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Improved Face Authentication by Constructing an Adjustable 3D Image from two 2D Images taken by Two Adjacent Cameras

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Abstract: With the vast spread of automation, the significant demand for communication services, adding IoT to the Internet, and the corresponding huge increase and sophistication in malicious attacks utilizing system vulnerabilities to penetrate systems. Identification and Authentication are heavily used in every access trial towards any electronic resource and communication networks. The traditional approach to coping with such challenges is using passwords, encryption, Secure ID, Firewall, Etc. More safety methods use Biometrics, which suffer from spoofing. The access control market is a fast-growing and highly volatile market that poses significant challenges for investors seeking to make secured decisions. As the market continues to evolve and become more mainstream, there is a growing demand for new identification and authentication technologies. This paper proposes expanding the number of features extracted from a 3D image, with unique features evolved during the generation of the 3D image of the prospect at the access control stage. We mounted two identical 2D cameras on the same bar, allowing the adjustment of the distance between the two mounted cameras. The two cameras are simultaneously activated, generating a unique 3D image, including some distortion. This stage is executed at the person enrollment process and repeated at the access stage, providing an enhanced, unique, and cannot be faked Authentication. Experiments support the proposed approach.

Keywords: Image processing, 3D image Construction, Authentication,

I. Introduction

Face recognition is a type of biometric recognition technology that uses information about a person's facial features to identify them. The goal is to identify the vital facial landmarks to distinguish factors. It looks for the following features: histogram, color, template, structural, Haar, visual, pixel statistical, face image transformation coefficient, and face algebra features. Face recognition uses the distances between the eyes, forehead to the chin, nose, and mouth, the Depth of the eye sockets, the shape of the cheekbones, and the lips contour, ears, and chin. 3D face recognition inherits 2D face features and adds variant facial positions and expressions, introducing pose-invariant, expression-invariant, and occlusion-invariant recognition. Pattern recognition is used in 3D face recognition, while in 2D, it is possible. It uses face depth. While 2D methods rely on flat images only, 3D face recognition uses a 3D face model, which allows it to take advantage of the human face's geometry. It offers a potent shield against pitfalls like changing lighting conditions, diverse facial expressions, and varying head angles. Advanced algorithms conduct pattern analysis on the 3D facial data, ensuring robust recognition even amidst pose variations and shifts in illumination. This algorithmic prowess bolsters the system's capabilities, rendering it resilient against diverse environmental factors. 3D models significantly improve facial recognition results compared to 2D images. The system's adaptability and accuracy are unparalleled when combining this depth analysis with Artificial intelligence algorithms.

While 2D might falter due to their striking resemblances, 3D would discern between their subtle facial depth differences, ensuring correct identification. The acquisition of 3D face samples involves infrared laser beams directed at the human face, drawing its shape features using triangulation methods to determine a precise map by calculating and grouping reflection points. It measures the deformation of the light pattern to calculate the surface shape. The system matches points observed from different cameras and calculates the exact 3D location of the matched point. The set of the matched points forms the 3D face. The most straightforward feature extraction is storing the entire face as a single feature vector in the database. In the feature matching stage, the target face is compared with faces in the database using statistical classification functions, using graph operators to extract the nose and eye parts and store these local features in the database. When a target face is inputted for recognition, it extracts the corresponding parts from the target faces and then searches the matched set of parts from the feature database.

2D face recognition will never have the accuracy needed for accurate Unsupervised Identity Verification and Authentication. This variability creates significant overlapping similarity between the 2D features of different humans and confuses the 2D algorithms, preventing them from achieving highly accurate F.A.R.s at usable F.R.R.s. 3D technology has recently evolved in various fields, such as access control, health imaging, and topography. It provides an illusion of Depth and makes simulating actual reality possible. Humans and animals are endowed with eyes, right and left, comprising a cornea, retina, and pupil, functioning as a sophisticated camera. An image enters each pupil as a 2D image, transmitted by neurons to the brain, and combined into a 3D image having the depth effect. The element that gives the 3D effect is the distance between the two pupils, approximately 6.35 cm. In birds, the distance between the pupils is more significant, allowing them to see their 3D prey image from huge distances. 3D cameras imitate the same concept of two parallel lenses with a distance of about 6.5 cm between their centers. The camera takes two pictures simultaneously with both lenses and a 3D image is generated with embedded software. 3D images are used in medicine, security, and smart home applications. This paper elaborates on a simplified, affordable, real-time, and calibratable method of transforming 2D images to 3D, generating a secured image I.D. with a unique embedded secret. We propose a system that connects two standard cameras mounted on an ordinary bar, allowing the calibration of the distance between the lenses of the two mounted cameras. Hence, the user can determine the camera's position, achieving vision of distant objects in 3D online. We propose adding several new features to the standard 3D image features, such as the distance between the camera lenses and between the cameras and the subject and distortion. We describe the required mechanical setup with calibration capabilities, real-time synchronization between the two cameras, and the composition process of building the 3D image by discovering interesting points common to the two 2D images and applying a stitching mechanism to design the desired secured 3D image.

