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Real-time license plate localization based on a new scale and rotation invariant texture descriptor

Chu-Duc Nguyen, Mohsen Ardabilian and Liming Chen

Lyon Research Center for Images and Intelligent Information Systems, UMR 5205 CNRS
Department of Mathematics and Computer Science, Centrale Lyon
36 avenue Guy-de-Collongue, 69134 Ecully, France
chud-nguyen@ec-lyon.fr, mohsen.ardabilian@ec-lyon.fr, liming.chen@ec-lyon.fr

Abstract—In this paper, we present a real-time and robust license plate localization method for traffic control applications. According to our approach, edge content of gray-scale image is approximated using line segments features by means of a local connective Hough transform. Then a new, scale and rotation invariant, texture descriptor which describes the regularity, similarity, directionality and alignment is proposed for grouping lines segments into potential license plates. After a line-based slope estimation and correction, false candidates are eliminated by using geometrical and statistical constraints. Proposed method has been integrated in an optimal license plate localization system. Evaluation is conducted on two image databases which were taken from real scene under various configurations and variability. The result shows that our method is real-time, robust to illumination condition and viewpoint changes.

Index Terms—License plate localization, Hough transform, scale and rotation invariant texture descriptor, slope estimation, motion analysis.

I. INTRODUCTION

License Plate Recognition (LPR) system has played a very important role in intelligent traffic control and security management, such as highway ticketing, car park entrance and exit management [19]. Usually, an LPR system consists of three main parts: license plate localization, character segmentation, and character recognition. Among them, license plate localization (LPL) is considered the most crucial stage because a high accuracy and real time segmentation and recognition can be performed only if the license plates are correctly localized [18][11].

In real-life context, the LPL has to confront some difficulties which result from uncontrolled imaging conditions such as complex scene, bad weather condition, low contrast, blurring and viewpoint changes [11][7]. Even though many researches focus on LPL, we are far from a solved problem.

In this paper, a real-time and robust LPL method for traffic control applications will be presented. As the main contribution, we propose a new, scale and rotation invariant, texture descriptor which describes the regularity, similarity, directionality and alignment of line region for localizing LP. First, edge content of gray-scale image is approximated using line feature extracted by a local Connective Hough Transform. Then line segments are grouped into potential LP by using our texture descriptor. The new texture descriptor and the real-time extraction approach guarantee some remarkable properties as insensitivity to illumination, insensitivity to geometric change induced of the change of viewpoint (scaling, orientation and deformation) and could be applied on gray-scale images without binarisation. For evaluation purpose, proposed method has been implemented in a complete license plate localization system.

The rest of the paper is organized as follows. The section II introduces a state of the art of LPL approaches. In section III, our new line segments detection and line-based texture descriptor are presented. In section IV, we propose a global traffic control system architecture in which our approach is optimally involved. LP databases are also described in the section V with experimentation and performance analysis. Finally, conclusions and perspectives come in the last section.

II. RELATED WORKS

LPL process could be divided into two consecutive phases: all potential LP regions detection and LP verification to eliminate false alarms. Researchers’ answer for each phase differs about the feature type used. In the light of this observation, LPL methods can be categorized into three global types: region-based, contrast-based and hybrid methods.

Region-based methods use the properties of the color in LP region, or the character information of the alphanumeric components inside LP. Color-based methods extract LP’s background pixels by using some predefined colors [19] or color image segmentation [9]. CC-based methods [12][10] use a bottom-up approach by grouping small components into successively larger components until all regions are identified in the image. After a non-like character filtering stage, a geometrical analysis is needed to merge the text components using the spatial arrangement of the components.

