Menpo Documentation

Release 0.8.0

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May 05, 2017

Contents

1 API Documentation **3**
1.1 menpo.base . . . 3
1.2 menpo.io . . . 7
1.3 menpo.image . . . 18
1.4 menpo.feature . . . 96
1.5 menpo.landmark . . . 110
1.6 menpo.math . . . 142
1.7 menpo.model . . . 148
1.8 menpo.shape . . . 178
1.9 menpo.transform . . . 319
1.10 menpo.visualize . . . 390
1.11 Changelog . . . 403

Menpo is a Python package designed to make manipulating annotated data more simple. In particular, sparse locations on either images or meshes, referred to as **landmarks** within Menpo, are tightly coupled with their reference objects. For areas such as Computer Vision that involve learning models based on prior knowledge of object location (such as object detection and landmark localisation), Menpo is a very powerful toolkit.

A short example is often more illustrative than a verbose explanation. Let's assume that you want to load a set of images that have been annotated with bounding boxes, and that these bounding box locations live in text files next to the images. Here's how we would load the images and extract the areas within the bounding boxes using Menpo:

```
import menpo.io as mio

images = []
for image in mio.import_images('./images_folder'):
    images.append(image.crop_to_landmarks())
```

Where `import_images` returns a `LazyList` to keep memory usage low.

Although the above is a very simple example, we believe that being able to easily manipulate and couple landmarks with images *and* meshes, is an important problem for building powerful models in areas such as facial point localisation.

Finally, please refer to Menpo's *Changelog* for a list of changes per release.

CHAPTER 1

API Documentation

This section attempts to provide a simple browsing experience for the Menpo documentation. In Menpo, we use legible docstrings, and therefore, all documentation should be easily accessible in any sensible IDE (or IPython) via tab completion. However, this section should make most of the core classes available for viewing online.

menpo.base

Core

Core interfaces of Menpo.

Copyable

class menpo.base.**Copyable**

Bases: object

Efficient copying of classes containing numpy arrays.

Interface that provides a single method for copying classes very efficiently.

copy()

Generate an efficient copy of this object.

Note that Numpy arrays and other *Copyable* objects on self will be deeply copied. Dictionaries and sets will be shallow copied, and everything else will be assigned (no copy will be made).

Classes that store state other than numpy arrays and immutable types should overwrite this method to ensure all state is copied.

Returns type(self) – A copy of this object

Vectorizable

class menpo.base.**Vectorizable**

Bases: *Copyable*

Flattening of rich objects to vectors and rebuilding them back.

Interface that provides methods for 'flattening' an object into a vector, and restoring from the same vectorized form. Useful for statistical analysis of objects, which commonly requires the data to be provided as a single vector.

as_vector(***kwargs*)

Returns a flattened representation of the object as a single vector.

Returns **vector** (*(N,) ndarray*) – The core representation of the object, flattened into a single vector. Note that this is always a view back on to the original object, but is not writable.

copy()

Generate an efficient copy of this object.

Note that Numpy arrays and other *Copyable* objects on `self` will be deeply copied. Dictionaries and sets will be shallow copied, and everything else will be assigned (no copy will be made).

Classes that store state other than numpy arrays and immutable types should overwrite this method to ensure all state is copied.

Returns `type(self)` – A copy of this object

from_vector(*vector*)

Build a new instance of the object from it's vectorized state.

`self` is used to fill out the missing state required to rebuild a full object from it's standardized flattened state. This is the default implementation, which is which is a `deepcopy` of the object followed by a call to *from_vector_inplace()*. This method can be overridden for a performance benefit if desired.

Parameters **vector** (`(n_parameters,)` *ndarray*) – Flattened representation of the object.

Returns **object** (`type(self)`) – An new instance of this class.

from_vector_inplace(*vector*)

Deprecated. Use the non-mutating API, *from_vector*.

For internal usage in performance-sensitive spots, see *_from_vector_inplace()*

Parameters **vector** (`(n_parameters,)` *ndarray*) – Flattened representation of this object

has_nan_values()

Tests if the vectorized form of the object contains `nan` values or not. This is particularly useful for objects with unknown values that have been mapped to `nan` values.

Returns **has_nan_values** (*bool*) – If the vectorized object contains `nan` values.

n_parameters

The length of the vector that this object produces.

Type *int*

Targetable

class menpo.base.**Targetable**

Bases: *Copyable*

Interface for objects that can produce a target *PointCloud*.

This could for instance be the result of an alignment or a generation of a *PointCloud* instance from a shape model.

Implementations must define sensible behavior for:

- what a target is: see *target*
- how to set a target: see *set_target()*
- how to update the object after a target is set: see `_sync_state_from_target()`
- how to produce a new target after the changes: see `_new_target_from_state()`

Note that `_sync_target_from_state()` needs to be triggered as appropriate by subclasses e.g. when *from_vector_inplace* is called. This will in turn trigger `_new_target_from_state()`, which each subclass must implement.

copy()

Generate an efficient copy of this object.

Note that Numpy arrays and other *Copyable* objects on `self` will be deeply copied. Dictionaries and sets will be shallow copied, and everything else will be assigned (no copy will be made).

Classes that store state other than numpy arrays and immutable types should overwrite this method to ensure all state is copied.

Returns `type(self)` – A copy of this object

set_target(*new_target*)

Update this object so that it attempts to recreate the `new_target`.

Parameters **new_target** (*PointCloud*) – The new target that this object should try and regenerate.

n_dims

The number of dimensions of the *target*.

Type *int*

n_points

The number of points on the *target*.

Type *int*

target

The current *PointCloud* that this object produces.

Type *PointCloud*

LazyList

class menpo.base.**LazyList**(*callables*)

Bases: `Sequence`, *Copyable*

An immutable sequence that provides the ability to lazily access objects. In truth, this sequence simply wraps a list of callables which are then indexed and invoked. However, if the callable represents a function that lazily access memory, then this list simply implements a lazy list paradigm.

When slicing, another *LazyList* is returned, containing the subset of callables.

Parameters **callables** (list of *callable*) – A list of *callable* objects that will be invoked if directly indexed.

copy()

Generate an efficient copy of this LazyList - copying the underlying callables will be lazy and shallow (each callable will **not** be called nor copied) but they will reside within in a new *list*.

Returns`type(self)` – A copy of this LazyList.

count(*value*) → integer – return number of occurrences of value

index(*value*) → integer – return first index of value.

Raises ValueError if the value is not present.

classmethod init_from_index_callable(*f*, *n_elements*)

Create a lazy list from a *callable* that expects a single parameter, the index into an underlying sequence. This allows for simply creating a *LazyList* from a *callable* that likely wraps another list in a closure.

Parameters

- **f** (*callable*) – Callable expecting a single integer parameter, index. This is an index into (presumably) an underlying sequence.
- **n_elements** (*int*) – The number of elements in the underlying sequence.

Returnslazy (*LazyList*) – A LazyList where each element returns the underlying indexable object wrapped by `f`.

classmethod init_from_iterable(*iterable*, *f=None*)

Create a lazy list from an existing iterable (think Python *list*) and optionally a *callable* that expects a single parameter which will be applied to each element of the list. This allows for simply creating a *LazyList* from an existing list and if no *callable* is provided the identity function is assumed.

Parameters

- **iterable** (*collections.Iterable*) – An iterable object such as a *list*.
- **f** (*callable*, optional) – Callable expecting a single parameter.

Returnslazy (*LazyList*) – A LazyList where each element returns each item of the provided iterable, optionally with *f* applied to it.

map(*f*)

Create a new LazyList where the passed callable `f` wraps each element.

`f` should take a single parameter, `x`, that is the result of the underlying callable - it must also return a value. Note that mapping is lazy and thus calling this function should return immediately.

Alternatively, `f` may be a list of *callable*, one per entry in the underlying list, with the same specification as above.

Parametersf (*callable* or *iterable* of *callable*) – Callable to wrap each element with. If an iterable of callables (think list) is passed then it **must** by the same length as this LazyList.

Returnslazy (*LazyList*) – A new LazyList where each element is wrapped by (each) `f`.

repeat(*n*)

Repeat each item of the underlying LazyList `n` times. Therefore, if a list currently has `D` items, the returned list will contain `D * n` items and will return immediately (method is lazy).

Parametersn (*int*) – The number of times to repeat each item.

Returnslazy (*LazyList*) – A LazyList where each element returns each item of the provided iterable, optionally with *f* applied to it.

Examples

```
>>> from menpo.base import LazyList
>>> ll = LazyList.init_from_list([0, 1])
>>> repeated_ll = ll.repeat(2)  # Returns immediately
>>> items = list(repeated_ll)   # [0, 0, 1, 1]
```

Convenience

menpo_src_dir_path

menpo.base.**menpo_src_dir_path**()

The path to the top of the menpo Python package.

Useful for locating where the data folder is stored.

Returnspath (pathlib.Path) – The full path to the top of the Menpo package

name_of_callable

menpo.base.**name_of_callable**(*c*)

Return the name of a callable (function or callable class) as a string. Recurses on partial function to attempt to find the wrapped methods actual name.

Parametersc (*callable*) – A callable class or function, or any valid Python object that can be wrapped with partial.

Returnsname (*str*) – The name of the passed object.

Warnings and Exceptions

MenpoDeprecationWarning

class menpo.base.**MenpoDeprecationWarning**

Bases: Warning

A warning that functionality in Menpo will be deprecated in a future major release.

MenpoMissingDependencyError

class menpo.base.**MenpoMissingDependencyError**(*package_name*)

Bases: Exception

An exception that a dependency required for the requested functionality was not detected.

menpo.io

Input

import_image

menpo.io.**import_image**(*filepath*, *landmark_resolver=<function same_name>*, *normalize=None*, *normalise=None*)

Single image (and associated landmarks) importer.

If an image file is found at *filepath*, returns an `Image` or subclass representing it. By default, landmark files sharing the same filename stem will be imported and attached with a group name based on the extension of the landmark file, although this behavior can be customised (see *landmark_resolver*). If the image defines a mask, this mask will be imported.

Parameters

- **filepath** (*pathlib.Path* or *str*) – A relative or absolute filepath to an image file.
- **landmark_resolver** (*function* or *None*, optional) – This function will be used to find landmarks for the image. The function should take one argument (the path to the image) and return a dictionary of the form `{'group_name': 'landmark_filepath'}` Default finds landmarks with the same name as the image file. If `None`, landmark importing will be skipped.
- **normalize** (*bool*, optional) – If `True`, normalize the image pixels between 0 and 1 and convert to floating point. If false, the native datatype of the image will be maintained (commonly *uint8*). Note that in general Menpo assumes `Image` instances contain floating point data - if you disable this flag you will have to manually convert the images you import to floating point before doing most Menpo operations. This however can be useful to save on memory usage if you only wish to view or crop images.
- **normalise** (*bool*, optional) – Deprecated version of normalize. Please use the normalize arg.

Returnsimages (`Image` or list of) – An instantiated `Image` or subclass thereof or a list of images.

import_images

menpo.io.**import_images**(*pattern*, *max_images=None*, *shuffle=False*, *landmark_resolver=<function same_name>*, *normalize=None*, *normalise=None*, *as_generator=False*, *verbose=False*)

Multiple image (and associated landmarks) importer.

For each image found creates an importer than returns a `Image` or subclass representing it. By default, landmark files sharing the same filename stem will be imported and attached with a group name based on the extension of the landmark file, although this behavior can be customised (see *landmark_resolver*). If the image defines a mask, this mask will be imported.

Note that this is a function returns a `LazyList`. Therefore, the function will return immediately and indexing into the returned list will load an image at run time. If all images should be loaded, then simply wrap the returned `LazyList` in a Python *list*.

Parameters

- **pattern** (*str*) – A glob path pattern to search for images. Every image found to match the glob will be imported one by one. See `image_paths` for more details of what images will be found.
- **max_images** (positive *int*, optional) – If not `None`, only import the first `max_images` found. Else, import all.
- **shuffle** (*bool*, optional) – If `True`, the order of the returned images will be randomised. If `False`, the order of the returned images will be alphanumerically ordered.

- **landmark_resolver** (*function* or *None*, optional) – This function will be used to find landmarks for the image. The function should take one argument (the image itself) and return a dictionary of the form `{'group_name': 'landmark_filepath'}` Default finds landmarks with the same name as the image file. If `None`, landmark importing will be skipped.
- **normalize** (*bool*, optional) – If `True`, normalize the image pixels between 0 and 1 and convert to floating point. If false, the native datatype of the image will be maintained (commonly *uint8*). Note that in general Menpo assumes `Image` instances contain floating point data - if you disable this flag you will have to manually convert the images you import to floating point before doing most Menpo operations. This however can be useful to save on memory usage if you only wish to view or crop images.
- **normalise** (*bool*, optional) – Deprecated version of normalize. Please use the normalize arg.
- **as_generator** (*bool*, optional) – If `True`, the function returns a generator and assets will be yielded one after another when the generator is iterated over.
- **verbose** (*bool*, optional) – If `True` progress of the importing will be dynamically reported with a progress bar.

Returnslazy_list (`LazyList` or generator of `Image`) – A `LazyList` or generator yielding `Image` instances found to match the glob pattern provided.

Raises`ValueError` – If no images are found at the provided glob.

Examples

Import images at 20% scale from a huge collection:

```
>>> rescale_20p = lambda x: x.rescale(0.2)
>>> images =  menpo.io.import_images('./massive_image_db/*')  # Returns␣
↪immediately
>>> images = images.map(rescale_20p)  # Returns immediately
>>> images[0]  # Get the first image, resize, lazily loaded
```

import_video

`menpo.io.`**`import_video`**(*filepath*, *landmark_resolver=<function same_name_video>*, *normalize=None*, *normalise=None*, *importer_method='ffmpeg'*, *exact_frame_count=True*)

Single video (and associated landmarks) importer.

If a video file is found at *filepath*, returns an `LazyList` wrapping all the frames of the video. By default, landmark files sharing the same filename stem will be imported and attached with a group name based on the extension of the landmark file appended with the frame number, although this behavior can be customised (see *landmark_resolver*).

> **Warning:** This method currently uses ffmpeg to perform the importing. In order to recover accurate frame counts from videos it is necessary to use ffprobe to count the frames. This involves reading the entire video in to memory which may cause a delay in loading despite the lazy nature of the video loading within Menpo. If ffprobe cannot be found, and *exact_frame_count* is `False`, Menpo falls back to ffmpeg itself which is not accurate and the user should proceed at their own risk.

Parameters

- **filepath** (*pathlib.Path* or *str*) – A relative or absolute filepath to a video file.
- **landmark_resolver** (*function* or *None*, optional) – This function will be used to find landmarks for the video. The function should take two arguments (the path to the video and the frame number) and return a dictionary of the form `{'group_name': 'landmark_filepath'}` Default finds landmarks with the same name as the video file, appended with '_{frame_number}'. If `None`, landmark importing will be skipped.
- **normalize** (*bool*, optional) – If `True`, normalize the frame pixels between 0 and 1 and convert to floating point. If `False`, the native datatype of the image will be maintained (commonly *uint8*). Note that in general Menpo assumes `Image` instances contain floating point data - if you disable this flag you will have to manually convert the farmes you import to floating point before doing most Menpo operations. This however can be useful to save on memory usage if you only wish to view or crop the frames.
- **normalise** (*bool*, optional) – Deprecated version of normalize. Please use the normalize arg.
- **importer_method** (*{'ffmpeg'}, optional*) – A string representing the type of importer to use, by default ffmpeg is used.
- **exact_frame_count** (*bool*, optional) – If `True`, the import fails if ffprobe is not available (reading from ffmpeg's output returns inexact frame count)

Returnsframes (`LazyList`) – An lazy list of `Image` or subclass thereof which wraps the frames of the video. This list can be treated as a normal list, but the frame is only read when the video is indexed or iterated.

Examples

```
>>> video = menpo.io.import_video('video.avi')
>>> # Lazily load the 100th frame without reading the entire video
>>> frame100 = video[100]
```

import_videos

`menpo.io.`**`import_videos`**(*pattern*, *max_videos=None*, *shuffle=False*, *landmark_resolver=<function same_name_video>*, *normalize=None*, *normalise=None*, *importer_method='ffmpeg'*, *exact_frame_count=True*, *as_generator=False*, *verbose=False*)

Multiple video (and associated landmarks) importer.

For each video found yields a `LazyList`. By default, landmark files sharing the same filename stem will be imported and attached with a group name based on the extension of the landmark file appended with the frame number, although this behavior can be customised (see *landmark_resolver*).

Note that this is a function returns a `LazyList`. Therefore, the function will return immediately and indexing into the returned list will load an image at run time. If all images should be loaded, then simply wrap the returned `LazyList` in a Python *list*.

> **Warning:** This method currently uses ffmpeg to perform the importing. In order to recover accurate frame counts from videos it is necessary to use ffprobe to count the frames. This involves reading the entire video in to memory which may cause a delay in loading despite the lazy nature of the video loading within Menpo.

If ffprobe cannot be found, and *exact_frame_count* is `False`, Menpo falls back to ffmpeg itself which is not accurate and the user should proceed at their own risk.

Parameters

- **pattern** (*str*) – A glob path pattern to search for videos. Every video found to match the glob will be imported one by one. See `video_paths` for more details of what videos will be found.
- **max_videos** (positive *int*, optional) – If not `None`, only import the first `max_videos` found. Else, import all.
- **shuffle** (*bool*, optional) – If `True`, the order of the returned videos will be randomised. If `False`, the order of the returned videos will be alphanumerically ordered.
- **landmark_resolver** (*function* or *None*, optional) – This function will be used to find landmarks for the video. The function should take two arguments (the path to the video and the frame number) and return a dictionary of the form `{'group_name': 'landmark_filepath'}` Default finds landmarks with the same name as the video file, appended with '_{frame_number}'. If `None`, landmark importing will be skipped.
- **normalize** (*bool*, optional) – If `True`, normalize the frame pixels between 0 and 1 and convert to floating point. If `False`, the native datatype of the image will be maintained (commonly *uint8*). Note that in general Menpo assumes `Image` instances contain floating point data - if you disable this flag you will have to manually convert the frames you import to floating point before doing most Menpo operations. This however can be useful to save on memory usage if you only wish to view or crop the frames.
- **normalise** (*bool*, optional) – Deprecated version of normalize. Please use the normalize arg.
- **importer_method** (*`{'ffmpeg'}`, optional*) – A string representing the type of importer to use, by default ffmpeg is used.
- **as_generator** (*bool*, optional) – If `True`, the function returns a generator and assets will be yielded one after another when the generator is iterated over.
- **exact_frame_count** (*bool*, optional) – If True, the import fails if ffmprobe is not available (reading from ffmpeg's output returns inexact frame count)
- **verbose** (*bool*, optional) – If `True` progress of the importing will be dynamically reported with a progress bar.

Returnslazy_list (`LazyList` or generator of `LazyList`) – A `LazyList` or generator yielding `LazyList` instances that wrap the video object.

Raises`ValueError` – If no videos are found at the provided glob.

Examples

Import videos at and rescale every frame of each video:

```
>>> videos = []
>>> for video in menpo.io.import_videos('./set_of_videos/*'):
>>>     frames = []
>>>     for frame in video:
>>>         # rescale to a sensible size as we go
>>>         frames.append(frame.rescale(0.2))
>>>     videos.append(frames)
```

import_landmark_file

`menpo.io.import_landmark_file`(*filepath*, *asset=None*)

Single landmark file importer.

If a landmark file is found at `filepath`, returns a `PointCloud` or `LabelledPointUndirectedGraph` depending on the format of the landmark file.

Parameters **filepath** (*pathlib.Path* or *str*) – A relative or absolute filepath to an landmark file.

Returns **landmarks** (`LabelledPointUndirectedGraph` or `PointCloud`) – The shape that the file format represents.

import_landmark_files

`menpo.io.import_landmark_files`(*pattern*, *max_landmarks=None*, *shuffle=False*, *as_generator=False*, *verbose=False*)

Import Multiple landmark files.

For each landmark file found returns an importer then returns a `LabelledPointUndirectedGraph` or a `PointCloud`.

Note that this is a function returns a `LazyList`. Therefore, the function will return immediately and indexing into the returned list will load the landmarks at run time. If all landmarks should be loaded, then simply wrap the returned `LazyList` in a Python *list*.

Parameters

- **pattern** (*str*) – A glob path pattern to search for landmark files. Every landmark file found to match the glob will be imported one by one. See `landmark_file_paths` for more details of what landmark files will be found.
- **max_landmarks** (positive *int*, optional) – If not `None`, only import the first `max_landmark_files` found. Else, import all.
- **shuffle** (*bool*, optional) – If `True`, the order of the returned landmark files will be randomised. If `False`, the order of the returned landmark files will be alphanumerically ordered.
- **as_generator** (*bool*, optional) – If `True`, the function returns a generator and assets will be yielded one after another when the generator is iterated over.
- **verbose** (*bool*, optional) – If `True` progress of the importing will be dynamically reported.

Returns **lazy_list** (`LazyList` or generator) – A `LazyList` or generator yielding `PointCloud` or `LabelledPointUndirectedGraph` instances found to match the glob pattern provided.

Raises `ValueError` – If no landmarks are found at the provided glob.

import_pickle

`menpo.io.import_pickle`(*filepath*, ***kwargs*)

Import a pickle file of arbitrary Python objects.

Menpo unambiguously uses `.pkl` as it's choice of extension for Pickle files. Menpo also supports automatic importing and exporting of gzip compressed pickle files - just choose a `filepath` ending `pkl.gz` and gzip compression will automatically be applied. Compression can massively reduce the filesize of a pickle file at the cost of longer import and export times.

Parameters **filepath** (*pathlib.Path* or *str*) – A relative or absolute filepath to a `.pkl` or `.pkl.gz` file.

Returns **object** (*object*) – Whatever Python objects are present in the Pickle file

import_pickles

`menpo.io.`**`import_pickles`**(*pattern*, *max_pickles=None*, *shuffle=False*, *as_generator=False*, *verbose=False*, ***kwargs*)

Multiple pickle importer.

Menpo unambiguously uses `.pkl` as it's choice of extension for Pickle files. Menpo also supports automatic importing and exporting of gzip compressed pickle files - just choose a `filepath` ending `pkl.gz` and gzip compression will automatically be applied. Compression can massively reduce the filesize of a pickle file at the cost of longer import and export times.

Note that this is a function returns a `LazyList`. Therefore, the function will return immediately and indexing into the returned list will load a pickle at run time. If all pickles should be loaded, then simply wrap the returned `LazyList` in a Python *list*.

Parameters

- **pattern** (*str*) – A glob path pattern to search for pickles. Every pickle found to match the glob will be imported one by one. See `pickle_paths` for more details of what pickles will be found.
- **max_pickles** (positive *int*, optional) – If not `None`, only import the first `max_pickles` found. Else, import all.
- **shuffle** (*bool*, optional) – If `True`, the order of the returned pickles will be randomised. If `False`, the order of the returned pickles will be alphanumerically ordered.
- **as_generator** (*bool*, optional) – If `True`, the function returns a generator and assets will be yielded one after another when the generator is iterated over.
- **verbose** (*bool*, optional) – If `True` progress of the importing will be dynamically reported with a progress bar.

Returns **lazy_list** (`LazyList` or generator of Python objects) – A `LazyList` or generator yielding whatever Python objects are present in the Pickle file instances that match the glob pattern provided.

Raises `ValueError` – If no pickles are found at the provided glob.

import_builtin_asset

`menpo.io.`**`import_builtin_asset`**()

This is a dynamically generated method. This method is designed to automatically generate import methods for each data file in the `data` folder. This method it designed to be tab completed, so you do not need to call this method explicitly. It should be treated more like a property that will dynamically generate functions that will import the shipped data. For example:

```
>>> import menpo
>>> bb_image = menpo.io.import_builtin_asset.breakingbad_jpg()
```

register_image_importer

`menpo.io.register_image_importer(extension, callable)`

Register a new importer for the given extension.

Parameters

- **ext_map** (*{'str' -> 'callable'}* dict) – Extensions map to callable.
- **extension** (*str*) – File extension to support. May be multi-part e.g. '.tar.gz'
- **callable** (*callable*) – The callable to invoke if a file with the provided extension is discovered during importing. Should take a single argument (the filepath) and any number of kwargs.

register_landmark_importer

`menpo.io.register_landmark_importer(extension, callable)`

Register a new importer for the given extension.

Parameters

- **ext_map** (*{'str' -> 'callable'}* dict) – Extensions map to callable.
- **extension** (*str*) – File extension to support. May be multi-part e.g. '.tar.gz'
- **callable** (*callable*) – The callable to invoke if a file with the provided extension is discovered during importing. Should take a single argument (the filepath) and any number of kwargs.

register_pickle_importer

`menpo.io.register_pickle_importer(extension, callable)`

Register a new importer for the given extension.

Parameters

- **ext_map** (*{'str' -> 'callable'}* dict) – Extensions map to callable.
- **extension** (*str*) – File extension to support. May be multi-part e.g. '.tar.gz'
- **callable** (*callable*) – The callable to invoke if a file with the provided extension is discovered during importing. Should take a single argument (the filepath) and any number of kwargs.

register_video_importer

`menpo.io.register_video_importer(extension, callable)`

Register a new importer for the given extension.

Parameters

- **ext_map** (*{'str' -> 'callable'}* dict) – Extensions map to callable.
- **extension** (*str*) – File extension to support. May be multi-part e.g. '.tar.gz'
- **callable** (*callable*) – The callable to invoke if a file with the provided extension is discovered during importing. Should take a single argument (the filepath) and any number of kwargs.

Output

export_image

`menpo.io.export_image(image, fp, extension=None, overwrite=False)`

Exports a given image. The `fp` argument can be either a *Path* or any Python type that acts like a file. If a file is provided, the `extension` kwarg **must** be provided. If no `extension` is provided and a *str* filepath is provided, then the export type is calculated based on the filepath extension.

Due to the mix of string and file types, an explicit overwrite argument is used which is `False` by default.

Parameters

- **image** (*Image*) – The image to export.
- **fp** (*Path* or *file*-like object) – The Path or file-like object to save the object at/into.
- **extension** (*str* or None, optional) – The extension to use, this must match the file path if the file path is a string. Determines the type of exporter that is used.
- **overwrite** (*bool*, optional) – Whether or not to overwrite a file if it already exists.

Raises

- `ValueError` – File already exists and `overwrite` != `True`
- `ValueError` – `fp` is a *str* and the `extension` is not `None` and the two extensions do not match
- `ValueError` – `fp` is a *file*-like object and `extension` is `None`
- `ValueError` – The provided extension does not match to an existing exporter type (the output type is not supported).

export_video

`menpo.io.export_video(images, file_path, overwrite=False, fps=30, **kwargs)`

Exports a given list of images as a video. Ensure that all the images have the same shape, otherwise you might get unexpected results from the ffmpeg writer. The `file_path` argument is a *Path* representing the path to save the video to. At this time, it is not possible to export videos directly to a file buffer.

Due to the mix of string and file types, an explicit overwrite argument is used which is `False` by default.

Note that exporting of GIF images is also supported.

Parameters

- **images** (list of *Image*) – The images to export as a video.
- **file_path** (*Path*) – The Path to save the video at. File buffers are not supported, unlike other exporting formats.
- **overwrite** (*bool*, optional) – Whether or not to overwrite a file if it already exists.
- **fps** (*int*, optional) – The number of frames per second.
- ***kwargs** (*dict*, optional) – Extra parameters that are passed through directly to the exporter. Please see the documentation in the `menpo.io.output.video` package for information about the supported arguments.

Raises

- `ValueError` – File already exists and `overwrite` != `True`

- `ValueError` – The input is a buffer and not a valid *Path*
- `ValueError` – The provided extension does not match to an existing exporter type (the output type is not supported).

export_landmark_file

`menpo.io.`**`export_landmark_file`**(*pointcloud*, *fp*, *extension=None*, *overwrite=False*)

Exports a given shape. The `fp` argument can be either or a *str* or any Python type that acts like a file. If a file is provided, the `extension` kwarg **must** be provided. If no `extension` is provided and a *str* filepath is provided, then the export type is calculated based on the filepath extension.

Due to the mix in string and file types, an explicit overwrite argument is used which is `False` by default.

Parameters

- **`pointcloud`** (`PointCloud` or subclass) – The landmarks to export. It can be any of `PointCloud`, `PointUndirectedGraph`, `PointDirectedGraph`, `PointTree` or `LabelledPointUndirectedGraph`.
- **`fp`** (*Path* or *file*-like object) – The Path or file-like object to save the object at/into.
- **`extension`** (*str* or None, optional) – The extension to use, this must match the file path if the file path is a string. Determines the type of exporter that is used.
- **`overwrite`** (*bool*, optional) – Whether or not to overwrite a file if it already exists.

Raises

- `ValueError` – File already exists and `overwrite` != `True`
- `ValueError` – `fp` is a *str* and the `extension` is not `None` and the two extensions do not match
- `ValueError` – `fp` is a *file*-like object and `extension` is `None`
- `ValueError` – The provided extension does not match to an existing exporter type (the output type is not supported).

export_pickle

`menpo.io.`**`export_pickle`**(*obj*, *fp*, *overwrite=False*, *protocol=2*)

Exports a given collection of Python objects with Pickle.

The `fp` argument can be either a *Path* or any Python type that acts like a file. If `fp` is a path, it must have the suffix *.pkl* or *.pkl.gz*. If *.pkl*, the object will be pickled using the selected Pickle protocol. If *.pkl.gz* the object will be pickled using the selected Pickle protocol with gzip compression (at a fixed compression level of 3).

Note that a special exception is made for *pathlib.Path* objects - they are pickled down as a *pathlib.PurePath* so that pickles can be easily moved between different platforms.

Parameters

- **`obj`** (`object`) – The object to export.
- **`fp`** (*Path* or *file*-like object) – The string path or file-like object to save the object at/into.
- **`overwrite`** (*bool*, optional) – Whether or not to overwrite a file if it already exists.
- **`protocol`** (*int*, optional) – The Pickle protocol used to serialize the file. The protocols were introduced in different versions of python, thus it is recommended to save with the highest protocol version that your python distribution can support. The protocol refers to:

Protocol	Functionality
0	Simplest protocol for text mode, backwards compatible.
1	Protocol for binary mode, backwards compatible.
2	Wider support for classes, compatible with python >= 2.3.
3	Support for byte objects, compatible with python >= 3.0.
4	Support for large objects, compatible with python >= 3.4.

Raises

- `ValueError` – File already exists and `overwrite` != `True`
- `ValueError` – `fp` is a *file*-like object and `extension` is `None`
- `ValueError` – The provided extension does not match to an existing exporter type (the output type is not supported).

Path Operations

image_paths

`menpo.io.`**`image_paths`**(*pattern*)

Return image filepaths that Menpo can import that match the glob pattern.

landmark_file_paths

`menpo.io.`**`landmark_file_paths`**(*pattern*)

Return landmark file filepaths that Menpo can import that match the glob pattern.

pickle_paths

`menpo.io.`**`pickle_paths`**(*pattern*)

Return pickle filepaths that Menpo can import that match the glob pattern.

video_paths

`menpo.io.`**`video_paths`**(*pattern*)

Return video filepaths that Menpo can import that match the glob pattern.

data_path_to

`menpo.io.`**`data_path_to`**(*asset_filename*)

The path to a builtin asset in the ./data folder on this machine.

Parameters`asset_filename` (*str*) – The filename (with extension) of a file builtin to Menpo. The full set of allowed names is given by `ls_builtin_assets()`

Returns`data_path` (*pathlib.Path*) – The path to a given asset in the ./data folder

Raises`ValueError` – If the asset_filename doesn't exist in the *data* folder.

data_dir_path

`menpo.io.data_dir_path()`

A path to the built in ./data folder on this machine.

Returns **path** (`pathlib.Path`) – The path to the local ./data folder

ls_builtin_assets

`menpo.io.ls_builtin_assets()`

List all the builtin asset examples provided.

Returns **file_paths** (list of *str*) – Filenames of all assets in the data directory shipped with the project.

menpo.image

Image Types

Image

class `menpo.image.Image(image_data, copy=True)`

Bases: `Vectorizable`, `Landmarkable`, `Viewable`, `LandmarkableViewable`

An n-dimensional image.

Images are n-dimensional homogeneous regular arrays of data. Each spatially distinct location in the array is referred to as a *pixel*. At a pixel, `k` distinct pieces of information can be stored. Each datum at a pixel is refereed to as being in a *channel*. All pixels in the image have the same number of channels, and all channels have the same data-type (*float64*).

Parameters

- **image_data** (`(C, M, N ..., Q)` *ndarray*) – Array representing the image pixels, with the first axis being channels.
- **copy** (*bool*, optional) – If `False`, the `image_data` will not be copied on assignment. Note that this will miss out on additional checks. Further note that we still demand that the array is C-contiguous - if it isn't, a copy will be generated anyway. In general, this should only be used if you know what you are doing.

Raises

- `Warning` – If `copy=False` cannot be honoured
- `ValueError` – If the pixel array is malformed

_view_2d(*figure_id=None, new_figure=False, channels=None, interpolation='bilinear', cmap_name=None, alpha=1.0, render_axes=False, axes_font_name='sans-serif', axes_font_size=10, axes_font_style='normal', axes_font_weight='normal', axes_x_limits=None, axes_y_limits=None, axes_x_ticks=None, axes_y_ticks=None, figure_size=(7, 7)*)

View the image using the default image viewer. This method will appear on the Image as `view` if the Image is 2D.

Returns

- **figure_id** (*object*, optional) – The id of the figure to be used.

- **new_figure** (*bool*, optional) – If `True`, a new figure is created.
- **channels** (*int* or *list* of *int* or `all` or `None`) – If *int* or *list* of *int*, the specified channel(s) will be rendered. If `all`, all the channels will be rendered in subplots. If `None` and the image is RGB, it will be rendered in RGB mode. If `None` and the image is not RGB, it is equivalent to `all`.
- **interpolation** (*See Below, optional*) – The interpolation used to render the image. For example, if `bilinear`, the image will be smooth and if `nearest`, the image will be pixelated. Example options

```
{none, nearest, bilinear, bicubic, spline16, spline36,
hanning, hamming, hermite, kaiser, quadric, catrom, gaussian,
bessel, mitchell, sinc, lanczos}
```

- **cmap_name** (*str*, optional,) – If `None`, single channel and three channel images default to greyscale and rgb colormaps respectively.
- **alpha** (*float*, optional) – The alpha blending value, between 0 (transparent) and 1 (opaque).
- **render_axes** (*bool*, optional) – If `True`, the axes will be rendered.
- **axes_font_name** (*See Below, optional*) – The font of the axes. Example options

```
{serif, sans-serif, cursive, fantasy, monospace}
```

- **axes_font_size** (*int*, optional) – The font size of the axes.
- **axes_font_style** ({`normal`, `italic`, `oblique`}, optional) – The font style of the axes.
- **axes_font_weight** (*See Below, optional*) – The font weight of the axes. Example options

```
{ultralight, light, normal, regular, book, medium, roman,
semibold, demibold, demi, bold, heavy, extra bold, black}
```

- **axes_x_limits** (*float* or (*float*, *float*) or `None`, optional) – The limits of the x axis. If *float*, then it sets padding on the right and left of the Image as a percentage of the Image's width. If *tuple* or *list*, then it defines the axis limits. If `None`, then the limits are set automatically.
- **axes_y_limits** ((*float*, *float*) *tuple* or `None`, optional) – The limits of the y axis. If *float*, then it sets padding on the top and bottom of the Image as a percentage of the Image's height. If *tuple* or *list*, then it defines the axis limits. If `None`, then the limits are set automatically.
- **axes_x_ticks** (*list* or *tuple* or `None`, optional) – The ticks of the x axis.
- **axes_y_ticks** (*list* or *tuple* or `None`, optional) – The ticks of the y axis.
- **figure_size** ((*float*, *float*) *tuple* or `None`, optional) – The size of the figure in inches.

Returnsviewer (*ImageViewer*) – The image viewing object.

_view_landmarks_2d(*channels=None*, *group=None*, *with_labels=None*, *without_labels=None*, *figure_id=None*, *new_figure=False*, *interpolation='bilinear'*, *cmap_name=None*, *alpha=1.0*, *render_lines=True*, *line_colour=None*, *line_style='-'*, *line_width=1*, *render_markers=True*, *marker_style='o'*, *marker_size=5*, *marker_face_colour=None*, *marker_edge_colour=None*, *marker_edge_width=1.0*, *render_numbering=False*, *numbers_horizontal_align='center'*, *numbers_vertical_align='bottom'*, *numbers_font_name='sans-serif'*, *numbers_font_size=10*, *numbers_font_style='normal'*, *numbers_font_weight='normal'*, *numbers_font_colour='k'*, *render_legend=False*, *legend_title=''*, *legend_font_name='sans-serif'*, *legend_font_style='normal'*, *legend_font_size=10*, *legend_font_weight='normal'*, *legend_marker_scale=None*, *legend_location=2*, *legend_bbox_to_anchor=(1.05, 1.0)*, *legend_border_axes_pad=None*, *legend_n_columns=1*, *legend_horizontal_spacing=None*, *legend_vertical_spacing=None*, *legend_border=True*, *legend_border_padding=None*, *legend_shadow=False*, *legend_rounded_corners=False*, *render_axes=False*, *axes_font_name='sans-serif'*, *axes_font_size=10*, *axes_font_style='normal'*, *axes_font_weight='normal'*, *axes_x_limits=None*, *axes_y_limits=None*, *axes_x_ticks=None*, *axes_y_ticks=None*, *figure_size=(7, 7)*)

Visualize the landmarks. This method will appear on the Image as `view_landmarks` if the Image is 2D.