II. Literature Review

We review articles on the main subjects relevant to our research. We first present papers approving that 3D recognition is better than 2D recognition due to added features, geometry, and better security resistance. The first stage in our proposal is 3D construction from two 2D images. Therefore, we outline several methods for how to transform 2D to 3D. Since this work is about 3D Authentication, we outline 3D face recognition methods.

3D face recognition is more accurate than 2D face recognition: Jing, Y et al. [1] comprehensively explain 3D face recognition, attributing face geometry and deep learning as the main drive for new developments. The use of A.I. methods help minimize the number of features and speed up the recognition process, making it suitable for near real-time applications, such as our proposal. Z.H.D. Eng et al. [2] claim that 3D face recognition is more accurate than 2D due to the geometric features 3D has and justifies our approach of utilizing 2D images to compose a reliable 3D image. Authors claim this is different when comparing 2D and 3D inverted faces due to the lack of 3D stereoscopic effects that influence face recognition during holistic processing but not during featural processing.

Generating 3D images from 2D images: An approach of transforming 2D images to 3D [3, 4], utilizing low-level linear features, neglecting extracted planar facades, or higher-order features. However, this approach is biased towards large elements such as buildings and does not fit face images. Xin Wen et al. [5] suggest reconstructing a 3D shape from a 2D image by capturing the 2D semantic features and reconstructing them through a 3D decoder of various forms, such as voxel, point cloud, and mesh. Although we get a 3D image, it needs to be completed and consistent concerning the feature richness, which is a crucial foundation of our proposal. Another attempt to generate a 3D from a 2D image is described in [6]; they introduce an automatic extension of Generative adversarial networks (GANs) images to become 3D aware, near 3D but not yet a complete 3D as it still lacking the 3D geometry and thus insufficient for our purpose. In [7], they highlight two issues in the [6] proposal: the function has a local perspective, needs to include the global view, and avoids producing high-resolution results, increasing the optimization difficulty. To cope with these problems, they propose explicitly learning a structural and textural representation. It learns a feature volume representing the underlying structure and then converts it to a feature field. The feature field is then summed into a 2D map as the textural representation, followed by a neural renderer for appearance merge, providing independent control of the shape and the appearance. Haochen Wang et al. [8] repurpose aggregating 2D scores at multiple camera viewpoints into a 3D score by using 2D images to predict a vector field of gradients, activate a chain rule on these gradients, and circulate the score of a diffusion model via the Jacobian of a differentiable renderer. This process requires many 2D images for the training stage to apply an ML complex mechanism, which is different from our goal of a fast, simple, affordable, and based on a firm concept such as mimicking the human eye. To speed up the process, [9] propose I2P-MAE and acquire superior 3D representations from 2D pre-trained models through Image-to-Point Masked Autoencoders.

3D face recognition methods (3DFR): Menghan et al. [10] provide a comprehensive 3DFR survey describing the standard and up-to-date methods, including feature extraction, classification, and disadvantages such as pose, illumination, expression variations, self-occlusion, and spoofing attack. [11] proposes to start with enhancing the image quality, apply a deep-learning (DL) based distance ternary search, extract key features, and execute the MIT-CBCL face recognition using Texas 3D face databases, obtaining 99.31% accuracy. W. Yang et al. [12] proposed injecting the head pose and facial expression variation between video frames into a face image to learn 3D face shapes and then extracting and reversing the injected variation to reconstruct the face image to its original state. During training, the model learns to decouple the pose and expression properties for performing cycle-consistent face reconstruction. Chen, G.Y [13] introduces selective denoising with block-matching and 3D filtering (BM3D), computes filter faces, and extracts the Histogram of Oriented Gradient (H.O.G.) features from the extracted feature maps, achieves the correct classification rate (98.4%) for the Extended Yale Face dataset B and similar results (100%) for the CMU-PIE datasets. For hyperspectral face recognition, the method achieves a perfect classification rate (100%) for the PolyU-HSFD and the CMU-HSFD dataset and dataset. Qi Wang et al. [14] claim that the point clouds lack detailed textures, causing facial features to be affected when expression or head pose changes. Therefore, it proposes a unique face recognition network comprising an operator based on a local feature descriptor and a feature enhancement mechanism to enhance the discrimination of facial features.