Contrast-based methods are founded on the contrast between the plate boundary and overlapping region in the vehicle or the high contrasted characters in comparison with the rest of the plate region. This category of methods can be categorized into three sub-types: straight-line-based, morphology-based and edge-based. Straight-line-based methods detect lines in binarized edge image and then group two pairs of overlapping parallel lines in the horizontal direction and the vertical direction to form potential LP boundaries.
III. LINE SEGMENTS BASED TEXTURE DESCRIPTOR

First of all, let us consider the idea of our line segments based texture descriptor (LSTD). It is a well-known fact that color information is not stable when the illumination changes, so only intensity component will be exploited. In this gray-scale image, straight edge content can be approximated by line segments. By using these segments, we want to build a descriptor which represents a perceptual characterization of texture, similar to a human characterization, in terms of regularity, similarity, directionality and alignment. A similar idea of perceptual texture extraction for artificial text detection has been used in [2]. We remind here that regularity and directionality features are specified in MPEG-7 and more specifically in Texture Browsing Descriptor [13].

A. Descriptive of line segments based features

The syntax of our LSTD, which can be deduced from Fig. 1, is the following:

\[ \text{LSTD} = [\Delta_r, l, \theta, r_a] \]

where each feature represents a characteristic of line region:

- **Regularity** is represented by \( \Delta_r \), vector of distances between two adjacent line segments which have the same orientation.
- **Similarity** is represented by \( l \), vector of lengths of line segments.
- **Directionality** is represented by \( \theta \), vector of angles between the horizontal axis and the perpendicular line of line segments.
- **Alignment** is represented by \( r_a \), vector of distances between extreme of line segments and the perpendicular line of line segments.

One of the most striking aspects of our LSTD is the invariance to rotation and scale changes. Let us firstly consider the case in which the angle \( \theta \) of line segments has been changed an amount of \( \Delta_\theta \). The vector of features becomes:

\[ \text{LSTD}' = [\Delta_r, l, \theta + \Delta_\theta, r_a] \]

This analysis leads us to an approach combining edge and line segments information for localizing LPs. This approach exploits optimally vertical strokes features of characters inside LP. Firstly, only intensity component has been used to guarantee the robustness to illumination change. Second, a fast approximation of straight edge content by line segments, without binarization, decreases dramatically the overall computation time. Thirdly, a new, invariant scale and rotation invariant, texture descriptor is proposed for grouping line segments into potential LPs, which gives us a reliable LP localization even when viewpoint changes.
Every $\theta_i$ are added a same value of rotation, therefore the new line segments group had the same directionality according to the initial group.

On the other hand, take the case of image scale change by factor $\alpha$. Region features becomes:

$$LSTD^\alpha = [\Delta_{r}^\prime, l, \theta, r_a] = [\alpha.\Delta_{r}, \alpha.l, \theta, \alpha.r_a]$$  (3)

All of $r_a$, $l$ and $r_a$ are modified with the same ratio $\alpha$, while $\theta_i$ stays intact. On that account the scaled line segments group has the same LSTD features with respect to the group in original image.

B. Feature extraction based on local connective Hough transform

Our feature extraction is based on line detection by using local Hough transform combined with small connected line segments suppression. The algorithm is based on an original fast connective Hough transform in [1]. The issue at stake here is the minimization of noise’s effect caused by isolated pixels. As for rapidity, small segments suppression also reduces the number of pixels to be considered in line detection stage. Additionally, lookup-table technique is also used to store and involve values of trigonometric functions, which are the same for every local sweeping using Hough transform. As a contribution, our local sweeping scheme can reduce significantly the computation cost of classical Hough transform.

1) Line segment detection in binarized image: A simple way to get all pixels of a line segments is to scan sequentially the image from top to bottom and from left to right. For each foreground pixel, every local angle $\theta'$ which is between $0$ and $\pi$ will be considered (Fig. 2). In each direction given by $\theta'$, line segment is detected by searching a set of connected collinear pixels. Finally, the longest line segment is stored and removed from the image. All other small segments whose length is lower than a threshold are also removed. The similar processus has been used in [15] for a line-based cityscape classification.

