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**Optimized Mean Shift Algorithm for Color Segmentation in Image**  
**ABSTRACT**  
 The paper presents an optimized mean shift algorithm for color segmentation in image. The algorithm is based on the mean shift algorithm proposed by Comaniciu and Meer. The main contribution of this paper is the introduction of a new stopping criterion based on the entropy of the color distribution. The proposed algorithm is able to segment images with complex color distributions. The experimental results show that the proposed algorithm outperforms the existing mean shift algorithms in terms of segmentation accuracy and execution time. The proposed algorithm is implemented in MATLAB and the source code is available at <http://www.cse.cmu.edu/~jbois/>.  
**1. INTRODUCTION**  
 The mean shift algorithm is a non-parametric, data-driven technique for finding the peaks of a density function. It is based on the idea of shifting a kernel towards the region of higher density. The algorithm is simple and efficient, and it has been widely used in computer vision applications. In this paper, we propose an optimized mean shift algorithm for color segmentation in image. The proposed algorithm is based on the mean shift algorithm proposed by Comaniciu and Meer. The main contribution of this paper is the introduction of a new stopping criterion based on the entropy of the color distribution. The proposed algorithm is able to segment images with complex color distributions. The experimental results show that the proposed algorithm outperforms the existing mean shift algorithms in terms of segmentation accuracy and execution time. The proposed algorithm is implemented in MATLAB and the source code is available at <http://www.cse.cmu.edu/~jbois/>.

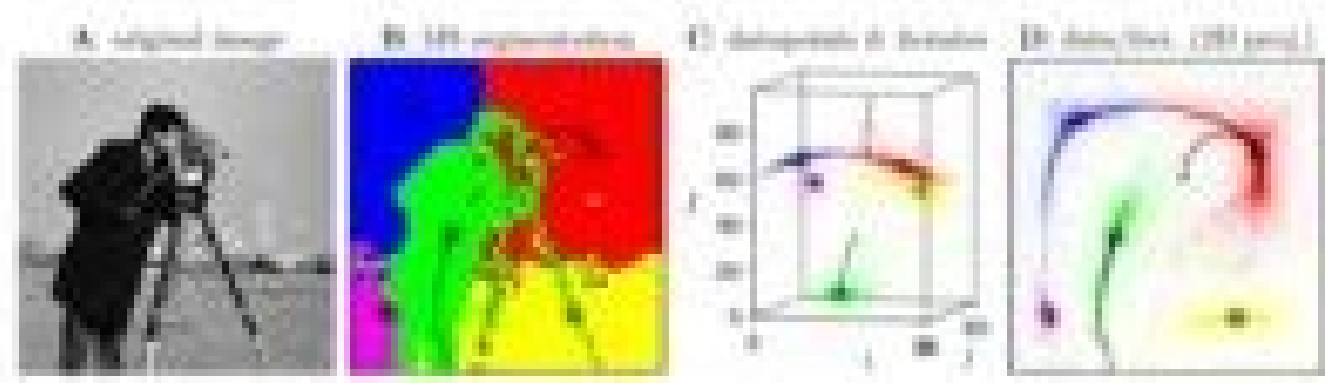
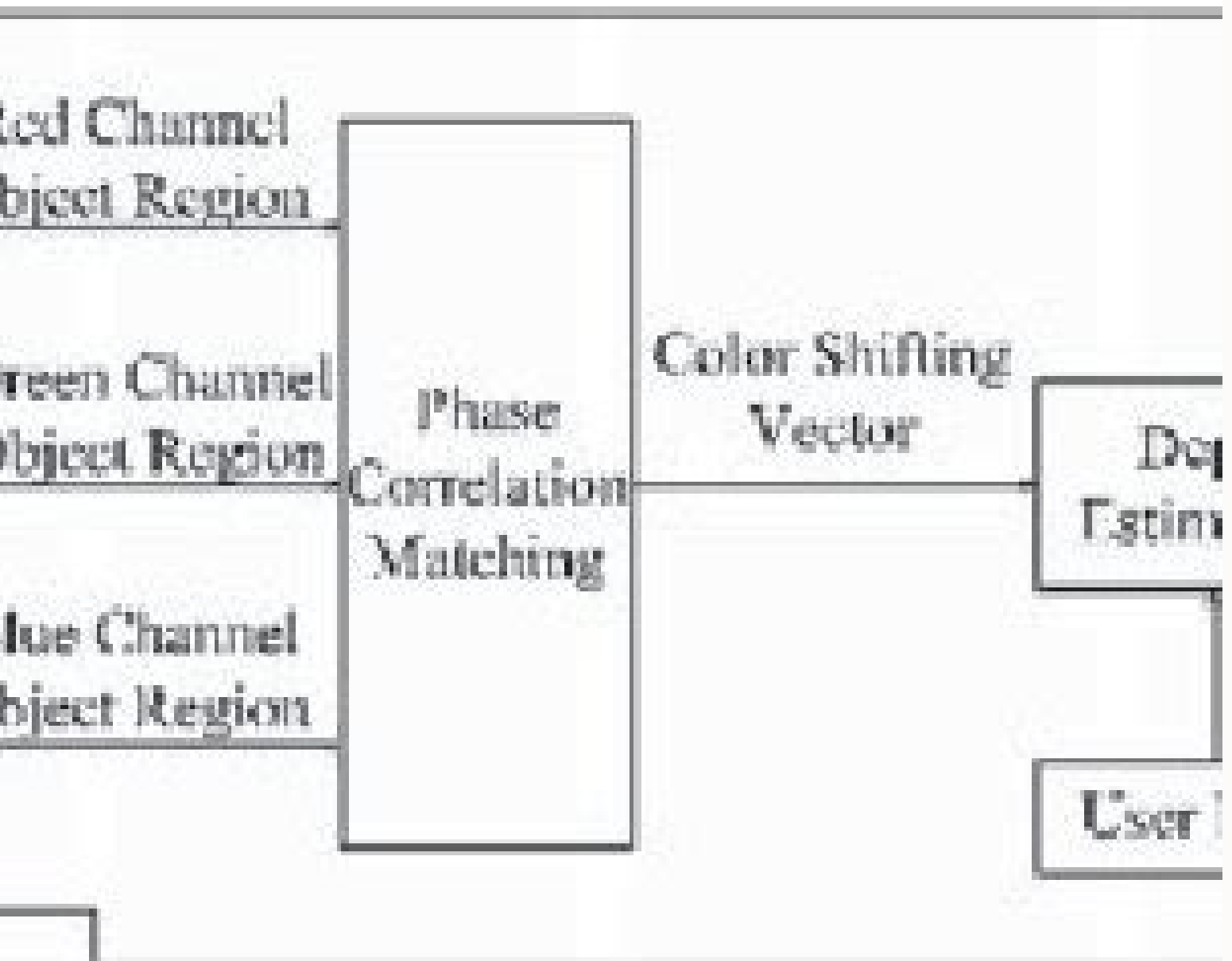