Parameters

- **channels** (*int* or *list* of *int* or `all` or `None`) – If *int* or *list* of *int*, the specified channel(s) will be rendered. If `all`, all the channels will be rendered in subplots. If `None` and the image is RGB, it will be rendered in RGB mode. If `None` and the image is not RGB, it is equivalent to `all`.
- **group** (*str* or''None'' optional) – The landmark group to be visualized. If `None` and there are more than one landmark groups, an error is raised.
- **with_labels** (`None` or *str* or *list* of *str*, optional) – If not `None`, only show the given label(s). Should **not** be used with the `without_labels` kwarg.
- **without_labels** (`None` or *str* or *list* of *str*, optional) – If not `None`, show all except the given label(s). Should **not** be used with the `with_labels` kwarg.
- **figure_id** (*object*, optional) – The id of the figure to be used.
- **new_figure** (*bool*, optional) – If `True`, a new figure is created.
- **interpolation** (*See Below, optional*) – The interpolation used to render the image. For example, if `bilinear`, the image will be smooth and if `nearest`, the image will be pixelated. Example options

```
{none, nearest, bilinear, bicubic, spline16, spline36, hanning,
hamming, hermite, kaiser, quadric, catrom, gaussian, bessel,
mitchell, sinc, lanczos}
```

- **cmap_name** (*str*, optional,) – If `None`, single channel and three channel images default to greyscale and rgb colormaps respectively.
- **alpha** (*float*, optional) – The alpha blending value, between 0 (transparent) and 1 (opaque).
- **render_lines** (*bool*, optional) – If `True`, the edges will be rendered.

- **line_colour** (*See Below, optional*) – The colour of the lines. Example options:

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **line_style** ({-, --, -., :}, optional) – The style of the lines.
- **line_width** (*float*, optional) – The width of the lines.
- **render_markers** (*bool*, optional) – If `True`, the markers will be rendered.
- **marker_style** (*See Below, optional*) – The style of the markers. Example options

```
{., ,, o, v, ^, <, >, +, x, D, d, s, p, *, h, H, 1, 2, 3, 4, 8}
```

- **marker_size** (*int*, optional) – The size of the markers in points.
- **marker_face_colour** (*See Below, optional*) – The face (filling) colour of the markers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **marker_edge_colour** (*See Below, optional*) – The edge colour of the markers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **marker_edge_width** (*float*, optional) – The width of the markers' edge.
- **render_numbering** (*bool*, optional) – If `True`, the landmarks will be numbered.
- **numbers_horizontal_align** ({center, right, left}, optional) – The horizontal alignment of the numbers' texts.
- **numbers_vertical_align** ({center, top, bottom, baseline}, optional) – The vertical alignment of the numbers' texts.
- **numbers_font_name** (*See Below, optional*) – The font of the numbers. Example options

```
{serif, sans-serif, cursive, fantasy, monospace}
```

- **numbers_font_size** (*int*, optional) – The font size of the numbers.
- **numbers_font_style** ({normal, italic, oblique}, optional) – The font style of the numbers.
- **numbers_font_weight** (*See Below, optional*) – The font weight of the numbers. Example options

```
{ultralight, light, normal, regular, book, medium, roman,
semibold, demibold, demi, bold, heavy, extra bold, black}
```

- **numbers_font_colour** (*See Below, optional*) – The font colour of the numbers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **render_legend** (*bool*, optional) – If `True`, the legend will be rendered.
- **legend_title** (*str*, optional) – The title of the legend.
- **legend_font_name** (*See below, optional*) – The font of the legend. Example options

```
{serif, sans-serif, cursive, fantasy, monospace}
```

- **legend_font_style** (`{normal, italic, oblique}`, optional) – The font style of the legend.
- **legend_font_size** (*int*, optional) – The font size of the legend.
- **legend_font_weight** (*See Below, optional*) – The font weight of the legend. Example options

```
{ultralight, light, normal, regular, book, medium, roman,
semibold, demibold, demi, bold, heavy, extra bold, black}
```

- **legend_marker_scale** (*float*, optional) – The relative size of the legend markers with respect to the original
- **legend_location** (*int*, optional) – The location of the legend. The predefined values are:

'best'	0
'upper right'	1
'upper left'	2
'lower left'	3
'lower right'	4
'right'	5
'center left'	6
'center right'	7
'lower center'	8
'upper center'	9
'center'	10

- **legend_bbox_to_anchor** ((*float*, *float*) *tuple*, optional) – The bbox that the legend will be anchored.
- **legend_border_axes_pad** (*float*, optional) – The pad between the axes and legend border.
- **legend_n_columns** (*int*, optional) – The number of the legend's columns.
- **legend_horizontal_spacing** (*float*, optional) – The spacing between the columns.
- **legend_vertical_spacing** (*float*, optional) – The vertical space between the legend entries.
- **legend_border** (*bool*, optional) – If `True`, a frame will be drawn around the legend.

- **legend_border_padding** (*float*, optional) – The fractional whitespace inside the legend border.
- **legend_shadow** (*bool*, optional) – If `True`, a shadow will be drawn behind legend.
- **legend_rounded_corners** (*bool*, optional) – If `True`, the frame's corners will be rounded (fancybox).
- **render_axes** (*bool*, optional) – If `True`, the axes will be rendered.
- **axes_font_name** (*See Below, optional*) – The font of the axes. Example options

```
{serif, sans-serif, cursive, fantasy, monospace}
```

- **axes_font_size** (*int*, optional) – The font size of the axes.
- **axes_font_style** (`{normal, italic, oblique}`, optional) – The font style of the axes.
- **axes_font_weight** (*See Below, optional*) – The font weight of the axes. Example options

```
{ultralight, light, normal, regular, book, medium, roman,
semibold,demibold, demi, bold, heavy, extra bold, black}
```

- **axes_x_limits** (*float* or (*float*, *float*) or `None`, optional) – The limits of the x axis. If *float*, then it sets padding on the right and left of the Image as a percentage of the Image's width. If *tuple* or *list*, then it defines the axis limits. If `None`, then the limits are set automatically.
- **axes_y_limits** ((*float*, *float*) *tuple* or `None`, optional) – The limits of the y axis. If *float*, then it sets padding on the top and bottom of the Image as a percentage of the Image's height. If *tuple* or *list*, then it defines the axis limits. If `None`, then the limits are set automatically.
- **axes_x_ticks** (*list* or *tuple* or `None`, optional) – The ticks of the x axis.
- **axes_y_ticks** (*list* or *tuple* or `None`, optional) – The ticks of the y axis.
- **figure_size** ((*float*, *float*) *tuple* or `None` optional) – The size of the figure in inches.

Raises

- `ValueError` – If both `with_labels` and `without_labels` are passed.
- `ValueError` – If the landmark manager doesn't contain the provided group label.

as_PILImage(*out_dtype=<type 'numpy.uint8'>*)

Return a PIL copy of the image scaled and cast to the correct values for the provided `out_dtype`.

Image must only have 1 or 3 channels and be 2 dimensional. Non *uint8* floating point images must be in the range `[0, 1]` to be converted.

Parametersout_dtype (*np.dtype*, optional) – The dtype the output array should be.

Returnspil_image (*PILImage*) – PIL copy of image

Raises

- `ValueError` – If image is not 2D and has 1 channel or 3 channels.
- `ValueError` – If pixels data type is *float32* or *float64* and the pixel range is outside of `[0, 1]`

- `ValueError` – If the output dtype is unsupported. Currently uint8 is supported.

as_greyscale(*mode='luminosity'*, *channel=None*)

Returns a greyscale version of the image. If the image does *not* represent a 2D RGB image, then the `luminosity` mode will fail.

Parameters

- **mode** (`{average, luminosity, channel}`, optional) –

mode	Greyscale Algorithm
average	Equal average of all channels
luminosity	Calculates the luminance using the CCIR 601 formula:
	$Y' = 0.2989R' + 0.5870G' + 0.1140B'$
channel	A specific channel is chosen as the intensity value.

- **channel** (*int*, optional) – The channel to be taken. Only used if mode is `channel`.

Returnsgreyscale_image (*MaskedImage*) – A copy of this image in greyscale.

as_histogram(*keep_channels=True*, *bins='unique'*)

Histogram binning of the values of this image.

Parameters

- **keep_channels** (*bool*, optional) – If set to `False`, it returns a single histogram for all the channels of the image. If set to `True`, it returns a *list* of histograms, one for each channel.
- **bins** (`{unique}`, positive *int* or sequence of scalars, optional) – If set equal to `'unique'`, the bins of the histograms are centred on the unique values of each channel. If set equal to a positive *int*, then this is the number of bins. If set equal to a sequence of scalars, these will be used as bins centres.

Returns

- **hist** (*ndarray* or *list* with `n_channels` *ndarrays* inside) – The histogram(s). If `keep_channels=False`, then hist is an *ndarray*. If `keep_channels=True`, then hist is a *list* with `len(hist)=n_channels`.
- **bin_edges** (*ndarray* or *list* with *n_channels ndarrays* inside) – An array or a list of arrays corresponding to the above histograms that store the bins' edges.

Raises`ValueError` – Bins can be either 'unique', positive int or a sequence of scalars.

Examples

Visualizing the histogram when a list of array bin edges is provided:

```
>>> hist, bin_edges = image.as_histogram()
>>> for k in range(len(hist)):
>>>     plt.subplot(1,len(hist),k)
>>>     width = 0.7 * (bin_edges[k][1] - bin_edges[k][0])
>>>     centre = (bin_edges[k][:-1] + bin_edges[k][1:]) / 2
>>>     plt.bar(centre, hist[k], align='center', width=width)
```

as_imageio(*out_dtype=<type 'numpy.uint8'>*)

Return an Imageio copy of the image scaled and cast to the correct values for the provided `out_dtype`.

Image must only have 1 or 3 channels and be 2 dimensional. Non *uint8* floating point images must be in the range `[0, 1]` to be converted.

Parameters
out_dtype (*np.dtype*, optional) – The dtype the output array should be.

Returns
imageio_image (*ndarray*) – Imageio image (which is just a numpy ndarray with the channels as the last axis).

Raises

- `ValueError` – If image is not 2D and has 1 channel or 3 channels.
- `ValueError` – If pixels data type is *float32* or *float64* and the pixel range is outside of `[0, 1]`
- `ValueError` – If the output dtype is unsupported. Currently uint8 and uint16 are supported.

as_masked(*mask=None*, *copy=True*)

Return a copy of this image with an attached mask behavior.

A custom mask may be provided, or `None`. See the `MaskedImage` constructor for details of how the kwargs will be handled.

Parameters

- **mask** (`(self.shape)` *ndarray* or `BooleanImage`) – A mask to attach to the newly generated masked image.
- **copy** (*bool*, optional) – If `False`, the produced `MaskedImage` will share pixels with `self`. Only suggested to be used for performance.

Returns
masked_image (`MaskedImage`) – An image with the same pixels and landmarks as this one, but with a mask.

as_vector(***kwargs*)

Returns a flattened representation of the object as a single vector.

Returns
vector (*(N,) ndarray*) – The core representation of the object, flattened into a single vector. Note that this is always a view back on to the original object, but is not writable.

bounds()

The bounds of the image, minimum is always (0, 0). The maximum is the maximum **index** that can be used to index into the image for each dimension. Therefore, bounds will be of the form: ((0, 0), (self.height - 1, self.width - 1)) for a 2D image.

Note that this is akin to supporting a nearest neighbour interpolation. Although the *actual* maximum subpixel value would be something like `self.height - eps` where `eps` is some value arbitrarily close to 0, this value at least allows sampling without worrying about floating point error.

Type *tuple*

centre()

The geometric centre of the Image - the subpixel that is in the middle.

Useful for aligning shapes and images.

Type (`n_dims`,) *ndarray*

clip_pixels(*minimum=None*, *maximum=None*)

A copy of this image with pixels linearly clipped to fit a range.

Parameters

- **minimum** (*float*, optional) – The minimal value of the clipped pixels. If None is provided, the default value will be 0.
- **maximum** (*float*, optional) – The maximal value of the clipped pixels. If None is provided, the default value will depend on the dtype.

Returnsrescaled_image (`type(self)`) – A copy of this image with pixels linearly rescaled to fit in the range provided.

constrain_landmarks_to_bounds()

Deprecated - please use the equivalent `constrain_to_bounds` method now on PointCloud, in conjunction with the new Image `bounds()` method. For example:

```
>>> im.constrain_landmarks_to_bounds()  # Equivalent to below
>>> im.landmarks['test'] = im.landmarks['test'].constrain_to_bounds(im.
↪bounds())
```

constrain_points_to_bounds(*points*)

Constrains the points provided to be within the bounds of this image.

Parameterspoints (`(d,)` *ndarray*) – Points to be snapped to the image boundaries.

Returnsbounded_points (`(d,)` *ndarray*) – Points snapped to not stray outside the image edges.

copy()

Generate an efficient copy of this object.

Note that Numpy arrays and other `Copyable` objects on `self` will be deeply copied. Dictionaries and sets will be shallow copied, and everything else will be assigned (no copy will be made).

Classes that store state other than numpy arrays and immutable types should overwrite this method to ensure all state is copied.

Returns`type(self)` – A copy of this object

crop(*min_indices*, *max_indices*, *constrain_to_boundary=False*, *return_transform=False*)

Return a cropped copy of this image using the given minimum and maximum indices. Landmarks are correctly adjusted so they maintain their position relative to the newly cropped image.

Parameters

- **min_indices** (`(n_dims,)` *ndarray*) – The minimum index over each dimension.
- **max_indices** (`(n_dims,)` *ndarray*) – The maximum index over each dimension.
- **constrain_to_boundary** (*bool*, optional) – If `True` the crop will be snapped to not go beyond this images boundary. If `False`, an `ImageBoundaryError` will be raised if an attempt is made to go beyond the edge of the image.
- **return_transform** (*bool*, optional) – If `True`, then the `Transform` object that was used to perform the cropping is also returned.

Returns

- **cropped_image** (*type(self)*) – A new instance of self, but cropped.
- **transform** (`Transform`) – The transform that was used. It only applies if *return_transform* is `True`.

Raises

- `ValueError` – `min_indices` and `max_indices` both have to be of length `n_dims`. All `max_indices` must be greater than `min_indices`.

- *ImageBoundaryError* – Raised if `constrain_to_boundary=False`, and an attempt is made to crop the image in a way that violates the image bounds.

crop_to_landmarks(*group=None*, *boundary=0*, *constrain_to_boundary=True*, *return_transform=False*)

Return a copy of this image cropped so that it is bounded around a set of landmarks with an optional `n_pixel` boundary

Parameters

- **group** (*str*, optional) – The key of the landmark set that should be used. If `None` and if there is only one set of landmarks, this set will be used.
- **boundary** (*int*, optional) – An extra padding to be added all around the landmarks bounds.
- **constrain_to_boundary** (*bool*, optional) – If `True` the crop will be snapped to not go beyond this images boundary. If `False`, an :map'ImageBoundaryError' will be raised if an attempt is made to go beyond the edge of the image.
- **return_transform** (*bool*, optional) – If `True`, then the *Transform* object that was used to perform the cropping is also returned.

Returns

- **image** (*Image*) – A copy of this image cropped to its landmarks.
- **transform** (*Transform*) – The transform that was used. It only applies if *return_transform* is `True`.

Raises *ImageBoundaryError* – Raised if `constrain_to_boundary=False`, and an attempt is made to crop the image in a way that violates the image bounds.

crop_to_landmarks_proportion(*boundary_proportion*, *group=None*, *minimum=True*, *constrain_to_boundary=True*, *return_transform=False*)

Crop this image to be bounded around a set of landmarks with a border proportional to the landmark spread or range.

Parameters

- **boundary_proportion** (*float*) – Additional padding to be added all around the landmarks bounds defined as a proportion of the landmarks range. See the minimum parameter for a definition of how the range is calculated.
- **group** (*str*, optional) – The key of the landmark set that should be used. If `None` and if there is only one set of landmarks, this set will be used.
- **minimum** (*bool*, optional) – If `True` the specified proportion is relative to the minimum value of the landmarks' per-dimension range; if `False` w.r.t. the maximum value of the landmarks' per-dimension range.
- **constrain_to_boundary** (*bool*, optional) – If `True`, the crop will be snapped to not go beyond this images boundary. If `False`, an *ImageBoundaryError* will be raised if an attempt is made to go beyond the edge of the image.
- **return_transform** (*bool*, optional) – If `True`, then the *Transform* object that was used to perform the cropping is also returned.

Returns

- **image** (*Image*) – This image, cropped to its landmarks with a border proportional to the landmark spread or range.

- **transform** (*Transform*) – The transform that was used. It only applies if *return_transform* is `True`.

Raises *ImageBoundaryError* – Raised if `constrain_to_boundary=False`, and an attempt is made to crop the image in a way that violates the image bounds.

crop_to_pointcloud(*pointcloud*, *boundary=0*, *constrain_to_boundary=True*, *return_transform=False*)

Return a copy of this image cropped so that it is bounded around a pointcloud with an optional `n_pixel` boundary.

Parameters

- **pointcloud** (*PointCloud*) – The pointcloud to crop around.
- **boundary** (*int*, optional) – An extra padding to be added all around the landmarks bounds.
- **constrain_to_boundary** (*bool*, optional) – If `True` the crop will be snapped to not go beyond this images boundary. If `False`, an :map'ImageBoundaryError' will be raised if an attempt is made to go beyond the edge of the image.
- **return_transform** (*bool*, optional) – If `True`, then the *Transform* object that was used to perform the cropping is also returned.

Returns

- **image** (*Image*) – A copy of this image cropped to the bounds of the pointcloud.
- **transform** (*Transform*) – The transform that was used. It only applies if *return_transform* is `True`.

Raises *ImageBoundaryError* – Raised if `constrain_to_boundary=False`, and an attempt is made to crop the image in a way that violates the image bounds.

crop_to_pointcloud_proportion(*pointcloud*, *boundary_proportion*, *minimum=True*, *constrain_to_boundary=True*, *return_transform=False*)

Return a copy of this image cropped so that it is bounded around a pointcloud with an optional `n_pixel` boundary.

Parameters

- **pointcloud** (*PointCloud*) – The pointcloud to crop around.
- **boundary_proportion** (*float*) – Additional padding to be added all around the landmarks bounds defined as a proportion of the landmarks range. See the minimum parameter for a definition of how the range is calculated.
- **minimum** (*bool*, optional) – If `True` the specified proportion is relative to the minimum value of the pointclouds' per-dimension range; if `False` w.r.t. the maximum value of the pointclouds' per-dimension range.
- **constrain_to_boundary** (*bool*, optional) – If `True`, the crop will be snapped to not go beyond this images boundary. If `False`, an *ImageBoundaryError* will be raised if an attempt is made to go beyond the edge of the image.
- **return_transform** (*bool*, optional) – If `True`, then the *Transform* object that was used to perform the cropping is also returned.

Returns

- **image** (*Image*) – A copy of this image cropped to the border proportional to the pointcloud spread or range.

- **transform** (*Transform*) – The transform that was used. It only applies if *return_transform* is `True`.

Raises *ImageBoundaryError* – Raised if `constrain_to_boundary=False`, and an attempt is made to crop the image in a way that violates the image bounds.

diagonal()

The diagonal size of this image

Type *float*

extract_channels(*channels*)

A copy of this image with only the specified channels.

Parameters **channels** (*int* or *[int]*) – The channel index or *list* of channel indices to retain.

Returns **image** (*type(self)*) – A copy of this image with only the channels requested.

extract_patches(*patch_centers*, *patch_shape=(16, 16)*, *sample_offsets=None*, *as_single_array=True*)

Extract a set of patches from an image. Given a set of patch centers and a patch size, patches are extracted from within the image, centred on the given coordinates. Sample offsets denote a set of offsets to extract from within a patch. This is very useful if you want to extract a dense set of features around a set of landmarks and simply sample the same grid of patches around the landmarks.

If sample offsets are used, to access the offsets for each patch you need to slice the resulting *list*. So for 2 offsets, the first centers offset patches would be `patches[:2]`.

Currently only 2D images are supported.

Parameters

- **patch_centers** (*PointCloud*) – The centers to extract patches around.
- **patch_shape** (`(1, n_dims)` *tuple* or *ndarray*, optional) – The size of the patch to extract
- **sample_offsets** (`(n_offsets, n_dims)` *ndarray* or `None`, optional) – The offsets to sample from within a patch. So `(0, 0)` is the centre of the patch (no offset) and `(1, 0)` would be sampling the patch from 1 pixel up the first axis away from the centre. If `None`, then no offsets are applied.
- **as_single_array** (*bool*, optional) – If `True`, an `(n_center, n_offset, n_channels, patch_shape)` *ndarray*, thus a single numpy array is returned containing each patch. If `False`, a *list* of `n_center * n_offset` *Image* objects is returned representing each patch.

Returns **patches** (*list* or *ndarray*) – Returns the extracted patches. Returns a list if `as_single_array=True` and an *ndarray* if `as_single_array=False`.

Raises `ValueError` – If image is not 2D

extract_patches_around_landmarks(*group=None*, *patch_shape=(16, 16)*, *sample_offsets=None*, *as_single_array=True*)

Extract patches around landmarks existing on this image. Provided the group label and optionally the landmark label extract a set of patches.

See *extract_patches* for more information.

Currently only 2D images are supported.

Parameters

- **group** (*str* or `None`, optional) – The landmark group to use as patch centres.

- **patch_shape** (*tuple* or *ndarray*, optional) – The size of the patch to extract
- **sample_offsets** (`(n_offsets, n_dims)` *ndarray* or `None`, optional) – The offsets to sample from within a patch. So `(0, 0)` is the centre of the patch (no offset) and `(1, 0)` would be sampling the patch from 1 pixel up the first axis away from the centre. If `None`, then no offsets are applied.
- **as_single_array** (*bool*, optional) – If `True`, an `(n_center, n_offset, n_channels, patch_shape)` *ndarray*, thus a single numpy array is returned containing each patch. If `False`, a *list* of `n_center * n_offset` *Image* objects is returned representing each patch.

Returnspatches (*list* or *ndarray*) – Returns the extracted patches. Returns a list if `as_single_array=True` and an *ndarray* if `as_single_array=False`.

Raises`ValueError` – If image is not 2D

from_vector(*vector*, *n_channels=None*, *copy=True*)

Takes a flattened vector and returns a new image formed by reshaping the vector to the correct pixels and channels.

The *n_channels* argument is useful for when we want to add an extra channel to an image but maintain the shape. For example, when calculating the gradient.

Note that landmarks are transferred in the process.

Parameters

- **vector** (`(n_parameters,)` *ndarray*) – A flattened vector of all pixels and channels of an image.
- **n_channels** (*int*, optional) – If given, will assume that vector is the same shape as this image, but with a possibly different number of channels.
- **copy** (*bool*, optional) – If `False`, the vector will not be copied in creating the new image.

Returnsimage (*Image*) – New image of same shape as this image and the number of specified channels.

Raises`Warning` – If the `copy=False` flag cannot be honored

from_vector_inplace(*vector*)

Deprecated. Use the non-mutating API, *from_vector*.

For internal usage in performance-sensitive spots, see *_from_vector_inplace()*

Parametersvector (`(n_parameters,)` *ndarray*) – Flattened representation of this object

gaussian_pyramid(*n_levels=3*, *downscale=2*, *sigma=None*)

Return the gaussian pyramid of this image. The first image of the pyramid will be a copy of the original, unmodified, image, and counts as level 1.

Parameters

- **n_levels** (*int*, optional) – Total number of levels in the pyramid, including the original unmodified image
- **downscale** (*float*, optional) – Downscale factor.
- **sigma** (*float*, optional) – Sigma for gaussian filter. Default is `downscale / 3.` which corresponds to a filter mask twice the size of the scale factor that covers more than 99% of the gaussian distribution.

Yieldsimage_pyramid (*generator*) – Generator yielding pyramid layers as *Image* objects.

has_landmarks_outside_bounds()
Indicates whether there are landmarks located outside the image bounds.

Type*bool*

has_nan_values()
Tests if the vectorized form of the object contains `nan` values or not. This is particularly useful for objects with unknown values that have been mapped to `nan` values.

Returnshas_nan_values (*bool*) – If the vectorized object contains `nan` values.

indices()
Return the indices of all pixels in this image.

Type(`n_dims`, `n_pixels`) ndarray

classmethod init_blank(*shape*, *n_channels=1*, *fill=0*, *dtype=<type 'float'>*)
Returns a blank image.

Parameters

- **shape** (*tuple* or *list*) – The shape of the image. Any floating point values are rounded up to the nearest integer.
- **n_channels** (*int*, optional) – The number of channels to create the image with.
- **fill** (*int*, optional) – The value to fill all pixels with.
- **dtype** (*numpy data type, optional*) – The data type of the image.

Returnsblank_image (*Image*) – A new image of the requested size.

classmethod init_from_channels_at_back(*pixels*)
Create an Image from a set of pixels where the channels axis is on the last axis (the back). This is common in other frameworks, and therefore this method provides a convenient means of creating a menpo Image from such data. Note that a copy is always created due to the need to rearrange the data.

Parameterspixels (`(M, N ..., Q, C)` *ndarray*) – Array representing the image pixels, with the last axis being channels.

Returnsimage (*Image*) – A new image from the given pixels, with the FIRST axis as the channels.

Raises`ValueError` – If image is not at least 2D, i.e. has at least 2 dimensions plus the channels in the end.

classmethod init_from_pointcloud(*pointcloud*, *group=None*, *boundary=0*, *n_channels=1*, *fill=0*, *dtype=<type 'float'>*, *return_transform=False*)
Create an Image that is big enough to contain the given pointcloud. The pointcloud will be translated to the origin and then translated according to its bounds in order to fit inside the new image. An optional boundary can be provided in order to increase the space around the boundary of the pointcloud. The boundary will be added to *all sides of the image* and so a boundary of 5 provides 10 pixels of boundary total for each dimension.

Parameters

- **pointcloud** (*PointCloud*) – Pointcloud to place inside the newly created image.
- **group** (*str*, optional) – If `None`, the pointcloud will only be used to create the image. If a *str* then the pointcloud will be attached as a landmark group to the image, with the given string as key.
- **boundary** (*float*) – A optional padding distance that is added to the pointcloud bounds. Default is `0`, meaning the max/min of tightest possible containing image is returned.

- **n_channels** (*int*, optional) – The number of channels to create the image with.
- **fill** (*int*, optional) – The value to fill all pixels with.
- **dtype** (*numpy data type, optional*) – The data type of the image.
- **return_transform** (*bool*, optional) – If `True`, then the *Transform* object that was used to adjust the PointCloud in order to build the image, is returned.

Returns

- **image** (`type(cls)` Image or subclass) – A new image with the same size as the given pointcloud, optionally with the pointcloud attached as landmarks.
- **transform** (*Transform*) – The transform that was used. It only applies if *return_transform* is `True`.

classmethod init_from_rolled_channels(*pixels*)

Deprecated - please use the equivalent `init_from_channels_at_back` method.

mirror(*axis=1*, *return_transform=False*)

Return a copy of this image, mirrored/flipped about a certain axis.

Parameters

- **axis** (*int*, optional) – The axis about which to mirror the image.
- **return_transform** (*bool*, optional) – If `True`, then the *Transform* object that was used to perform the mirroring is also returned.

Returns

- **mirrored_image** (`type(self)`) – The mirrored image.
- **transform** (*Transform*) – The transform that was used. It only applies if *return_transform* is `True`.

Raises

- `ValueError` – axis cannot be negative
- `ValueError` – axis={} but the image has {} dimensions

normalize_norm(*mode='all'*, ***kwargs*)

Returns a copy of this image normalized such that its pixel values have zero mean and its norm equals 1.

Parameters
mode (`{all, per_channel}`, optional) – If `all`, the normalization is over all channels. If `per_channel`, each channel individually is mean centred and unit norm.

Returns
image (`type(self)`) – A copy of this image, normalized.

normalize_std(*mode='all'*, ***kwargs*)

Returns a copy of this image normalized such that its pixel values have zero mean and unit variance.

Parameters
mode (`{all, per_channel}`, optional) – If `all`, the normalization is over all channels. If `per_channel`, each channel individually is mean centred and normalized in variance.

Returns
image (`type(self)`) – A copy of this image, normalized.

pixels_range()

The range of the pixel values (min and max pixel values).

Returns
min_max (`(dtype, dtype)`) – The minimum and maximum value of the pixels array.

pixels_with_channels_at_back(*out_dtype=None*)

Returns the pixels matrix, with the channels rolled to the back axis. This may be required for interacting with external code bases that require images to have channels as the last axis, rather than the Menpo convention of channels as the first axis.

If this image is single channel, the final axis is dropped.

Parametersout_dtype (*np.dtype*, optional) – The dtype the output array should be.

Returnsrolled_channels (*ndarray*) – Pixels with channels as the back (last) axis. If single channel, the last axis will be dropped.

pyramid(*n_levels=3*, *downscale=2*)

Return a rescaled pyramid of this image. The first image of the pyramid will be a copy of the original, unmodified, image, and counts as level 1.

Parameters

- **n_levels** (*int*, optional) – Total number of levels in the pyramid, including the original unmodified image
- **downscale** (*float*, optional) – Downscale factor.

Yieldsimage_pyramid (*generator*) – Generator yielding pyramid layers as `Image` objects.

rasterize_landmarks(*group=None*, *render_lines=True*, *line_style='-'*, *line_colour='b'*, *line_width=1*, *render_markers=True*, *marker_style='o'*, *marker_size=1*, *marker_face_colour='b'*, *marker_edge_colour='b'*, *marker_edge_width=1*, *backend='matplotlib'*)

This method provides the ability to rasterize 2D landmarks onto the image. The returned image has the specified landmark groups rasterized onto the image - which is useful for things like creating result examples or rendering videos with annotations.

Since multiple landmark groups can be specified, all arguments can take lists of parameters that map to the provided groups list. Therefore, the parameters must be lists of the correct length or a single parameter to apply to every landmark group.

Multiple backends are provided, all with different strengths. The 'pillow' backend is very fast, but not very flexible. The *matplotlib* backend should be feature compatible with other Menpo rendering methods, but is much slower due to the overhead of creating a figure to render into.

Parameters

- **group** (*str* or *list* of *str*, optional) – The landmark group key, or a list of keys.
- **render_lines** (*bool*, optional) – If `True`, and the provided landmark group is a `PointDirectedGraph`, the edges are rendered.
- **line_style** (*str*, optional) – The style of the edge line. Not all backends support this argument.
- **line_colour** (*str* or *tuple*, optional) – A Matplotlib style colour or a backend dependant colour.
- **line_width** (*int*, optional) – The width of the line to rasterize.
- **render_markers** (*bool*, optional) – If `True`, render markers at the coordinates of each landmark.
- **marker_style** (*str*, optional) – A Matplotlib marker style. Not all backends support all marker styles.
- **marker_size** (*int*, optional) – The size of the marker - different backends use different scale spaces so consistent output may by difficult.

- **marker_face_colour** (*str*, optional) – A Matplotlib style colour or a backend dependant colour.
- **marker_edge_colour** (*str*, optional) – A Matplotlib style colour or a backend dependant colour.
- **marker_edge_width** (*int*, optional) – The width of the marker edge. Not all backends support this.
- **backend** (*{'matplotlib', 'pillow'}, optional*) – The backend to use.

Returnsrasterized_image (*Image*) – The image with the landmarks rasterized directly into the pixels.

Raises

- `ValueError` – Only 2D images are supported.
- `ValueError` – Only RGB (3-channel) or Greyscale (1-channel) images are supported.

rescale(*scale*, *round='ceil'*, *order=1*, *return_transform=False*)

Return a copy of this image, rescaled by a given factor. Landmarks are rescaled appropriately.

Parameters

- **scale** (*float* or *tuple* of *floats*) – The scale factor. If a tuple, the scale to apply to each dimension. If a single *float*, the scale will be applied uniformly across each dimension.
- **round** (`{ceil, floor, round}`, optional) – Rounding function to be applied to floating point shapes.
- **order** (*int*, optional) – The order of interpolation. The order has to be in the range [0,5]

Order	Interpolation
0	Nearest-neighbor
1	Bi-linear *(default)*
2	Bi-quadratic
3	Bi-cubic
4	Bi-quartic
5	Bi-quintic

- **return_transform** (*bool*, optional) – If `True`, then the *Transform* object that was used to perform the rescale is also returned.

Returns

- **rescaled_image** (`type(self)`) – A copy of this image, rescaled.
- **transform** (*Transform*) – The transform that was used. It only applies if *return_transform* is `True`.

RaisesValueError: – If less scales than dimensions are provided. If any scale is less than or equal to 0.

rescale_landmarks_to_diagonal_range(*diagonal_range*, *group=None*, *round='ceil'*, *order=1*, *return_transform=False*)

Return a copy of this image, rescaled so that the `diagonal_range` of the bounding box containing its landmarks matches the specified `diagonal_range` range.

Parameters

- **diagonal_range** (`(n_dims,)` *ndarray*) – The diagonal_range range that we want the landmarks of the returned image to have.

- **group** (*str*, optional) – The key of the landmark set that should be used. If `None` and if there is only one set of landmarks, this set will be used.
- **round** (`{ceil, floor, round}`, optional) – Rounding function to be applied to floating point shapes.
- **order** (*int*, optional) – The order of interpolation. The order has to be in the range [0,5]

Order	Interpolation
0	Nearest-neighbor
1	Bi-linear *(default)*
2	Bi-quadratic
3	Bi-cubic
4	Bi-quartic
5	Bi-quintic

- **return_transform** (*bool*, optional) – If `True`, then the `Transform` object that was used to perform the rescale is also returned.

Returns

- **rescaled_image** (`type(self)`) – A copy of this image, rescaled.
- **transform** (`Transform`) – The transform that was used. It only applies if *return_transform* is `True`.

rescale_pixels (*minimum*, *maximum*, *per_channel=True*)

A copy of this image with pixels linearly rescaled to fit a range.

Note that the only pixels that will be considered and rescaled are those that feature in the vectorized form of this image. If you want to use this routine on all the pixels in a `MaskedImage`, consider using *as_unmasked()* prior to this call.

Parameters

- **minimum** (*float*) – The minimal value of the rescaled pixels
- **maximum** (*float*) – The maximal value of the rescaled pixels
- **per_channel** (*boolean*, optional) – If `True`, each channel will be rescaled independently. If `False`, the scaling will be over all channels.

Returnsrescaled_image (`type(self)`) – A copy of this image with pixels linearly rescaled to fit in the range provided.

rescale_to_diagonal (*diagonal*, *round='ceil'*, *return_transform=False*)

Return a copy of this image, rescaled so that the it's diagonal is a new size.

Parameters

- **diagonal** (*int*) – The diagonal size of the new image.
- **round** (`{ceil, floor, round}`, optional) – Rounding function to be applied to floating point shapes.
- **return_transform** (*bool*, optional) – If `True`, then the `Transform` object that was used to perform the rescale is also returned.

Returns

- **rescaled_image** (*type(self)*) – A copy of this image, rescaled.
- **transform** (`Transform`) – The transform that was used. It only applies if *return_transform* is `True`.

rescale_to_pointcloud(*pointcloud*, *group=None*, *round='ceil'*, *order=1*, *return_transform=False*)

Return a copy of this image, rescaled so that the scale of a particular group of landmarks matches the scale of the passed reference pointcloud.

Parameters

- **pointcloud** (*PointCloud*) – The reference pointcloud to which the landmarks specified by `group` will be scaled to match.
- **group** (*str*, optional) – The key of the landmark set that should be used. If `None`, and if there is only one set of landmarks, this set will be used.
- **round** (`{ceil, floor, round}`, optional) – Rounding function to be applied to floating point shapes.
- **order** (*int*, optional) – The order of interpolation. The order has to be in the range [0,5]

Order	Interpolation
0	Nearest-neighbor
1	Bi-linear *(default)*
2	Bi-quadratic
3	Bi-cubic
4	Bi-quartic
5	Bi-quintic

- **return_transform** (*bool*, optional) – If `True`, then the *Transform* object that was used to perform the rescale is also returned.

Returns

- **rescaled_image** (`type(self)`) – A copy of this image, rescaled.
- **transform** (*Transform*) – The transform that was used. It only applies if *return_transform* is `True`.

resize(*shape*, *order=1*, *return_transform=False*)

Return a copy of this image, resized to a particular shape. All image information (landmarks, and mask in the case of *MaskedImage*) is resized appropriately.

Parameters

- **shape** (*tuple*) – The new shape to resize to.
- **order** (*int*, optional) – The order of interpolation. The order has to be in the range [0,5]

Order	Interpolation
0	Nearest-neighbor
1	Bi-linear *(default)*
2	Bi-quadratic
3	Bi-cubic
4	Bi-quartic
5	Bi-quintic

- **return_transform** (*bool*, optional) – If `True`, then the *Transform* object that was used to perform the resize is also returned.

Returns

- **resized_image** (`type(self)`) – A copy of this image, resized.
- **transform** (*Transform*) – The transform that was used. It only applies if *return_transform* is `True`.

Raises ValueError: – If the number of dimensions of the new shape does not match the number of dimensions of the image.

rolled_channels()

Deprecated - please use the equivalent `pixels_with_channels_at_back` method.

rotate_ccw_about_centre(*theta*, *degrees=True*, *retain_shape=False*, *cval=0.0*, *round='round'*, *order=1*, *return_transform=False*)

Return a copy of this image, rotated counter-clockwise about its centre.

Note that the *retain_shape* argument defines the shape of the rotated image. If `retain_shape=True`, then the shape of the rotated image will be the same as the one of current image, so some regions will probably be cropped. If `retain_shape=False`, then the returned image has the correct size so that the whole area of the current image is included.

Parameters

- **theta** (*float*) – The angle of rotation about the centre.
- **degrees** (*bool*, optional) – If `True`, *theta* is interpreted in degrees. If `False`, `theta` is interpreted as radians.
- **retain_shape** (*bool*, optional) – If `True`, then the shape of the rotated image will be the same as the one of current image, so some regions will probably be cropped. If `False`, then the returned image has the correct size so that the whole area of the current image is included.
- **cval** (*float*, optional) – The value to be set outside the rotated image boundaries.
- **round** (`{'ceil', 'floor', 'round'}`, optional) – Rounding function to be applied to floating point shapes. This is only used in case `retain_shape=True`.
- **order** (*int*, optional) – The order of interpolation. The order has to be in the range `[0, 5]`. This is only used in case `retain_shape=True`.

Order	Interpolation
0	Nearest-neighbor
1	Bi-linear *(default)*
2	Bi-quadratic
3	Bi-cubic
4	Bi-quartic
5	Bi-quintic

- **return_transform** (*bool*, optional) – If `True`, then the `Transform` object that was used to perform the rotation is also returned.

Returns

- **rotated_image** (`type(self)`) – The rotated image.
- **transform** (`Transform`) – The transform that was used. It only applies if *return_transform* is `True`.