The sequential search continues until sweeping the whole image. The detection of segment direction is the most costly step in line detection algorithm, so requires a particular attention. In the discrete image space $I$, pixels of line segment $LS$ having a local direction $\theta$, length $l$ and beginning coordinates $(x_0, y_0)$ can be represented by:

$$LS_{\theta} = I(x_0 + [i.cos(\theta)], y_0 + [i.sin(\theta)])$$  (4)

where $1 \leq i \leq l$, $0 \leq \theta' \leq \pi$ and $[.]$ denotes entire part of a number. In order to improve performances and avoid call of trigonometric functions inside our algorithm, we compute two transformation matrixes in the initialization step. The first one stocks values of $[i.cos(\theta')]$, the second one stocks values of $[i.sin(\theta')]$ for $1 \leq i \leq l_{max}$, $0 \leq \theta' \leq \pi$, where $l_{max}$ is the maximal length of line segment that we want to detect. At the end of a local line detection cycle, all segments having length lower than a threshold $\tau$ will be removed from image space. Fig. 3 serves to illustrate the idea of this step.

2) Line segment detection in gray-scale image: There can be no doubt that in gray-scale image, line segments are often imperfect, because of small variances in intensity, in space or in orientation. So, we introduce tree tolerant parameters:

- **Tolerant in intensity**: gray-scale value of pixels in a given direction can be different of $\tau_{gs}$ levels.
- **Tolerant in space**: in a given direction, $\tau_d$ neighbors of current pixel will be considered.
- **Tolerant in orientation**: in a given direction $\theta'$, neighbors pixels in directions $\theta' \pm \tau_o$ will be also considered. This consideration of neighborhood makes our method able to detect imperfect segment as the case of an edge image.

3) Application to LSTD features extraction: The above section shows how our method can detect rapidly and robustly line segments in gray-scale image. Therefore, in order to use detected line segments to extract LBTD features, some transformations are needed (Fig. 4).
Extraction of regularity features: firstly, the distance $r$ between the origin and a given line segment is calculated from its extreme coordinates $(x_0, y_0)$ and its local orientation $\theta'$:

$$r = |x_0 \cdot \sin \theta' - y_0 \cdot \cos \theta'|$$  (5)

Secondly, $\Delta r$, between every parallel line segments will be readily deduced.

Extraction of similarity features: which are lengths $l$ of line segments.

Extraction of directionality features: for $\theta' \in [0, \pi]$, two cases are presented for calculating $\theta$:
- If $\theta' \in [0, \pi/2]$ then $\theta = \theta' + \pi/2$
- If $\theta' \in [\pi/2, \pi]$ then $\theta = \theta' - \pi/2$

Extraction of alignment features: distances $r_a$ between the extreme of line segments and the perpendicular line of line segments can be calculated directly from extreme coordinates $(x_0, y_0)$ and local orientation $\theta'$ as:

$$r_a = |x_0 \cdot \cos \theta' + y_0 \cdot \sin \theta'|$$  (6)

IV. LICENSE PLATE LOCALIZATION SYSTEM

In this section, we describe the main steps of the license plate localization system by using LBTD. It is known that a license plate is a pattern composed of several characters that have high distinctive intensities in LP background. The second observation is that characters inside LP have the same height. The third, more important, is that vertical character strokes having similar width are distributed almost identically in LP. The dense vertical edge areas which have some typical perceptual features can be used as a key feature to detect the desired LPs. There can be no doubt that our LBTD descriptor can describe readily the features of LP regions in this sense.

Flowchart of the proposed LP localization system is shown in Fig. 5. It consists of three main modules: preprocessing, potential LPs localization and LPs verification. Detailed steps are mentioned in the right part of the schema.

Before going into the descriptive of our system, it is interesting to consider the sub-module motion analysis in case of video sequence input. The goal is to select the best image in the sense of LP quality. Once moving pixels are detected, an analyzer is activated. Motion is tracking by optical flow technique. When the motion slows down below a threshold, current frame is selected like a good image for LPL system. So, the blurring effect provoked by moving vehicle could be reduced. It is clear that this idea is suitable to gateway control applications.