Figure 3. (A) Original image (resolution  $512 \times 512$  pixels). (B) Gaussian MRF segmentation with bandwidth  $\sigma = 4$  pixels, resulting in 5 clusters (shown in different colors), with the respective modes marked  $\times$ . (C) The distance function (pixels) and all the MRF modes for all starting points in  $(x, y)$  space, colored by cluster. (D) Projection of the surface (plot on  $(x, y)$  space). The paths for two starting points are shown in plots (B)–(D).



Figure 4. Sequence of clusters  $K^0, \dots, K^6$  obtained by Gaussian MRF for the cameraman image of Fig. 3 with bandwidth  $\sigma = 4$ , resulting in 7 clusters. We show the 2D projection on the spatial domain of every data point (pixels), colored by cluster, as in Fig. 3(B). Note: (1) points very quickly move towards a centroid and collapse into it (shrinking property); (2) for each cluster to be, the local direction of maximum contour collapse tends more slowly than the lower-order direction, producing banana-shaped clusters (shrinking property) that elongates and divides. The MRF stopping criterion stopped MRF at iteration  $t = 11$ , when the distant modes of 7 clusters of collection points. If not stopping, these clusters would keep merging and eventually merge into a single cluster.

pixels. The edge features are used to again approximately the range of the spatial features. This way, all features and the bandwidth have pixel units. For example, for the image of Fig. 3, we consider the original grayscale image in the range  $[0, 255]$ , as a feature vector  $(x, y, I)$  would correspond to the pixel located at coordinates  $(x, y)$ , which has an intensity equal to  $I$  of the maximum intensity (white). The gradient vector will affect the clustering and should be done carefully. Using spatial features is beneficial because they introduce spatial coherence (pixels which tend to belong to the same cluster), although sometimes only the range features are used. One should use a perceptually uniform color space such as LAB rather than the RGB space, so that Euclidean distance approximately match perceptual differences in color [36].  
 Fig. 3 shows an example with a grayscale image of  $512 \times 512$  pixels. Thus, the feature contains  $N = 259$  points in 3D (feature  $(x, y)$  and intensity  $I$ ). Fig. 3 shows the result with MRF while Fig. 4 shows the result with









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