Raises `ValueError` – Image rotation is presently only supported on 2D images

sample(*points_to_sample*, *order=1*, *mode='constant'*, *cval=0.0*)

Sample this image at the given sub-pixel accurate points. The input PointCloud should have the same number of dimensions as the image e.g. a 2D PointCloud for a 2D multi-channel image. A numpy array will be returned the has the values for every given point across each channel of the image.

Parameters

- **points_to_sample** (*PointCloud*) – Array of points to sample from the image. Should be *(n_points, n_dims)*
- **order** (*int*, optional) – The order of interpolation. The order has to be in the range [0,5]. See warp_to_shape for more information.
- **mode** (`{constant, nearest, reflect, wrap}`, optional) – Points outside the boundaries of the input are filled according to the given mode.
- **cval** (*float*, optional) – Used in conjunction with mode `constant`, the value outside the image boundaries.

Returnssampled_pixels ((*n_points*, *n_channels*) *ndarray*) – The interpolated values taken across every channel of the image.

set_patches (*patches*, *patch_centers*, *offset=None*, *offset_index=None*)

Set the values of a group of patches into the correct regions of a copy of this image. Given an array of patches and a set of patch centers, the patches' values are copied in the regions of the image that are centred on the coordinates of the given centers.

The patches argument can have any of the two formats that are returned from the *extract_patches()* and *extract_patches_around_landmarks()* methods. Specifically it can be:

1. `(n_center, n_offset, self.n_channels, patch_shape)` *ndarray*
2. *list* of `n_center * n_offset` *Image* objects

Currently only 2D images are supported.

Parameters

- **patches** (*ndarray* or *list*) – The values of the patches. It can have any of the two formats that are returned from the *extract_patches()* and *extract_patches_around_landmarks()* methods. Specifically, it can either be an `(n_center, n_offset, self.n_channels, patch_shape)` *ndarray* or a *list* of `n_center * n_offset` *Image* objects.
- **patch_centers** (*PointCloud*) – The centers to set the patches around.
- **offset** (*list* or *tuple* or `(1, 2)` *ndarray* or `None`, optional) – The offset to apply on the patch centers within the image. If `None`, then `(0, 0)` is used.
- **offset_index** (*int* or `None`, optional) – The offset index within the provided *patches* argument, thus the index of the second dimension from which to sample. If `None`, then `0` is used.

Raises

- `ValueError` – If image is not 2D
- `ValueError` – If offset does not have shape (1, 2)

set_patches_around_landmarks (*patches*, *group=None*, *offset=None*, *offset_index=None*)

Set the values of a group of patches around the landmarks existing in a copy of this image. Given an array of patches, a group and a label, the patches' values are copied in the regions of the image that are centred on the coordinates of corresponding landmarks.

The patches argument can have any of the two formats that are returned from the *extract_patches()* and *extract_patches_around_landmarks()* methods. Specifically it can be:

1. `(n_center, n_offset, self.n_channels, patch_shape)` *ndarray*
2. *list* of `n_center * n_offset` *Image* objects

Currently only 2D images are supported.

Parameters

- **patches** (*ndarray* or *list*) – The values of the patches. It can have any of the two formats that are returned from the *extract_patches()* and *extract_patches_around_landmarks()* methods. Specifically, it can either be an `(n_center, n_offset, self.n_channels, patch_shape)` *ndarray* or a *list* of `n_center * n_offset` *Image* objects.
- **group** (*str* or `None` optional) – The landmark group to use as patch centres.
- **offset** (*list* or *tuple* or `(1, 2)` *ndarray* or `None`, optional) – The offset to apply on the patch centers within the image. If `None`, then `(0, 0)` is used.
- **offset_index** (*int* or `None`, optional) – The offset index within the provided *patches* argument, thus the index of the second dimension from which to sample. If `None`, then `0` is used.

Raises

- `ValueError` – If image is not 2D
- `ValueError` – If offset does not have shape (1, 2)

transform_about_centre(*transform*, *retain_shape=False*, *cval=0.0*, *round='round'*, *order=1*, *return_transform=False*)

Return a copy of this image, transformed about its centre.

Note that the *retain_shape* argument defines the shape of the transformed image. If `retain_shape=True`, then the shape of the transformed image will be the same as the one of current image, so some regions will probably be cropped. If `retain_shape=False`, then the returned image has the correct size so that the whole area of the current image is included.

Note: This method will not work for transforms that result in a transform chain as *TransformChain* is not invertible.

Note: Be careful when defining transforms for warping imgaes. All pixel locations must fall within a valid range as expected by the transform. Therefore, your transformation must accept 'negative' pixel locations as the pixel locations provided to your transform will have the object centre subtracted from them.

Parameters

- **transform** (*ComposableTransform* and *VInvertible* type) – A composable transform. `pseudoinverse` will be invoked on the resulting transform so it must implement a valid inverse.
- **retain_shape** (*bool*, optional) – If `True`, then the shape of the sheared image will be the same as the one of current image, so some regions will probably be cropped. If `False`, then the returned image has the correct size so that the whole area of the current image is included.
- **cval** (*float*, optional) – The value to be set outside the sheared image boundaries.
- **round** (`{'ceil', 'floor', 'round'}`, optional) – Rounding function to be applied to floating point shapes. This is only used in case `retain_shape=True`.
- **order** (*int*, optional) – The order of interpolation. The order has to be in the range `[0, 5]`. This is only used in case `retain_shape=True`.

Order	Interpolation
0	Nearest-neighbor
1	Bi-linear *(default)*
2	Bi-quadratic
3	Bi-cubic
4	Bi-quartic
5	Bi-quintic

- **return_transform** (*bool*, optional) – If `True`, then the *`Transform`* object that was used to perform the shearing is also returned.

Returns

- **transformed_image** (`type(self)`) – The transformed image.
- **transform** (*`Transform`*) – The transform that was used. It only applies if *return_transform* is `True`.

Examples

This is an example for rotating an image about its center. Let's first load an image, create the rotation transform and then apply it

```
import matplotlib.pyplot as plt
import menpo.io as mio
from menpo.transform import Rotation

# Load image
im = mio.import_builtin_asset.lenna_png()

# Create shearing transform
rot_tr = Rotation.init_from_2d_ccw_angle(45)

# Render original image
plt.subplot(131)
im.view_landmarks()
plt.title('Original')

# Render rotated image
plt.subplot(132)
im.transform_about_centre(rot_tr).view_landmarks()
plt.title('Rotated')

# Render rotated image that has shape equal as original image
plt.subplot(133)
im.transform_about_centre(rot_tr, retain_shape=True).view_landmarks()
plt.title('Rotated (Retain original shape)')
```

Similarly, in order to apply a shear transform

```
import matplotlib.pyplot as plt
import menpo.io as mio
from menpo.transform import Affine

# Load image
im = mio.import_builtin_asset.lenna_png()
```

```
# Create shearing transform
shear_tr = Affine.init_from_2d_shear(25, 10)

# Render original image
plt.subplot(131)
im.view_landmarks()
plt.title('Original')

# Render sheared image
plt.subplot(132)
im.transform_about_centre(shear_tr).view_landmarks()
plt.title('Sheared')

# Render sheared image that has shape equal as original image
plt.subplot(133)
im.transform_about_centre(shear_tr,
                          retain_shape=True).view_landmarks()
plt.title('Sheared (Retain original shape)')
```

view_widget (*figure_size=(7, 7)*)

Visualizes the image using an interactive widget.

Parameters **figure_size** ((*int*, *int*), optional) – The initial size of the rendered figure.

warp_to_mask (*template_mask*, *transform*, *warp_landmarks=True*, *order=1*, *mode='constant'*, *cval=0.0*, *batch_size=None*, *return_transform=False*)

Return a copy of this image warped into a different reference space.

Note that warping into a mask is slower than warping into a full image. If you don't need a non-linear mask, consider :meth:`warp_to_shape` instead.

Parameters

- **template_mask** (*BooleanImage*) – Defines the shape of the result, and what pixels should be sampled.
- **transform** (*Transform*) – Transform **from the template space back to this image**. Defines, for each pixel location on the template, which pixel location should be sampled from on this image.
- **warp_landmarks** (*bool*, optional) – If `True`, result will have the same landmark dictionary as `self`, but with each landmark updated to the warped position.
- **order** (*int*, optional) – The order of interpolation. The order has to be in the range [0,5]

Order	Interpolation
0	Nearest-neighbor
1	Bi-linear *(default)*
2	Bi-quadratic
3	Bi-cubic
4	Bi-quartic
5	Bi-quintic

- **mode** (`{constant, nearest, reflect, wrap}`, optional) – Points outside the boundaries of the input are filled according to the given mode.
- **cval** (*float*, optional) – Used in conjunction with mode `constant`, the value outside the image boundaries.
- **batch_size** (*int* or `None`, optional) – This should only be considered for large images. Setting this value can cause warping to become much slower, particular for cached warps

such as Piecewise Affine. This size indicates how many points in the image should be warped at a time, which keeps memory usage low. If `None`, no batching is used and all points are warped at once.

- **return_transform** (*bool*, optional) – This argument is for internal use only. If `True`, then the `Transform` object is also returned.

Returns

- **warped_image** (`MaskedImage`) – A copy of this image, warped.
- **transform** (`Transform`) – The transform that was used. It only applies if *return_transform* is `True`.

warp_to_shape(*template_shape*, *transform*, *warp_landmarks=True*, *order=1*, *mode='constant'*, *cval=0.0*, *batch_size=None*, *return_transform=False*)

Return a copy of this image warped into a different reference space.

Parameters

- **template_shape** (*tuple* or *ndarray*) – Defines the shape of the result, and what pixel indices should be sampled (all of them).
- **transform** (`Transform`) – Transform **from the template_shape space back to this image**. Defines, for each index on template_shape, which pixel location should be sampled from on this image.
- **warp_landmarks** (*bool*, optional) – If `True`, result will have the same landmark dictionary as self, but with each landmark updated to the warped position.
- **order** (*int*, optional) – The order of interpolation. The order has to be in the range [0,5]

Order	Interpolation
0	Nearest-neighbor
1	Bi-linear *(default)*
2	Bi-quadratic
3	Bi-cubic
4	Bi-quartic
5	Bi-quintic

- **mode** (`{constant, nearest, reflect, wrap}`, optional) – Points outside the boundaries of the input are filled according to the given mode.
- **cval** (*float*, optional) – Used in conjunction with mode `constant`, the value outside the image boundaries.
- **batch_size** (*int* or `None`, optional) – This should only be considered for large images. Setting this value can cause warping to become much slower, particular for cached warps such as Piecewise Affine. This size indicates how many points in the image should be warped at a time, which keeps memory usage low. If `None`, no batching is used and all points are warped at once.
- **return_transform** (*bool*, optional) – This argument is for internal use only. If `True`, then the `Transform` object is also returned.

Returns

- **warped_image** (*type(self)*) – A copy of this image, warped.
- **transform** (`Transform`) – The transform that was used. It only applies if *return_transform* is `True`.

zoom(*scale*, *cval=0.0*, *return_transform=False*)

Return a copy of this image, zoomed about the centre point. `scale` values greater than 1.0 denote zooming **in** to the image and values less than 1.0 denote zooming **out** of the image. The size of the image will not change, if you wish to scale an image, please see `rescale()`.

Parameters

- **scale** (*float*) – `scale > 1.0` denotes zooming in. Thus the image will appear larger and areas at the edge of the zoom will be 'cropped' out. `scale < 1.0` denotes zooming out. The image will be padded by the value of `cval`.
- **cval** (`float`, optional) – The value to be set outside the zoomed image boundaries.
- **return_transform** (*bool*, optional) – If `True`, then the `Transform` object that was used to perform the zooming is also returned.

Returns

- **zoomed_image** (`type(self)`) – A copy of this image, zoomed.
- **transform** (`Transform`) – The transform that was used. It only applies if *return_transform* is `True`.

has_landmarks

Whether the object has landmarks.

Type *bool*

height

The height of the image.

This is the height according to image semantics, and is thus the size of the **second to last** dimension.

Type *int*

landmarks

The landmarks object.

Type `LandmarkManager`

n_channels

The number of channels on each pixel in the image.

Type *int*

n_dims

The number of dimensions in the image. The minimum possible `n_dims` is 2.

Type *int*

n_elements

Total number of data points in the image `(prod(shape), n_channels)`

Type *int*

n_landmark_groups

The number of landmark groups on this object.

Type *int*

n_parameters

The length of the vector that this object produces.

Type *int*

n_pixels
Total number of pixels in the image `(prod(shape),)`

Type*int*

shape
The shape of the image (with `n_channel` values at each point).

Type*tuple*

width
The width of the image.

This is the width according to image semantics, and is thus the size of the **last** dimension.

Type*int*

BooleanImage

class `menpo.image.`**`BooleanImage`**(*mask_data*, *copy=True*)
Bases: `Image`

A mask image made from binary pixels. The region of the image that is left exposed by the mask is referred to as the 'masked region'. The set of 'masked' pixels is those pixels corresponding to a `True` value in the mask.

Parameters

- **mask_data** (`(M, N, ..., L)` *ndarray*) – The binary mask data. Note that there is no channel axis - a 2D Mask Image is built from just a 2D numpy array of mask_data. Automatically coerced in to boolean values.
- **copy** (*bool*, optional) – If `False`, the image_data will not be copied on assignment. Note that if the array you provide is not boolean, there **will still be copy**. In general this should only be used if you know what you are doing.

all_true()
`True` iff every element of the mask is `True`.

Type*bool*

as_PILImage(*out_dtype=<type 'numpy.uint8'>*)
Return a PIL copy of the image scaled and cast to the correct values for the provided `out_dtype`.

Image must only have 1 or 3 channels and be 2 dimensional. Non *uint8* floating point images must be in the range `[0, 1]` to be converted.

Parametersout_dtype (*np.dtype*, optional) – The dtype the output array should be.

Returnspil_image (*PILImage*) – PIL copy of image

Raises

- `ValueError` – If image is not 2D and has 1 channel or 3 channels.
- `ValueError` – If pixels data type is *float32* or *float64* and the pixel range is outside of `[0, 1]`
- `ValueError` – If the output dtype is unsupported. Currently uint8 is supported.

as_greyscale(*mode='luminosity'*, *channel=None*)
Returns a greyscale version of the image. If the image does *not* represent a 2D RGB image, then the `luminosity` mode will fail.

Parameters

- **mode** ({average, luminosity, channel}, optional) –

mode	Greyscale Algorithm
average	Equal average of all channels
luminosity	Calculates the luminance using the CCIR 601 formula:
	$Y' = 0.2989R' + 0.5870G' + 0.1140B'$
channel	A specific channel is chosen as the intensity value.

- **channel** (*int*, optional) – The channel to be taken. Only used if mode is `channel`.

Returnsgreyscale_image (*MaskedImage*) – A copy of this image in greyscale.

as_histogram(*keep_channels=True*, *bins='unique'*)

Histogram binning of the values of this image.

Parameters

- **keep_channels** (*bool*, optional) – If set to `False`, it returns a single histogram for all the channels of the image. If set to `True`, it returns a *list* of histograms, one for each channel.
- **bins** ({unique}, positive *int* or sequence of scalars, optional) – If set equal to `'unique'`, the bins of the histograms are centred on the unique values of each channel. If set equal to a positive *int*, then this is the number of bins. If set equal to a sequence of scalars, these will be used as bins centres.

Returns

- **hist** (*ndarray* or *list* with `n_channels` *ndarrays* inside) – The histogram(s). If `keep_channels=False`, then hist is an *ndarray*. If `keep_channels=True`, then hist is a *list* with `len(hist)=n_channels`.
- **bin_edges** (*ndarray* or *list* with *n_channels ndarrays* inside) – An array or a list of arrays corresponding to the above histograms that store the bins' edges.

Raises`ValueError` – Bins can be either 'unique', positive int or a sequence of scalars.

Examples

Visualizing the histogram when a list of array bin edges is provided:

```
>>> hist, bin_edges = image.as_histogram()
>>> for k in range(len(hist)):
>>>     plt.subplot(1,len(hist),k)
>>>     width = 0.7 * (bin_edges[k][1] - bin_edges[k][0])
>>>     centre = (bin_edges[k][:-1] + bin_edges[k][1:]) / 2
>>>     plt.bar(centre, hist[k], align='center', width=width)
```

---

as_imageio(*out_dtype=<type 'numpy.uint8'>*)

Return an Imageio copy of the image scaled and cast to the correct values for the provided `out_dtype`.

Image must only have 1 or 3 channels and be 2 dimensional. Non *uint8* floating point images must be in the range `[0, 1]` to be converted.

Parametersout_dtype (*np.dtype*, optional) – The dtype the output array should be.

Returns

imageio_image (*ndarray*) – Imageio image (which is just a numpy ndarray with the channels as the last axis).

Raises

- `ValueError` – If image is not 2D and has 1 channel or 3 channels.
- `ValueError` – If pixels data type is *float32* or *float64* and the pixel range is outside of `[0, 1]`
- `ValueError` – If the output dtype is unsupported. Currently uint8 and uint16 are supported.

as_masked(*mask=None*, *copy=True*)

Impossible for a `BooleanImage` to be transformed to a `MaskedImage`.

as_vector(***kwargs*)

Returns a flattened representation of the object as a single vector.

Returns

vector (*(N,) ndarray*) – The core representation of the object, flattened into a single vector. Note that this is always a view back on to the original object, but is not writable.

bounds()

The bounds of the image, minimum is always (0, 0). The maximum is the maximum **index** that can be used to index into the image for each dimension. Therefore, bounds will be of the form: ((0, 0), (self.height - 1, self.width - 1)) for a 2D image.

Note that this is akin to supporting a nearest neighbour interpolation. Although the *actual* maximum subpixel value would be something like `self.height - eps` where `eps` is some value arbitrarily close to 0, this value at least allows sampling without worrying about floating point error.

Type *tuple*

bounds_false(*boundary=0*, *constrain_to_bounds=True*)

Returns the minimum to maximum indices along all dimensions that the mask includes which fully surround the False mask values. In the case of a 2D Image for instance, the min and max define two corners of a rectangle bounding the False pixel values.

Parameters

- **boundary** (*int* >= 0, optional) – A number of pixels that should be added to the extent. A negative value can be used to shrink the bounds in.
- **constrain_to_bounds** (*bool*, optional) – If `True`, the bounding extent is snapped to not go beyond the edge of the image. If `False`, the bounds are left unchanged.

Returns

- **min_b** (`(D,)` *ndarray*) – The minimum extent of the `True` mask region with the boundary along each dimension. If `constrain_to_bounds=True`, is clipped to legal image bounds.
- **max_b** (`(D,)` *ndarray*) – The maximum extent of the `True` mask region with the boundary along each dimension. If `constrain_to_bounds=True`, is clipped to legal image bounds.

bounds_true(*boundary=0*, *constrain_to_bounds=True*)

Returns the minimum to maximum indices along all dimensions that the mask includes which fully surround the `True` mask values. In the case of a 2D Image for instance, the min and max define two corners of a rectangle bounding the True pixel values.

Parameters

- **boundary** (*int*, optional) – A number of pixels that should be added to the extent. A negative value can be used to shrink the bounds in.
- **constrain_to_bounds** (*bool*, optional) – If `True`, the bounding extent is snapped to not go beyond the edge of the image. If `False`, the bounds are left unchanged.

Returns

- **min_b** (`(D,)` *ndarray*) – The minimum extent of the `True` mask region with the boundary along each dimension. If `constrain_to_bounds=True`, is clipped to legal image bounds.
- **max_b** (`(D,)` *ndarray*) – The maximum extent of the `True` mask region with the boundary along each dimension. If `constrain_to_bounds=True`, is clipped to legal image bounds.

centre()

The geometric centre of the Image - the subpixel that is in the middle.

Useful for aligning shapes and images.

Type(`n_dims`,) *ndarray*

clip_pixels(*minimum=None*, *maximum=None*)

A copy of this image with pixels linearly clipped to fit a range.

Parameters

- **minimum** (*float*, optional) – The minimal value of the clipped pixels. If None is provided, the default value will be 0.
- **maximum** (*float*, optional) – The maximal value of the clipped pixels. If None is provided, the default value will depend on the dtype.

Returnsrescaled_image (`type(self)`) – A copy of this image with pixels linearly rescaled to fit in the range provided.

constrain_landmarks_to_bounds()

Deprecated - please use the equivalent `constrain_to_bounds` method now on PointCloud, in conjunction with the new Image `bounds()` method. For example:

```
>>> im.constrain_landmarks_to_bounds()  # Equivalent to below
>>> im.landmarks['test'] = im.landmarks['test'].constrain_to_bounds(im.
↪bounds())
```

constrain_points_to_bounds(*points*)

Constrains the points provided to be within the bounds of this image.

Parameterspoints (`(d,)` *ndarray*) – Points to be snapped to the image boundaries.

Returnsbounded_points (`(d,)` *ndarray*) – Points snapped to not stray outside the image edges.

constrain_to_landmarks(*group=None*, *batch_size=None*)

Returns a copy of this image whereby the `True` values in the image are restricted to be equal to the convex hull around the landmarks chosen. This is not a per-pixel convex hull, but instead relies on a triangulated approximation. If the landmarks in question are an instance of *`TriMesh`*, the triangulation of the landmarks will be used in the convex hull calculation. If the landmarks are an instance of *`PointCloud`*, Delaunay triangulation will be used to create a triangulation.

Parameters

- **group** (*str*, optional) – The key of the landmark set that should be used. If `None`, and if there is only one set of landmarks, this set will be used.

- **batch_size** (*int* or `None`, optional) – This should only be considered for large images. Setting this value will cause constraining to become much slower. This size indicates how many points in the image should be checked at a time, which keeps memory usage low. If `None`, no batching is used and all points are checked at once.

Returns **constrained** (`BooleanImage`) – The new boolean image, constrained by the given landmark group.

constrain_to_pointcloud(*pointcloud*, *batch_size=None*, *point_in_pointcloud='pwa'*)

Returns a copy of this image whereby the `True` values in the image are restricted to be equal to the convex hull around a pointcloud. The choice of whether a pixel is inside or outside of the pointcloud is determined by the `point_in_pointcloud` parameter. By default a Piecewise Affine transform is used to test for containment, which is useful when aligning images by their landmarks. Triangluation will be decided by Delauny - if you wish to customise it, a `TriMesh` instance can be passed for the `pointcloud` argument. In this case, the triangulation of the Trimesh will be used to define the retained region.

For large images, a faster and pixel-accurate method can be used ('convex_hull'). Here, there is no specialization for `TriMesh` instances. Alternatively, a callable can be provided to override the test. By default, the provided implementations are only valid for 2D images.

Parameters

- **pointcloud** (`PointCloud` or `TriMesh`) – The pointcloud of points that should be constrained to. See *point_in_pointcloud* for how in some cases a `TriMesh` may be used to control triangulation.
- **batch_size** (*int* or `None`, optional) – This should only be considered for large images. Setting this value will cause constraining to become much slower. This size indicates how many points in the image should be checked at a time, which keeps memory usage low. If `None`, no batching is used and all points are checked at once. By default, this is only used for the 'pwa' point_in_pointcloud choice.
- **point_in_pointcloud** ({'pwa', 'convex_hull'} or *callable*) – The method used to check if pixels in the image fall inside the `pointcloud` or not. If 'pwa', Menpo's `PiecewiseAffine` transform will be used to test for containment. In this case `pointcloud` should be a `TriMesh`. If it isn't, Delauny triangulation will be used to first triangulate `pointcloud` into a `TriMesh` before testing for containment. If a callable is passed, it should take two parameters, the `PointCloud` to constrain with and the pixel locations ((d, n_dims) ndarray) to test and should return a (d, 1) boolean ndarray of whether the pixels were inside (True) or outside (False) of the `PointCloud`.

Returns **constrained** (`BooleanImage`) – The new boolean image, constrained by the given pointcloud.

Raises

- `ValueError` – If the image is not 2D and a default implementation is chosen.
- `ValueError` – If the chosen `point_in_pointcloud` is unknown.

copy()

Generate an efficient copy of this object.

Note that Numpy arrays and other `Copyable` objects on `self` will be deeply copied. Dictionaries and sets will be shallow copied, and everything else will be assigned (no copy will be made).

Classes that store state other than numpy arrays and immutable types should overwrite this method to ensure all state is copied.

Returns `type(self)` – A copy of this object

crop(*min_indices*, *max_indices*, *constrain_to_boundary=False*, *return_transform=False*)

Return a cropped copy of this image using the given minimum and maximum indices. Landmarks are correctly adjusted so they maintain their position relative to the newly cropped image.

Parameters

- **min_indices** ((n_dims,) *ndarray*) – The minimum index over each dimension.
- **max_indices** ((n_dims,) *ndarray*) – The maximum index over each dimension.
- **constrain_to_boundary** (*bool*, optional) – If `True` the crop will be snapped to not go beyond this images boundary. If `False`, an `ImageBoundaryError` will be raised if an attempt is made to go beyond the edge of the image.
- **return_transform** (*bool*, optional) – If `True`, then the `Transform` object that was used to perform the cropping is also returned.

Returns

- **cropped_image** (*type(self)*) – A new instance of self, but cropped.
- **transform** (`Transform`) – The transform that was used. It only applies if *return_transform* is `True`.

Raises

- `ValueError` – `min_indices` and `max_indices` both have to be of length `n_dims`. All `max_indices` must be greater than `min_indices`.
- `ImageBoundaryError` – Raised if `constrain_to_boundary=False`, and an attempt is made to crop the image in a way that violates the image bounds.

crop_to_landmarks(*group=None*, *boundary=0*, *constrain_to_boundary=True*, *return_transform=False*)

Return a copy of this image cropped so that it is bounded around a set of landmarks with an optional `n_pixel` boundary

Parameters

- **group** (*str*, optional) – The key of the landmark set that should be used. If `None` and if there is only one set of landmarks, this set will be used.
- **boundary** (*int*, optional) – An extra padding to be added all around the landmarks bounds.
- **constrain_to_boundary** (*bool*, optional) – If `True` the crop will be snapped to not go beyond this images boundary. If `False`, an :map'ImageBoundaryError' will be raised if an attempt is made to go beyond the edge of the image.
- **return_transform** (*bool*, optional) – If `True`, then the `Transform` object that was used to perform the cropping is also returned.

Returns

- **image** (`Image`) – A copy of this image cropped to its landmarks.
- **transform** (`Transform`) – The transform that was used. It only applies if *return_transform* is `True`.

Raises `ImageBoundaryError` – Raised if `constrain_to_boundary=False`, and an attempt is made to crop the image in a way that violates the image bounds.

crop_to_landmarks_proportion(*boundary_proportion*, *group=None*, *minimum=True*, *constrain_to_boundary=True*, *return_transform=False*)

Crop this image to be bounded around a set of landmarks with a border proportional to the landmark spread or range.

Parameters

- **boundary_proportion** (*float*) – Additional padding to be added all around the landmarks bounds defined as a proportion of the landmarks range. See the minimum parameter for a definition of how the range is calculated.
- **group** (*str*, optional) – The key of the landmark set that should be used. If `None` and if there is only one set of landmarks, this set will be used.
- **minimum** (*bool*, optional) – If `True` the specified proportion is relative to the minimum value of the landmarks' per-dimension range; if `False` w.r.t. the maximum value of the landmarks' per-dimension range.
- **constrain_to_boundary** (*bool*, optional) – If `True`, the crop will be snapped to not go beyond this images boundary. If `False`, an `ImageBoundaryError` will be raised if an attempt is made to go beyond the edge of the image.
- **return_transform** (*bool*, optional) – If `True`, then the `Transform` object that was used to perform the cropping is also returned.

Returns

- **image** (`Image`) – This image, cropped to its landmarks with a border proportional to the landmark spread or range.
- **transform** (`Transform`) – The transform that was used. It only applies if *return_transform* is `True`.

Raises `ImageBoundaryError` – Raised if `constrain_to_boundary=False`, and an attempt is made to crop the image in a way that violates the image bounds.

crop_to_pointcloud(*pointcloud*, *boundary=0*, *constrain_to_boundary=True*, *return_transform=False*)

Return a copy of this image cropped so that it is bounded around a pointcloud with an optional `n_pixel` boundary.

Parameters

- **pointcloud** (`PointCloud`) – The pointcloud to crop around.
- **boundary** (*int*, optional) – An extra padding to be added all around the landmarks bounds.
- **constrain_to_boundary** (*bool*, optional) – If `True` the crop will be snapped to not go beyond this images boundary. If `False`, an :map'ImageBoundaryError' will be raised if an attempt is made to go beyond the edge of the image.
- **return_transform** (*bool*, optional) – If `True`, then the `Transform` object that was used to perform the cropping is also returned.

Returns

- **image** (`Image`) – A copy of this image cropped to the bounds of the pointcloud.
- **transform** (`Transform`) – The transform that was used. It only applies if *return_transform* is `True`.

Raises `ImageBoundaryError` – Raised if `constrain_to_boundary=False`, and an attempt is made to crop the image in a way that violates the image bounds.

crop_to_pointcloud_proportion(*pointcloud*, *boundary_proportion*, *minimum=True*, *constrain_to_boundary=True*, *return_transform=False*)

Return a copy of this image cropped so that it is bounded around a pointcloud with an optional `n_pixel` boundary.

Parameters

- **pointcloud** (*PointCloud*) – The pointcloud to crop around.
- **boundary_proportion** (*float*) – Additional padding to be added all around the landmarks bounds defined as a proportion of the landmarks range. See the minimum parameter for a definition of how the range is calculated.
- **minimum** (*bool*, optional) – If `True` the specified proportion is relative to the minimum value of the pointclouds' per-dimension range; if `False` w.r.t. the maximum value of the pointclouds' per-dimension range.
- **constrain_to_boundary** (*bool*, optional) – If `True`, the crop will be snapped to not go beyond this images boundary. If `False`, an *ImageBoundaryError* will be raised if an attempt is made to go beyond the edge of the image.
- **return_transform** (*bool*, optional) – If `True`, then the *Transform* object that was used to perform the cropping is also returned.

Returns

- **image** (*Image*) – A copy of this image cropped to the border proportional to the pointcloud spread or range.
- **transform** (*Transform*) – The transform that was used. It only applies if *return_transform* is `True`.

Raises *ImageBoundaryError* – Raised if `constrain_to_boundary=False`, and an attempt is made to crop the image in a way that violates the image bounds.

diagonal()

The diagonal size of this image

Type *float*

extract_channels(*channels*)

A copy of this image with only the specified channels.

Parameters **channels** (*int* or *[int]*) – The channel index or *list* of channel indices to retain.

Returns **image** (*type(self)*) – A copy of this image with only the channels requested.

extract_patches(*patch_centers*, *patch_shape=(16, 16)*, *sample_offsets=None*, *as_single_array=True*)

Extract a set of patches from an image. Given a set of patch centers and a patch size, patches are extracted from within the image, centred on the given coordinates. Sample offsets denote a set of offsets to extract from within a patch. This is very useful if you want to extract a dense set of features around a set of landmarks and simply sample the same grid of patches around the landmarks.

If sample offsets are used, to access the offsets for each patch you need to slice the resulting *list*. So for 2 offsets, the first centers offset patches would be `patches[:2]`.

Currently only 2D images are supported.

Parameters

- **patch_centers** (*PointCloud*) – The centers to extract patches around.
- **patch_shape** (`(1, n_dims)` *tuple* or *ndarray*, optional) – The size of the patch to extract

- **sample_offsets** ((n_offsets, n_dims) *ndarray* or None, optional) – The offsets to sample from within a patch. So (0, 0) is the centre of the patch (no offset) and (1, 0) would be sampling the patch from 1 pixel up the first axis away from the centre. If None, then no offsets are applied.
- **as_single_array** (*bool*, optional) – If True, an (n_center, n_offset, n_channels, patch_shape) *ndarray*, thus a single numpy array is returned containing each patch. If False, a *list* of n_center * n_offset *Image* objects is returned representing each patch.

Returns **patches** (*list* or *ndarray*) – Returns the extracted patches. Returns a list if as_single_array=True and an *ndarray* if as_single_array=False.

Raises ValueError – If image is not 2D

extract_patches_around_landmarks(*group=None*, *patch_shape=(16, 16)*, *sample_offsets=None*, *as_single_array=True*)

Extract patches around landmarks existing on this image. Provided the group label and optionally the landmark label extract a set of patches.

See *extract_patches* for more information.

Currently only 2D images are supported.

Parameters

- **group** (*str* or None, optional) – The landmark group to use as patch centres.
- **patch_shape** (*tuple* or *ndarray*, optional) – The size of the patch to extract
- **sample_offsets** ((n_offsets, n_dims) *ndarray* or None, optional) – The offsets to sample from within a patch. So (0, 0) is the centre of the patch (no offset) and (1, 0) would be sampling the patch from 1 pixel up the first axis away from the centre. If None, then no offsets are applied.
- **as_single_array** (*bool*, optional) – If True, an (n_center, n_offset, n_channels, patch_shape) *ndarray*, thus a single numpy array is returned containing each patch. If False, a *list* of n_center * n_offset *Image* objects is returned representing each patch.

Returns **patches** (*list* or *ndarray*) – Returns the extracted patches. Returns a list if as_single_array=True and an *ndarray* if as_single_array=False.

Raises ValueError – If image is not 2D

false_indices()

The indices of pixels that are Flase.

Type (n_dims, n_false) *ndarray*

from_vector(*vector*, *copy=True*)

Takes a flattened vector and returns a new *BooleanImage* formed by reshaping the vector to the correct dimensions. Note that this is rebuilding a boolean image **itself** from boolean values. The mask is in no way interpreted in performing the operation, in contrast to *MaskedImage*, where only the masked region is used in *from_vector()* and :meth'as_vector'. Any image landmarks are transferred in the process.

Parameters

- **vector** ((n_pixels,) *bool ndarray*) – A flattened vector of all the pixels of a *BooleanImage*.
- **copy** (*bool*, optional) – If False, no copy of the vector will be taken.

Returns **image** (*BooleanImage*) – New BooleanImage of same shape as this image

Raises`Warning` – If `copy=False` cannot be honored.

from_vector_inplace(*vector*)

Deprecated. Use the non-mutating API, `from_vector`.

For internal usage in performance-sensitive spots, see *_from_vector_inplace()*

Parameters
vector (`(n_parameters,)` *ndarray*) – Flattened representation of this object

gaussian_pyramid(*n_levels=3*, *downscale=2*, *sigma=None*)

Return the gaussian pyramid of this image. The first image of the pyramid will be a copy of the original, unmodified, image, and counts as level 1.

Parameters

- **n_levels** (*int*, optional) – Total number of levels in the pyramid, including the original unmodified image
- **downscale** (*float*, optional) – Downscale factor.
- **sigma** (*float*, optional) – Sigma for gaussian filter. Default is `downscale / 3.` which corresponds to a filter mask twice the size of the scale factor that covers more than 99% of the gaussian distribution.

Yields
image_pyramid (*generator*) – Generator yielding pyramid layers as `Image` objects.

has_landmarks_outside_bounds()

Indicates whether there are landmarks located outside the image bounds.

Type
bool

has_nan_values()

Tests if the vectorized form of the object contains `nan` values or not. This is particularly useful for objects with unknown values that have been mapped to `nan` values.

Returns
has_nan_values (*bool*) – If the vectorized object contains `nan` values.

indices()

Return the indices of all pixels in this image.

Type
(`n_dims`, `n_pixels`) ndarray

classmethod init_blank(*shape*, *fill=True*, *round='ceil'*, ***kwargs*)

Returns a blank `BooleanImage` of the requested shape

Parameters

- **shape** (*tuple* or *list*) – The shape of the image. Any floating point values are rounded according to the `round` kwarg.
- **fill** (*bool*, optional) – The mask value to be set everywhere.
- **round** (`{ceil, floor, round}`, optional) – Rounding function to be applied to floating point shapes.

Returns
blank_image (`BooleanImage`) – A blank mask of the requested size

classmethod init_from_channels_at_back(*pixels*)

This method is not required for `BooleanImage` types as boolean images do not expect a channel axis for construction.

Parameters
pixels (`(M, N ..., Q)` *ndarray*) – Array representing the image pixels, with NO channel axis.

Returns
image (`BooleanImage`) – A new image from the given boolean pixels.

classmethod **init_from_pointcloud**(*pointcloud*, *group=None*, *boundary=0*, *constrain=True*, *fill=True*)

Create an Image that is big enough to contain the given pointcloud. The pointcloud will be translated to the origin and then translated according to its bounds in order to fit inside the new image. An optional boundary can be provided in order to increase the space around the boundary of the pointcloud. The boundary will be added to *all sides of the image* and so a boundary of 5 provides 10 pixels of boundary total for each dimension.

By default, the mask will be constrained to the convex hull of the provided pointcloud.

Parameters

- **pointcloud** (*PointCloud*) – Pointcloud to place inside the newly created image.
- **group** (*str*, optional) – If `None`, the pointcloud will only be used to create the image. If a *str* then the pointcloud will be attached as a landmark group to the image, with the given string as key.
- **boundary** (*float*) – A optional padding distance that is added to the pointcloud bounds. Default is `0`, meaning the max/min of tightest possible containing image is returned.
- **fill** (*int*, optional) – The value to fill all pixels with.
- **constrain** (*bool*, optional) – If `True`, the `True` values will be image will be constrained to the convex hull of the provided pointcloud. If `False`, the mask will be the value of `fill`.

Returnsimage (*MaskedImage*) – A new image with the same size as the given pointcloud, optionally with the pointcloud attached as landmarks and the mask constrained to the convex hull of the pointcloud.

init_from_rolled_channels(*pixels*)

Deprecated - please use the equivalent `init_from_channels_at_back` method.

invert()

Returns a copy of this boolean image, which is inverted.

Returnsinverted (*BooleanImage*) – A copy of this boolean mask, where all `True` values are `False` and all `False` values are `True`.

mirror(*axis=1*, *return_transform=False*)

Return a copy of this image, mirrored/flipped about a certain axis.

Parameters

- **axis** (*int*, optional) – The axis about which to mirror the image.
- **return_transform** (*bool*, optional) – If `True`, then the *Transform* object that was used to perform the mirroring is also returned.

Returns

- **mirrored_image** (`type(self)`) – The mirrored image.
- **transform** (*Transform*) – The transform that was used. It only applies if *return_transform* is `True`.

Raises

- `ValueError` – axis cannot be negative
- `ValueError` – axis={} but the image has {} dimensions

n_false()

The number of `False` values in the mask.