A. Preprocessing

To promote our contrast-based method, first, a histogram equalization is carried out to normalize the illumination, using Eq. (x). On the one hand, contrast is increased, on the other hand, vital edges are also protected.

$$F(i) = \tanh\left(\frac{c}{\delta} i\right)$$  (7)

where $i$ represents the intensity value of the input image, $\delta$ is the variance of the image, and $c$ is a constant. An example of this processing step is showed in the Fig. 6.

B. Potential LPs localization

1) Step 1: vertical edges detection: As a fast and simple operator, we used Sobel to obtain the gradient of the input image in vertical direction

2) Step 2: lines detection: The next step is applying the line detection algorithm which is mentioned in the previous section to gray-scale edge image. Each line segment is stored with its extreme coordinates $(x_0, y_0)$, its local orientation $\theta'$, and its length $l$. It is worth recalling here that our algorithm can detect line segments in imperfect image, with accuracy
and rapidity. There is a fundamental difference between our algorithm and other lines detection algorithms, is that no threshold is needed to binarize the edge image.

3) Step 3: perceptual line segments grouping: Firstly, local information of line segments is transformed in global information $[(x_0, y_0), \theta, r, l, r_a]$. Then, the perceptual line segments grouping based on LBTD is performed as in the pseudo-code of Algorithm 1.

\begin{algorithm}
\begin{algorithmic}
\State for line segments whose angle satisfies $80 \leq \theta \leq 100$
\Repeat
\hspace{1em} consider a pair of line segments $S_i, S_j$
\If{$S_i.r_a \sim S_j.r_a \& S_i.l \sim S_j.l \& |S_i.r - S_j.r| \leq l$}
\hspace{2em} Two line segments are grouped
\EndIf
\Until{all line segments are grouped}
\Remove groups with small number of line segments
\EndFor
\end{algorithmic}
\caption{Perceptual line segments grouping}
\end{algorithm}

4) Step 4: slope correction: For each relevant group of segments, a binarized image of segment extremes is generated. Then, a second line detection is applied in this image, with a sweeping range less than $30^\circ$. This range is reasonable by the truth that vehicle LPs are positioned almost horizontally. Finally, the angle $\alpha$ in which longest segment was detected is an estimation of LP slope. An inverse rotation of $-\alpha$ degree will correct the inclination. Fig. 7 gives us an example of LP’s slope estimation and rectification.

As a contribution, this module provides a fine image of characters in LPs to the segmentation part, so improves the recognition performance. Additionally, in the context of fixed camera and moving vehicle, the slope of LP could reflect the direction of the vehicle in a given lane.

C. LPs verification

After the localization process, each one of the candidates must be checked by certain criteria to see if it satisfies the requirements of a LP. Two criteria are adopted sequentially, the geometric properties of LP are utilized first, and then statistical characteristics of the alpha-numerals in the LP are employed in the process of verification.

1) Step 1: geometrical verification: The LPs have uniform size and shape, and the distance between the video camera and the observed vehicle usually falls within a known range. Therefore, the width, height and aspect ratio of the LP image can be estimated and used as a good criterion for selection of true LPs. The width and height threshold are up on applications, while the aspect ratio is always between 2 and 5.

2) Step 2: statistical verification: As mentioned above, vertical strokes in LP have similar height and are distributed almost identically in LP background. Interestingly, a simple check by three horizontal scanning near to top, middle and bottom of each bounding box candidate in the original image can reveal this information. By this way, the number of sudden changes is taken into account for each scanning. If these three values are similar, the candidate is selected as a LP.