III. The Matching Process

Standard Identification and Authorization systems are done in two processes, Enrollment and Authentication, as described in Fig. 1. At the Enrollment step, the person's picture is taken, and its features are extracted and saved in the database. Later, when the person tries to access a secured resource, his picture is taken, and its features are extracted and matched against any of the features in the database by the Feature Matcher. If the extracted features match any features set in the database, the access is approved; otherwise, it is denied. In our proposal, we change the matching process to a 3D image matching instead of a 2D matching process, where the core change is in the enhanced features associated with a 3D image Vs. a 2D image, and in addition, several more features representing the measurements of the transformation from 2D to 3D, such as the distance between lenses and the distance between the cameras and the prospect, at the image taking moment. The 3D feature values are unique to each distance between the camera lenses or between the cameras and the prospect. This difference is the secret hidden behind the 3d image features. This attribute makes the 3D comparison very reliable with very low F.R.R. and ERR measurements.

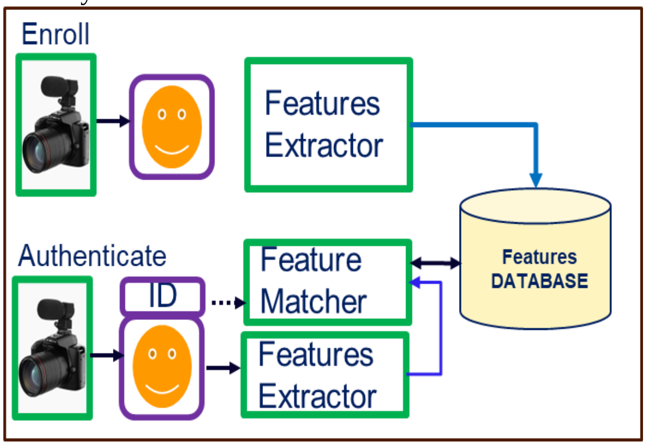

Figure 1: Enrollment and Feature Macher

Fig.2 depicts the three-stagetransformation of a pair of2D images into one 3D image.The processes are designated by the numbers 1, 2, and 3, while the outcome of each process is designated by the lettersa, b, c. In stage 1, the two cameras are syncedand simultaneously shot to createidentical images of the prospect from two different angles. a. This stage is performed by a process developed in C++. The algorithm starts by reading the two images, validating their completeness and correct synchronization, and saves them asR.jpg and L.jpg, ready for the next stage, mergingthem into a 3D image. In stage 2, the two 2D images are merged to generate one 3D image, b.A Python module does this in three steps. Step 1: Scan the images to identify their "interesting points" using the Haris algorithm. Step 2: Identifycommon interesting pointsto the two images and apply the Image“stitching algorithm”to combine the two images into one panoramic image.Step 3: We use the "Epipolar Line" algorithm. More details about Epipolar Geometry and the associated code can be found at [16].

In stage 3, features are extracted from the 3Dimageby adding the following features: distance between the two cameras and from the subject and % distortion.Before executing the transformation process, the system is set by the followingattributes: a. The distance between the two cameras. b. The cameras' location defines the exact distance from the subject. c. The feature-extract algorithms are to be used in stage 3. These setup parameters will be added to the features list of the 3D image.