Type*int*

n_true()

The number of `True` values in the mask.

Type*int*

normalize_norm(*mode='all', **kwargs*)

Returns a copy of this image normalized such that its pixel values have zero mean and its norm equals 1.

Parameters

mode (`{all, per_channel}`, optional) – If `all`, the normalization is over all channels. If `per_channel`, each channel individually is mean centred and unit norm.

Returns

image (`type(self)`) – A copy of this image, normalized.

normalize_std(*mode='all', **kwargs*)

Returns a copy of this image normalized such that its pixel values have zero mean and unit variance.

Parameters

mode (`{all, per_channel}`, optional) – If `all`, the normalization is over all channels. If `per_channel`, each channel individually is mean centred and normalized in variance.

Returns

image (`type(self)`) – A copy of this image, normalized.

pixels_range()

The range of the pixel values (min and max pixel values).

Returns

min_max (`(dtype, dtype)`) – The minimum and maximum value of the pixels array.

pixels_with_channels_at_back(*out_dtype=None*)

Returns the pixels matrix, with the channels rolled to the back axis. This may be required for interacting with external code bases that require images to have channels as the last axis, rather than the Menpo convention of channels as the first axis.

If this image is single channel, the final axis is dropped.

Parameters

out_dtype (*np.dtype*, optional) – The dtype the output array should be.

Returns

rolled_channels (*ndarray*) – Pixels with channels as the back (last) axis. If single channel, the last axis will be dropped.

proportion_false()

The proportion of the mask which is `False`

Type*float*

proportion_true()

The proportion of the mask which is `True`.

Type*float*

pyramid(*n_levels=3, downscale=2*)

Return a rescaled pyramid of this image. The first image of the pyramid will be a copy of the original, unmodified, image, and counts as level 1.

Parameters

- **n_levels** (*int*, optional) – Total number of levels in the pyramid, including the original unmodified image
- **downscale** (*float*, optional) – Downscale factor.

Yields

image_pyramid (*generator*) – Generator yielding pyramid layers as `Image` objects.

rasterize_landmarks(*group=None*, *render_lines=True*, *line_style='-'*, *line_colour='b'*, *line_width=1*, *render_markers=True*, *marker_style='o'*, *marker_size=1*, *marker_face_colour='b'*, *marker_edge_colour='b'*, *marker_edge_width=1*, *backend='matplotlib'*)

This method provides the ability to rasterize 2D landmarks onto the image. The returned image has the specified landmark groups rasterized onto the image - which is useful for things like creating result examples or rendering videos with annotations.

Since multiple landmark groups can be specified, all arguments can take lists of parameters that map to the provided groups list. Therefore, the parameters must be lists of the correct length or a single parameter to apply to every landmark group.

Multiple backends are provided, all with different strengths. The 'pillow' backend is very fast, but not very flexible. The *matplotlib* backend should be feature compatible with other Menpo rendering methods, but is much slower due to the overhead of creating a figure to render into.

Parameters

- **group** (*str* or *list* of *str*, optional) – The landmark group key, or a list of keys.
- **render_lines** (*bool*, optional) – If `True`, and the provided landmark group is a `PointDirectedGraph`, the edges are rendered.
- **line_style** (*str*, optional) – The style of the edge line. Not all backends support this argument.
- **line_colour** (*str* or *tuple*, optional) – A Matplotlib style colour or a backend dependant colour.
- **line_width** (*int*, optional) – The width of the line to rasterize.
- **render_markers** (*bool*, optional) – If `True`, render markers at the coordinates of each landmark.
- **marker_style** (*str*, optional) – A Matplotlib marker style. Not all backends support all marker styles.
- **marker_size** (*int*, optional) – The size of the marker - different backends use different scale spaces so consistent output may by difficult.
- **marker_face_colour** (*str*, optional) – A Matplotlib style colour or a backend dependant colour.
- **marker_edge_colour** (*str*, optional) – A Matplotlib style colour or a backend dependant colour.
- **marker_edge_width** (*int*, optional) – The width of the marker edge. Not all backends support this.
- **backend** (*{'matplotlib', 'pillow'}, optional*) – The backend to use.

Returnsrasterized_image (`Image`) – The image with the landmarks rasterized directly into the pixels.

Raises

- `ValueError` – Only 2D images are supported.
- `ValueError` – Only RGB (3-channel) or Greyscale (1-channel) images are supported.

rescale(*scale*, *round='ceil'*, *order=1*, *return_transform=False*)

Return a copy of this image, rescaled by a given factor. Landmarks are rescaled appropriately.

Parameters

- **scale** (*float* or *tuple* of *floats*) – The scale factor. If a tuple, the scale to apply to each dimension. If a single *float*, the scale will be applied uniformly across each dimension.
- **round** (`{ceil, floor, round}`, optional) – Rounding function to be applied to floating point shapes.
- **order** (*int*, optional) – The order of interpolation. The order has to be in the range [0,5]

Order	Interpolation
0	Nearest-neighbor
1	Bi-linear *(default)*
2	Bi-quadratic
3	Bi-cubic
4	Bi-quartic
5	Bi-quintic

- **return_transform** (*bool*, optional) – If `True`, then the `Transform` object that was used to perform the rescale is also returned.

Returns

- **rescaled_image** (`type(self)`) – A copy of this image, rescaled.
- **transform** (`Transform`) – The transform that was used. It only applies if *return_transform* is `True`.

Raises ValueError: – If less scales than dimensions are provided. If any scale is less than or equal to 0.

rescale_landmarks_to_diagonal_range(*diagonal_range*, *group=None*, *round='ceil'*, *order=1*, *return_transform=False*)

Return a copy of this image, rescaled so that the `diagonal_range` of the bounding box containing its landmarks matches the specified `diagonal_range` range.

Parameters

- **diagonal_range** (`(n_dims,)` *ndarray*) – The diagonal_range range that we want the landmarks of the returned image to have.
- **group** (*str*, optional) – The key of the landmark set that should be used. If `None` and if there is only one set of landmarks, this set will be used.
- **round** (`{ceil, floor, round}`, optional) – Rounding function to be applied to floating point shapes.
- **order** (*int*, optional) – The order of interpolation. The order has to be in the range [0,5]

Order	Interpolation
0	Nearest-neighbor
1	Bi-linear *(default)*
2	Bi-quadratic
3	Bi-cubic
4	Bi-quartic
5	Bi-quintic

- **return_transform** (*bool*, optional) – If `True`, then the `Transform` object that was used to perform the rescale is also returned.

Returns

- **rescaled_image** (`type(self)`) – A copy of this image, rescaled.

- **transform** (*Transform*) – The transform that was used. It only applies if *return_transform* is `True`.

rescale_pixels(*minimum*, *maximum*, *per_channel=True*)

A copy of this image with pixels linearly rescaled to fit a range.

Note that the only pixels that will be considered and rescaled are those that feature in the vectorized form of this image. If you want to use this routine on all the pixels in a *MaskedImage*, consider using *as_unmasked()* prior to this call.

Parameters

- **minimum** (*float*) – The minimal value of the rescaled pixels
- **maximum** (*float*) – The maximal value of the rescaled pixels
- **per_channel** (*boolean*, optional) – If `True`, each channel will be rescaled independently. If `False`, the scaling will be over all channels.

Returnsrescaled_image (`type(self)`) – A copy of this image with pixels linearly rescaled to fit in the range provided.

rescale_to_diagonal(*diagonal*, *round='ceil'*, *return_transform=False*)

Return a copy of this image, rescaled so that the it's diagonal is a new size.

Parameters

- **diagonal** (*int*) – The diagonal size of the new image.
- **round** (`{ceil, floor, round}`, optional) – Rounding function to be applied to floating point shapes.
- **return_transform** (*bool*, optional) – If `True`, then the *Transform* object that was used to perform the rescale is also returned.

Returns

- **rescaled_image** (*type(self)*) – A copy of this image, rescaled.
- **transform** (*Transform*) – The transform that was used. It only applies if *return_transform* is `True`.

rescale_to_pointcloud(*pointcloud*, *group=None*, *round='ceil'*, *order=1*, *return_transform=False*)

Return a copy of this image, rescaled so that the scale of a particular group of landmarks matches the scale of the passed reference pointcloud.

Parameters

- **pointcloud** (*PointCloud*) – The reference pointcloud to which the landmarks specified by `group` will be scaled to match.
- **group** (*str*, optional) – The key of the landmark set that should be used. If `None`, and if there is only one set of landmarks, this set will be used.
- **round** (`{ceil, floor, round}`, optional) – Rounding function to be applied to floating point shapes.
- **order** (*int*, optional) – The order of interpolation. The order has to be in the range [0,5]

Order	Interpolation
0	Nearest-neighbor
1	Bi-linear *(default)*
2	Bi-quadratic
3	Bi-cubic
4	Bi-quartic
5	Bi-quintic

- **return_transform** (*bool*, optional) – If `True`, then the `Transform` object that was used to perform the rescale is also returned.

Returns

- **rescaled_image** (`type(self)`) – A copy of this image, rescaled.
- **transform** (`Transform`) – The transform that was used. It only applies if *return_transform* is `True`.

resize(*shape*, *order=1*, *return_transform=False*)

Return a copy of this image, resized to a particular shape. All image information (landmarks, and mask in the case of `MaskedImage`) is resized appropriately.

Parameters

- **shape** (*tuple*) – The new shape to resize to.
- **order** (*int*, optional) – The order of interpolation. The order has to be in the range [0,5]

Order	Interpolation
0	Nearest-neighbor
1	Bi-linear *(default)*
2	Bi-quadratic
3	Bi-cubic
4	Bi-quartic
5	Bi-quintic

- **return_transform** (*bool*, optional) – If `True`, then the `Transform` object that was used to perform the resize is also returned.

Returns

- **resized_image** (`type(self)`) – A copy of this image, resized.
- **transform** (`Transform`) – The transform that was used. It only applies if *return_transform* is `True`.

Raises ValueError: – If the number of dimensions of the new shape does not match the number of dimensions of the image.

rolled_channels()

Deprecated - please use the equivalent `pixels_with_channels_at_back` method.

rotate_ccw_about_centre(*theta*, *degrees=True*, *retain_shape=False*, *cval=0.0*, *round='round'*, *order=1*, *return_transform=False*)

Return a copy of this image, rotated counter-clockwise about its centre.

Note that the *retain_shape* argument defines the shape of the rotated image. If `retain_shape=True`, then the shape of the rotated image will be the same as the one of current image, so some regions will probably be cropped. If `retain_shape=False`, then the returned image has the correct size so that the whole area of the current image is included.

Parameters

- **theta** (*float*) – The angle of rotation about the centre.
- **degrees** (*bool*, optional) – If `True`, *theta* is interpreted in degrees. If `False`, `theta` is interpreted as radians.
- **retain_shape** (*bool*, optional) – If `True`, then the shape of the rotated image will be the same as the one of current image, so some regions will probably be cropped. If `False`, then the returned image has the correct size so that the whole area of the current image is included.
- **cval** (*float*, optional) – The value to be set outside the rotated image boundaries.
- **round** (`{'ceil', 'floor', 'round'}`, optional) – Rounding function to be applied to floating point shapes. This is only used in case `retain_shape=True`.
- **order** (*int*, optional) – The order of interpolation. The order has to be in the range `[0, 5]`. This is only used in case `retain_shape=True`.

Order	Interpolation
0	Nearest-neighbor
1	Bi-linear *(default)*
2	Bi-quadratic
3	Bi-cubic
4	Bi-quartic
5	Bi-quintic

- **return_transform** (*bool*, optional) – If `True`, then the `Transform` object that was used to perform the rotation is also returned.

Returns

- **rotated_image** (`type(self)`) – The rotated image.
- **transform** (`Transform`) – The transform that was used. It only applies if *return_transform* is `True`.

Raises `ValueError` – Image rotation is presently only supported on 2D images

sample (*points_to_sample*, *mode='constant'*, *cval=False*, ***kwargs*)

Sample this image at the given sub-pixel accurate points. The input PointCloud should have the same number of dimensions as the image e.g. a 2D PointCloud for a 2D multi-channel image. A numpy array will be returned the has the values for every given point across each channel of the image.

Parameters

- **points_to_sample** (`PointCloud`) – Array of points to sample from the image. Should be *(n_points, n_dims)*
- **mode** (`{constant, nearest, reflect, wrap}`, optional) – Points outside the boundaries of the input are filled according to the given mode.
- **cval** (*float*, optional) – Used in conjunction with mode `constant`, the value outside the image boundaries.

Returns **sampled_pixels** (*(n_points, n_channels) bool ndarray*) – The interpolated values taken across every channel of the image.

set_patches (*patches*, *patch_centers*, *offset=None*, *offset_index=None*)

Set the values of a group of patches into the correct regions in a copy of this image. Given an array of patches and a set of patch centers, the patches' values are copied in the regions of the image that are centred on the coordinates of the given centers.

The patches argument can have any of the two formats that are returned from the *extract_patches()* and *extract_patches_around_landmarks()* methods. Specifically it can be:

1. `(n_center, n_offset, self.n_channels, patch_shape)` *ndarray*
2. *list* of `n_center * n_offset` *Image* objects

Currently only 2D images are supported.

Parameters

- **patches** (*ndarray* or *list*) – The values of the patches. It can have any of the two formats that are returned from the *extract_patches()* and *extract_patches_around_landmarks()* methods. Specifically, it can either be an `(n_center, n_offset, self.n_channels, patch_shape)` *ndarray* or a *list* of `n_center * n_offset` *Image* objects.
- **patch_centers** (*PointCloud*) – The centers to set the patches around.
- **offset** (*list* or *tuple* or `(1, 2)` *ndarray* or `None`, optional) – The offset to apply on the patch centers within the image. If `None`, then `(0, 0)` is used.
- **offset_index** (*int* or `None`, optional) – The offset index within the provided *patches* argument, thus the index of the second dimension from which to sample. If `None`, then `0` is used.

Raises

- `ValueError` – If image is not 2D
- `ValueError` – If offset does not have shape (1, 2)

Returnsnew_image (*BooleanImage*) – A new boolean image where the provided patch locations have been set to the provided values.

set_patches_around_landmarks (*patches*, *group=None*, *offset=None*, *offset_index=None*)

Set the values of a group of patches around the landmarks existing in a copy of this image. Given an array of patches, a group and a label, the patches' values are copied in the regions of the image that are centred on the coordinates of corresponding landmarks.

The patches argument can have any of the two formats that are returned from the *extract_patches()* and *extract_patches_around_landmarks()* methods. Specifically it can be:

1. `(n_center, n_offset, self.n_channels, patch_shape)` *ndarray*
2. *list* of `n_center * n_offset` *Image* objects

Currently only 2D images are supported.

Parameters

- **patches** (*ndarray* or *list*) – The values of the patches. It can have any of the two formats that are returned from the *extract_patches()* and *extract_patches_around_landmarks()* methods. Specifically, it can either be an `(n_center, n_offset, self.n_channels, patch_shape)` *ndarray* or a *list* of `n_center * n_offset` *Image* objects.
- **group** (*str* or `None` optional) – The landmark group to use as patch centres.
- **offset** (*list* or *tuple* or `(1, 2)` *ndarray* or `None`, optional) – The offset to apply on the patch centers within the image. If `None`, then `(0, 0)` is used.
- **offset_index** (*int* or `None`, optional) – The offset index within the provided *patches* argument, thus the index of the second dimension from which to sample. If `None`, then `0` is used.

Raises

- `ValueError` – If image is not 2D
- `ValueError` – If offset does not have shape (1, 2)

transform_about_centre(*transform*, *retain_shape=False*, *cval=0.0*, *round='round'*, *order=1*, *return_transform=False*)

Return a copy of this image, transformed about its centre.

Note that the *retain_shape* argument defines the shape of the transformed image. If `retain_shape=True`, then the shape of the transformed image will be the same as the one of current image, so some regions will probably be cropped. If `retain_shape=False`, then the returned image has the correct size so that the whole area of the current image is included.

Note: This method will not work for transforms that result in a transform chain as `TransformChain` is not invertible.

Note: Be careful when defining transforms for warping imgaes. All pixel locations must fall within a valid range as expected by the transform. Therefore, your transformation must accept 'negative' pixel locations as the pixel locations provided to your transform will have the object centre subtracted from them.

Parameters

- **transform** (`ComposableTransform` and `VInvertible` type) – A composable transform. `pseudoinverse` will be invoked on the resulting transform so it must implement a valid inverse.
- **retain_shape** (*bool*, optional) – If `True`, then the shape of the sheared image will be the same as the one of current image, so some regions will probably be cropped. If `False`, then the returned image has the correct size so that the whole area of the current image is included.
- **cval** (*float*, optional) – The value to be set outside the sheared image boundaries.
- **round** (`{'ceil', 'floor', 'round'}`, optional) – Rounding function to be applied to floating point shapes. This is only used in case `retain_shape=True`.
- **order** (*int*, optional) – The order of interpolation. The order has to be in the range `[0, 5]`. This is only used in case `retain_shape=True`.

Order	Interpolation
0	Nearest-neighbor
1	Bi-linear *(default)*
2	Bi-quadratic
3	Bi-cubic
4	Bi-quartic
5	Bi-quintic

- **return_transform** (*bool*, optional) – If `True`, then the `Transform` object that was used to perform the shearing is also returned.

Returns

- **transformed_image** (`type(self)`) – The transformed image.

- **transform** (*Transform*) – The transform that was used. It only applies if *return_transform* is `True`.

Examples

This is an example for rotating an image about its center. Let's first load an image, create the rotation transform and then apply it

```
import matplotlib.pyplot as plt
import menpo.io as mio
from menpo.transform import Rotation

# Load image
im = mio.import_builtin_asset.lenna_png()

# Create shearing transform
rot_tr = Rotation.init_from_2d_ccw_angle(45)

# Render original image
plt.subplot(131)
im.view_landmarks()
plt.title('Original')

# Render rotated image
plt.subplot(132)
im.transform_about_centre(rot_tr).view_landmarks()
plt.title('Rotated')

# Render rotated image that has shape equal as original image
plt.subplot(133)
im.transform_about_centre(rot_tr, retain_shape=True).view_landmarks()
plt.title('Rotated (Retain original shape)')
```

Similarly, in order to apply a shear transform

```
import matplotlib.pyplot as plt
import menpo.io as mio
from menpo.transform import Affine

# Load image
im = mio.import_builtin_asset.lenna_png()

# Create shearing transform
shear_tr = Affine.init_from_2d_shear(25, 10)

# Render original image
plt.subplot(131)
im.view_landmarks()
plt.title('Original')

# Render sheared image
plt.subplot(132)
im.transform_about_centre(shear_tr).view_landmarks()
plt.title('Sheared')

# Render sheared image that has shape equal as original image
```

```
plt.subplot(133)
im.transform_about_centre(shear_tr,
                          retain_shape=True).view_landmarks()
plt.title('Sheared (Retain original shape)')
```

true_indices()

The indices of pixels that are `True`.

Type `(n_dims, n_true)` *ndarray*

view_widget(*figure_size=(7, 7)*)

Visualizes the image using an interactive widget.

Parameters **figure_size** ((*int*, *int*), optional) – The initial size of the rendered figure.

warp_to_mask(*template_mask*, *transform*, *warp_landmarks=True*, *mode='constant'*, *cval=False*, *batch_size=None*, *return_transform=False*)

Return a copy of this `BooleanImage` warped into a different reference space.

Note that warping into a mask is slower than warping into a full image. If you don't need a non-linear mask, consider warp_to_shape instead.

Parameters

- **template_mask** (`BooleanImage`) – Defines the shape of the result, and what pixels should be sampled.
- **transform** (`Transform`) – Transform **from the template space back to this image**. Defines, for each pixel location on the template, which pixel location should be sampled from on this image.
- **warp_landmarks** (*bool*, optional) – If `True`, result will have the same landmark dictionary as self, but with each landmark updated to the warped position.
- **mode** (`{constant, nearest, reflect or wrap}`, optional) – Points outside the boundaries of the input are filled according to the given mode.
- **cval** (*float*, optional) – Used in conjunction with mode `constant`, the value outside the image boundaries.
- **batch_size** (*int* or `None`, optional) – This should only be considered for large images. Setting this value can cause warping to become much slower, particular for cached warps such as Piecewise Affine. This size indicates how many points in the image should be warped at a time, which keeps memory usage low. If `None`, no batching is used and all points are warped at once.
- **return_transform** (*bool*, optional) – This argument is for internal use only. If `True`, then the `Transform` object is also returned.

Returns

- **warped_image** (`BooleanImage`) – A copy of this image, warped.
- **transform** (`Transform`) – The transform that was used. It only applies if *return_transform* is `True`.

warp_to_shape(*template_shape*, *transform*, *warp_landmarks=True*, *mode='constant'*, *cval=False*, *order=None*, *batch_size=None*, *return_transform=False*)

Return a copy of this `BooleanImage` warped into a different reference space.

Note that the order keyword argument is in fact ignored, as any order other than 0 makes no sense on a binary image. The keyword argument is present only for compatibility with the `Image` warp_to_shape API.

Parameters

- **template_shape** (`(n_dims, )` *tuple* or *ndarray*) – Defines the shape of the result, and what pixel indices should be sampled (all of them).
- **transform** (`Transform`) – Transform **from the template_shape space back to this image**. Defines, for each index on template_shape, which pixel location should be sampled from on this image.
- **warp_landmarks** (*bool*, optional) – If `True`, result will have the same landmark dictionary as self, but with each landmark updated to the warped position.
- **mode** (`{constant, nearest, reflect or wrap}`, optional) – Points outside the boundaries of the input are filled according to the given mode.
- **cval** (*float*, optional) – Used in conjunction with mode `constant`, the value outside the image boundaries.
- **batch_size** (*int* or `None`, optional) – This should only be considered for large images. Setting this value can cause warping to become much slower, particular for cached warps such as Piecewise Affine. This size indicates how many points in the image should be warped at a time, which keeps memory usage low. If `None`, no batching is used and all points are warped at once.
- **return_transform** (*bool*, optional) – This argument is for internal use only. If `True`, then the `Transform` object is also returned.

Returns

- **warped_image** (`BooleanImage`) – A copy of this image, warped.
- **transform** (`Transform`) – The transform that was used. It only applies if *return_transform* is `True`.

zoom(*scale*, *cval=0.0*, *return_transform=False*)

Return a copy of this image, zoomed about the centre point. `scale` values greater than 1.0 denote zooming **in** to the image and values less than 1.0 denote zooming **out** of the image. The size of the image will not change, if you wish to scale an image, please see `rescale()`.

Parameters

- **scale** (*float*) – `scale > 1.0` denotes zooming in. Thus the image will appear larger and areas at the edge of the zoom will be 'cropped' out. `scale < 1.0` denotes zooming out. The image will be padded by the value of `cval`.
- **cval** (`float`, optional) – The value to be set outside the zoomed image boundaries.
- **return_transform** (*bool*, optional) – If `True`, then the `Transform` object that was used to perform the zooming is also returned.

Returns

- **zoomed_image** (`type(self)`) – A copy of this image, zoomed.
- **transform** (`Transform`) – The transform that was used. It only applies if *return_transform* is `True`.

has_landmarks

Whether the object has landmarks.

Type*bool*

height

The height of the image.

This is the height according to image semantics, and is thus the size of the **second to last** dimension.

Type *int*

landmarks
The landmarks object.

Type `LandmarkManager`

mask
Returns the pixels of the mask with no channel axis. This is what should be used to mask any k-dimensional image.

Type `(M, N, ..., L)`, *bool ndarray*

n_channels
The number of channels on each pixel in the image.

Type *int*

n_dims
The number of dimensions in the image. The minimum possible `n_dims` is 2.

Type *int*

n_elements
Total number of data points in the image `(prod(shape), n_channels)`

Type *int*

n_landmark_groups
The number of landmark groups on this object.

Type *int*

n_parameters
The length of the vector that this object produces.

Type *int*

n_pixels
Total number of pixels in the image `(prod(shape),)`

Type *int*

shape
The shape of the image (with `n_channel` values at each point).

Type *tuple*

width
The width of the image.

This is the width according to image semantics, and is thus the size of the **last** dimension.

Type *int*

MaskedImage

class `menpo.image.`**`MaskedImage`**(*image_data*, *mask=None*, *copy=True*)
Bases: `Image`

Represents an *n*-dimensional *k*-channel image, which has a mask. Images can be masked in order to identify a region of interest. All images implicitly have a mask that is defined as the the entire image. The mask is an instance of `BooleanImage`.

Parameters

- **image_data** (`(C, M, N ..., Q)` *ndarray*) – The pixel data for the image, where the first axis represents the number of channels.
- **mask** (`(M, N)` *bool ndarray* or `BooleanImage`, optional) – A binary array representing the mask. Must be the same shape as the image. Only one mask is supported for an image (so the mask is applied to every channel equally).
- **copy** (*bool*, optional) – If `False`, the `image_data` will not be copied on assignment. If a mask is provided, this also won't be copied. In general this should only be used if you know what you are doing.

Raises `ValueError` – Mask is not the same shape as the image

_view_2d(*figure_id=None*, *new_figure=False*, *channels=None*, *masked=True*, *interpolation='bilinear'*, *cmap_name=None*, *alpha=1.0*, *render_axes=False*, *axes_font_name='sans-serif'*, *axes_font_size=10*, *axes_font_style='normal'*, *axes_font_weight='normal'*, *axes_x_limits=None*, *axes_y_limits=None*, *axes_x_ticks=None*, *axes_y_ticks=None*, *figure_size=(7, 7)*)

View the image using the default image viewer. This method will appear on the Image as `view` if the Image is 2D.

Returns

- **figure_id** (*object*, optional) – The id of the figure to be used.
- **new_figure** (*bool*, optional) – If `True`, a new figure is created.
- **channels** (*int* or *list* of *int* or `all` or `None`) – If *int* or *list* of *int*, the specified channel(s) will be rendered. If `all`, all the channels will be rendered in subplots. If `None` and the image is RGB, it will be rendered in RGB mode. If `None` and the image is not RGB, it is equivalent to `all`.
- **masked** (*bool*, optional) – If `True`, only the masked pixels will be rendered.
- **interpolation** (*See Below, optional*) – The interpolation used to render the image. For example, if `bilinear`, the image will be smooth and if `nearest`, the image will be pixelated. Example options

```
{none, nearest, bilinear, bicubic, spline16, spline36,
hanning, hamming, hermite, kaiser, quadric, catrom, gaussian,
bessel, mitchell, sinc, lanczos}
```

- **cmap_name** (*str*, optional,) – If `None`, single channel and three channel images default to greyscale and rgb colormaps respectively.
- **alpha** (*float*, optional) – The alpha blending value, between 0 (transparent) and 1 (opaque).
- **render_axes** (*bool*, optional) – If `True`, the axes will be rendered.
- **axes_font_name** (*See Below, optional*) – The font of the axes. Example options

```
{serif, sans-serif, cursive, fantasy, monospace}
```

- **axes_font_size** (*int*, optional) – The font size of the axes.
- **axes_font_style** ({`normal`, `italic`, `oblique`}, optional) – The font style of the axes.
- **axes_font_weight** (*See Below, optional*) – The font weight of the axes. Example options

```
{ultralight, light, normal, regular, book, medium, roman,
semibold, demibold, demi, bold, heavy, extra bold, black}
```

- **axes_x_limits** (*float* or (*float*, *float*) or `None`, optional) – The limits of the x axis. If *float*, then it sets padding on the right and left of the Image as a percentage of the Image's width. If *tuple* or *list*, then it defines the axis limits. If `None`, then the limits are set automatically.
- **axes_y_limits** ((*float*, *float*) *tuple* or `None`, optional) – The limits of the y axis. If *float*, then it sets padding on the top and bottom of the Image as a percentage of the Image's height. If *tuple* or *list*, then it defines the axis limits. If `None`, then the limits are set automatically.
- **axes_x_ticks** (*list* or *tuple* or `None`, optional) – The ticks of the x axis.
- **axes_y_ticks** (*list* or *tuple* or `None`, optional) – The ticks of the y axis.
- **figure_size** ((*float*, *float*) *tuple* or `None`, optional) – The size of the figure in inches.

Raises `ValueError` – If Image is not 2D

_view_landmarks_2d(*channels=None*, *masked=True*, *group=None*, *with_labels=None*, *without_labels=None*, *figure_id=None*, *new_figure=False*, *interpolation='bilinear'*, *cmap_name=None*, *alpha=1.0*, *render_lines=True*, *line_colour=None*, *line_style='-'*, *line_width=1*, *render_markers=True*, *marker_style='o'*, *marker_size=5*, *marker_face_colour=None*, *marker_edge_colour=None*, *marker_edge_width=1.0*, *render_numbering=False*, *numbers_horizontal_align='center'*, *numbers_vertical_align='bottom'*, *numbers_font_name='sans-serif'*, *numbers_font_size=10*, *numbers_font_style='normal'*, *numbers_font_weight='normal'*, *numbers_font_colour='k'*, *render_legend=False*, *legend_title=''*, *legend_font_name='sans-serif'*, *legend_font_style='normal'*, *legend_font_size=10*, *legend_font_weight='normal'*, *legend_marker_scale=None*, *legend_location=2*, *legend_bbox_to_anchor=(1.05, 1.0)*, *legend_border_axes_pad=None*, *legend_n_columns=1*, *legend_horizontal_spacing=None*, *legend_vertical_spacing=None*, *legend_border=True*, *legend_border_padding=None*, *legend_shadow=False*, *legend_rounded_corners=False*, *render_axes=False*, *axes_font_name='sans-serif'*, *axes_font_size=10*, *axes_font_style='normal'*, *axes_font_weight='normal'*, *axes_x_limits=None*, *axes_y_limits=None*, *axes_x_ticks=None*, *axes_y_ticks=None*, *figure_size=(7, 7)*)

Visualize the landmarks. This method will appear on the Image as `view_landmarks` if the Image is 2D.

Parameters

- **channels** (*int* or *list* of *int* or `all` or `None`) – If *int* or *list* of *int*, the specified channel(s) will be rendered. If `all`, all the channels will be rendered in subplots. If `None` and the image is RGB, it will be rendered in RGB mode. If `None` and the image is not RGB, it is equivalent to `all`.
- **masked** (*bool*, optional) – If `True`, only the masked pixels will be rendered.
- **group** (*str* or''None'' optionals) – The landmark group to be visualized. If `None` and there are more than one landmark groups, an error is raised.
- **with_labels** (`None` or *str* or *list* of *str*, optional) – If not `None`, only show the given label(s). Should **not** be used with the `without_labels` kwarg.
- **without_labels** (`None` or *str* or *list* of *str*, optional) – If not `None`, show all except the given label(s). Should **not** be used with the `with_labels` kwarg.
- **figure_id** (*object*, optional) – The id of the figure to be used.

- **new_figure** (*bool*, optional) – If `True`, a new figure is created.
- **interpolation** (*See Below, optional*) – The interpolation used to render the image. For example, if `bilinear`, the image will be smooth and if `nearest`, the image will be pixelated. Example options

```
{none, nearest, bilinear, bicubic, spline16, spline36, hanning,
hamming, hermite, kaiser, quadric, catrom, gaussian, bessel,
mitchell, sinc, lanczos}
```

- **cmap_name** (*str*, optional,) – If `None`, single channel and three channel images default to greyscale and rgb colormaps respectively.
- **alpha** (*float*, optional) – The alpha blending value, between 0 (transparent) and 1 (opaque).
- **render_lines** (*bool*, optional) – If `True`, the edges will be rendered.
- **line_colour** (*See Below, optional*) – The colour of the lines. Example options:

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **line_style** (`{-, --, -., :}`, optional) – The style of the lines.
- **line_width** (*float*, optional) – The width of the lines.
- **render_markers** (*bool*, optional) – If `True`, the markers will be rendered.
- **marker_style** (*See Below, optional*) – The style of the markers. Example options

```
{., ,, o, v, ^, <, >, +, x, D, d, s, p, *, h, H, 1, 2, 3, 4, 8}
```

- **marker_size** (*int*, optional) – The size of the markers in points.
- **marker_face_colour** (*See Below, optional*) – The face (filling) colour of the markers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **marker_edge_colour** (*See Below, optional*) – The edge colour of the markers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **marker_edge_width** (*float*, optional) – The width of the markers' edge.
- **render_numbering** (*bool*, optional) – If `True`, the landmarks will be numbered.
- **numbers_horizontal_align** (`{center, right, left}`, optional) – The horizontal alignment of the numbers' texts.
- **numbers_vertical_align** (`{center, top, bottom, baseline}`, optional) – The vertical alignment of the numbers' texts.

- **numbers_font_name** (*See Below, optional*) – The font of the numbers. Example options

```
{serif, sans-serif, cursive, fantasy, monospace}
```

- **numbers_font_size** (*int*, optional) – The font size of the numbers.
- **numbers_font_style** ({normal, italic, oblique}, optional) – The font style of the numbers.
- **numbers_font_weight** (*See Below, optional*) – The font weight of the numbers. Example options

```
{ultralight, light, normal, regular, book, medium, roman,
semibold, demibold, demi, bold, heavy, extra bold, black}
```

- **numbers_font_colour** (*See Below, optional*) – The font colour of the numbers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **render_legend** (*bool*, optional) – If `True`, the legend will be rendered.
- **legend_title** (*str*, optional) – The title of the legend.
- **legend_font_name** (*See below, optional*) – The font of the legend. Example options

```
{serif, sans-serif, cursive, fantasy, monospace}
```

- **legend_font_style** ({normal, italic, oblique}, optional) – The font style of the legend.
- **legend_font_size** (*int*, optional) – The font size of the legend.
- **legend_font_weight** (*See Below, optional*) – The font weight of the legend. Example options

```
{ultralight, light, normal, regular, book, medium, roman,
semibold, demibold, demi, bold, heavy, extra bold, black}
```

- **legend_marker_scale** (*float*, optional) – The relative size of the legend markers with respect to the original
- **legend_location** (*int*, optional) – The location of the legend. The predefined values are:

'best'	0
'upper right'	1
'upper left'	2
'lower left'	3
'lower right'	4
'right'	5
'center left'	6
'center right'	7
'lower center'	8
'upper center'	9
'center'	10

- **legend_bbox_to_anchor** ((*float*, *float*) *tuple*, optional) – The bbox that the legend will be anchored.
- **legend_border_axes_pad** (*float*, optional) – The pad between the axes and legend border.
- **legend_n_columns** (*int*, optional) – The number of the legend's columns.
- **legend_horizontal_spacing** (*float*, optional) – The spacing between the columns.
- **legend_vertical_spacing** (*float*, optional) – The vertical space between the legend entries.
- **legend_border** (*bool*, optional) – If `True`, a frame will be drawn around the legend.
- **legend_border_padding** (*float*, optional) – The fractional whitespace inside the legend border.
- **legend_shadow** (*bool*, optional) – If `True`, a shadow will be drawn behind legend.
- **legend_rounded_corners** (*bool*, optional) – If `True`, the frame's corners will be rounded (fancybox).
- **render_axes** (*bool*, optional) – If `True`, the axes will be rendered.
- **axes_font_name** (*See Below, optional*) – The font of the axes. Example options

```
{serif, sans-serif, cursive, fantasy, monospace}
```

- **axes_font_size** (*int*, optional) – The font size of the axes.
- **axes_font_style** (`{normal, italic, oblique}`, optional) – The font style of the axes.
- **axes_font_weight** (*See Below, optional*) – The font weight of the axes. Example options

```
{ultralight, light, normal, regular, book, medium, roman,
semibold,demibold, demi, bold, heavy, extra bold, black}
```

- **axes_x_limits** (*float* or (*float*, *float*) or `None`, optional) – The limits of the x axis. If *float*, then it sets padding on the right and left of the Image as a percentage of the Image's width. If *tuple* or *list*, then it defines the axis limits. If `None`, then the limits are set automatically.
- **axes_y_limits** ((*float*, *float*) *tuple* or `None`, optional) – The limits of the y axis. If *float*, then it sets padding on the top and bottom of the Image as a percentage of the Image's height. If *tuple* or *list*, then it defines the axis limits. If `None`, then the limits are set automatically.
- **axes_x_ticks** (*list* or *tuple* or `None`, optional) – The ticks of the x axis.
- **axes_y_ticks** (*list* or *tuple* or `None`, optional) – The ticks of the y axis.
- **figure_size** ((*float*, *float*) *tuple* or `None` optional) – The size of the figure in inches.

Raises

- `ValueError` – If both `with_labels` and `without_labels` are passed.
- `ValueError` – If the landmark manager doesn't contain the provided group label.

as_PILImage(*out_dtype=<type 'numpy.uint8'>*)

Return a PIL copy of the image scaled and cast to the correct values for the provided `out_dtype`.

Image must only have 1 or 3 channels and be 2 dimensional. Non *uint8* floating point images must be in the range `[0, 1]` to be converted.

Parameters

out_dtype (*np.dtype*, optional) – The dtype the output array should be.

Returns

pil_image (*PILImage*) – PIL copy of image

Raises

- `ValueError` – If image is not 2D and has 1 channel or 3 channels.
- `ValueError` – If pixels data type is *float32* or *float64* and the pixel range is outside of `[0, 1]`
- `ValueError` – If the output dtype is unsupported. Currently uint8 is supported.

as_greyscale(*mode='luminosity'*, *channel=None*)

Returns a greyscale version of the image. If the image does *not* represent a 2D RGB image, then the `luminosity` mode will fail.

Parameters

- **mode** (`{average, luminosity, channel}`, optional) –

mode	Greyscale Algorithm
average	Equal average of all channels
luminosity	Calculates the luminance using the CCIR 601 formula:
	$Y' = 0.2989R' + 0.5870G' + 0.1140B'$
channel	A specific channel is chosen as the intensity value.

- **channel** (*int*, optional) – The channel to be taken. Only used if mode is `channel`.

Returns

greyscale_image (`MaskedImage`) – A copy of this image in greyscale.

as_histogram(*keep_channels=True*, *bins='unique'*)

Histogram binning of the values of this image.

Parameters

- **keep_channels** (*bool*, optional) – If set to `False`, it returns a single histogram for all the channels of the image. If set to `True`, it returns a *list* of histograms, one for each channel.
- **bins** (`{unique}`, positive *int* or sequence of scalars, optional) – If set equal to `'unique'`, the bins of the histograms are centred on the unique values of each channel. If set equal to a positive *int*, then this is the number of bins. If set equal to a sequence of scalars, these will be used as bins centres.

