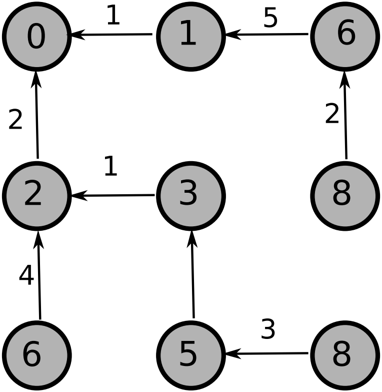

Figure 56: Dijkstra's algorithm.

Implementing Dijkstra's algorithm

- Just like with Prim's algorithm, we can use a *priority queue* to efficiently extract the vertex for which $f(P^*(v))$ is minimum.
- The algorithm can be shown to run in $O(|E| + |V| \log |V|)$. (For some types of graphs, we can do better)

Live-wire segmentation

- The perhaps most straightforward way of utilizing shortest cost path calculations in image segmentation is to consider the path itself as a boundary between two regions. This idea is used in the *live-wire* method.
- To segment an object in a 2D image with live-wire, the user selects a point on the object boundary. Dijkstras algorithm is then used to compute shortest paths from this point to all other points in the image.
- As the user moves the pointer through the image, a minimal cost path from the current position to the seed-point the live wire is displayed in real-time.

Live-wire segmentation

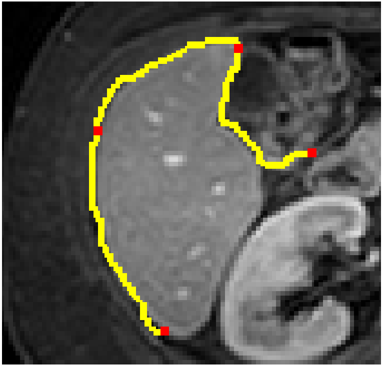

Figure 57: Live-wire segmentation.

Seeded segmentation with shortest paths

- Associate each seed-point with a label, and assign to all other vertices the label of the closest seedpoint as determined by the minimum cost path forest.
- We can modify Dijkstra's algorithm to propagate the labels along with the shortest paths.

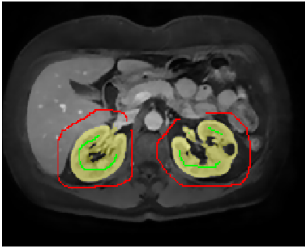

Figure 58: Seeded segmentation with shortest paths.

Approximating Euclidean distances

- The length of the minimal cost path between two vertices can be interpreted as a "distance" between them.
- On a 2D or 3D regular grid, the cost of the minimal path between two vertices can approximate the Euclidean distance between the corresponding points.
- The quality of this approximation depends on the definition of the graph, and the selection of edge weights [8].

Approximating Euclidean distances

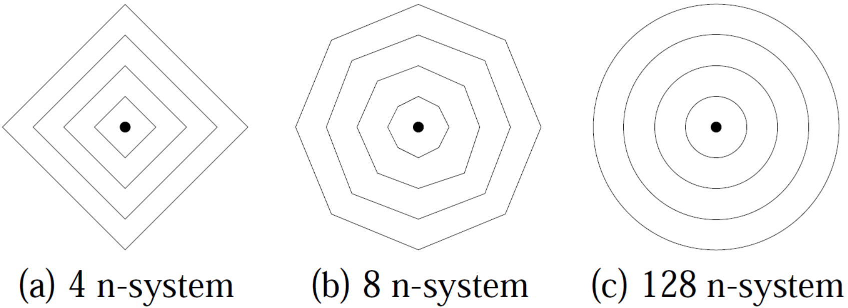

Figure 59: Distances in discrete grids [3]. The weight of each edge is equal to its Euclidean length.

Alternative path costs

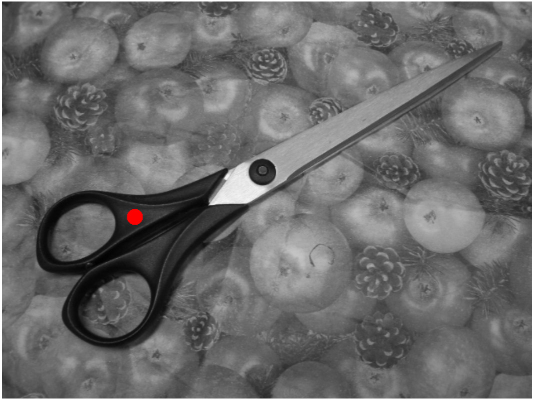

Figure 60: Image, with seedpoints in red.

Alternative path costs

Figure 61: Path costs (inverted).

Alternative path costs

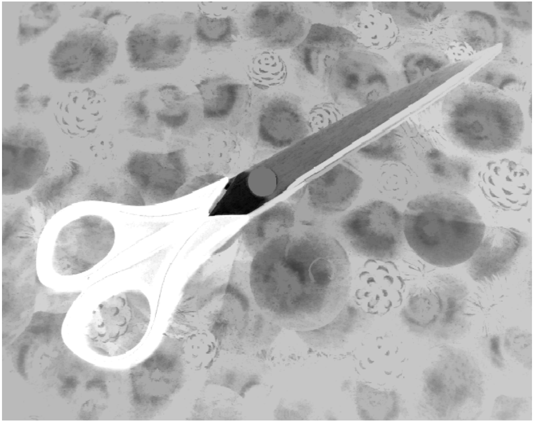

Figure 62: Path cost function: The cost of a path is the maximum value found along the path. *Dijkstra's algorithm still works!*

Alternative path costs

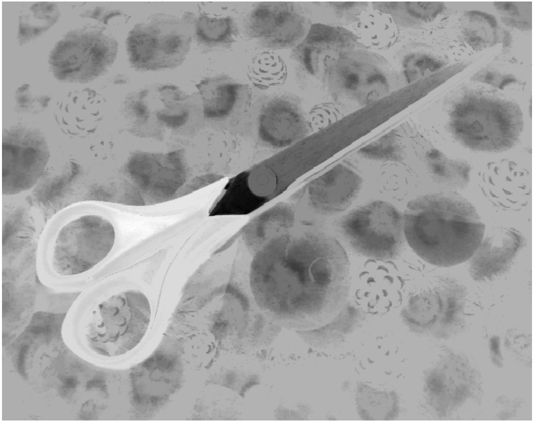

Figure 63: Path cost function: The cost of a path is the absolute difference between the maximum and minimum values found along the path. *Dijkstra's algorithm no longer works!*.

Extensions of Dijkstra's algorithm

For now, we have defined the length of a path as the sum of edge weights along the path.

- Are there other path cost functions that could be of interest in image processing?
- If so, what conditions do these functions need to satisfy in order to guarantee the existence of a shortest path forest?
- These questions were investigated by Falcao et al. [5].
- (Chris's talk next week!)

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