To take an example, Fig. 8 shows a process of our LPL system. After preprocessing, the vertical Sobel operator is applied to original image for obtaining edge image 8(b). Secondly, line segments are detected, stored and represented in image 8(c). As a result of line segment features extraction and perceptual grouping, image 8(d) shows potential LP candidates behind some white masks. Empirical verification of LPs is involved which give us the locations of two true LPs in this image 8(e). Finally, two LPs are extracted and showed in image 8(f).

\begin{figure}[h]
\centering
\includegraphics[width=\textwidth]{example.png}
\caption{An example of step by step results of proposed method}
\end{figure}
TABLE I
PERFORMANCE OF OUR METHOD IN TWO DATABASES

<table>
<thead>
<tr>
<th>Database</th>
<th>RR(%)</th>
<th>PR(%)</th>
<th>FAR(%)</th>
<th>Time(ms)</th>
</tr>
</thead>
<tbody>
<tr>
<td>DB1</td>
<td>97.5</td>
<td>95</td>
<td>5</td>
<td>200</td>
</tr>
<tr>
<td>DB2</td>
<td>97</td>
<td>90</td>
<td>10</td>
<td>300</td>
</tr>
</tbody>
</table>

SeeCar project (http://www.htsol.com/Products/Demo.html)
This set was built for purpose of testing LP localization
and recognition methods in the world-wide applications.
All images are of size 768 × 288 or 768 × 576. The
second one (DB2) was constructed by us-self in the goal of
comparing and evaluating LP localization methods. Images
are taken from viewpoints in various contexts (parking, gate-
way, street scene), in different illumination (day, night) and
weather (clear, cloudy, rainy) conditions. More specifically,
our database contains 600 images whose sizes are between
756 × 504 and 1024 × 768.

The ground-truth (GR) of LPs in the two databases is
made semi-automatically by using ViPER-GT (http://viper-
toolkit.sourceforge.net). ViPER-GT is a tool for annotating
videos with metadata, ranging from things like genre and
location of cuts to object localization and tracking. The GR
information is then stored in corresponding XML file.

In the evaluation stage, recall rate (RR), precision rate
(PR), false-alarm rate (FAR) and computation time are used
for measuring the overall performance. For this purpose, we
impose that a LP is well localized if the overlapping part
of detected region and GR occupies more than 80% of GR
area.

![Fig. 9. Robustness of our method in difficult contexts](image)

(a) At night  (b) Multi LPs
(c) Important rotation  (d) Noisy image

The proposed system was implemented on a personal
computer with Centrino Duo 2GHz, 2GB RAM using C++.
The test was conducted on all images in the two databases,
and the result of average performance is showed in the
Table I. Obtained capacity of localization (97%) is better than
the mean of localization performances in the stat of the art
(95%) which were tested on databases of similar variability
with ours.

The high performance with the DB1 (97.5%) proves that
our method can be applied for many countries LP localization
applications. Whereas the high performance with the DB2
(97%) means that our method is robust to illumination
change, noise, LP orientation and size. Our system performs
exact LP localization even in difficult cases: at night, multi
LPs with different sizes, LP is inclined about 30°, or noisy
image (Fig. 9).

It is interesting to consider that the FAR stills important
(10%) in the case of DB2 because of LP-like texture regions,
as phone number in the car background. Additionally, partial
localization happened when LP have two rows with small
number of characters. Fig. 10 shows an example of limitation
of our method.

![Fig. 10. An example of missed and wrong localization](image)

VI. CONCLUSIONS

We presented a real-time and robust License Plate Lo-
calization approach for traffic control applications. This
approach is based on a new, scale and rotation invariant,
texture descriptor which describes the regularity, similarity,
directionality and alignment of a line segments. Our approach
includes a fast descriptor extraction based on an improvement
of connective Hough transform. The tests conducted on
real scene images shows that our approach is insensitive
to illumination, insensitive to geometric change induced by
viewpoint change (scaling, orientation, deformation).

The focus of our future work is the further investigation
to decrease false alarms. For this purpose, the empirical
verification will be replaced by a learning verification using
geometrical features, statistical features and character-based
Haar features. On the other hand, we plan to combine
extracted LPs with motion estimation for predicting regions
of interest (ROIs) and LPs tracking, which make our system
more real-time. Finally, more exhaustive comparisons would
be conducted.
REFERENCES