Returns

- **hist** (*ndarray* or *list* with `n_channels` *ndarrays* inside) – The histogram(s). If `keep_channels=False`, then hist is an *ndarray*. If `keep_channels=True`, then hist is a *list* with `len(hist)=n_channels`.

- **bin_edges** (*ndarray* or *list* with *n_channels ndarrays* inside) – An array or a list of arrays corresponding to the above histograms that store the bins' edges.

Raises `ValueError` – Bins can be either 'unique', positive int or a sequence of scalars.

Examples

Visualizing the histogram when a list of array bin edges is provided:

```
>>> hist, bin_edges = image.as_histogram()
>>> for k in range(len(hist)):
>>>     plt.subplot(1,len(hist),k)
>>>     width = 0.7 * (bin_edges[k][1] - bin_edges[k][0])
>>>     centre = (bin_edges[k][:-1] + bin_edges[k][1:]) / 2
>>>     plt.bar(centre, hist[k], align='center', width=width)
```

---

as_imageio(*out_dtype=<type 'numpy.uint8'>*)

Return an Imageio copy of the image scaled and cast to the correct values for the provided `out_dtype`.

Image must only have 1 or 3 channels and be 2 dimensional. Non *uint8* floating point images must be in the range `[0, 1]` to be converted.

Parameters **out_dtype** (*np.dtype*, optional) – The dtype the output array should be.

Returns **imageio_image** (*ndarray*) – Imageio image (which is just a numpy ndarray with the channels as the last axis).

Raises

- `ValueError` – If image is not 2D and has 1 channel or 3 channels.
- `ValueError` – If pixels data type is *float32* or *float64* and the pixel range is outside of `[0, 1]`
- `ValueError` – If the output dtype is unsupported. Currently uint8 and uint16 are supported.

as_masked(*mask=None*, *copy=True*)

Return a copy of this image with an attached mask behavior.

A custom mask may be provided, or `None`. See the `MaskedImage` constructor for details of how the kwargs will be handled.

Parameters

- **mask** (`(self.shape)` *ndarray* or `BooleanImage`) – A mask to attach to the newly generated masked image.
- **copy** (*bool*, optional) – If `False`, the produced `MaskedImage` will share pixels with `self`. Only suggested to be used for performance.

Returns **masked_image** (`MaskedImage`) – An image with the same pixels and landmarks as this one, but with a mask.

as_unmasked(*copy=True*, *fill=None*)

Return a copy of this image without the masking behavior.

By default the mask is simply discarded. However, there is an optional kwarg, `fill`, that can be set which will fill the **non-masked** areas with the given value.

Parameters

- **copy** (*bool*, optional) – If `False`, the produced *`Image`* will share pixels with `self`. Only suggested to be used for performance.
- **fill** (*float* or `(n_channels,)` iterable or `None`, optional) – If `None` the mask is simply discarded. If a scalar or iterable, the *unmasked* regions are filled with the given value.

Returnsimage (*`Image`*) – An image with the same pixels and landmarks as this one, but with no mask.

as_vector(***kwargs*)

Returns a flattened representation of the object as a single vector.

Returnsvector (*(N,) ndarray*) – The core representation of the object, flattened into a single vector. Note that this is always a view back on to the original object, but is not writable.

bounds()

The bounds of the image, minimum is always (0, 0). The maximum is the maximum **index** that can be used to index into the image for each dimension. Therefore, bounds will be of the form: ((0, 0), (self.height - 1, self.width - 1)) for a 2D image.

Note that this is akin to supporting a nearest neighbour interpolation. Although the *actual* maximum subpixel value would be something like `self.height - eps` where `eps` is some value arbitrarily close to 0, this value at least allows sampling without worrying about floating point error.

Type*tuple*

build_mask_around_landmarks(*patch_shape*, *group=None*)

Deprecated - please use the equivalent *constrain_mask_to_patches_around_landmarks* method.

centre()

The geometric centre of the Image - the subpixel that is in the middle.

Useful for aligning shapes and images.

Type(`n_dims`,) *ndarray*

clip_pixels(*minimum=None*, *maximum=None*)

A copy of this image with pixels linearly clipped to fit a range.

Parameters

- **minimum** (*float*, optional) – The minimal value of the clipped pixels. If None is provided, the default value will be 0.
- **maximum** (*float*, optional) – The maximal value of the clipped pixels. If None is provided, the default value will depend on the dtype.

Returnsrescaled_image (`type(self)`) – A copy of this image with pixels linearly rescaled to fit in the range provided.

constrain_landmarks_to_bounds()

Deprecated - please use the equivalent `constrain_to_bounds` method now on PointCloud, in conjunction with the new Image `bounds()` method. For example:

```
>>> im.constrain_landmarks_to_bounds()  # Equivalent to below
>>> im.landmarks['test'] = im.landmarks['test'].constrain_to_bounds(im.
↪bounds())
```

constrain_mask_to_landmarks(*group=None*, *batch_size=None*, *point_in_pointcloud='pwa'*)

Returns a copy of this image whereby the mask is restricted to be equal to the convex hull around the chosen landmarks.

The choice of whether a pixel is inside or outside of the pointcloud is determined by the `point_in_pointcloud` parameter. By default a Piecewise Affine transform is used to test for containment, which is useful when building efficiently aligning images. For large images, a faster and pixel-accurate method can be used ('convex_hull'). Alternatively, a callable can be provided to override the test. By default, the provided implementations are only valid for 2D images.

Parameters

- **group** (*str*, optional) – The key of the landmark set that should be used. If `None`, and if there is only one set of landmarks, this set will be used. If the landmarks in question are an instance of `TriMesh`, the triangulation of the landmarks will be used in the convex hull calculation. If the landmarks are an instance of `PointCloud`, Delaunay triangulation will be used to create a triangulation.
- **batch_size** (*int* or `None`, optional) – This should only be considered for large images. Setting this value will cause constraining to become much slower. This size indicates how many points in the image should be checked at a time, which keeps memory usage low. If `None`, no batching is used and all points are checked at once. By default, this is only used for the 'pwa' point_in_pointcloud choice.
- **point_in_pointcloud** ({'pwa', 'convex_hull'} or *callable*) – The method used to check if pixels in the image fall inside the pointcloud or not. Can be accurate to a Piecewise Affine transform, a pixel accurate convex hull or any arbitrary callable. If a callable is passed, it should take two parameters, the `PointCloud` to constrain with and the pixel locations ((d, n_dims) ndarray) to test and should return a (d, 1) boolean ndarray of whether the pixels were inside (True) or outside (False) of the `PointCloud`.

Returnsconstrained (`MaskedImage`) – A new image where the mask is constrained by the provided landmarks.

constrain_mask_to_patches_around_landmarks(*patch_shape*, *group=None*)

Returns a copy of this image whereby the mask is restricted to be patches around each landmark in the chosen landmark group. The patch will be centred on the nearest pixel for each point in the chosen landmark group.

Parameters

- **patch_shape** (*tuple*) – The size of the patch.
- **group** (*str*, optional) – The key of the landmark set that should be used. If `None`, and if there is only one set of landmarks, this set will be used.

Returnsconstrained (`MaskedImage`) – A new image where the mask is constrained as patches centred on each point in the provided landmarks.

constrain_points_to_bounds(*points*)

Constrains the points provided to be within the bounds of this image.

Parameterspoints (`(d,)` *ndarray*) – Points to be snapped to the image boundaries.

Returnsbounded_points (`(d,)` *ndarray*) – Points snapped to not stray outside the image edges.

copy()

Generate an efficient copy of this object.

Note that Numpy arrays and other `Copyable` objects on `self` will be deeply copied. Dictionaries and sets will be shallow copied, and everything else will be assigned (no copy will be made).

Classes that store state other than numpy arrays and immutable types should overwrite this method to ensure all state is copied.

Returns`type(self)` – A copy of this object

crop(*min_indices*, *max_indices*, *constrain_to_boundary=False*, *return_transform=False*)

Return a cropped copy of this image using the given minimum and maximum indices. Landmarks are correctly adjusted so they maintain their position relative to the newly cropped image.

Parameters

- **min_indices** (`(n_dims,)` *ndarray*) – The minimum index over each dimension.
- **max_indices** (`(n_dims,)` *ndarray*) – The maximum index over each dimension.
- **constrain_to_boundary** (*bool*, optional) – If `True` the crop will be snapped to not go beyond this images boundary. If `False`, an `ImageBoundaryError` will be raised if an attempt is made to go beyond the edge of the image.
- **return_transform** (*bool*, optional) – If `True`, then the `Transform` object that was used to perform the cropping is also returned.

Returns

- **cropped_image** (*type(self)*) – A new instance of self, but cropped.
- **transform** (`Transform`) – The transform that was used. It only applies if *return_transform* is `True`.

Raises

- `ValueError` – `min_indices` and `max_indices` both have to be of length `n_dims`. All `max_indices` must be greater than `min_indices`.
- `ImageBoundaryError` – Raised if `constrain_to_boundary=False`, and an attempt is made to crop the image in a way that violates the image bounds.

crop_to_landmarks(*group=None*, *boundary=0*, *constrain_to_boundary=True*, *return_transform=False*)

Return a copy of this image cropped so that it is bounded around a set of landmarks with an optional `n_pixel` boundary

Parameters

- **group** (*str*, optional) – The key of the landmark set that should be used. If `None` and if there is only one set of landmarks, this set will be used.
- **boundary** (*int*, optional) – An extra padding to be added all around the landmarks bounds.
- **constrain_to_boundary** (*bool*, optional) – If `True` the crop will be snapped to not go beyond this images boundary. If `False`, an :map'ImageBoundaryError' will be raised if an attempt is made to go beyond the edge of the image.
- **return_transform** (*bool*, optional) – If `True`, then the `Transform` object that was used to perform the cropping is also returned.

Returns

- **image** (`Image`) – A copy of this image cropped to its landmarks.
- **transform** (`Transform`) – The transform that was used. It only applies if *return_transform* is `True`.

Raises `ImageBoundaryError` – Raised if `constrain_to_boundary=False`, and an attempt is made to crop the image in a way that violates the image bounds.

crop_to_landmarks_proportion(*boundary_proportion*, *group=None*, *minimum=True*, *constrain_to_boundary=True*, *return_transform=False*)

Crop this image to be bounded around a set of landmarks with a border proportional to the landmark spread or range.

Parameters

- **boundary_proportion** (*float*) – Additional padding to be added all around the landmarks bounds defined as a proportion of the landmarks range. See the minimum parameter for a definition of how the range is calculated.
- **group** (*str*, optional) – The key of the landmark set that should be used. If `None` and if there is only one set of landmarks, this set will be used.
- **minimum** (*bool*, optional) – If `True` the specified proportion is relative to the minimum value of the landmarks' per-dimension range; if `False` w.r.t. the maximum value of the landmarks' per-dimension range.
- **constrain_to_boundary** (*bool*, optional) – If `True`, the crop will be snapped to not go beyond this images boundary. If `False`, an `ImageBoundaryError` will be raised if an attempt is made to go beyond the edge of the image.
- **return_transform** (*bool*, optional) – If `True`, then the `Transform` object that was used to perform the cropping is also returned.

Returns

- **image** (`Image`) – This image, cropped to its landmarks with a border proportional to the landmark spread or range.
- **transform** (`Transform`) – The transform that was used. It only applies if *return_transform* is `True`.

Raises `ImageBoundaryError` – Raised if `constrain_to_boundary=False`, and an attempt is made to crop the image in a way that violates the image bounds.

crop_to_pointcloud(*pointcloud*, *boundary=0*, *constrain_to_boundary=True*, *return_transform=False*)

Return a copy of this image cropped so that it is bounded around a pointcloud with an optional `n_pixel` boundary.

Parameters

- **pointcloud** (`PointCloud`) – The pointcloud to crop around.
- **boundary** (*int*, optional) – An extra padding to be added all around the landmarks bounds.
- **constrain_to_boundary** (*bool*, optional) – If `True` the crop will be snapped to not go beyond this images boundary. If `False`, an :map'ImageBoundaryError' will be raised if an attempt is made to go beyond the edge of the image.
- **return_transform** (*bool*, optional) – If `True`, then the `Transform` object that was used to perform the cropping is also returned.

Returns

- **image** (`Image`) – A copy of this image cropped to the bounds of the pointcloud.
- **transform** (`Transform`) – The transform that was used. It only applies if *return_transform* is `True`.

Raises `ImageBoundaryError` – Raised if `constrain_to_boundary=False`, and an attempt is made to crop the image in a way that violates the image bounds.

crop_to_pointcloud_proportion(*pointcloud*, *boundary_proportion*, *minimum=True*, *constrain_to_boundary=True*, *return_transform=False*)

Return a copy of this image cropped so that it is bounded around a pointcloud with an optional `n_pixel` boundary.

Parameters

- **pointcloud** (*PointCloud*) – The pointcloud to crop around.
- **boundary_proportion** (*float*) – Additional padding to be added all around the landmarks bounds defined as a proportion of the landmarks range. See the minimum parameter for a definition of how the range is calculated.
- **minimum** (*bool*, optional) – If `True` the specified proportion is relative to the minimum value of the pointclouds' per-dimension range; if `False` w.r.t. the maximum value of the pointclouds' per-dimension range.
- **constrain_to_boundary** (*bool*, optional) – If `True`, the crop will be snapped to not go beyond this images boundary. If `False`, an *ImageBoundaryError* will be raised if an attempt is made to go beyond the edge of the image.
- **return_transform** (*bool*, optional) – If `True`, then the *Transform* object that was used to perform the cropping is also returned.

Returns

- **image** (*Image*) – A copy of this image cropped to the border proportional to the pointcloud spread or range.
- **transform** (*Transform*) – The transform that was used. It only applies if *return_transform* is `True`.

Raises *ImageBoundaryError* – Raised if `constrain_to_boundary=False`, and an attempt is made to crop the image in a way that violates the image bounds.

crop_to_true_mask(*boundary=0*, *constrain_to_boundary=True*, *return_transform=False*)

Crop this image to be bounded just the *True* values of it's mask.

Parameters

- **boundary** (*int*, optional) – An extra padding to be added all around the true mask region.
- **constrain_to_boundary** (*bool*, optional) – If `True` the crop will be snapped to not go beyond this images boundary. If `False`, an *ImageBoundaryError* will be raised if an attempt is made to go beyond the edge of the image. Note that is only possible if `boundary != 0`.
- **return_transform** (*bool*, optional) – If `True`, then the *Transform* object that was used to perform the cropping is also returned.

Returns

- **cropped_image** (`type(self)`) – A copy of this image, cropped to the true mask.
- **transform** (*Transform*) – The transform that was used. It only applies if *return_transform* is `True`.

Raises *ImageBoundaryError* – Raised if 11constrain_to_boundary=False'1, and an attempt is made to crop the image in a way that violates the image bounds.

diagonal()

The diagonal size of this image

Type *float*

dilate(*n_pixels=1*)

Returns a copy of this `MaskedImage` in which its mask has been expanded by n pixels along its boundary.

Parameters **n_pixels** (*int*, optional) – The number of pixels by which we want to expand the mask along its own boundary.

Returns **dilated_image** (`MaskedImage`) – The copy of the masked image in which the mask has been expanded by n pixels along its boundary.

erode(*n_pixels=1*)

Returns a copy of this `MaskedImage` in which the mask has been shrunk by n pixels along its boundary.

Parameters **n_pixels** (*int*, optional) – The number of pixels by which we want to shrink the mask along its own boundary.

Returns **eroded_image** (`MaskedImage`) – The copy of the masked image in which the mask has been shrunk by n pixels along its boundary.

extract_channels(*channels*)

A copy of this image with only the specified channels.

Parameters **channels** (*int* or *[int]*) – The channel index or *list* of channel indices to retain.

Returns **image** (*type(self)*) – A copy of this image with only the channels requested.

extract_patches(*patch_centers*, *patch_shape=(16, 16)*, *sample_offsets=None*, *as_single_array=True*)

Extract a set of patches from an image. Given a set of patch centers and a patch size, patches are extracted from within the image, centred on the given coordinates. Sample offsets denote a set of offsets to extract from within a patch. This is very useful if you want to extract a dense set of features around a set of landmarks and simply sample the same grid of patches around the landmarks.

If sample offsets are used, to access the offsets for each patch you need to slice the resulting *list*. So for 2 offsets, the first centers offset patches would be `patches[:2]`.

Currently only 2D images are supported.

Parameters

- **patch_centers** (`PointCloud`) – The centers to extract patches around.
- **patch_shape** (`(1, n_dims)` *tuple* or *ndarray*, optional) – The size of the patch to extract
- **sample_offsets** (`(n_offsets, n_dims)` *ndarray* or `None`, optional) – The offsets to sample from within a patch. So `(0, 0)` is the centre of the patch (no offset) and `(1, 0)` would be sampling the patch from 1 pixel up the first axis away from the centre. If `None`, then no offsets are applied.
- **as_single_array** (*bool*, optional) – If `True`, an `(n_center, n_offset, n_channels, patch_shape)` *ndarray*, thus a single numpy array is returned containing each patch. If `False`, a *list* of `n_center * n_offset` `Image` objects is returned representing each patch.

Returns **patches** (*list* or *ndarray*) – Returns the extracted patches. Returns a list if `as_single_array=True` and an *ndarray* if `as_single_array=False`.

Raises `ValueError` – If image is not 2D

extract_patches_around_landmarks(*group=None*, *patch_shape=(16, 16)*, *sample_offsets=None*, *as_single_array=True*)

Extract patches around landmarks existing on this image. Provided the group label and optionally the landmark label extract a set of patches.

See *extract_patches* for more information.

Currently only 2D images are supported.

Parameters

- **group** (*str* or `None`, optional) – The landmark group to use as patch centres.
- **patch_shape** (*tuple* or *ndarray*, optional) – The size of the patch to extract
- **sample_offsets** (`(n_offsets, n_dims)` *ndarray* or `None`, optional) – The offsets to sample from within a patch. So `(0, 0)` is the centre of the patch (no offset) and `(1, 0)` would be sampling the patch from 1 pixel up the first axis away from the centre. If `None`, then no offsets are applied.
- **as_single_array** (*bool*, optional) – If `True`, an `(n_center, n_offset, n_channels, patch_shape)` *ndarray*, thus a single numpy array is returned containing each patch. If `False`, a *list* of `n_center * n_offset` *Image* objects is returned representing each patch.

Returnspatches (*list* or *ndarray*) – Returns the extracted patches. Returns a list if `as_single_array=True` and an *ndarray* if `as_single_array=False`.

Raises`ValueError` – If image is not 2D

from_vector(*vector*, *n_channels=None*)

Takes a flattened vector and returns a new image formed by reshaping the vector to the correct pixels and channels. Note that the only region of the image that will be filled is the masked region.

On masked images, the vector is always copied.

The `n_channels` argument is useful for when we want to add an extra channel to an image but maintain the shape. For example, when calculating the gradient.

Note that landmarks are transferred in the process.

Parameters

- **vector** (`(n_pixels,)`) – A flattened vector of all pixels and channels of an image.
- **n_channels** (*int*, optional) – If given, will assume that vector is the same shape as this image, but with a possibly different number of channels.

Returnsimage (*MaskedImage*) – New image of same shape as this image and the number of specified channels.

from_vector_inplace(*vector*)

Deprecated. Use the non-mutating API, *from_vector*.

For internal usage in performance-sensitive spots, see *_from_vector_inplace()*

Parametersvector (`(n_parameters,)` *ndarray*) – Flattened representation of this object

gaussian_pyramid(*n_levels=3*, *downscale=2*, *sigma=None*)

Return the gaussian pyramid of this image. The first image of the pyramid will be a copy of the original, unmodified, image, and counts as level 1.

Parameters

- **n_levels** (*int*, optional) – Total number of levels in the pyramid, including the original unmodified image
- **downscale** (*float*, optional) – Downscale factor.

- **sigma** (*float*, optional) – Sigma for gaussian filter. Default is `downscale / 3.` which corresponds to a filter mask twice the size of the scale factor that covers more than 99% of the gaussian distribution.

Yieldsimage_pyramid (*generator*) – Generator yielding pyramid layers as `Image` objects.

has_landmarks_outside_bounds()

Indicates whether there are landmarks located outside the image bounds.

Type*bool*

has_nan_values()

Tests if the vectorized form of the object contains `nan` values or not. This is particularly useful for objects with unknown values that have been mapped to `nan` values.

Returnshas_nan_values (*bool*) – If the vectorized object contains `nan` values.

indices()

Return the indices of all true pixels in this image.

Type `(n_dims, n_true_pixels)` *ndarray*

classmethod init_blank(*shape*, *n_channels=1*, *fill=0*, *dtype=<type 'float'>*, *mask=None*)

Generate a blank masked image

Parameters

- **shape** (*tuple* or *list*) – The shape of the image. Any floating point values are rounded up to the nearest integer.
- **n_channels** (*int*, optional) – The number of channels to create the image with.
- **fill** (*int*, optional) – The value to fill all pixels with.
- **dtype** (*numpy datatype*, optional) – The datatype of the image.
- **mask** (`(M, N)` *bool ndarray* or `BooleanImage`) – An optional mask that can be applied to the image. Has to have a shape equal to that of the image.

Notes

Subclasses of `MaskedImage` need to overwrite this method and explicitly call this superclass method

```
super(SubClass, cls).init_blank(shape,**kwargs)
```

in order to appropriately propagate the subclass type to `cls`.

Returnsblank_image (`MaskedImage`) – A new masked image of the requested size.

classmethod init_from_channels_at_back(*pixels*, *mask=None*)

Create an Image from a set of pixels where the channels axis is on the last axis (the back). This is common in other frameworks, and therefore this method provides a convenient means of creating a menpo Image from such data. Note that a copy is always created due to the need to rearrange the data.

Parameters

- **pixels** (`(M, N ..., Q, C)` *ndarray*) – Array representing the image pixels, with the last axis being channels.
- **mask** (`(M, N)` *bool ndarray* or `BooleanImage`, optional) – A binary array representing the mask. Must be the same shape as the image. Only one mask is supported for an image (so the mask is applied to every channel equally).

Returnsimage (*Image*) – A new image from the given pixels, with the FIRST axis as the channels.

classmethod init_from_pointcloud(*pointcloud*, *group=None*, *boundary=0*, *constrain_mask=True*, *n_channels=1*, *fill=0*, *dtype=<type 'float'>*)

Create an Image that is big enough to contain the given pointcloud. The pointcloud will be translated to the origin and then translated according to its bounds in order to fit inside the new image. An optional boundary can be provided in order to increase the space around the boundary of the pointcloud. The boundary will be added to *all sides of the image* and so a boundary of 5 provides 10 pixels of boundary total for each dimension.

By default, the mask will be constrained to the convex hull of the provided pointcloud.

Parameters

- **pointcloud** (*PointCloud*) – Pointcloud to place inside the newly created image.
- **group** (*str*, optional) – If `None`, the pointcloud will only be used to create the image. If a *str* then the pointcloud will be attached as a landmark group to the image, with the given string as key.
- **boundary** (*float*) – A optional padding distance that is added to the pointcloud bounds. Default is `0`, meaning the max/min of tightest possible containing image is returned.
- **n_channels** (*int*, optional) – The number of channels to create the image with.
- **fill** (*int*, optional) – The value to fill all pixels with.
- **dtype** (*numpy data type, optional*) – The data type of the image.
- **constrain_mask** (*bool*, optional) – If `True`, the mask will be constrained to the convex hull of the provided pointcloud. If `False`, the mask will be all `True`.

Returnsimage (*MaskedImage*) – A new image with the same size as the given pointcloud, optionally with the pointcloud attached as landmarks and the mask constrained to the convex hull of the pointcloud.

init_from_rolled_channels(*pixels*)

Deprecated - please use the equivalent `init_from_channels_at_back` method.

masked_pixels()

Get the pixels covered by the *True* values in the mask.

Type `(n_channels, mask.n_true)` *ndarray*

mirror(*axis=1*, *return_transform=False*)

Return a copy of this image, mirrored/flipped about a certain axis.

Parameters

- **axis** (*int*, optional) – The axis about which to mirror the image.
- **return_transform** (*bool*, optional) – If `True`, then the *Transform* object that was used to perform the mirroring is also returned.

Returns

- **mirrored_image** (`type(self)`) – The mirrored image.
- **transform** (*Transform*) – The transform that was used. It only applies if *return_transform* is `True`.

Raises

- `ValueError` – axis cannot be negative

- `ValueError` – axis={} but the image has {} dimensions

n_false_elements()

The number of `False` elements of the image over all the channels.

Type*int*

n_false_pixels()

The number of `False` values in the mask.

Type*int*

n_true_elements()

The number of `True` elements of the image over all the channels.

Type*int*

n_true_pixels()

The number of `True` values in the mask.

Type*int*

normalize_norm(*mode='all'*, *limit_to_mask=True*, ***kwargs*)

Returns a copy of this image normalized such that it's pixel values have zero mean and its norm equals 1.

Parameters

- **mode** (`{all, per_channel}`, optional) – If `all`, the normalization is over all channels. If `per_channel`, each channel individually is mean centred and normalized in variance.
- **limit_to_mask** (*bool*, optional) – If `True`, the normalization is only performed wrt the masked pixels. If `False`, the normalization is wrt all pixels, regardless of their masking value.

Returnsimage (`type(self)`) – A copy of this image, normalized.

normalize_std(*mode='all'*, *limit_to_mask=True*)

Returns a copy of this image normalized such that it's pixel values have zero mean and unit variance.

Parameters

- **mode** (`{all, per_channel}`, optional) – If `all`, the normalization is over all channels. If `per_channel`, each channel individually is mean centred and normalized in variance.
- **limit_to_mask** (*bool*, optional) – If `True`, the normalization is only performed wrt the masked pixels. If `False`, the normalization is wrt all pixels, regardless of their masking value.

Returnsimage (`type(self)`) – A copy of this image, normalized.

pixels_range()

The range of the pixel values (min and max pixel values).

Returnsmin_max (`(dtype, dtype)`) – The minimum and maximum value of the pixels array.

pixels_with_channels_at_back(*out_dtype=None*)

Returns the pixels matrix, with the channels rolled to the back axis. This may be required for interacting with external code bases that require images to have channels as the last axis, rather than the Menpo convention of channels as the first axis.

If this image is single channel, the final axis is dropped.

Parametersout_dtype (*np.dtype*, optional) – The dtype the output array should be.

Returnsrolled_channels (*ndarray*) – Pixels with channels as the back (last) axis. If single channel, the last axis will be dropped.

pyramid(*n_levels=3*, *downscale=2*)

Return a rescaled pyramid of this image. The first image of the pyramid will be a copy of the original, unmodified, image, and counts as level 1.

Parameters

- **n_levels** (*int*, optional) – Total number of levels in the pyramid, including the original unmodified image
- **downscale** (*float*, optional) – Downscale factor.

Yieldsimage_pyramid (*generator*) – Generator yielding pyramid layers as `Image` objects.

rasterize_landmarks(*group=None*, *render_lines=True*, *line_style='-'*, *line_colour='b'*, *line_width=1*, *render_markers=True*, *marker_style='o'*, *marker_size=1*, *marker_face_colour='b'*, *marker_edge_colour='b'*, *marker_edge_width=1*, *backend='matplotlib'*)

This method provides the ability to rasterize 2D landmarks onto the image. The returned image has the specified landmark groups rasterized onto the image - which is useful for things like creating result examples or rendering videos with annotations.

Since multiple landmark groups can be specified, all arguments can take lists of parameters that map to the provided groups list. Therefore, the parameters must be lists of the correct length or a single parameter to apply to every landmark group.

Multiple backends are provided, all with different strengths. The 'pillow' backend is very fast, but not very flexible. The *matplotlib* backend should be feature compatible with other Menpo rendering methods, but is much slower due to the overhead of creating a figure to render into.

Images will always be rendered masked with a black background. If an unmasked image is required, please use `as_unmasked()`.

Parameters

- **group** (*str* or *list* of *str*, optional) – The landmark group key, or a list of keys.
- **render_lines** (*bool*, optional) – If `True`, and the provided landmark group is a `PointDirectedGraph`, the edges are rendered.
- **line_style** (*str*, optional) – The style of the edge line. Not all backends support this argument.
- **line_colour** (*str* or *tuple*, optional) – A Matplotlib style colour or a backend dependant colour.
- **line_width** (*int*, optional) – The width of the line to rasterize.
- **render_markers** (*bool*, optional) – If `True`, render markers at the coordinates of each landmark.
- **marker_style** (*str*, optional) – A Matplotlib marker style. Not all backends support all marker styles.
- **marker_size** (*int*, optional) – The size of the marker - different backends use different scale spaces so consistent output may by difficult.
- **marker_face_colour** (*str*, optional) – A Matplotlib style colour or a backend dependant colour.

- **marker_edge_colour** (*str*, optional) – A Matplotlib style colour or a backend dependant colour.
- **marker_edge_width** (*int*, optional) – The width of the marker edge. Not all backends support this.
- **backend** (*{'matplotlib', 'pillow'}, optional*) – The backend to use.

Returnsrasterized_image (*Image*) – The image with the landmarks rasterized directly into the pixels.

Raises

- `ValueError` – Only 2D images are supported.
- `ValueError` – Only RGB (3-channel) or Greyscale (1-channel) images are supported.

rescale(*scale*, *round='ceil'*, *order=1*, *return_transform=False*)

Return a copy of this image, rescaled by a given factor. Landmarks are rescaled appropriately.

Parameters

- **scale** (*float* or *tuple* of *floats*) – The scale factor. If a tuple, the scale to apply to each dimension. If a single *float*, the scale will be applied uniformly across each dimension.
- **round** (`{ceil, floor, round}`, optional) – Rounding function to be applied to floating point shapes.
- **order** (*int*, optional) – The order of interpolation. The order has to be in the range [0,5]

Order	Interpolation
0	Nearest-neighbor
1	Bi-linear *(default)*
2	Bi-quadratic
3	Bi-cubic
4	Bi-quartic
5	Bi-quintic

- **return_transform** (*bool*, optional) – If `True`, then the *Transform* object that was used to perform the rescale is also returned.

Returns

- **rescaled_image** (`type(self)`) – A copy of this image, rescaled.
- **transform** (*Transform*) – The transform that was used. It only applies if *return_transform* is `True`.

RaisesValueError: – If less scales than dimensions are provided. If any scale is less than or equal to 0.

rescale_landmarks_to_diagonal_range(*diagonal_range*, *group=None*, *round='ceil'*, *order=1*, *return_transform=False*)

Return a copy of this image, rescaled so that the `diagonal_range` of the bounding box containing its landmarks matches the specified `diagonal_range` range.

Parameters

- **diagonal_range** (`(n_dims,)` *ndarray*) – The diagonal_range range that we want the landmarks of the returned image to have.
- **group** (*str*, optional) – The key of the landmark set that should be used. If `None` and if there is only one set of landmarks, this set will be used.

- **round** ({ceil, floor, round}, optional) – Rounding function to be applied to floating point shapes.
- **order** (*int*, optional) – The order of interpolation. The order has to be in the range [0,5]

Order	Interpolation
0	Nearest-neighbor
1	Bi-linear *(default)*
2	Bi-quadratic
3	Bi-cubic
4	Bi-quartic
5	Bi-quintic

- **return_transform** (*bool*, optional) – If True, then the *Transform* object that was used to perform the rescale is also returned.

Returns

- **rescaled_image** (type(self)) – A copy of this image, rescaled.
- **transform** (*Transform*) – The transform that was used. It only applies if *return_transform* is True.

rescale_pixels (*minimum*, *maximum*, *per_channel=True*)

A copy of this image with pixels linearly rescaled to fit a range.

Note that the only pixels that will be considered and rescaled are those that feature in the vectorized form of this image. If you want to use this routine on all the pixels in a *MaskedImage*, consider using *as_unmasked()* prior to this call.

Parameters

- **minimum** (*float*) – The minimal value of the rescaled pixels
- **maximum** (*float*) – The maximal value of the rescaled pixels
- **per_channel** (*boolean*, optional) – If True, each channel will be rescaled independently. If False, the scaling will be over all channels.

Returnsrescaled_image (type(self)) – A copy of this image with pixels linearly rescaled to fit in the range provided.

rescale_to_diagonal (*diagonal*, *round='ceil'*, *return_transform=False*)

Return a copy of this image, rescaled so that the it's diagonal is a new size.

Parameters

- **diagonal** (*int*) – The diagonal size of the new image.
- **round** ({ceil, floor, round}, optional) – Rounding function to be applied to floating point shapes.
- **return_transform** (*bool*, optional) – If True, then the *Transform* object that was used to perform the rescale is also returned.

Returns

- **rescaled_image** (*type(self)*) – A copy of this image, rescaled.
- **transform** (*Transform*) – The transform that was used. It only applies if *return_transform* is True.

rescale_to_pointcloud(*pointcloud*, *group=None*, *round='ceil'*, *order=1*, *return_transform=False*)

Return a copy of this image, rescaled so that the scale of a particular group of landmarks matches the scale of the passed reference pointcloud.

Parameters

- **pointcloud** (*PointCloud*) – The reference pointcloud to which the landmarks specified by `group` will be scaled to match.
- **group** (*str*, optional) – The key of the landmark set that should be used. If `None`, and if there is only one set of landmarks, this set will be used.
- **round** (`{ceil, floor, round}`, optional) – Rounding function to be applied to floating point shapes.
- **order** (*int*, optional) – The order of interpolation. The order has to be in the range [0,5]

Order	Interpolation
0	Nearest-neighbor
1	Bi-linear *(default)*
2	Bi-quadratic
3	Bi-cubic
4	Bi-quartic
5	Bi-quintic

- **return_transform** (*bool*, optional) – If `True`, then the *Transform* object that was used to perform the rescale is also returned.

Returns

- **rescaled_image** (`type(self)`) – A copy of this image, rescaled.
- **transform** (*Transform*) – The transform that was used. It only applies if *return_transform* is `True`.

resize(*shape*, *order=1*, *return_transform=False*)

Return a copy of this image, resized to a particular shape. All image information (landmarks, and mask in the case of *MaskedImage*) is resized appropriately.

Parameters

- **shape** (*tuple*) – The new shape to resize to.
- **order** (*int*, optional) – The order of interpolation. The order has to be in the range [0,5]

Order	Interpolation
0	Nearest-neighbor
1	Bi-linear *(default)*
2	Bi-quadratic
3	Bi-cubic
4	Bi-quartic
5	Bi-quintic

- **return_transform** (*bool*, optional) – If `True`, then the *Transform* object that was used to perform the resize is also returned.

Returns

- **resized_image** (`type(self)`) – A copy of this image, resized.
- **transform** (*Transform*) – The transform that was used. It only applies if *return_transform* is `True`.

Raises ValueError: – If the number of dimensions of the new shape does not match the number of dimensions of the image.

rolled_channels()

Deprecated - please use the equivalent `pixels_with_channels_at_back` method.

rotate_ccw_about_centre(*theta*, *degrees=True*, *retain_shape=False*, *cval=0.0*, *round='round'*, *order=1*, *return_transform=False*)

Return a copy of this image, rotated counter-clockwise about its centre.

Note that the *retain_shape* argument defines the shape of the rotated image. If `retain_shape=True`, then the shape of the rotated image will be the same as the one of current image, so some regions will probably be cropped. If `retain_shape=False`, then the returned image has the correct size so that the whole area of the current image is included.

Parameters

- **theta** (*float*) – The angle of rotation about the centre.
- **degrees** (*bool*, optional) – If `True`, *theta* is interpreted in degrees. If `False`, `theta` is interpreted as radians.
- **retain_shape** (*bool*, optional) – If `True`, then the shape of the rotated image will be the same as the one of current image, so some regions will probably be cropped. If `False`, then the returned image has the correct size so that the whole area of the current image is included.
- **cval** (*float*, optional) – The value to be set outside the rotated image boundaries.
- **round** (`{'ceil', 'floor', 'round'}`, optional) – Rounding function to be applied to floating point shapes. This is only used in case `retain_shape=True`.
- **order** (*int*, optional) – The order of interpolation. The order has to be in the range `[0, 5]`. This is only used in case `retain_shape=True`.

Order	Interpolation
0	Nearest-neighbor
1	Bi-linear *(default)*
2	Bi-quadratic
3	Bi-cubic
4	Bi-quartic
5	Bi-quintic

- **return_transform** (*bool*, optional) – If `True`, then the `Transform` object that was used to perform the rotation is also returned.

Returns

- **rotated_image** (`type(self)`) – The rotated image.
- **transform** (`Transform`) – The transform that was used. It only applies if *return_transform* is `True`.

Raises `ValueError` – Image rotation is presently only supported on 2D images

sample(*points_to_sample*, *order=1*, *mode='constant'*, *cval=0.0*)

Sample this image at the given sub-pixel accurate points. The input PointCloud should have the same number of dimensions as the image e.g. a 2D PointCloud for a 2D multi-channel image. A numpy array will be returned the has the values for every given point across each channel of the image.

If the points to sample are *outside* of the mask (fall on a `False` value in the mask), an exception is raised. This exception contains the information of which points were outside of the mask (`False`) and *also* returns the sampled points.

Parameters

- **points_to_sample** (*PointCloud*) – Array of points to sample from the image. Should be *(n_points, n_dims)*
- **order** (*int*, optional) – The order of interpolation. The order has to be in the range [0,5]. See warp_to_shape for more information.
- **mode** (`{constant, nearest, reflect, wrap}`, optional) – Points outside the boundaries of the input are filled according to the given mode.
- **cval** (*float*, optional) – Used in conjunction with mode `constant`, the value outside the image boundaries.

Returnssampled_pixels ((*n_points*, *n_channels*) *ndarray*) – The interpolated values taken across every channel of the image.

Raises*OutOfMaskSampleError* – One of the points to sample was outside of the valid area of the mask (`False` in the mask). This exception contains both the mask of valid sample points, **as well as** the sampled points themselves, in case you want to ignore the error.

set_boundary_pixels(*value=0.0*, *n_pixels=1*)

Returns a copy of this *MaskedImage* for which n pixels along the its mask boundary have been set to a particular value. This is useful in situations where there is absent data in the image which can cause, for example, erroneous computations of gradient or features.

Parameters

- **value** (*float* or (n_channels, 1) ndarray) –
- **n_pixels** (*int*, optional) – The number of pixels along the mask boundary that will be set to 0.