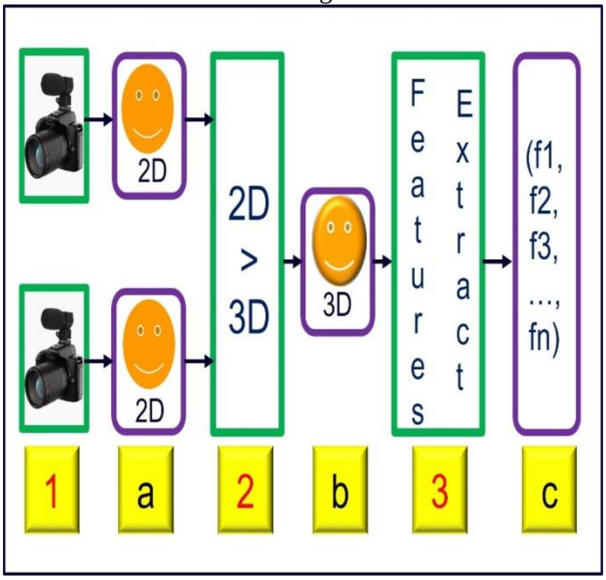

Figure 2: The extended matching process incorporating the 2D to 3D transformation.

AS mentioned earlier, in stage 2, the two 2D images are merged to generate one 3D image, as depicted in Fig. 3. The 3D construction was developed in the Python language in three steps. Step 1: Scan the images to discover their "interesting points" using the Multi-Scale Harris algorithm [15], which has been proven to be most stable against rotation and noise and insensitive to scale change. The algorithm consists of two main stages. In stage one, candidate interesting points are found for each scale level, and in stage two, the stability of each point is measured, and based on the measure, the final "interesting point" is selected from candidates. Step 2 identifies common "interesting points" to the two images and applies the Image "stitching algorithm" to combine the two images into one panoramic image. Step 3: We use the "Epipolar Line" algorithm [16] to combine the images into one 3D image. Multiple-view geometry relates the camera points in 3D, and the corresponding observation is called the Epipolar geometry of a stereo pair. In Stage 3, features are extracted from the 3D image using a standard method. With the addition of the following features: Distance between the two cameras and from the subject and % distortion. Before executing the transformation process, the system is set by the following attributes: a. The Distance between the two cameras. b. The cameras' location defines the exact Distance from the subject. c. The feature-extract algorithms are to be used in stage 3. These setup parameters will be added to the features list of the 3D image.

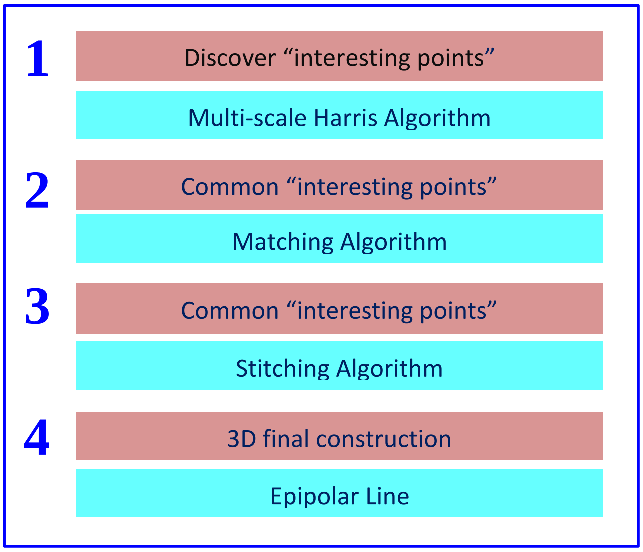

Figure 3: The process of constructing 3D image from two 2D images

IV. Experiment

The experiment is divided into two consecutive stages: 1. constructing a 3D image from two 2D identical images taken from different locations. 2. testing of the identification and authentication accuracy.

Constructing the 3D image out of 2D images: This experiment aims to prove the feasibility and quality of our merging process of two 2D images into one 3D image. We started the experiment with large non-human objects. We photographed the object simultaneously from three cameras, two 2D cameras and one 3D camera. We applied our 2D to 3D transformation, compared the resulting 3D image with the 3D image from the third camera, and found the images very similar, proving our proposal's accuracy. After applying some distortions to avoid face identification, we repeated the experiment with a human face. Fig.4a and 4b show the two input 2D objects and the resulting 3D image, 4c. We repeated the same experiment, analyzed all the intermediate results, and found the same results, proving that the process is accurate, reliable, and robust. We continued testing with more real faces and got similar results. The features of image 4c contain the additional features of the distance between the camera and the distance between the cameras and the subject, which proves the feasibility of the physical setup to merge two images into one 3D image.