Returnsnew_image (*MaskedImage*) – The copy of the image for which the `n` pixels along its mask boundary have been set to a particular value.

set_masked_pixels(*pixels*, *copy=True*)

Deprecated - please use the equivalent `from_vector`

set_patches(*patches*, *patch_centers*, *offset=None*, *offset_index=None*)

Set the values of a group of patches into the correct regions of a copy of this image. Given an array of patches and a set of patch centers, the patches' values are copied in the regions of the image that are centred on the coordinates of the given centers.

The patches argument can have any of the two formats that are returned from the *extract_patches()* and *extract_patches_around_landmarks()* methods. Specifically it can be:

1. `(n_center, n_offset, self.n_channels, patch_shape)` *ndarray*
2. *list* of `n_center * n_offset` *Image* objects

Currently only 2D images are supported.

Parameters

- **patches** (*ndarray* or *list*) – The values of the patches. It can have any of the two formats that are returned from the *extract_patches()* and *extract_patches_around_landmarks()* methods. Specifically, it can either be an `(n_center, n_offset, self.n_channels, patch_shape)` *ndarray* or a *list* of `n_center * n_offset` *Image* objects.
- **patch_centers** (*PointCloud*) – The centers to set the patches around.

- **offset** (*list* or *tuple* or `(1, 2)` *ndarray* or `None`, optional) – The offset to apply on the patch centers within the image. If `None`, then `(0, 0)` is used.
- **offset_index** (*int* or `None`, optional) – The offset index within the provided *patches* argument, thus the index of the second dimension from which to sample. If `None`, then `0` is used.

Raises

- `ValueError` – If image is not 2D
- `ValueError` – If offset does not have shape (1, 2)

set_patches_around_landmarks(*patches*, *group=None*, *offset=None*, *offset_index=None*)

Set the values of a group of patches around the landmarks existing in a copy of this image. Given an array of patches, a group and a label, the patches' values are copied in the regions of the image that are centred on the coordinates of corresponding landmarks.

The patches argument can have any of the two formats that are returned from the *extract_patches()* and *extract_patches_around_landmarks()* methods. Specifically it can be:

1. `(n_center, n_offset, self.n_channels, patch_shape)` *ndarray*
2. *list* of `n_center * n_offset` *Image* objects

Currently only 2D images are supported.

Parameters

- **patches** (*ndarray* or *list*) – The values of the patches. It can have any of the two formats that are returned from the *extract_patches()* and *extract_patches_around_landmarks()* methods. Specifically, it can either be an `(n_center, n_offset, self.n_channels, patch_shape)` *ndarray* or a *list* of `n_center * n_offset` *Image* objects.
- **group** (*str* or `None` optional) – The landmark group to use as patch centres.
- **offset** (*list* or *tuple* or `(1, 2)` *ndarray* or `None`, optional) – The offset to apply on the patch centers within the image. If `None`, then `(0, 0)` is used.
- **offset_index** (*int* or `None`, optional) – The offset index within the provided *patches* argument, thus the index of the second dimension from which to sample. If `None`, then `0` is used.

Raises

- `ValueError` – If image is not 2D
- `ValueError` – If offset does not have shape (1, 2)

transform_about_centre(*transform*, *retain_shape=False*, *cval=0.0*, *round='round'*, *order=1*, *return_transform=False*)

Return a copy of this image, transformed about its centre.

Note that the *retain_shape* argument defines the shape of the transformed image. If `retain_shape=True`, then the shape of the transformed image will be the same as the one of current image, so some regions will probably be cropped. If `retain_shape=False`, then the returned image has the correct size so that the whole area of the current image is included.

Note: This method will not work for transforms that result in a transform chain as *TransformChain* is not invertible.

Note: Be careful when defining transforms for warping imgaes. All pixel locations must fall within a valid range as expected by the transform. Therefore, your transformation must accept 'negative' pixel locations as the pixel locations provided to your transform will have the object centre subtracted from them.

Parameters

- **transform** (*ComposableTransform* and *VInvertible* type) – A composable transform. `pseudoinverse` will be invoked on the resulting transform so it must implement a valid inverse.
- **retain_shape** (*bool*, optional) – If `True`, then the shape of the sheared image will be the same as the one of current image, so some regions will probably be cropped. If `False`, then the returned image has the correct size so that the whole area of the current image is included.
- **cval** (*float*, optional) – The value to be set outside the sheared image boundaries.
- **round** (`{'ceil', 'floor', 'round'}`, optional) – Rounding function to be applied to floating point shapes. This is only used in case `retain_shape=True`.
- **order** (*int*, optional) – The order of interpolation. The order has to be in the range `[0, 5]`. This is only used in case `retain_shape=True`.

Order	Interpolation
0	Nearest-neighbor
1	Bi-linear *(default)*
2	Bi-quadratic
3	Bi-cubic
4	Bi-quartic
5	Bi-quintic

- **return_transform** (*bool*, optional) – If `True`, then the *Transform* object that was used to perform the shearing is also returned.

Returns

- **transformed_image** (`type(self)`) – The transformed image.
- **transform** (*Transform*) – The transform that was used. It only applies if *return_transform* is `True`.

Examples

This is an example for rotating an image about its center. Let's first load an image, create the rotation transform and then apply it

```
import matplotlib.pyplot as plt
import menpo.io as mio
from menpo.transform import Rotation

# Load image
im = mio.import_builtin_asset.lenna_png()

# Create shearing transform
rot_tr = Rotation.init_from_2d_ccw_angle(45)
```

```
# Render original image
plt.subplot(131)
im.view_landmarks()
plt.title('Original')

# Render rotated image
plt.subplot(132)
im.transform_about_centre(rot_tr).view_landmarks()
plt.title('Rotated')

# Render rotated image that has shape equal as original image
plt.subplot(133)
im.transform_about_centre(rot_tr, retain_shape=True).view_landmarks()
plt.title('Rotated (Retain original shape)')
```

Similarly, in order to apply a shear transform

```
import matplotlib.pyplot as plt
import menpo.io as mio
from menpo.transform import Affine

# Load image
im = mio.import_builtin_asset.lenna_png()

# Create shearing transform
shear_tr = Affine.init_from_2d_shear(25, 10)

# Render original image
plt.subplot(131)
im.view_landmarks()
plt.title('Original')

# Render sheared image
plt.subplot(132)
im.transform_about_centre(shear_tr).view_landmarks()
plt.title('Sheared')

# Render sheared image that has shape equal as original image
plt.subplot(133)
im.transform_about_centre(shear_tr,
                          retain_shape=True).view_landmarks()
plt.title('Sheared (Retain original shape)')
```

view_widget (*figure_size=(7, 7)*)

Visualizes the image using an interactive widget.

Parameters **figure_size** ((*int*, *int*), optional) – The initial size of the rendered figure.

warp_to_mask (*template_mask*, *transform*, *warp_landmarks=False*, *order=1*, *mode='constant'*, *cval=0.0*, *batch_size=None*, *return_transform=False*)

Warps this image into a different reference space.

Parameters

- **template_mask** (*BooleanImage*) – Defines the shape of the result, and what pixels should be sampled.
- **transform** (*Transform*) – Transform **from the template space back to this image**.

Defines, for each pixel location on the template, which pixel location should be sampled from on this image.

- **warp_landmarks** (*bool*, optional) – If `True`, result will have the same landmark dictionary as `self`, but with each landmark updated to the warped position.
- **order** (*int*, optional) – The order of interpolation. The order has to be in the range [0,5]

Order	Interpolation
0	Nearest-neighbor
1	Bi-linear *(default)*
2	Bi-quadratic
3	Bi-cubic
4	Bi-quartic
5	Bi-quintic

- **mode** (`{constant, nearest, reflect, wrap}`, optional) – Points outside the boundaries of the input are filled according to the given mode.
- **cval** (*float*, optional) – Used in conjunction with mode `constant`, the value outside the image boundaries.
- **batch_size** (*int* or `None`, optional) – This should only be considered for large images. Setting this value can cause warping to become much slower, particular for cached warps such as Piecewise Affine. This size indicates how many points in the image should be warped at a time, which keeps memory usage low. If `None`, no batching is used and all points are warped at once.
- **return_transform** (*bool*, optional) – This argument is for internal use only. If `True`, then the `Transform` object is also returned.

Returns

- **warped_image** (`type(self)`) – A copy of this image, warped.
- **transform** (`Transform`) – The transform that was used. It only applies if *return_transform* is `True`.

warp_to_shape(*template_shape*, *transform*, *warp_landmarks=False*, *order=1*, *mode='constant'*, *cval=0.0*, *batch_size=None*, *return_transform=False*)

Return a copy of this `MaskedImage` warped into a different reference space.

Parameters

- **template_shape** (*tuple* or *ndarray*) – Defines the shape of the result, and what pixel indices should be sampled (all of them).
- **transform** (`Transform`) – Transform **from the template_shape space back to this image**. Defines, for each index on template_shape, which pixel location should be sampled from on this image.
- **warp_landmarks** (*bool*, optional) – If `True`, result will have the same landmark dictionary as self, but with each landmark updated to the warped position.
- **order** (*int*, optional) – The order of interpolation. The order has to be in the range [0,5]

Order	Interpolation
0	Nearest-neighbor
1	Bi-linear *(default)*
2	Bi-quadratic
3	Bi-cubic
4	Bi-quartic
5	Bi-quintic

- **mode** (`{constant, nearest, reflect, wrap}`, optional) – Points outside the boundaries of the input are filled according to the given mode.
- **cval** (*float*, optional) – Used in conjunction with mode `constant`, the value outside the image boundaries.
- **batch_size** (*int* or `None`, optional) – This should only be considered for large images. Setting this value can cause warping to become much slower, particular for cached warps such as Piecewise Affine. This size indicates how many points in the image should be warped at a time, which keeps memory usage low. If `None`, no batching is used and all points are warped at once.
- **return_transform** (*bool*, optional) – This argument is for internal use only. If `True`, then the `Transform` object is also returned.

Returns

- **warped_image** (`MaskedImage`) – A copy of this image, warped.
- **transform** (`Transform`) – The transform that was used. It only applies if *return_transform* is `True`.

zoom(*scale*, *cval=0.0*, *return_transform=False*)

Return a copy of this image, zoomed about the centre point. `scale` values greater than 1.0 denote zooming **in** to the image and values less than 1.0 denote zooming **out** of the image. The size of the image will not change, if you wish to scale an image, please see `rescale()`.

Parameters

- **scale** (*float*) – `scale > 1.0` denotes zooming in. Thus the image will appear larger and areas at the edge of the zoom will be 'cropped' out. `scale < 1.0` denotes zooming out. The image will be padded by the value of `cval`.
- **cval** (`float`, optional) – The value to be set outside the zoomed image boundaries.
- **return_transform** (*bool*, optional) – If `True`, then the `Transform` object that was used to perform the zooming is also returned.

Returns

- **zoomed_image** (`type(self)`) – A copy of this image, zoomed.
- **transform** (`Transform`) – The transform that was used. It only applies if *return_transform* is `True`.

has_landmarks

Whether the object has landmarks.

Type *bool*

height

The height of the image.

This is the height according to image semantics, and is thus the size of the **second to last** dimension.

Type *int*

landmarks
The landmarks object.

Type *LandmarkManager*

n_channels
The number of channels on each pixel in the image.

Type *int*

n_dims
The number of dimensions in the image. The minimum possible `n_dims` is 2.

Type *int*

n_elements
Total number of data points in the image `(prod(shape), n_channels)`

Type *int*

n_landmark_groups
The number of landmark groups on this object.

Type *int*

n_parameters
The length of the vector that this object produces.

Type *int*

n_pixels
Total number of pixels in the image `(prod(shape),)`

Type *int*

shape
The shape of the image (with `n_channel` values at each point).

Type *tuple*

width
The width of the image.

This is the width according to image semantics, and is thus the size of the **last** dimension.

Type *int*

Exceptions

ImageBoundaryError

class `menpo.image.`**`ImageBoundaryError`**(*requested_min*, *requested_max*, *snapped_min*, *snapped_max*)

Bases: `ValueError`

Exception that is thrown when an attempt is made to crop an image beyond the edge of it's boundary.

Parameters

- **requested_min** (`(d,)` *ndarray*) – The per-dimension minimum index requested for the crop
- **requested_max** (`(d,)` *ndarray*) – The per-dimension maximum index requested for the crop

- **snapped_min** ((d,) *ndarray*) – The per-dimension minimum index that could be used if the crop was constrained to the image boundaries.
- **requested_max** – The per-dimension maximum index that could be used if the crop was constrained to the image boundaries.

OutOfMaskSampleError

class menpo.image.**OutOfMaskSampleError**(*sampled_mask*, *sampled_values*)

Bases: ValueError

Exception that is thrown when an attempt is made to sample an MaskedImage in an area that is masked out (where the mask is False).

Parameters

- **sampled_mask** (*bool ndarray*) – The sampled mask, True where the image's mask was True and False otherwise. Useful for masking out the sampling array.
- **sampled_values** (*ndarray*) – The sampled values, no attempt at masking is made.

menpo.feature

Features

no_op

menpo.feature.**no_op**(*image*, **args*, ***kwargs*)

A no operation feature - does nothing but return a copy of the pixels passed in.

Parameters **pixels** (*Image* or subclass or (C, X, Y, ..., Z) *ndarray*) – Either the image object itself or an array with the pixels. The first dimension is interpreted as channels. This means an N-dimensional image is represented by an N+1 dimensional array.

Returns **pixels** (*Image* or subclass or (X, Y, ..., Z, C) *ndarray*) – A copy of the image that was passed in.

gradient

menpo.feature.**gradient**(*image*, **args*, ***kwargs*)

Calculates the gradient of an input image. The image is assumed to have channel information on the first axis. In the case of multiple channels, it returns the gradient over each axis over each channel as the first axis.

The gradient is computed using second order accurate central differences in the interior and first order accurate one-side (forward or backwards) differences at the boundaries.

Parameters **pixels** (*Image* or subclass or (C, X, Y, ..., Z) *ndarray*) – Either the image object itself or an array where the first dimension is interpreted as channels. This means an N-dimensional image is represented by an N+1 dimensional array. If the image is 2-dimensional the pixels should be of type float/double (int is not supported).

Returns **gradient** (*ndarray*) – The gradient over each axis over each channel. Therefore, the first axis of the gradient of a 2D, single channel image, will have length *2*. The first axis of the gradient of a 2D, 3-channel image, will have length *6*, the ordering being I[:, 0, 0] = [R0_y, G0_y, B0_y, R0_x, G0_x, B0_x]. To be clear, all the y-gradients are returned over each channel, then all the x-gradients.

gaussian_filter

`menpo.feature.gaussian_filter`(*image*, **args*, ***kwargs*)

Calculates the convolution of the input image with a multidimensional Gaussian filter.

Parameters

- **pixels** (*Image* or subclass or `(C, X, Y, ..., Z)` *ndarray*) – Either the image object itself or an array with the pixels. The first dimension is interpreted as channels. This means an N-dimensional image is represented by an N+1 dimensional array.
- **sigma** (*float* or *list* of *float*) – The standard deviation for Gaussian kernel. The standard deviations of the Gaussian filter are given for each axis as a *list*, or as a single *float*, in which case it is equal for all axes.

Returnsoutput_image (*Image* or subclass or `(X, Y, ..., Z, C)` *ndarray*) – The filtered image has the same type and size as the input `pixels`.

igo

`menpo.feature.igo`(*image*, **args*, ***kwargs*)

Extracts Image Gradient Orientation (IGO) features from the input image. The output image has `N * C` number of channels, where `N` is the number of channels of the original image and `C = 2` or `C = 4` depending on whether double angles are used.

Parameters

- **pixels** (*Image* or subclass or `(C, X, Y, ..., Z)` *ndarray*) – Either the image object itself or an array with the pixels. The first dimension is interpreted as channels. This means an N-dimensional image is represented by an N+1 dimensional array.
- **double_angles** (*bool*, optional) – Assume that `phi` represents the gradient orientations.

  If this flag is `False`, the features image is the concatenation of `cos(phi)` and `sin(phi)`, thus 2 channels.

  If `True`, the features image is the concatenation of `cos(phi)`, `sin(phi)`, `cos(2 * phi)`, `sin(2 * phi)`, thus 4 channels.
- **verbose** (*bool*, optional) – Flag to print IGO related information.

Returnsigo (*Image* or subclass or `(X, Y, ..., Z, C)` *ndarray*) – The IGO features image. It has the same type and shape as the input `pixels`. The output number of channels depends on the `double_angles` flag.

Raises`ValueError` – Image has to be 2D in order to extract IGOs.

References

es

`menpo.feature.es`(*image*, **args*, ***kwargs*)

Extracts Edge Structure (ES) features from the input image. The output image has `N * C` number of channels, where `N` is the number of channels of the original image and `C = 2`.

Parameters

- **pixels** (*Image* or subclass or `(C, X, Y, ..., Z)` *ndarray*) – Either an image object itself or an array where the first axis represents the number of channels. This means an N-dimensional image is represented by an N+1 dimensional array.
- **verbose** (*bool*, optional) – Flag to print ES related information.

Returns (*Image* or subclass or `(X, Y, ..., Z, C)` *ndarray*) – The ES features image. It has the same type and shape as the input `pixels`. The output number of channels is `C = 2`.

Raises `ValueError` – Image has to be 2D in order to extract ES features.

References

lbp

`menpo.feature.lbp`(*image*, **args*, ***kwargs*)

Extracts Local Binary Pattern (LBP) features from the input image. The output image has `N * C` number of channels, where `N` is the number of channels of the original image and `C` is the number of radius/samples values combinations that are used in the LBP computation.

Parameters

- **pixels** (*Image* or subclass or `(C, X, Y, ..., Z)` *ndarray*) – Either the image object itself or an array with the pixels. The first dimension is interpreted as channels. This means an N-dimensional image is represented by an N+1 dimensional array.
- **radius** (*int* or *list* of *int* or `None`, optional) – It defines the radius of the circle (or circles) at which the sampling points will be extracted. The radius (or radii) values must be greater than zero. There must be a radius value for each samples value, thus they both need to have the same length. If `None`, then `[1, 2, 3, 4]` is used.
- **samples** (*int* or *list* of *int* or `None`, optional) – It defines the number of sampling points that will be extracted at each circle. The samples value (or values) must be greater than zero. There must be a samples value for each radius value, thus they both need to have the same length. If `None`, then `[8, 8, 8, 8]` is used.
- **mapping_type** ({`u2`, `ri`, `riu2`, `none`}, optional) – It defines the mapping type of the LBP codes. Select `u2` for uniform-2 mapping, `ri` for rotation-invariant mapping, `riu2` for uniform-2 and rotation-invariant mapping and `none` to use no mapping and only the decimal values instead.
- **window_step_vertical** (*float*, optional) – Defines the vertical step by which the window is moved, thus it controls the features density. The metric unit is defined by *window_step_unit*.
- **window_step_horizontal** (*float*, optional) – Defines the horizontal step by which the window is moved, thus it controls the features density. The metric unit is defined by *window_step_unit*.
- **window_step_unit** ({`pixels`, `window`}, optional) – Defines the metric unit of the *window_step_vertical* and *window_step_horizontal* parameters.
- **padding** (*bool*, optional) – If `True`, the output image is padded with zeros to match the input image's size.
- **verbose** (*bool*, optional) – Flag to print LBP related information.
- **skip_checks** (*bool*, optional) – If `True`, do not perform any validation of the parameters.

Returnslbp (*Image* or subclass or `(X, Y, ..., Z, C)` *ndarray*) – The ES features image. It has the same type and shape as the input `pixels`. The output number of channels is `C = len(radius) * len(samples)`.

Raises

- `ValueError` – Radius and samples must both be either integers or lists
- `ValueError` – Radius and samples must have the same length
- `ValueError` – Radius must be > 0
- `ValueError` – Radii must be > 0
- `ValueError` – Samples must be > 0
- `ValueError` – Mapping type must be u2, ri, riu2 or none
- `ValueError` – Horizontal window step must be > 0
- `ValueError` – Vertical window step must be > 0
- `ValueError` – Window step unit must be either pixels or window

References

hog

`menpo.feature.`**`hog`**(*image*, **args*, ***kwargs*)

Extracts Histograms of Oriented Gradients (HOG) features from the input image.

Parameters

- **`pixels`** (*Image* or subclass or `(C, X, Y, ..., Z)` *ndarray*) – Either the image object itself or an array with the pixels. The first dimension is interpreted as channels. This means an N-dimensional image is represented by an N+1 dimensional array.
- **`mode`** (`{dense, sparse}`, optional) – The `sparse` case refers to the traditional usage of HOGs, so predefined parameters values are used.

  The `sparse` case of `dalaltriggs` algorithm sets `window_height = window_width = block_size` and `window_step_horizontal = window_step_vertical = cell_size`.

  The `sparse` case of `zhuramanan` algorithm sets `window_height = window_width = 3 * cell_size` and `window_step_horizontal = window_step_vertical = cell_size`.

  In the `dense` case, the user can choose values for *window_height*, *window_width*, *window_unit*, *window_step_vertical*, *window_step_horizontal*, *window_step_unit* and *padding* to customize the HOG calculation.
- **`window_height`** (*float*, optional) – Defines the height of the window. The metric unit is defined by *window_unit*.
- **`window_width`** (*float*, optional) – Defines the width of the window. The metric unit is defined by *window_unit*.
- **`window_unit`** (`{blocks, pixels}`, optional) – Defines the metric unit of the *window_height* and *window_width* parameters.

- **window_step_vertical** (*float*, optional) – Defines the vertical step by which the window is moved, thus it controls the features' density. The metric unit is defined by *window_step_unit*.
- **window_step_horizontal** (*float*, optional) – Defines the horizontal step by which the window is moved, thus it controls the features' density. The metric unit is defined by *window_step_unit*.
- **window_step_unit** (`{pixels, cells}`, optional) – Defines the metric unit of the *window_step_vertical* and *window_step_horizontal* parameters.
- **padding** (*bool*, optional) – If `True`, the output image is padded with zeros to match the input image's size.
- **algorithm** (`{dalaltriggs, zhuramanan}`, optional) – Specifies the algorithm used to compute HOGs. `dalaltriggs` is the implementation of [1] and `zhuramanan` is the implementation of [2].
- **cell_size** (*float*, optional) – Defines the cell size in pixels. This value is set to both the width and height of the cell. This option is valid for both algorithms.
- **block_size** (*float*, optional) – Defines the block size in cells. This value is set to both the width and height of the block. This option is valid only for the `dalaltriggs` algorithm.
- **num_bins** (*float*, optional) – Defines the number of orientation histogram bins. This option is valid only for the `dalaltriggs` algorithm.
- **signed_gradient** (*bool*, optional) – Flag that defines whether we use signed or unsigned gradient angles. This option is valid only for the `dalaltriggs` algorithm.
- **l2_norm_clip** (*float*, optional) – Defines the clipping value of the gradients' L2-norm. This option is valid only for the `dalaltriggs` algorithm.
- **verbose** (*bool*, optional) – Flag to print HOG related information.

Returns

hog (`Image` or subclass or `(X, Y, ..., Z, K)` *ndarray*) – The HOG features image. It has the same type as the input `pixels`. The output number of channels in the case of `dalaltriggs` is `K = num_bins * block_size *block_size` and `K = 31` in the case of `zhuramanan`.

Raises

- `ValueError` – HOG features mode must be either dense or sparse
- `ValueError` – Algorithm must be either dalaltriggs or zhuramanan
- `ValueError` – Number of orientation bins must be > 0
- `ValueError` – Cell size (in pixels) must be > 0
- `ValueError` – Block size (in cells) must be > 0
- `ValueError` – Value for L2-norm clipping must be > 0.0
- `ValueError` – Window height must be >= block size and <= image height
- `ValueError` – Window width must be >= block size and <= image width
- `ValueError` – Window unit must be either pixels or blocks
- `ValueError` – Horizontal window step must be > 0
- `ValueError` – Vertical window step must be > 0
- `ValueError` – Window step unit must be either pixels or cells

References

daisy

`menpo.feature.`**`daisy`**(*image*, **args*, ***kwargs*)

Extracts Daisy features from the input image. The output image has `N * C` number of channels, where `N` is the number of channels of the original image and `C` is the feature channels determined by the input options. Specifically, `C = (rings * histograms + 1) * orientations`.

Parameters

- **`pixels`** (*`Image`* or subclass or `(C, X, Y, ..., Z)` *ndarray*) – Either the image object itself or an array with the pixels. The first dimension is interpreted as channels. This means an N-dimensional image is represented by an N+1 dimensional array.
- **`step`** (*int*, optional) – The sampling step that defines the density of the output image.
- **`radius`** (*int*, optional) – The radius (in pixels) of the outermost ring.
- **`rings`** (*int*, optional) – The number of rings to be used.
- **`histograms`** (*int*, optional) – The number of histograms sampled per ring.
- **`orientations`** (*int*, optional) – The number of orientations (bins) per histogram.
- **`normalization`** (*`[ 'l1', 'l2', 'daisy', None ], optional`*) – It defines how to normalize the descriptors If 'l1' then L1-normalization is applied at each descriptor. If 'l2' then L2-normalization is applied at each descriptor. If 'daisy' then L2-normalization is applied at individual histograms. If None then no normalization is employed.
- **`sigmas`** (*list* of *float* or `None`, optional) – Standard deviation of spatial Gaussian smoothing for the centre histogram and for each ring of histograms. The *list* of sigmas should be sorted from the centre and out. I.e. the first sigma value defines the spatial smoothing of the centre histogram and the last sigma value defines the spatial smoothing of the outermost ring. Specifying sigmas overrides the *rings* parameter by setting `rings = len(sigmas) - 1`.
- **`ring_radii`** (*list* of *float* or `None`, optional) – Radius (in pixels) for each ring. Specifying *ring_radii* overrides the *rings* and *radius* parameters by setting `rings = len(ring_radii)` and `radius = ring_radii[-1]`.

  If both sigmas and ring_radii are given, they must satisfy

  ```
  len(ring_radii) == len(sigmas) + 1
  ```

  since no radius is needed for the centre histogram.
- **`verbose`** (*bool*) – Flag to print Daisy related information.

Returnsdaisy (*`Image`* or subclass or `(X, Y, ..., Z, C)` *ndarray*) – The ES features image. It has the same type and shape as the input `pixels`. The output number of channels is `C = (rings * histograms + 1) * orientations`.

Raises

- `ValueError` – len(sigmas)-1 != len(ring_radii)
- `ValueError` – Invalid normalization method.

References

Optional Features

The following features are optional and may or may not be available depending on whether the required packages that implement them are available. If conda was used to install menpo then it is highly likely that all the optional packages will be available.

Vlfeat: Features that have been wrapped from the Vlfeat[1] project. Currently, the wrapped features are all variants on the SIFT[2] algorithm.

dsift

`menpo.feature.`**`dsift`**(*image*, **args*, ***kwargs*)

Computes a 2-dimensional dense SIFT features image with `C` number of channels, where `C = num_bins_horizontal * num_bins_vertical * num_or_bins`. The dense SIFT[2] implementation is taken from Vlfeat[1].

Parameters

- **`pixels`** (*`Image`* or subclass or `(C, Y, X)` *ndarray*) – Either the image object itself or an array with the pixels. The first dimension is interpreted as channels.
- **`window_step_horizontal`** (*int*, optional) – Defines the horizontal step by which the window is moved, thus it controls the features density. The metric unit is pixels.
- **`window_step_vertical`** (*int*, optional) – Defines the vertical step by which the window is moved, thus it controls the features density. The metric unit is pixels.
- **`num_bins_horizontal`** (*int*, optional) – Defines the number of histogram bins in the X direction.
- **`num_bins_vertical`** (*int*, optional) – Defines the number of histogram bins in the Y direction.
- **`num_or_bins`** (*int*, optional) – Defines the number of orientation histogram bins.
- **`cell_size_horizontal`** (*int*, optional) – Defines cell width in pixels. The cell is the region that is covered by a spatial bin.
- **`cell_size_vertical`** (*int*, optional) – Defines cell height in pixels. The cell is the region that is covered by a spatial bin.
- **`fast`** (*bool*, optional) – If `True`, then the windowing function is a piecewise-flat, rather than Gaussian. While this breaks exact SIFT equivalence, in practice it is much faster to compute.
- **`verbose`** (*bool*, optional) – Flag to print SIFT related information.

Raises

- `ValueError` – Only 2D arrays are supported

[1] Vedaldi, Andrea, and Brian Fulkerson. "VLFeat: An open and portable library of computer vision algorithms." Proceedings of the international conference on Multimedia. ACM, 2010.

[2] Lowe, David G. "Distinctive image features from scale-invariant keypoints." International journal of computer vision 60.2 (2004): 91-110.

[2] Lowe, David G. "Distinctive image features from scale-invariant keypoints." International journal of computer vision 60.2 (2004): 91-110.

[1] Vedaldi, Andrea, and Brian Fulkerson. "VLFeat: An open and portable library of computer vision algorithms." Proceedings of the international conference on Multimedia. ACM, 2010.

- `ValueError` – Size must only contain positive integers.
- `ValueError` – Step must only contain positive integers.
- `ValueError` – Window size must be a positive integer.
- `ValueError` – Geometry must only contain positive integers.

References

fast_dsift

`menpo.feature.`**`fast_dsift`**`()`

Computes a 2-dimensional dense SIFT features image with `C` number of channels, where `C = num_bins_horizontal * num_bins_vertical * num_or_bins`. The dense SIFT[2] implementation is taken from Vlfeat[1].

Parameters

- **`pixels`** (*`Image`* or subclass or `(C, Y, X)` *ndarray*) – Either the image object itself or an array with the pixels. The first dimension is interpreted as channels.
- **`window_step_horizontal`** (*int*, optional) – Defines the horizontal step by which the window is moved, thus it controls the features density. The metric unit is pixels.
- **`window_step_vertical`** (*int*, optional) – Defines the vertical step by which the window is moved, thus it controls the features density. The metric unit is pixels.
- **`num_bins_horizontal`** (*int*, optional) – Defines the number of histogram bins in the X direction.
- **`num_bins_vertical`** (*int*, optional) – Defines the number of histogram bins in the Y direction.
- **`num_or_bins`** (*int*, optional) – Defines the number of orientation histogram bins.
- **`cell_size_horizontal`** (*int*, optional) – Defines cell width in pixels. The cell is the region that is covered by a spatial bin.
- **`cell_size_vertical`** (*int*, optional) – Defines cell height in pixels. The cell is the region that is covered by a spatial bin.
- **`fast`** (*bool*, optional) – If `True`, then the windowing function is a piecewise-flat, rather than Gaussian. While this breaks exact SIFT equivalence, in practice it is much faster to compute.
- **`verbose`** (*bool*, optional) – Flag to print SIFT related information.

Raises

- `ValueError` – Only 2D arrays are supported
- `ValueError` – Size must only contain positive integers.
- `ValueError` – Step must only contain positive integers.
- `ValueError` – Window size must be a positive integer.
- `ValueError` – Geometry must only contain positive integers.

[2] Lowe, David G. "Distinctive image features from scale-invariant keypoints." International journal of computer vision 60.2 (2004): 91-110.
[1] Vedaldi, Andrea, and Brian Fulkerson. "VLFeat: An open and portable library of computer vision algorithms." Proceedings of the international conference on Multimedia. ACM, 2010.

References

vector_128_dsift

`menpo.feature.`**`vector_128_dsift`**(*x*, *dtype=<type 'numpy.float32'>*)

Computes a SIFT feature vector from a square patch (or image). Patch **must** be square and the output vector will *always* be a `(128,)` vector. Please see `dsift()` for more information.

Parameters

- **x** (`Image` or subclass or `(C, Y, Y)` *ndarray*) – Either the image object itself or an array with the pixels. The first dimension is interpreted as channels. Must be square i.e. `height == width`.
- **dtype** (`np.dtype`, optional) – The dtype of the returned vector.

Raises `ValueError` – Only square images are supported.

hellinger_vector_128_dsift

`menpo.feature.`**`hellinger_vector_128_dsift`**(*x*, *dtype=<type 'numpy.float32'>*)

Computes a SIFT feature vector from a square patch (or image). Patch **must** be square and the output vector will *always* be a `(128,)` vector. Please see `dsift()` for more information.

The output of `vector_128_dsift()` is normalized using the hellinger norm (also called the Bhattacharyya distance) which is a measure designed to quantify the similarity between two probability distributions. Since SIFT is a histogram based feature, this has been shown to improve performance. Please see[1] for more information.

Parameters

- **x** (`Image` or subclass or `(C, Y, Y)` *ndarray*) – Either the image object itself or an array with the pixels. The first dimension is interpreted as channels. Must be square i.e. `height == width`.
- **dtype** (`np.dtype`, optional) – The dtype of the returned vector.

Raises `ValueError` – Only square images are supported.

References

Predefined (Partial Features)

The following features are are built from the features listed above, but are partial functions. This implies that some sensible parameter choices have already been made that provides a unique set of properties.

double_igo

`menpo.feature.`**`double_igo`**()

Extracts Image Gradient Orientation (IGO) features from the input image. The output image has `N * C` number

[1] Arandjelovic, Relja, and Andrew Zisserman. "Three things everyone should know to improve object retrieval.", CVPR, 2012.

of channels, where `N` is the number of channels of the original image and `C = 2` or `C = 4` depending on whether double angles are used.

Parameters

- **pixels** (*Image* or subclass or `(C, X, Y, ..., Z)` *ndarray*) – Either the image object itself or an array with the pixels. The first dimension is interpreted as channels. This means an N-dimensional image is represented by an N+1 dimensional array.
- **double_angles** (*bool*, optional) – Assume that `phi` represents the gradient orientations.

  If this flag is `False`, the features image is the concatenation of `cos(phi)` and `sin(phi)`, thus 2 channels.

  If `True`, the features image is the concatenation of `cos(phi)`, `sin(phi)`, `cos(2 * phi)`, `sin(2 * phi)`, thus 4 channels.
- **verbose** (*bool*, optional) – Flag to print IGO related information.

Returns **igo** (*Image* or subclass or `(X, Y, ..., Z, C)` *ndarray*) – The IGO features image. It has the same type and shape as the input `pixels`. The output number of channels depends on the `double_angles` flag.

Raises `ValueError` – Image has to be 2D in order to extract IGOs.

References

sparse_hog

`menpo.feature.`**`sparse_hog`**`()`

Extracts Histograms of Oriented Gradients (HOG) features from the input image.

Parameters

- **pixels** (*Image* or subclass or `(C, X, Y, ..., Z)` *ndarray*) – Either the image object itself or an array with the pixels. The first dimension is interpreted as channels. This means an N-dimensional image is represented by an N+1 dimensional array.
- **mode** (`{dense, sparse}`, optional) – The `sparse` case refers to the traditional usage of HOGs, so predefined parameters values are used.

  The `sparse` case of `dalaltriggs` algorithm sets `window_height = window_width = block_size` and `window_step_horizontal = window_step_vertical = cell_size`.

  The `sparse` case of `zhuramanan` algorithm sets `window_height = window_width = 3 * cell_size` and `window_step_horizontal = window_step_vertical = cell_size`.

  In the `dense` case, the user can choose values for *window_height*, *window_width*, *window_unit*, *window_step_vertical*, *window_step_horizontal*, *window_step_unit* and *padding* to customize the HOG calculation.
- **window_height** (*float*, optional) – Defines the height of the window. The metric unit is defined by *window_unit*.
- **window_width** (*float*, optional) – Defines the width of the window. The metric unit is defined by *window_unit*.

- **window_unit** ({blocks, pixels}, optional) – Defines the metric unit of the *window_height* and *window_width* parameters.
- **window_step_vertical** (*float*, optional) – Defines the vertical step by which the window is moved, thus it controls the features' density. The metric unit is defined by *window_step_unit*.
- **window_step_horizontal** (*float*, optional) – Defines the horizontal step by which the window is moved, thus it controls the features' density. The metric unit is defined by *window_step_unit*.
- **window_step_unit** ({pixels, cells}, optional) – Defines the metric unit of the *window_step_vertical* and *window_step_horizontal* parameters.
- **padding** (*bool*, optional) – If `True`, the output image is padded with zeros to match the input image's size.
- **algorithm** ({dalaltriggs, zhuramanan}, optional) – Specifies the algorithm used to compute HOGs. `dalaltriggs` is the implementation of [1] and `zhuramanan` is the implementation of [2].
- **cell_size** (*float*, optional) – Defines the cell size in pixels. This value is set to both the width and height of the cell. This option is valid for both algorithms.
- **block_size** (*float*, optional) – Defines the block size in cells. This value is set to both the width and height of the block. This option is valid only for the `dalaltriggs` algorithm.
- **num_bins** (*float*, optional) – Defines the number of orientation histogram bins. This option is valid only for the `dalaltriggs` algorithm.
- **signed_gradient** (*bool*, optional) – Flag that defines whether we use signed or unsigned gradient angles. This option is valid only for the `dalaltriggs` algorithm.
- **l2_norm_clip** (*float*, optional) – Defines the clipping value of the gradients' L2-norm. This option is valid only for the `dalaltriggs` algorithm.
- **verbose** (*bool*, optional) – Flag to print HOG related information.

Returns

hog (`Image` or subclass or `(X, Y, ..., Z, K)` *ndarray*) – The HOG features image. It has the same type as the input `pixels`. The output number of channels in the case of `dalaltriggs` is `K = num_bins * block_size *block_size` and `K = 31` in the case of `zhuramanan`.

Raises

- `ValueError` – HOG features mode must be either dense or sparse
- `ValueError` – Algorithm must be either dalaltriggs or zhuramanan
- `ValueError` – Number of orientation bins must be > 0
- `ValueError` – Cell size (in pixels) must be > 0
- `ValueError` – Block size (in cells) must be > 0
- `ValueError` – Value for L2-norm clipping must be > 0.0
- `ValueError` – Window height must be >= block size and <= image height
- `ValueError` – Window width must be >= block size and <= image width
- `ValueError` – Window unit must be either pixels or blocks
- `ValueError` – Horizontal window step must be > 0
- `ValueError` – Vertical window step must be > 0

•`ValueError` – Window step unit must be either pixels or cells

References

Normalization

The following functions perform some kind of normalization on an image.

normalize

`menpo.feature.`**`normalize`**(*image*, **args*, ***kwargs*)

Normalize the pixel values via mean centering and an optional scaling. By default the scaling will be `1.0`. The `mode` parameter selects whether the normalisation is computed across all pixels in the image or per-channel.

Parameters

- **`img`** (*`Image`* or subclass or `(C, X, Y, ..., Z)` *ndarray*) – Either the image object itself or an array with the pixels. The first dimension is interpreted as channels. This means an N-dimensional image is represented by an N+1 dimensional array.
- **`scale_func`** (*callable*, optional) – Compute the scaling factor. Expects a single parameter and an optional *axis* keyword argument and will be passed the entire pixel array. Should return a 1D numpy array of one or more values.
- **`mode`** (`{all, per_channel}`, optional) – If `all`, the normalization is over all channels. If `per_channel`, each channel individually is mean centred and normalized in variance.
- **`error_on_divide_by_zero`** (*bool*, optional) – If `True`, will raise a `ValueError` on dividing by zero. If `False`, will merely raise a warning and only those values with non-zero denominators will be normalized.

Returnspixels (*`Image`* or subclass or `(X, Y, ..., Z, C)` *ndarray*) – A normalized copy of the image that was passed in.

Raises`ValueError` – If any of the denominators are 0 and `error_on_divide_by_zero` is `True`.

normalize_norm

`menpo.feature.`**`normalize_norm`**(*image*, **args*, ***kwargs*)

Normalize the pixels to be mean centred and have unit norm. The `mode` parameter selects whether the normalisation is computed across all pixels in the image or per-channel.

Parameters

- **`pixels`** (*`Image`* or subclass or `(C, X, Y, ..., Z)` *ndarray*) – Either the image object itself or an array with the pixels. The first dimension is interpreted as channels. This means an N-dimensional image is represented by an N+1 dimensional array.
- **`mode`** (`{all, per_channel}`, optional) – If `all`, the normalization is over all channels. If `per_channel`, each channel individually is mean centred and normalized in variance.

- **error_on_divide_by_zero** (*bool*, optional) – If `True`, will raise a `ValueError` on dividing by zero. If `False`, will merely raise a warning and only those values with non-zero denominators will be normalized.

Returns **pixels** (*Image* or subclass or `(X, Y, ..., Z, C)` *ndarray*) – A normalized copy of the image that was passed in.

Raises `ValueError` – If any of the denominators are 0 and `error_on_divide_by_zero` is `True`.

normalize_std

`menpo.feature.`**`normalize_std`**(*image*, **args*, ***kwargs*)

Normalize the pixels to be mean centred and have unit standard deviation. The `mode` parameter selects whether the normalisation is computed across all pixels in the image or per-channel.

Parameters

- **pixels** (*Image* or subclass or `(C, X, Y, ..., Z)` *ndarray*) – Either the image object itself or an array with the pixels. The first dimension is interpreted as channels. This means an N-dimensional image is represented by an N+1 dimensional array.
- **mode** (`{all, per_channel}`, optional) – If `all`, the normalization is over all channels. If `per_channel`, each channel individually is mean centred and normalized in variance.
- **error_on_divide_by_zero** (*bool*, optional) – If `True`, will raise a `ValueError` on dividing by zero. If `False`, will merely raise a warning and only those values with non-zero denominators will be normalized.

Returns **pixels** (*Image* or subclass or `(X, Y, ..., Z, C)` *ndarray*) – A normalized copy of the image that was passed in.

Raises `ValueError` – If any of the denominators are 0 and `error_on_divide_by_zero` is `True`.

normalize_var

`menpo.feature.`**`normalize_var`**(*image*, **args*, ***kwargs*)

Normalize the pixels to be mean centred and normalize according to the variance. The `mode` parameter selects whether the normalisation is computed across all pixels in the image or per-channel.

Parameters

- **pixels** (*Image* or subclass or `(C, X, Y, ..., Z)` *ndarray*) – Either the image object itself or an array with the pixels. The first dimension is interpreted as channels. This means an N-dimensional image is represented by an N+1 dimensional array.
- **mode** (`{all, per_channel}`, optional) – If `all`, the normalization is over all channels. If `per_channel`, each channel individually is mean centred and normalized in variance.
- **error_on_divide_by_zero** (*bool*, optional) – If `True`, will raise a `ValueError` on dividing by zero. If `False`, will merely raise a warning and only those values with non-zero denominators will be normalized.

Returns **pixels** (*Image* or subclass or `(X, Y, ..., Z, C)` *ndarray*) – A normalized copy of the image that was passed in.

Raises `ValueError` – If any of the denominators are 0 and `error_on_divide_by_zero` is `True`.

Visualization

glyph

`menpo.feature.glyph`(*image*, **args*, ***kwargs*)

Create the glyph of a feature image that can be used for visualization. If *pixels* have negative values, the *use_negative* flag controls whether there will be created a glyph of both positive and negative values concatenated the one on top of the other.

Parameters

- **pixels** (*Image* or subclass or `(C, X, Y, ..., Z)` *ndarray*) – Either the image object itself or an array with the pixels. The first dimension is interpreted as channels.
- **vectors_block_size** (*int*) – Defines the size of each block with vectors of the glyph image.
- **use_negative** (*bool*) – Defines whether to take into account possible negative values of feature_data.
- **channels** (*list* of *int* or `None`) – The list of channels to be used. If `None`, then all the channels are employed.

sum_channels

`menpo.feature.sum_channels`(*image*, **args*, ***kwargs*)

Create the sum of the channels of an image that can be used for visualization.

Parameters

- **pixels** (*Image* or subclass or `(C, X, Y, ..., Z)` *ndarray*) – Either the image object itself or an array with the pixels. The first dimension is interpreted as channels.
- **channels** (*list* of *int* or `None`) – The list of channels to be used. If `None`, then all the channels are employed.

Widget

features_selection_widget

`menpo.feature.features_selection_widget`()

Widget that allows for easy selection of a features function and its options. It also has a 'preview' tab for visual inspection. It returns a *list* of length 1 with the selected features function closure.

Returns

features_function (*list* of length `1`) – The function closure of the features function using *functools.partial*. So the function can be called as:

```
features_image = features_function[0](image)
```

Examples

The widget can be invoked as

```
from menpo.feature import features_selection_widget
features_fun = features_selection_widget()
```

And the returned function can be used as

```
import menpo.io as mio
image = mio.import_builtin_asset.lenna_png()
features_image = features_fun[0](image)
```

References

menpo.landmark

Abstract Classes

Landmarkable

class menpo.landmark.**Landmarkable**

Bases: *Copyable*

Abstract interface for object that can have landmarks attached to them. Landmarkable objects have a public dictionary of landmarks which are managed by a *LandmarkManager*. This means that different sets of landmarks can be attached to the same object. Landmarks can be N-dimensional and are expected to be some subclass of *PointCloud* or *LabelledPointUndirectedGraph*.

copy()

Generate an efficient copy of this object.

Note that Numpy arrays and other *Copyable* objects on `self` will be deeply copied. Dictionaries and sets will be shallow copied, and everything else will be assigned (no copy will be made).

Classes that store state other than numpy arrays and immutable types should overwrite this method to ensure all state is copied.

Returns `type(self)` – A copy of this object

n_dims()

The total number of dimensions.

Type *int*

has_landmarks

Whether the object has landmarks.

Type *bool*

landmarks

The landmarks object.

Type *LandmarkManager*

n_landmark_groups

The number of landmark groups on this object.

Type*int*

Exceptions

LabellingError

class `menpo.landmark.`**`LabellingError`**

Bases: `Exception`

Raised when labelling a landmark manager and the set of landmarks does not match the expected semantic layout.

Landmarks & Labeller

LandmarkManager

class `menpo.landmark.`**`LandmarkManager`**

Bases: `MutableMapping`, *`Transformable`*

Store for *`PointCloud`* or :*`LabelledPointUndirectedGraph`* instances associated with an object.

Every *`Landmarkable`* instance has an instance of this class available at the `.landmarks` property. It is through this class that all access to landmarks attached to instances is handled. In general the *`LandmarkManager`* provides a dictionary-like interface for storing landmarks. The LandmarkManager will contain instances of *`PointCloud`* or *`LabelledPointUndirectedGraph`* or subclasses thereof. *`LabelledPointUndirectedGraph`* is unique in it's ability to include labels that refer to subsets of the underlying points that represent interesting semantic *labels*. These *`PointCloud`* or *`LabelledPointUndirectedGraph`* (or subclasses) are stored under string keys - these keys are refereed to as the **group name**. A special case is where there is a single unambiguous group attached to a *`LandmarkManager`* - in this case `None` can be used as a key to access this sole group.

Note that all groups stored on a *`Landmarkable`* in it's attached *`LandmarkManager`* are automatically transformed and copied with their parent object.

`clear``()` → None. Remove all items from D.

`copy``()`

Generate an efficient copy of this *`LandmarkManager`*.

Returns`type(self)` – A copy of this object

`get``(`*k*[, *d*]`)` → D[k] if k in D, else d. d defaults to None.

`items``()` → list of D's (key, value) pairs, as 2-tuples

`items_matching``(`*glob_pattern*`)`

Yield only items `(group, PointCloud)` where the key matches a given glob.

Parameters`glob_pattern` (*str*) – A glob pattern e.g. 'frontal_face_*'

Yields`item` (`(group, PointCloud)`) – Tuple of (str, PointCloud) where the group matches the glob.

`iteritems``()` → an iterator over the (key, value) items of D

`iterkeys``()` → an iterator over the keys of D

`itervalues``()` → an iterator over the values of D

`keys``()` → list of D's keys

keys_matching(*glob_pattern*)
Yield only landmark group names (keys) matching a given glob.

Parametersglob_pattern (*str*) – A glob pattern e.g. 'frontal_face_*'

Yieldskeys (*group labels that match the glob pattern*)

pop(*k*[, *d*]) → v, remove specified key and return the corresponding value.
If key is not found, d is returned if given, otherwise KeyError is raised.

popitem() → (k, v), remove and return some (key, value) pair
as a 2-tuple; but raise KeyError if D is empty.

setdefault(*k*[, *d*]) → D.get(k,d), also set D[k]=d if k not in D

update([*E*], **F) → None. Update D from mapping/iterable E and F.
If E present and has a .keys() method, does: for k in E: D[k] = E[k] If E present and lacks .keys() method, does: for (k, v) in E: D[k] = v In either case, this is followed by: for k, v in F.items(): D[k] = v

values() → list of D's values

group_labels
All the labels for the landmark set sorted by insertion order.

Type*list* of *str*

has_landmarks
Whether the object has landmarks or not

Type*int*

n_dims
The total number of dimensions.

Type*int*

n_groups
Total number of labels.

Type*int*

labeller

menpo.landmark.**labeller**(*landmarkable*, *group*, *label_func*)
Re-label an existing landmark group on a `Landmarkable` object with a new label set.

Parameters

- **landmarkable** (`Landmarkable`) – `Landmarkable` that will have it's `LandmarkManager` augmented with a new `LabelledPointUndirectedGraph` or `PointCloud`
- **group** (*str*) – The group label of the existing pointcloud that should be re-labelled. A copy of this group will be attached to it's landmark manager with new labels. The group label of this new group and the labels it will have is determined by `label_func`
- **label_func** (*func -> (str, LabelledPointUndirectedGraph)*) – A labelling function taken from this module. Takes as input a `PointCloud` or `LabelledPointUndirectedGraph` or subclass and returns a tuple of (new group label, new LabelledPointUndirectedGraph with semantic labels applied).

Returnslandmarkable (`Landmarkable`) – Augmented `landmarkable` (this is just for convenience, the object will actually be modified in place)

Bounding Box Labels

bounding_box_mirrored_to_bounding_box

menpo.landmark.**bounding_box_mirrored_to_bounding_box**(*x*, *return_mapping=False*)

Apply a single 'all' label to a given bounding box that has been mirrored around the vertical axis (flipped around the Y-axis). This bounding box must be as specified by the `bounding_box` method (but mirrored).

Parameters

- **x** (*LabelledPointUndirectedGraph* or *PointCloud* or *ndarray*) – The input labelled point graph, pointcloud, subclass of those or array to label. If a pointcloud is passed, then only the connectivity information is propagated to the pointcloud (a subclass of *PointCloud* may be returned).
- **return_mapping** (*bool*, optional) – Only applicable if a *PointCloud* or *ndarray* is passed. Returns the mapping dictionary which maps labels to indices into the resulting *PointCloud* (which is then used to for building a *LabelledPointUndirectedGraph*. This parameter is only provided for internal use so that other labellers can piggyback off one another.

Returns

- **x_labelled** (*LabelledPointUndirectedGraph* or *PointCloud*) – If a *LabelledPointUndirectedGraph* was passed, a *LabelledPointUndirectedGraph* is returned. This labelled pointgraph will contain specific labels and these labels may refer to sub-pointclouds with specific connectivity information.

  If a *PointCloud* was passed, a *PointCloud* is returned. Only the connectivity information is propagated to the pointcloud (a subclass of *PointCloud* may be returned).
- **mapping_dict** (*ordereddict* {*str* -> *int ndarray*}, optional) – Only returned if `return_mapping==True`. Used for building *LabelledPointUndirectedGraph*.

Raises: *:map:'LabellingError'* – If the given labelled point graph/pointcloud contains less than the expected number of points.

bounding_box_to_bounding_box

menpo.landmark.**bounding_box_to_bounding_box**(*x*, *return_mapping=False*)

Apply a single 'all' label to a given bounding box. This bounding box must be as specified by the `bounding_box` method.

Parameters

- **x** (*LabelledPointUndirectedGraph* or *PointCloud* or *ndarray*) – The input labelled point graph, pointcloud, subclass of those or array to label. If a pointcloud is passed, then only the connectivity information is propagated to the pointcloud (a subclass of *PointCloud* may be returned).
- **return_mapping** (*bool*, optional) – Only applicable if a *PointCloud* or *ndarray* is passed. Returns the mapping dictionary which maps labels to indices into the resulting *PointCloud* (which is then used to for building a *LabelledPointUndirectedGraph*. This parameter is only provided for internal use so that other labellers can piggyback off one another.

Returns

- **x_labelled** (*LabelledPointUndirectedGraph* or *PointCloud*) – If a *LabelledPointUndirectedGraph* was passed, a *LabelledPointUndirectedGraph* is returned. This labelled pointgraph will contain specific labels and these labels may refer to sub-pointclouds with specific connectivity information.

  If a *PointCloud* was passed, a *PointCloud* is returned. Only the connectivity information is propagated to the pointcloud (a subclass of *PointCloud* may be returned).

- **mapping_dict** (*ordereddict* {*str* -> *int ndarray*}, optional) – Only returned if `return_mapping==True`. Used for building *LabelledPointUndirectedGraph*.

Raises: *:map:'LabellingError'* – If the given labelled point graph/pointcloud contains less than the expected number of points.

Labels

Pre-defined landmark labels that normally correspond to standard database mark-ups.

Human Face

face_ibug_68_to_face_ibug_49

`menpo.landmark.`**`face_ibug_68_to_face_ibug_49`**(*x*, *return_mapping=False*)

Apply the IBUG 49-point semantic labels, but removing the annotations corresponding to the jaw region and the 2 describing the inner mouth corners.

The semantic labels applied are as follows:

- left_eyebrow
- right_eyebrow
- nose
- left_eye
- right_eye
- mouth

References

Parameters

- **x** (*LabelledPointUndirectedGraph* or *PointCloud* or *ndarray*) – The input labelled point graph, pointcloud, subclass of those or array to label. If a pointcloud is passed, then only the connectivity information is propagated to the pointcloud (a subclass of *PointCloud* may be returned).

- **return_mapping** (*bool*, optional) – Only applicable if a *PointCloud* or *ndarray* is passed. Returns the mapping dictionary which maps labels to indices into the resulting *PointCloud* (which is then used to for building a *LabelledPointUndirectedGraph*. This parameter is only provided for internal use so that other labellers can piggyback off one another.

Returns

- **x_labelled** (`LabelledPointUndirectedGraph` or `PointCloud`) – If a `LabelledPointUndirectedGraph` was passed, a `LabelledPointUndirectedGraph` is returned. This labelled pointgraph will contain specific labels and these labels may refer to sub-pointclouds with specific connectivity information.

  If a `PointCloud` was passed, a `PointCloud` is returned. Only the connectivity information is propagated to the pointcloud (a subclass of `PointCloud` may be returned).

- **mapping_dict** (*ordereddict* {*str* -> *int ndarray*}, optional) – Only returned if `return_mapping==True`. Used for building `LabelledPointUndirectedGraph`.

Raises: *:map:'LabellingError'* – If the given labelled point graph/pointcloud contains less than the expected number of points.

face_ibug_68_to_face_ibug_49_trimesh

`menpo.landmark.`**`face_ibug_68_to_face_ibug_49_trimesh`**(*x*, *return_mapping=False*)

Apply the IBUG 49-point semantic labels, with trimesh connectivity.

The semantic labels applied are as follows:

- tri

References

Parameters

- **x** (`LabelledPointUndirectedGraph` or `PointCloud` or *ndarray*) – The input labelled point graph, pointcloud, subclass of those or array to label. If a pointcloud is passed, then only the connectivity information is propagated to the pointcloud (a subclass of `PointCloud` may be returned).

- **return_mapping** (*bool*, optional) – Only applicable if a `PointCloud` or *ndarray* is passed. Returns the mapping dictionary which maps labels to indices into the resulting `PointCloud` (which is then used to for building a `LabelledPointUndirectedGraph`. This parameter is only provided for internal use so that other labellers can piggyback off one another.

Returns

- **x_labelled** (`LabelledPointUndirectedGraph` or `PointCloud`) – If a `LabelledPointUndirectedGraph` was passed, a `LabelledPointUndirectedGraph` is returned. This labelled pointgraph will contain specific labels and these labels may refer to sub-pointclouds with specific connectivity information.

  If a `PointCloud` was passed, a `PointCloud` is returned. Only the connectivity information is propagated to the pointcloud (a subclass of `PointCloud` may be returned).

- **mapping_dict** (*ordereddict* {*str* -> *int ndarray*}, optional) – Only returned if `return_mapping==True`. Used for building `LabelledPointUndirectedGraph`.

Raises: *:map:'LabellingError'* – If the given labelled point graph/pointcloud contains less than the expected number of points.

face_ibug_68_to_face_ibug_51

`menpo.landmark.`**`face_ibug_68_to_face_ibug_51`**(*x*, *return_mapping=False*)

Apply the IBUG 51-point semantic labels, but removing the annotations corresponding to the jaw region.

The semantic labels applied are as follows:

- left_eyebrow
- right_eyebrow
- nose
- left_eye
- right_eye
- mouth

References

Parameters

- **x** (`LabelledPointUndirectedGraph` or `PointCloud` or *ndarray*) – The input labelled point graph, pointcloud, subclass of those or array to label. If a pointcloud is passed, then only the connectivity information is propagated to the pointcloud (a subclass of `PointCloud` may be returned).
- **return_mapping** (*bool*, optional) – Only applicable if a `PointCloud` or *ndarray* is passed. Returns the mapping dictionary which maps labels to indices into the resulting `PointCloud` (which is then used to for building a `LabelledPointUndirectedGraph`. This parameter is only provided for internal use so that other labellers can piggyback off one another.

Returns

- **x_labelled** (`LabelledPointUndirectedGraph` or `PointCloud`) – If a `LabelledPointUndirectedGraph` was passed, a `LabelledPointUndirectedGraph` is returned. This labelled pointgraph will contain specific labels and these labels may refer to sub-pointclouds with specific connectivity information.

  If a `PointCloud` was passed, a `PointCloud` is returned. Only the connectivity information is propagated to the pointcloud (a subclass of `PointCloud` may be returned).
- **mapping_dict** (*ordereddict* {*str* -> *int ndarray*}, optional) – Only returned if `return_mapping==True`. Used for building `LabelledPointUndirectedGraph`.

Raises: *:map:'LabellingError'* – If the given labelled point graph/pointcloud contains less than the expected number of points.

face_ibug_68_to_face_ibug_51_trimesh

menpo.landmark.**face_ibug_68_to_face_ibug_51_trimesh**(*x*, *return_mapping=False*)

Apply the IBUG 51-point semantic labels, with trimesh connectivity..

The semantic labels applied are as follows:

- tri

References

Parameters

- **x** (*LabelledPointUndirectedGraph* or *PointCloud* or *ndarray*) – The input labelled point graph, pointcloud, subclass of those or array to label. If a pointcloud is passed, then only the connectivity information is propagated to the pointcloud (a subclass of *PointCloud* may be returned).
- **return_mapping** (*bool*, optional) – Only applicable if a *PointCloud* or *ndarray* is passed. Returns the mapping dictionary which maps labels to indices into the resulting *PointCloud* (which is then used to for building a *LabelledPointUndirectedGraph*. This parameter is only provided for internal use so that other labellers can piggyback off one another.

Returns

- **x_labelled** (*LabelledPointUndirectedGraph* or *PointCloud*) – If a *LabelledPointUndirectedGraph* was passed, a *LabelledPointUndirectedGraph* is returned. This labelled pointgraph will contain specific labels and these labels may refer to sub-pointclouds with specific connectivity information.

  If a *PointCloud* was passed, a *PointCloud* is returned. Only the connectivity information is propagated to the pointcloud (a subclass of *PointCloud* may be returned).
- **mapping_dict** (*ordereddict* {*str* -> *int* *ndarray*}, optional) – Only returned if `return_mapping==True`. Used for building *LabelledPointUndirectedGraph*.

Raises: *:map:'LabellingError'* – If the given labelled point graph/pointcloud contains less than the expected number of points.

face_ibug_68_to_face_ibug_65

menpo.landmark.**face_ibug_68_to_face_ibug_65**(*x*, *return_mapping=False*)

Apply the IBUG 68 point semantic labels, but ignore the 3 points that are coincident for a closed mouth (bottom of the inner mouth).

The semantic labels applied are as follows:

- jaw
- left_eyebrow
- right_eyebrow
- nose
- left_eye

•right_eye

•mouth

References

Parameters

•**x** (*LabelledPointUndirectedGraph* or *PointCloud* or *ndarray*) – The input labelled point graph, pointcloud, subclass of those or array to label. If a pointcloud is passed, then only the connectivity information is propagated to the pointcloud (a subclass of *PointCloud* may be returned).

•**return_mapping** (*bool*, optional) – Only applicable if a *PointCloud* or *ndarray* is passed. Returns the mapping dictionary which maps labels to indices into the resulting *PointCloud* (which is then used to for building a *LabelledPointUndirectedGraph*. This parameter is only provided for internal use so that other labellers can piggyback off one another.

Returns

•**x_labelled** (*LabelledPointUndirectedGraph* or *PointCloud*) – If a *LabelledPointUndirectedGraph* was passed, a *LabelledPointUndirectedGraph* is returned. This labelled pointgraph will contain specific labels and these labels may refer to sub-pointclouds with specific connectivity information.

If a *PointCloud* was passed, a *PointCloud* is returned. Only the connectivity information is propagated to the pointcloud (a subclass of *PointCloud* may be returned).

•**mapping_dict** (*ordereddict* {*str* -> *int ndarray*}, optional) – Only returned if `return_mapping==True`. Used for building *LabelledPointUndirectedGraph*.

Raises: *:map:'LabellingError'* – If the given labelled point graph/pointcloud contains less than the expected number of points.

face_ibug_68_to_face_ibug_66

`menpo.landmark.`**`face_ibug_68_to_face_ibug_66`**(*x*, *return_mapping=False*)

Apply the IBUG 66-point semantic labels, but ignoring the 2 points describing the inner mouth corners).

The semantic labels applied are as follows:

•jaw

•left_eyebrow

•right_eyebrow

•nose

•left_eye

•right_eye

•mouth

References

Parameters

- **x** (*LabelledPointUndirectedGraph* or *PointCloud* or *ndarray*) – The input labelled point graph, pointcloud, subclass of those or array to label. If a pointcloud is passed, then only the connectivity information is propagated to the pointcloud (a subclass of *PointCloud* may be returned).
- **return_mapping** (*bool*, optional) – Only applicable if a *PointCloud* or *ndarray* is passed. Returns the mapping dictionary which maps labels to indices into the resulting *PointCloud* (which is then used to for building a *LabelledPointUndirectedGraph*. This parameter is only provided for internal use so that other labellers can piggyback off one another.

Returns

- **x_labelled** (*LabelledPointUndirectedGraph* or *PointCloud*) – If a *LabelledPointUndirectedGraph* was passed, a *LabelledPointUndirectedGraph* is returned. This labelled pointgraph will contain specific labels and these labels may refer to sub-pointclouds with specific connectivity information.

  If a *PointCloud* was passed, a *PointCloud* is returned. Only the connectivity information is propagated to the pointcloud (a subclass of *PointCloud* may be returned).
- **mapping_dict** (*ordereddict* {*str* -> *int ndarray*}, optional) – Only returned if `return_mapping==True`. Used for building *LabelledPointUndirectedGraph*.

Raises: *:map:'LabellingError'* – If the given labelled point graph/pointcloud contains less than the expected number of points.

face_ibug_68_to_face_ibug_66_trimesh

`menpo.landmark.`**`face_ibug_68_to_face_ibug_66_trimesh`**(*x*, *return_mapping=False*)

Apply the IBUG 66-point semantic labels, with trimesh connectivity.

The semantic labels applied are as follows:

- tri

References

Parameters

- **x** (*LabelledPointUndirectedGraph* or *PointCloud* or *ndarray*) – The input labelled point graph, pointcloud, subclass of those or array to label. If a pointcloud is passed, then only the connectivity information is propagated to the pointcloud (a subclass of *PointCloud* may be returned).
- **return_mapping** (*bool*, optional) – Only applicable if a *PointCloud* or *ndarray* is passed. Returns the mapping dictionary which maps labels to indices into the resulting *PointCloud* (which is then used to for building a

`LabelledPointUndirectedGraph`. This parameter is only provided for internal use so that other labellers can piggyback off one another.

Returns

- **x_labelled** (`LabelledPointUndirectedGraph` or `PointCloud`) – If a `LabelledPointUndirectedGraph` was passed, a `LabelledPointUndirectedGraph` is returned. This labelled pointgraph will contain specific labels and these labels may refer to sub-pointclouds with specific connectivity information.

  If a `PointCloud` was passed, a `PointCloud` is returned. Only the connectivity information is propagated to the pointcloud (a subclass of `PointCloud` may be returned).

- **mapping_dict** (*ordereddict {str -> int ndarray}*, optional) – Only returned if `return_mapping==True`. Used for building `LabelledPointUndirectedGraph`.

Raises: *:map:'LabellingError'* – If the given labelled point graph/pointcloud contains less than the expected number of points.

face_ibug_68_to_face_ibug_68

`menpo.landmark.`**`face_ibug_68_to_face_ibug_68`**(*x*, *return_mapping=False*)

Apply the IBUG 68-point semantic labels.

The semantic labels are as follows:

- jaw
- left_eyebrow
- right_eyebrow
- nose
- left_eye
- right_eye
- mouth

References

Parameters

- **x** (`LabelledPointUndirectedGraph` or `PointCloud` or *ndarray*) – The input labelled point graph, pointcloud, subclass of those or array to label. If a pointcloud is passed, then only the connectivity information is propagated to the pointcloud (a subclass of `PointCloud` may be returned).

- **return_mapping** (*bool*, optional) – Only applicable if a `PointCloud` or *ndarray* is passed. Returns the mapping dictionary which maps labels to indices into the resulting `PointCloud` (which is then used to for building a `LabelledPointUndirectedGraph`. This parameter is only provided for internal use so that other labellers can piggyback off one another.

Returns

- **x_labelled** (*LabelledPointUndirectedGraph* or *PointCloud*) – If a *LabelledPointUndirectedGraph* was passed, a *LabelledPointUndirectedGraph* is returned. This labelled pointgraph will contain specific labels and these labels may refer to sub-pointclouds with specific connectivity information.

  If a *PointCloud* was passed, a *PointCloud* is returned. Only the connectivity information is propagated to the pointcloud (a subclass of *PointCloud* may be returned).

- **mapping_dict** (*ordereddict {str -> int ndarray}*, optional) – Only returned if `return_mapping==True`. Used for building *LabelledPointUndirectedGraph*.

Raises: *:map:'LabellingError'* – If the given labelled point graph/pointcloud contains less than the expected number of points.

face_ibug_68_to_face_ibug_68_trimesh

`menpo.landmark.`**`face_ibug_68_to_face_ibug_68_trimesh`**(*x*, *return_mapping=False*)

Apply the IBUG 68-point semantic labels, with trimesh connectivity.

The semantic labels applied are as follows:

- tri

References

Parameters

- **x** (*LabelledPointUndirectedGraph* or *PointCloud* or *ndarray*) – The input labelled point graph, pointcloud, subclass of those or array to label. If a pointcloud is passed, then only the connectivity information is propagated to the pointcloud (a subclass of *PointCloud* may be returned).

- **return_mapping** (*bool*, optional) – Only applicable if a *PointCloud* or *ndarray* is passed. Returns the mapping dictionary which maps labels to indices into the resulting *PointCloud* (which is then used to for building a *LabelledPointUndirectedGraph*. This parameter is only provided for internal use so that other labellers can piggyback off one another.

Returns

- **x_labelled** (*LabelledPointUndirectedGraph* or *PointCloud*) – If a *LabelledPointUndirectedGraph* was passed, a *LabelledPointUndirectedGraph* is returned. This labelled pointgraph will contain specific labels and these labels may refer to sub-pointclouds with specific connectivity information.

  If a *PointCloud* was passed, a *PointCloud* is returned. Only the connectivity information is propagated to the pointcloud (a subclass of *PointCloud* may be returned).

- **mapping_dict** (*ordereddict {str -> int ndarray}*, optional) – Only returned if `return_mapping==True`. Used for building *LabelledPointUndirectedGraph*.

Raises: *:map:'LabellingError'* – If the given labelled point graph/pointcloud contains less than the expected number of points.

face_ibug_68_mirrored_to_face_ibug_68

`menpo.landmark.face_ibug_68_mirrored_to_face_ibug_68`(*x*, *return_mapping=False*)

Apply the IBUG 68-point semantic labels, on a pointcloud that has been mirrored around the vertical axis (flipped around the Y-axis). Thus, on the flipped image the jaw etc would be the wrong way around. This rectifies that and returns a new PointCloud whereby all the points are oriented correctly.

The semantic labels applied are as follows:

- jaw
- left_eyebrow
- right_eyebrow
- nose
- left_eye
- right_eye
- mouth

References

Parameters

- **x** (*LabelledPointUndirectedGraph* or *PointCloud* or *ndarray*) – The input labelled point graph, pointcloud, subclass of those or array to label. If a pointcloud is passed, then only the connectivity information is propagated to the pointcloud (a subclass of *PointCloud* may be returned).
- **return_mapping** (*bool*, optional) – Only applicable if a *PointCloud* or *ndarray* is passed. Returns the mapping dictionary which maps labels to indices into the resulting *PointCloud* (which is then used to for building a *LabelledPointUndirectedGraph*. This parameter is only provided for internal use so that other labellers can piggyback off one another.

Returns

- **x_labelled** (*LabelledPointUndirectedGraph* or *PointCloud*) – If a *LabelledPointUndirectedGraph* was passed, a *LabelledPointUndirectedGraph* is returned. This labelled pointgraph will contain specific labels and these labels may refer to sub-pointclouds with specific connectivity information.

  If a *PointCloud* was passed, a *PointCloud* is returned. Only the connectivity information is propagated to the pointcloud (a subclass of *PointCloud* may be returned).
- **mapping_dict** (*ordereddict* {*str* -> *int ndarray*}, optional) – Only returned if `return_mapping==True`. Used for building *LabelledPointUndirectedGraph*.

Raises: *:map:'LabellingError'* – If the given labelled point graph/pointcloud contains less than the expected number of points.

face_ibug_49_to_face_ibug_49

menpo.landmark.**face_ibug_49_to_face_ibug_49**(*x*, *return_mapping=False*)

Apply the IBUG 49-point semantic labels.

The semantic labels applied are as follows:

- left_eyebrow
- right_eyebrow
- nose
- left_eye
- right_eye
- mouth

References

Parameters

- **x** (*LabelledPointUndirectedGraph* or *PointCloud* or *ndarray*) – The input labelled point graph, pointcloud, subclass of those or array to label. If a pointcloud is passed, then only the connectivity information is propagated to the pointcloud (a subclass of *PointCloud* may be returned).
- **return_mapping** (*bool*, optional) – Only applicable if a *PointCloud* or *ndarray* is passed. Returns the mapping dictionary which maps labels to indices into the resulting *PointCloud* (which is then used to for building a *LabelledPointUndirectedGraph*. This parameter is only provided for internal use so that other labellers can piggyback off one another.

Returns

- **x_labelled** (*LabelledPointUndirectedGraph* or *PointCloud*) – If a *LabelledPointUndirectedGraph* was passed, a *LabelledPointUndirectedGraph* is returned. This labelled pointgraph will contain specific labels and these labels may refer to sub-pointclouds with specific connectivity information.

  If a *PointCloud* was passed, a *PointCloud* is returned. Only the connectivity information is propagated to the pointcloud (a subclass of *PointCloud* may be returned).
- **mapping_dict** (*ordereddict* {*str* -> *int ndarray*}, optional) – Only returned if `return_mapping==True`. Used for building *LabelledPointUndirectedGraph*.

Raises: *:map:'LabellingError'* – If the given labelled point graph/pointcloud contains less than the expected number of points.

face_imm_58_to_face_imm_58

menpo.landmark.**face_imm_58_to_face_imm_58**(*x*, *return_mapping=False*)

Apply the 58-point semantic labels from the IMM dataset.

The semantic labels applied are as follows:

- jaw
- left_eye
- right_eye
- left_eyebrow
- right_eyebrow
- mouth
- nose

References

Parameters

- **x** (*LabelledPointUndirectedGraph* or *PointCloud* or *ndarray*) – The input labelled point graph, pointcloud, subclass of those or array to label. If a pointcloud is passed, then only the connectivity information is propagated to the pointcloud (a subclass of *PointCloud* may be returned).
- **return_mapping** (*bool*, optional) – Only applicable if a *PointCloud* or *ndarray* is passed. Returns the mapping dictionary which maps labels to indices into the resulting *PointCloud* (which is then used to for building a *LabelledPointUndirectedGraph*. This parameter is only provided for internal use so that other labellers can piggyback off one another.

Returns

- **x_labelled** (*LabelledPointUndirectedGraph* or *PointCloud*) – If a *LabelledPointUndirectedGraph* was passed, a *LabelledPointUndirectedGraph* is returned. This labelled pointgraph will contain specific labels and these labels may refer to sub-pointclouds with specific connectivity information.

  If a *PointCloud* was passed, a *PointCloud* is returned. Only the connectivity information is propagated to the pointcloud (a subclass of *PointCloud* may be returned).
- **mapping_dict** (*ordereddict* {*str* -> *int* *ndarray*}, optional) – Only returned if `return_mapping==True`. Used for building *LabelledPointUndirectedGraph*.

Raises: *:map:'LabellingError'* – If the given labelled point graph/pointcloud contains less than the expected number of points.

face_lfpw_29_to_face_lfpw_29

`menpo.landmark.`**`face_lfpw_29_to_face_lfpw_29`**(*x*, *return_mapping=False*)

Apply the 29-point semantic labels from the original LFPW dataset.

The semantic labels applied are as follows:

- chin
- left_eye
- right_eye

- left_eyebrow
- right_eyebrow
- mouth
- nose

References

Parameters

- **x** (*LabelledPointUndirectedGraph* or *PointCloud* or *ndarray*) – The input labelled point graph, pointcloud, subclass of those or array to label. If a pointcloud is passed, then only the connectivity information is propagated to the pointcloud (a subclass of *PointCloud* may be returned).
- **return_mapping** (*bool*, optional) – Only applicable if a *PointCloud* or *ndarray* is passed. Returns the mapping dictionary which maps labels to indices into the resulting *PointCloud* (which is then used to for building a *LabelledPointUndirectedGraph*. This parameter is only provided for internal use so that other labellers can piggyback off one another.

Returns

- **x_labelled** (*LabelledPointUndirectedGraph* or *PointCloud*) – If a *LabelledPointUndirectedGraph* was passed, a *LabelledPointUndirectedGraph* is returned. This labelled pointgraph will contain specific labels and these labels may refer to sub-pointclouds with specific connectivity information.

  If a *PointCloud* was passed, a *PointCloud* is returned. Only the connectivity information is propagated to the pointcloud (a subclass of *PointCloud* may be returned).
- **mapping_dict** (*ordereddict* {*str* -> *int ndarray*}, optional) – Only returned if `return_mapping==True`. Used for building *LabelledPointUndirectedGraph*.

Raises: *:map:'LabellingError'* – If the given labelled point graph/pointcloud contains less than the expected number of points.

face_bu3dfe_83_to_face_bu3dfe_83

`menpo.landmark.`**`face_bu3dfe_83_to_face_bu3dfe_83`**(*x*, *return_mapping=False*)

Apply the BU-3DFE (Binghamton University 3D Facial Expression) Database 83-point facial semantic labels.

The semantic labels applied are as follows:

- right_eye
- left_eye
- right_eyebrow
- left_eyebrow
- right_nose
- left_nose

- nostrils
- outer_mouth
- inner_mouth
- jaw

References

Parameters

- **x** (*LabelledPointUndirectedGraph* or *PointCloud* or *ndarray*) – The input labelled point graph, pointcloud, subclass of those or array to label. If a pointcloud is passed, then only the connectivity information is propagated to the pointcloud (a subclass of *PointCloud* may be returned).
- **return_mapping** (*bool*, optional) – Only applicable if a *PointCloud* or *ndarray* is passed. Returns the mapping dictionary which maps labels to indices into the resulting *PointCloud* (which is then used to for building a *LabelledPointUndirectedGraph*. This parameter is only provided for internal use so that other labellers can piggyback off one another.

Returns

- **x_labelled** (*LabelledPointUndirectedGraph* or *PointCloud*) – If a *LabelledPointUndirectedGraph* was passed, a *LabelledPointUndirectedGraph* is returned. This labelled pointgraph will contain specific labels and these labels may refer to sub-pointclouds with specific connectivity information.