We proceeded with the experiment with 12 adults. We first took a picture of their face and transformed it into a 3D image with our system, extracted its features, and saved them in the database. We asked them to come again and go through the same process with the same setup and distance from the camera. We compared each 2D image feature to the 3D features in the database, and as expected, there was no match. We then extracted the 3D features, compared them to the database features, and found a match. We asked the person to repeat the process, but the distance from the cameras was lower than the one in the database. We repeated the same for the following nine people. In two cases, the system ended with no match, while in reality, it is the same person due to the very tight numbers and hence sensitive to the exact measures. It is handled by setting a threshold to allow a small grace margin.

Further testing is planned when we continue this project. Fig.5 depicts the physical experiment setup. On top is a mounted computer, which controls the camera synchronization, collects the images from the two cameras, and processes them to get the desired 3D image. Below the computer are two cameras mounted on the horizontal pole, having a mechanism to adjust the distance between them. The cameras are connected to the computer system at the top. The system controls the distance between the cameras, schedules the simultaneous shooting of both cameras, accepts the 2D images, merges them into a 3D image, and saves the extended features of the 3D image. Our proposed system of constructing the 3D image is feasible, reliable, robust, affordable, and easy to implement, and hence, appropriate to be used as a platform for 3D face authentication.

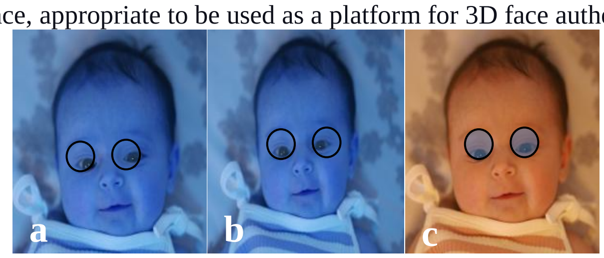

Figure 4: From 2D (a, b) to 3D © images

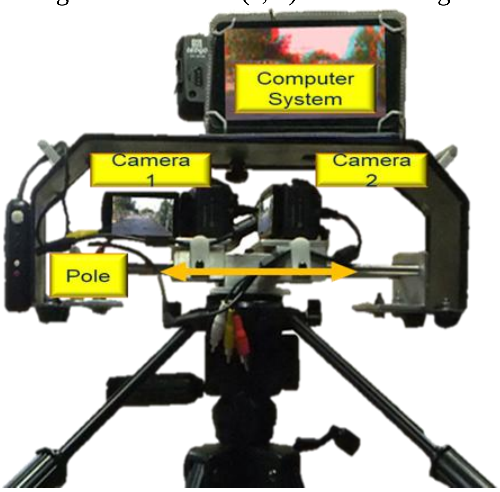

Figure 5: The experiment's physical setup

Testing the feasibility and accuracy of our proposal towards the identification and Authentication: We started with setting up the cameras stand in a solid location, set the distance between the two cameras to 6.5 cm, and designated the person's distance of 150 cm from the cameras. We asked the person to stand at the designated location. Photograph the person by the two cameras simultaneously, transmit the two images to the on-top mounted computer, which activates the 3D contraction application and generates a 3D image, and finally extract the features from the 3D image, add to the features list three more features, the inter-camera distance of 6.5 cm, the 100 cm distance between the person and the cameras, and the distortion of 4%. Store the collected features in the database with the persons' I.D. and demographic data. The registration of the person is complete.

In the next step, we authenticate the same person. We asked the person to repeat the registration photography and get a current 3D image and its features list. We then compared the current 3D features to those stored in the database, and they match. We then changed the person's distance from the camera to 150 cm, constructing the 3D image and features. We found differences in the generic 3D features and the three extended features. We repeated the test but changed the inter-cameras distance to 6.8cm, and again, it did not match the generic and the extended features, meaning that changing the photography setup impacts the 3D image and the corresponding features.

IV. Conclusions

This work described a simple, affordable, solid face-authentication process based on two 2D person images taken simultaneously, given specific inter-cameras and person-to-camera distances. We performed an experiment feasibility testing and an initial test of a few cases. Soon, we plan a comprehensive test using about 200-300 people's faces who will agree to take part in our experiment. In the future, we will consider 3 and 4 cameras activated simultaneously and explore their contribution to authentication accuracy and long-term operations.

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