  If a *PointCloud* was passed, a *PointCloud* is returned. Only the connectivity information is propagated to the pointcloud (a subclass of *PointCloud* may be returned).
- **mapping_dict** (*ordereddict* {*str* -> *int ndarray*}, optional) – Only returned if `return_mapping==True`. Used for building *LabelledPointUndirectedGraph*.

Raises: *:map:'LabellingError'* – If the given labelled point graph/pointcloud contains less than the expected number of points.

Human Eyes

eye_ibug_close_17_to_eye_ibug_close_17

`menpo.landmark.`**`eye_ibug_close_17_to_eye_ibug_close_17`**(*x*, *return_mapping=False*)

Apply the IBUG 17-point close eye semantic labels.

The semantic labels applied are as follows:

- upper_eyelid
- lower_eyelid

Parameters

- **x** (*LabelledPointUndirectedGraph* or *PointCloud* or *ndarray*) – The input labelled point graph, pointcloud, subclass of those or array to label. If a pointcloud is

passed, then only the connectivity information is propagated to the pointcloud (a subclass of `PointCloud` may be returned).

- **return_mapping** (*bool*, optional) – Only applicable if a `PointCloud` or *ndarray* is passed. Returns the mapping dictionary which maps labels to indices into the resulting `PointCloud` (which is then used to for building a `LabelledPointUndirectedGraph`. This parameter is only provided for internal use so that other labellers can piggyback off one another.

Returns

- **x_labelled** (`LabelledPointUndirectedGraph` or `PointCloud`) – If a `LabelledPointUndirectedGraph` was passed, a `LabelledPointUndirectedGraph` is returned. This labelled pointgraph will contain specific labels and these labels may refer to sub-pointclouds with specific connectivity information.

  If a `PointCloud` was passed, a `PointCloud` is returned. Only the connectivity information is propagated to the pointcloud (a subclass of `PointCloud` may be returned).

- **mapping_dict** (*ordereddict* {*str* -> *int ndarray*}, optional) – Only returned if `return_mapping==True`. Used for building `LabelledPointUndirectedGraph`.

Raises: *:map:'LabellingError'* – If the given labelled point graph/pointcloud contains less than the expected number of points.

eye_ibug_close_17_to_eye_ibug_close_17_trimesh

`menpo.landmark.`**`eye_ibug_close_17_to_eye_ibug_close_17_trimesh`**(*x*, *return_mapping=False*)

Apply the IBUG 17-point close eye semantic labels, with trimesh connectivity.

The semantic labels applied are as follows:

- tri

Parameters

- **x** (`LabelledPointUndirectedGraph` or `PointCloud` or *ndarray*) – The input labelled point graph, pointcloud, subclass of those or array to label. If a pointcloud is passed, then only the connectivity information is propagated to the pointcloud (a subclass of `PointCloud` may be returned).

- **return_mapping** (*bool*, optional) – Only applicable if a `PointCloud` or *ndarray* is passed. Returns the mapping dictionary which maps labels to indices into the resulting `PointCloud` (which is then used to for building a `LabelledPointUndirectedGraph`. This parameter is only provided for internal use so that other labellers can piggyback off one another.

Returns

- **x_labelled** (`LabelledPointUndirectedGraph` or `PointCloud`) – If a `LabelledPointUndirectedGraph` was passed, a `LabelledPointUndirectedGraph` is returned. This labelled pointgraph will contain specific labels and these labels may refer to sub-pointclouds with specific connectivity information.

  If a `PointCloud` was passed, a `PointCloud` is returned. Only the connectivity information is propagated to the pointcloud (a subclass of `PointCloud` may be returned).

- **mapping_dict** (*ordereddict {str -> int ndarray}*, optional) – Only returned if `return_mapping==True`. Used for building `LabelledPointUndirectedGraph`.

Raises: *:map:'LabellingError'* – If the given labelled point graph/pointcloud contains less than the expected number of points.

eye_ibug_open_38_to_eye_ibug_open_38

`menpo.landmark.`**`eye_ibug_open_38_to_eye_ibug_open_38`**(*x*, *return_mapping=False*)

Apply the IBUG 38-point open eye semantic labels.

The semantic labels applied are as follows:

- upper_eyelid
- lower_eyelid
- iris
- pupil
- sclera

Parameters

- **x** (`LabelledPointUndirectedGraph` or `PointCloud` or *ndarray*) – The input labelled point graph, pointcloud, subclass of those or array to label. If a pointcloud is passed, then only the connectivity information is propagated to the pointcloud (a subclass of `PointCloud` may be returned).
- **return_mapping** (*bool*, optional) – Only applicable if a `PointCloud` or *ndarray* is passed. Returns the mapping dictionary which maps labels to indices into the resulting `PointCloud` (which is then used to for building a `LabelledPointUndirectedGraph`. This parameter is only provided for internal use so that other labellers can piggyback off one another.

Returns

- **x_labelled** (`LabelledPointUndirectedGraph` or `PointCloud`) – If a `LabelledPointUndirectedGraph` was passed, a `LabelledPointUndirectedGraph` is returned. This labelled pointgraph will contain specific labels and these labels may refer to sub-pointclouds with specific connectivity information.

  If a `PointCloud` was passed, a `PointCloud` is returned. Only the connectivity information is propagated to the pointcloud (a subclass of `PointCloud` may be returned).
- **mapping_dict** (*ordereddict {str -> int ndarray}*, optional) – Only returned if `return_mapping==True`. Used for building `LabelledPointUndirectedGraph`.

Raises: *:map:'LabellingError'* – If the given labelled point graph/pointcloud contains less than the expected number of points.

eye_ibug_open_38_to_eye_ibug_open_38_trimesh

menpo.landmark.**eye_ibug_open_38_to_eye_ibug_open_38_trimesh**(*x*, *return_mapping=False*)

Apply the IBUG 38-point open eye semantic labels, with trimesh connectivity.

The semantic labels applied are as follows:

- tri

Parameters

- **x** (*LabelledPointUndirectedGraph* or *PointCloud* or *ndarray*) – The input labelled point graph, pointcloud, subclass of those or array to label. If a pointcloud is passed, then only the connectivity information is propagated to the pointcloud (a subclass of *PointCloud* may be returned).
- **return_mapping** (*bool*, optional) – Only applicable if a *PointCloud* or *ndarray* is passed. Returns the mapping dictionary which maps labels to indices into the resulting *PointCloud* (which is then used to for building a *LabelledPointUndirectedGraph*. This parameter is only provided for internal use so that other labellers can piggyback off one another.

Returns

- **x_labelled** (*LabelledPointUndirectedGraph* or *PointCloud*) – If a *LabelledPointUndirectedGraph* was passed, a *LabelledPointUndirectedGraph* is returned. This labelled pointgraph will contain specific labels and these labels may refer to sub-pointclouds with specific connectivity information.

  If a *PointCloud* was passed, a *PointCloud* is returned. Only the connectivity information is propagated to the pointcloud (a subclass of *PointCloud* may be returned).
- **mapping_dict** (*ordereddict* {*str* -> *int* *ndarray*}, optional) – Only returned if `return_mapping==True`. Used for building *LabelledPointUndirectedGraph*.

Raises: *:map:'LabellingError'* – If the given labelled point graph/pointcloud contains less than the expected number of points.

Human Hand

hand_ibug_39_to_hand_ibug_39

menpo.landmark.**hand_ibug_39_to_hand_ibug_39**(*x*, *return_mapping=False*)

Apply the IBUG 39-point semantic labels.

The semantic labels applied are as follows:

- thumb
- index
- middle
- ring
- pinky
- palm

Parameters

- **x** (`LabelledPointUndirectedGraph` or `PointCloud` or *ndarray*) – The input labelled point graph, pointcloud, subclass of those or array to label. If a pointcloud is passed, then only the connectivity information is propagated to the pointcloud (a subclass of `PointCloud` may be returned).
- **return_mapping** (*bool*, optional) – Only applicable if a `PointCloud` or *ndarray* is passed. Returns the mapping dictionary which maps labels to indices into the resulting `PointCloud` (which is then used to for building a `LabelledPointUndirectedGraph`. This parameter is only provided for internal use so that other labellers can piggyback off one another.

Returns

- **x_labelled** (`LabelledPointUndirectedGraph` or `PointCloud`) – If a `LabelledPointUndirectedGraph` was passed, a `LabelledPointUndirectedGraph` is returned. This labelled pointgraph will contain specific labels and these labels may refer to sub-pointclouds with specific connectivity information.

  If a `PointCloud` was passed, a `PointCloud` is returned. Only the connectivity information is propagated to the pointcloud (a subclass of `PointCloud` may be returned).
- **mapping_dict** (*ordereddict* {*str* -> *int ndarray*}, optional) – Only returned if `return_mapping==True`. Used for building `LabelledPointUndirectedGraph`.

Raises: *:map:'LabellingError'* – If the given labelled point graph/pointcloud contains less than the expected number of points.

Human Body Pose

pose_flic_11_to_pose_flic_11

`menpo.landmark.`**`pose_flic_11_to_pose_flic_11`**(*x*, *return_mapping=False*)

Apply the flic 11-point semantic labels.

The semantic labels applied are as follows:

- left_arm
- right_arm
- hips
- face

References

Parameters

- **x** (`LabelledPointUndirectedGraph` or `PointCloud` or *ndarray*) – The input labelled point graph, pointcloud, subclass of those or array to label. If a pointcloud is passed, then only the connectivity information is propagated to the pointcloud (a subclass of `PointCloud` may be returned).

- **return_mapping** (*bool*, optional) – Only applicable if a `PointCloud` or *ndarray* is passed. Returns the mapping dictionary which maps labels to indices into the resulting `PointCloud` (which is then used to for building a `LabelledPointUndirectedGraph`. This parameter is only provided for internal use so that other labellers can piggyback off one another.

Returns

- **x_labelled** (`LabelledPointUndirectedGraph` or `PointCloud`) – If a `LabelledPointUndirectedGraph` was passed, a `LabelledPointUndirectedGraph` is returned. This labelled pointgraph will contain specific labels and these labels may refer to sub-pointclouds with specific connectivity information.

  If a `PointCloud` was passed, a `PointCloud` is returned. Only the connectivity information is propagated to the pointcloud (a subclass of `PointCloud` may be returned).

- **mapping_dict** (*ordereddict* {*str* -> *int* *ndarray*}, optional) – Only returned if `return_mapping==True`. Used for building `LabelledPointUndirectedGraph`.

Raises: *:map:'LabellingError'* – If the given labelled point graph/pointcloud contains less than the expected number of points.

pose_human36M_32_to_pose_human36M_17

`menpo.landmark.`**`pose_human36M_32_to_pose_human36M_17`**(*x*, *return_mapping=False*)

Apply the human3.6M 17-point semantic labels (based on the original semantic labels of Human3.6 but removing the annotations corresponding to duplicate points, soles and palms), originally 32-points.

The semantic labels applied are as follows:

- pelvis
- right_leg
- left_leg
- spine
- head
- left_arm
- right_arm
- torso

References

Parameters

- **x** (`LabelledPointUndirectedGraph` or `PointCloud` or *ndarray*) – The input labelled point graph, pointcloud, subclass of those or array to label. If a pointcloud is passed, then only the connectivity information is propagated to the pointcloud (a subclass of `PointCloud` may be returned).

- **return_mapping** (*bool*, optional) – Only applicable if a `PointCloud` or *ndarray* is passed. Returns the mapping dictionary which maps labels to indices into the resulting `PointCloud` (which is then used to for building a `LabelledPointUndirectedGraph`. This parameter is only provided for internal use so that other labellers can piggyback off one another.

Returns

- **x_labelled** (`LabelledPointUndirectedGraph` or `PointCloud`) – If a `LabelledPointUndirectedGraph` was passed, a `LabelledPointUndirectedGraph` is returned. This labelled pointgraph will contain specific labels and these labels may refer to sub-pointclouds with specific connectivity information.

  If a `PointCloud` was passed, a `PointCloud` is returned. Only the connectivity information is propagated to the pointcloud (a subclass of `PointCloud` may be returned).

- **mapping_dict** (*ordereddict* {*str* -> *int* *ndarray*}, optional) – Only returned if `return_mapping==True`. Used for building `LabelledPointUndirectedGraph`.

Raises: *:map:'LabellingError'* – If the given labelled point graph/pointcloud contains less than the expected number of points.

pose_human36M_32_to_pose_human36M_32

`menpo.landmark.`**`pose_human36M_32_to_pose_human36M_32`**(*x*, *return_mapping=False*)

Apply the human3.6M 32-point semantic labels.

The semantic labels applied are as follows:

- pelvis
- right_leg
- left_leg
- spine
- head
- left_arm
- left_hand
- right_arm
- right_hand
- torso

References

Parameters

- **x** (`LabelledPointUndirectedGraph` or `PointCloud` or *ndarray*) – The input labelled point graph, pointcloud, subclass of those or array to label. If a pointcloud is passed, then only the connectivity information is propagated to the pointcloud (a subclass of `PointCloud` may be returned).

- **return_mapping** (*bool*, optional) – Only applicable if a `PointCloud` or *ndarray* is passed. Returns the mapping dictionary which maps labels to indices into the resulting `PointCloud` (which is then used to for building a `LabelledPointUndirectedGraph`. This parameter is only provided for internal use so that other labellers can piggyback off one another.

Returns

- **x_labelled** (`LabelledPointUndirectedGraph` or `PointCloud`) – If a `LabelledPointUndirectedGraph` was passed, a `LabelledPointUndirectedGraph` is returned. This labelled pointgraph will contain specific labels and these labels may refer to sub-pointclouds with specific connectivity information.

  If a `PointCloud` was passed, a `PointCloud` is returned. Only the connectivity information is propagated to the pointcloud (a subclass of `PointCloud` may be returned).

- **mapping_dict** (*ordereddict* {*str* -> *int* *ndarray*}, optional) – Only returned if `return_mapping==True`. Used for building `LabelledPointUndirectedGraph`.

Raises: *:map:'LabellingError'* – If the given labelled point graph/pointcloud contains less than the expected number of points.

pose_lsp_14_to_pose_lsp_14

`menpo.landmark.`**`pose_lsp_14_to_pose_lsp_14`**(*x*, *return_mapping=False*)

Apply the lsp 14-point semantic labels.

The semantic labels applied are as follows:

- left_leg
- right_leg
- left_arm
- right_arm
- head

References

Parameters

- **x** (`LabelledPointUndirectedGraph` or `PointCloud` or *ndarray*) – The input labelled point graph, pointcloud, subclass of those or array to label. If a pointcloud is passed, then only the connectivity information is propagated to the pointcloud (a subclass of `PointCloud` may be returned).

- **return_mapping** (*bool*, optional) – Only applicable if a `PointCloud` or *ndarray* is passed. Returns the mapping dictionary which maps labels to indices into the resulting `PointCloud` (which is then used to for building a `LabelledPointUndirectedGraph`. This parameter is only provided for internal use so that other labellers can piggyback off one another.

Returns

- **x_labelled** (*LabelledPointUndirectedGraph* or *PointCloud*) – If a *LabelledPointUndirectedGraph* was passed, a *LabelledPointUndirectedGraph* is returned. This labelled pointgraph will contain specific labels and these labels may refer to sub-pointclouds with specific connectivity information.

  If a *PointCloud* was passed, a *PointCloud* is returned. Only the connectivity information is propagated to the pointcloud (a subclass of *PointCloud* may be returned).

- **mapping_dict** (*ordereddict {str -> int ndarray}*, optional) – Only returned if `return_mapping==True`. Used for building *LabelledPointUndirectedGraph*.

Raises: *:map:'LabellingError'* – If the given labelled point graph/pointcloud contains less than the expected number of points.

pose_stickmen_12_to_pose_stickmen_12

`menpo.landmark.`**`pose_stickmen_12_to_pose_stickmen_12`**(*x*, *return_mapping=False*)

Apply the 'stickmen' 12-point semantic labels.

The semantic labels applied are as follows:

- torso
- right_upper_arm
- left_upper_arm
- right_lower_arm
- left_lower_arm
- head

References

Parameters

- **x** (*LabelledPointUndirectedGraph* or *PointCloud* or *ndarray*) – The input labelled point graph, pointcloud, subclass of those or array to label. If a pointcloud is passed, then only the connectivity information is propagated to the pointcloud (a subclass of *PointCloud* may be returned).

- **return_mapping** (*bool*, optional) – Only applicable if a *PointCloud* or *ndarray* is passed. Returns the mapping dictionary which maps labels to indices into the resulting *PointCloud* (which is then used to for building a *LabelledPointUndirectedGraph*. This parameter is only provided for internal use so that other labellers can piggyback off one another.

Returns

- **x_labelled** (*LabelledPointUndirectedGraph* or *PointCloud*) – If a *LabelledPointUndirectedGraph* was passed, a *LabelledPointUndirectedGraph* is returned. This labelled pointgraph will contain specific labels and these labels may refer to sub-pointclouds with specific connectivity information.

If a `PointCloud` was passed, a `PointCloud` is returned. Only the connectivity information is propagated to the pointcloud (a subclass of `PointCloud` may be returned).

- **mapping_dict** (*ordereddict {str -> int ndarray}*, optional) – Only returned if `return_mapping==True`. Used for building `LabelledPointUndirectedGraph`.

Raises: *:map:'LabellingError'* – If the given labelled point graph/pointcloud contains less than the expected number of points.

Car

car_streetscene_20_to_car_streetscene_view_0_8

`menpo.landmark.`**`car_streetscene_20_to_car_streetscene_view_0_8`**(*x*, *return_mapping=False*)

Apply the 8-point semantic labels of "view 0" from the MIT Street Scene Car dataset (originally a 20-point markup).

The semantic labels applied are as follows:

- front
- bonnet
- windshield

References

Parameters

- **x** (`LabelledPointUndirectedGraph` or `PointCloud` or *ndarray*) – The input labelled point graph, pointcloud, subclass of those or array to label. If a pointcloud is passed, then only the connectivity information is propagated to the pointcloud (a subclass of `PointCloud` may be returned).
- **return_mapping** (*bool*, optional) – Only applicable if a `PointCloud` or *ndarray* is passed. Returns the mapping dictionary which maps labels to indices into the resulting `PointCloud` (which is then used to for building a `LabelledPointUndirectedGraph`. This parameter is only provided for internal use so that other labellers can piggyback off one another.

Returns

- **x_labelled** (`LabelledPointUndirectedGraph` or `PointCloud`) – If a `LabelledPointUndirectedGraph` was passed, a `LabelledPointUndirectedGraph` is returned. This labelled pointgraph will contain specific labels and these labels may refer to sub-pointclouds with specific connectivity information.

  If a `PointCloud` was passed, a `PointCloud` is returned. Only the connectivity information is propagated to the pointcloud (a subclass of `PointCloud` may be returned).
- **mapping_dict** (*ordereddict {str -> int ndarray}*, optional) – Only returned if `return_mapping==True`. Used for building `LabelledPointUndirectedGraph`.

Raises: *:map:'LabellingError'* – If the given labelled point graph/pointcloud contains less than the expected number of points.

car_streetscene_20_to_car_streetscene_view_1_14

`menpo.landmark.`**`car_streetscene_20_to_car_streetscene_view_1_14`**(*x*, *return_mapping=False*)

Apply the 14-point semantic labels of "view 1" from the MIT Street Scene Car dataset (originally a 20-point markup).

The semantic labels applied are as follows:

- front
- bonnet
- windshield
- left_side

References

Parameters

- **x** (`LabelledPointUndirectedGraph` or `PointCloud` or *ndarray*) – The input labelled point graph, pointcloud, subclass of those or array to label. If a pointcloud is passed, then only the connectivity information is propagated to the pointcloud (a subclass of `PointCloud` may be returned).
- **return_mapping** (*bool*, optional) – Only applicable if a `PointCloud` or *ndarray* is passed. Returns the mapping dictionary which maps labels to indices into the resulting `PointCloud` (which is then used to for building a `LabelledPointUndirectedGraph`. This parameter is only provided for internal use so that other labellers can piggyback off one another.

Returns

- **x_labelled** (`LabelledPointUndirectedGraph` or `PointCloud`) – If a `LabelledPointUndirectedGraph` was passed, a `LabelledPointUndirectedGraph` is returned. This labelled pointgraph will contain specific labels and these labels may refer to sub-pointclouds with specific connectivity information.

  If a `PointCloud` was passed, a `PointCloud` is returned. Only the connectivity information is propagated to the pointcloud (a subclass of `PointCloud` may be returned).
- **mapping_dict** (*ordereddict* {*str* -> *int ndarray*}, optional) – Only returned if `return_mapping==True`. Used for building `LabelledPointUndirectedGraph`.

Raises: *:map:'LabellingError'* – If the given labelled point graph/pointcloud contains less than the expected number of points.

car_streetscene_20_to_car_streetscene_view_2_10

`menpo.landmark.car_streetscene_20_to_car_streetscene_view_2_10(x, return_mapping=False)`

Apply the 10-point semantic labels of "view 2" from the MIT Street Scene Car dataset (originally a 20-point markup).

The semantic labels applied are as follows:

- left_side

References

Parameters

- **x** (`LabelledPointUndirectedGraph` or `PointCloud` or *ndarray*) – The input labelled point graph, pointcloud, subclass of those or array to label. If a pointcloud is passed, then only the connectivity information is propagated to the pointcloud (a subclass of `PointCloud` may be returned).
- **return_mapping** (*bool*, optional) – Only applicable if a `PointCloud` or *ndarray* is passed. Returns the mapping dictionary which maps labels to indices into the resulting `PointCloud` (which is then used to for building a `LabelledPointUndirectedGraph`. This parameter is only provided for internal use so that other labellers can piggyback off one another.

Returns

- **x_labelled** (`LabelledPointUndirectedGraph` or `PointCloud`) – If a `LabelledPointUndirectedGraph` was passed, a `LabelledPointUndirectedGraph` is returned. This labelled pointgraph will contain specific labels and these labels may refer to sub-pointclouds with specific connectivity information.

  If a `PointCloud` was passed, a `PointCloud` is returned. Only the connectivity information is propagated to the pointcloud (a subclass of `PointCloud` may be returned).
- **mapping_dict** (*ordereddict* {*str* -> *int* *ndarray*}, optional) – Only returned if `return_mapping==True`. Used for building `LabelledPointUndirectedGraph`.

Raises: *:map:'LabellingError'* – If the given labelled point graph/pointcloud contains less than the expected number of points.

car_streetscene_20_to_car_streetscene_view_3_14

`menpo.landmark.car_streetscene_20_to_car_streetscene_view_3_14(x, return_mapping=False)`

Apply the 14-point semantic labels of "view 3" from the MIT Street Scene Car dataset (originally a 20-point markup).

The semantic labels applied are as follows:

- left_side
- rear windshield
- trunk

•rear

References

Parameters

•**x** (*LabelledPointUndirectedGraph* or *PointCloud* or *ndarray*) – The input labelled point graph, pointcloud, subclass of those or array to label. If a pointcloud is passed, then only the connectivity information is propagated to the pointcloud (a subclass of *PointCloud* may be returned).

•**return_mapping** (*bool*, optional) – Only applicable if a *PointCloud* or *ndarray* is passed. Returns the mapping dictionary which maps labels to indices into the resulting *PointCloud* (which is then used to for building a *LabelledPointUndirectedGraph*. This parameter is only provided for internal use so that other labellers can piggyback off one another.

Returns

•**x_labelled** (*LabelledPointUndirectedGraph* or *PointCloud*) – If a *LabelledPointUndirectedGraph* was passed, a *LabelledPointUndirectedGraph* is returned. This labelled pointgraph will contain specific labels and these labels may refer to sub-pointclouds with specific connectivity information.

If a *PointCloud* was passed, a *PointCloud* is returned. Only the connectivity information is propagated to the pointcloud (a subclass of *PointCloud* may be returned).

•**mapping_dict** (*ordereddict* {*str* -> *int ndarray*}, optional) – Only returned if `return_mapping==True`. Used for building *LabelledPointUndirectedGraph*.

Raises: *:map:'LabellingError'* – If the given labelled point graph/pointcloud contains less than the expected number of points.

car_streetscene_20_to_car_streetscene_view_4_14

`menpo.landmark.`**`car_streetscene_20_to_car_streetscene_view_4_14`**(*x*, *return_mapping=False*)

Apply the 14-point semantic labels of "view 4" from the MIT Street Scene Car dataset (originally a 20-point markup).

The semantic labels applied are as follows:

•front

•bonnet

•windshield

•right_side

References

Parameters

- **x** (*LabelledPointUndirectedGraph* or *PointCloud* or *ndarray*) – The input labelled point graph, pointcloud, subclass of those or array to label. If a pointcloud is passed, then only the connectivity information is propagated to the pointcloud (a subclass of *PointCloud* may be returned).
- **return_mapping** (*bool*, optional) – Only applicable if a *PointCloud* or *ndarray* is passed. Returns the mapping dictionary which maps labels to indices into the resulting *PointCloud* (which is then used to for building a *LabelledPointUndirectedGraph*. This parameter is only provided for internal use so that other labellers can piggyback off one another.

Returns

- **x_labelled** (*LabelledPointUndirectedGraph* or *PointCloud*) – If a *LabelledPointUndirectedGraph* was passed, a *LabelledPointUndirectedGraph* is returned. This labelled pointgraph will contain specific labels and these labels may refer to sub-pointclouds with specific connectivity information.

  If a *PointCloud* was passed, a *PointCloud* is returned. Only the connectivity information is propagated to the pointcloud (a subclass of *PointCloud* may be returned).
- **mapping_dict** (*ordereddict* {*str* -> *int ndarray*}, optional) – Only returned if `return_mapping==True`. Used for building *LabelledPointUndirectedGraph*.

Raises: *:map:'LabellingError'* – If the given labelled point graph/pointcloud contains less than the expected number of points.

car_streetscene_20_to_car_streetscene_view_5_10

`menpo.landmark.`**`car_streetscene_20_to_car_streetscene_view_5_10`**(*x*, *return_mapping=False*)

Apply the 10-point semantic labels of "view 5" from the MIT Street Scene Car dataset (originally a 20-point markup).

The semantic labels applied are as follows:

- right_side

References

Parameters

- **x** (*LabelledPointUndirectedGraph* or *PointCloud* or *ndarray*) – The input labelled point graph, pointcloud, subclass of those or array to label. If a pointcloud is passed, then only the connectivity information is propagated to the pointcloud (a subclass of *PointCloud* may be returned).
- **return_mapping** (*bool*, optional) – Only applicable if a *PointCloud* or *ndarray* is passed. Returns the mapping dictionary which maps labels to indices into the resulting *PointCloud* (which is then used to for building a *LabelledPointUndirectedGraph*. This parameter is only provided for internal use so that other labellers can piggyback off one another.

Returns

- **x_labelled** (*LabelledPointUndirectedGraph* or *PointCloud*) – If a *LabelledPointUndirectedGraph* was passed, a *LabelledPointUndirectedGraph* is returned. This labelled pointgraph will contain specific labels and these labels may refer to sub-pointclouds with specific connectivity information.

  If a *PointCloud* was passed, a *PointCloud* is returned. Only the connectivity information is propagated to the pointcloud (a subclass of *PointCloud* may be returned).

- **mapping_dict** (*ordereddict {str -> int ndarray}*, optional) – Only returned if `return_mapping==True`. Used for building *LabelledPointUndirectedGraph*.

Raises: *:map:'LabellingError'* – If the given labelled point graph/pointcloud contains less than the expected number of points.

car_streetscene_20_to_car_streetscene_view_6_14

`menpo.landmark.`**`car_streetscene_20_to_car_streetscene_view_6_14`**(*x*, *return_mapping=False*)

Apply the 14-point semantic labels of "view 6" from the MIT Street Scene Car dataset (originally a 20-point markup).

The semantic labels applied are as follows:

- right_side
- rear_windshield
- trunk
- rear

References

Parameters

- **x** (*LabelledPointUndirectedGraph* or *PointCloud* or *ndarray*) – The input labelled point graph, pointcloud, subclass of those or array to label. If a pointcloud is passed, then only the connectivity information is propagated to the pointcloud (a subclass of *PointCloud* may be returned).

- **return_mapping** (*bool*, optional) – Only applicable if a *PointCloud* or *ndarray* is passed. Returns the mapping dictionary which maps labels to indices into the resulting *PointCloud* (which is then used to for building a *LabelledPointUndirectedGraph*. This parameter is only provided for internal use so that other labellers can piggyback off one another.

Returns

- **x_labelled** (*LabelledPointUndirectedGraph* or *PointCloud*) – If a *LabelledPointUndirectedGraph* was passed, a *LabelledPointUndirectedGraph* is returned. This labelled pointgraph will contain specific labels and these labels may refer to sub-pointclouds with specific connectivity information.

  If a *PointCloud* was passed, a *PointCloud* is returned. Only the connectivity information is propagated to the pointcloud (a subclass of *PointCloud* may be returned).

- **mapping_dict** (*ordereddict {str -> int ndarray}*, optional) – Only returned if `return_mapping==True`. Used for building `LabelledPointUndirectedGraph`.

Raises: *:map:'LabellingError'* – If the given labelled point graph/pointcloud contains less than the expected number of points.

car_streetscene_20_to_car_streetscene_view_7_8

`menpo.landmark.`**`car_streetscene_20_to_car_streetscene_view_7_8`**(*x*, *return_mapping=False*)

Apply the 8-point semantic labels of "view 7" from the MIT Street Scene Car dataset (originally a 20-point markup).

The semantic labels applied are as follows:

- rear_windshield
- trunk
- rear

References

Parameters

- **x** (`LabelledPointUndirectedGraph` or `PointCloud` or *ndarray*) – The input labelled point graph, pointcloud, subclass of those or array to label. If a pointcloud is passed, then only the connectivity information is propagated to the pointcloud (a subclass of `PointCloud` may be returned).
- **return_mapping** (*bool*, optional) – Only applicable if a `PointCloud` or *ndarray* is passed. Returns the mapping dictionary which maps labels to indices into the resulting `PointCloud` (which is then used to for building a `LabelledPointUndirectedGraph`. This parameter is only provided for internal use so that other labellers can piggyback off one another.

Returns

- **x_labelled** (`LabelledPointUndirectedGraph` or `PointCloud`) – If a `LabelledPointUndirectedGraph` was passed, a `LabelledPointUndirectedGraph` is returned. This labelled pointgraph will contain specific labels and these labels may refer to sub-pointclouds with specific connectivity information.

  If a `PointCloud` was passed, a `PointCloud` is returned. Only the connectivity information is propagated to the pointcloud (a subclass of `PointCloud` may be returned).
- **mapping_dict** (*ordereddict {str -> int ndarray}*, optional) – Only returned if `return_mapping==True`. Used for building `LabelledPointUndirectedGraph`.

Raises: *:map:'LabellingError'* – If the given labelled point graph/pointcloud contains less than the expected number of points.

Human Tongue

tongue_ibug_19_to_tongue_ibug_19

`menpo.landmark.tongue_ibug_19_to_tongue_ibug_19`(*x*, *return_mapping=False*)

Apply the IBUG 19-point tongue semantic labels.

The semantic labels applied are as follows:

- outline
- bisector

Parameters

- **x** (`LabelledPointUndirectedGraph` or `PointCloud` or *ndarray*) – The input labelled point graph, pointcloud, subclass of those or array to label. If a pointcloud is passed, then only the connectivity information is propagated to the pointcloud (a subclass of `PointCloud` may be returned).
- **return_mapping** (*bool*, optional) – Only applicable if a `PointCloud` or *ndarray* is passed. Returns the mapping dictionary which maps labels to indices into the resulting `PointCloud` (which is then used to for building a `LabelledPointUndirectedGraph`. This parameter is only provided for internal use so that other labellers can piggyback off one another.

Returns

- **x_labelled** (`LabelledPointUndirectedGraph` or `PointCloud`) – If a `LabelledPointUndirectedGraph` was passed, a `LabelledPointUndirectedGraph` is returned. This labelled pointgraph will contain specific labels and these labels may refer to sub-pointclouds with specific connectivity information.

  If a `PointCloud` was passed, a `PointCloud` is returned. Only the connectivity information is propagated to the pointcloud (a subclass of `PointCloud` may be returned).
- **mapping_dict** (*ordereddict* {*str* -> *int* *ndarray*}, optional) – Only returned if `return_mapping==True`. Used for building `LabelledPointUndirectedGraph`.

Raises: *:map:'LabellingError'* – If the given labelled point graph/pointcloud contains less than the expected number of points.

menpo.math

Decomposition

eigenvalue_decomposition

`menpo.math.eigenvalue_decomposition`(*C*, *is_inverse=False*, *eps=1e-10*)

Eigenvalue decomposition of a given covariance (or scatter) matrix.

Parameters

- **C** (`(N, N)` *ndarray* or *scipy.sparse*) – The Covariance/Scatter matrix. If it is a *numpy.array*, then *numpy.linalg.eigh* is used. If it is an instance of *scipy.sparse*, then

scipy.sparse.linalg.eigsh is used. If it is a precision matrix (inverse covariance), then set *is_inverse=True*.

- **is_inverse** (*bool*, optional) – It `True`, then it is assumed that *C* is a precision matrix (inverse covariance). Thus, the eigenvalues will be inverted. If `False`, then it is assumed that *C* is a covariance matrix.
- **eps** (*float*, optional) – Tolerance value for positive eigenvalue. Those eigenvalues smaller than the specified eps value, together with their corresponding eigenvectors, will be automatically discarded. The final limit is computed as

```
limit = np.max(np.abs(eigenvalues)) * eps
```

Returns

- **pos_eigenvectors** (`(N, p)` *ndarray*) – The matrix with the eigenvectors corresponding to positive eigenvalues.
- **pos_eigenvalues** (`(p,)` *ndarray*) – The array of positive eigenvalues.

pca

`menpo.math.`**`pca`**(*X*, *centre=True*, *inplace=False*, *eps=1e-10*)

Apply Principal Component Analysis (PCA) on the data matrix *X*. In the case where the data matrix is very large, it is advisable to set `inplace = True`. However, note this destructively edits the data matrix by subtracting the mean inplace.

Parameters

- **X** (`(n_samples, n_dims)` *ndarray*) – Data matrix.
- **centre** (*bool*, optional) – Whether to centre the data matrix. If *False*, zero will be subtracted.
- **inplace** (*bool*, optional) – Whether to do the mean subtracting inplace or not. This is crucial if the data matrix is greater than half the available memory size.
- **eps** (*float*, optional) – Tolerance value for positive eigenvalue. Those eigenvalues smaller than the specified eps value, together with their corresponding eigenvectors, will be automatically discarded.

Returns

- **U (eigenvectors)** (`(``(n_components, n_dims))`` *ndarray*) – Eigenvectors of the data matrix.
- **l (eigenvalues)** (`(n_components,)` *ndarray*) – Positive eigenvalues of the data matrix.
- **m (mean vector)** (`(n_dimensions,)` *ndarray*) – Mean that was subtracted from the data matrix.

pcacov

`menpo.math.`**`pcacov`**(*C*, *is_inverse=False*, *eps=1e-05*)

Apply Principal Component Analysis (PCA) given a covariance/scatter matrix *C*. In the case where the data matrix is very large, it is advisable to set `inplace = True`. However, note this destructively edits the data matrix by subtracting the mean inplace.

Parameters

- **C** (`(N, N)` *ndarray* or *scipy.sparse*) – The Covariance/Scatter matrix. If it is a precision matrix (inverse covariance), then set *is_inverse=True*.
- **is_inverse** (*bool*, optional) – It `True`, then it is assumed that *C* is a precision matrix (inverse covariance). Thus, the eigenvalues will be inverted. If `False`, then it is assumed that *C* is a covariance matrix.
- **eps** (*float*, optional) – Tolerance value for positive eigenvalue. Those eigenvalues smaller than the specified eps value, together with their corresponding eigenvectors, will be automatically discarded.

Returns

- **U (eigenvectors)** (`(n_components, n_dims)` *ndarray*) – Eigenvectors of the data matrix.
- **l (eigenvalues)** (`(n_components,)` *ndarray*) – Positive eigenvalues of the data matrix.

ipca

`menpo.math.`**`ipca`**(*B*, *U_a*, *l_a*, *n_a*, *m_a=None*, *f=1.0*, *eps=1e-10*)

Perform Incremental PCA on the eigenvectors `U_a`, eigenvalues `l_a` and mean vector `m_a` (if present) given a new data matrix `B`.

Parameters

- **B** (`(n_samples, n_dims)` *ndarray*) – New data matrix.
- **U_a** (`(n_components, n_dims)` *ndarray*) – Eigenvectors to be updated.
- **l_a** ((n_components) *ndarray*) – Eigenvalues to be updated.
- **n_a** (*int*) – Total number of samples used to produce U_a, s_a and m_a.
- **m_a** (`(n_dims,)` *ndarray*, optional) – Mean to be updated. If `None` or `(n_dims,)` *ndarray* filled with 0s the data matrix will not be centred.
- **f** (`[0, 1]` *float*, optional) – Forgetting factor that weights the relative contribution of new samples vs old samples. If 1.0, all samples are weighted equally and, hence, the results is the exact same as performing batch PCA on the concatenated list of old and new simples. If <1.0, more emphasis is put on the new samples. See [1] for details.
- **eps** (*float*, optional) – Tolerance value for positive eigenvalue. Those eigenvalues smaller than the specified eps value, together with their corresponding eigenvectors, will be automatically discarded.

Returns

- **U (eigenvectors)** (`(n_components, n_dims)` *ndarray*) – Updated eigenvectors.
- **s (eigenvalues)** (`(n_components,)` *ndarray*) – Updated positive eigenvalues.
- **m (mean vector)** (`(n_dims,)` *ndarray*) – Updated mean.

References

Linear Algebra

dot_inplace_right

`menpo.math.`**`dot_inplace_right`**(*a*, *b*, *block_size=1000*)

Inplace dot product for memory efficiency. It computes `a * b = c` where `b` will be replaced inplace with `c`.

Parameters

- **a** (`(n_small, k)` *ndarray*, n_small <= k) – The first array to dot - assumed to be small. `n_small` must be smaller than `k` so the result can be stored within the memory space of `b`.
- **b** (`(k, n_big)` *ndarray*) – Second array to dot - assumed to be large. Will be damaged by this function call as it is used to store the output inplace.
- **block_size** (*int*, optional) – The size of the block of `b` that `a` will be dotted against in each iteration. larger block sizes increase the time performance of the dot product at the cost of a higher memory overhead for the operation.

Returnsc (`(n_small, n_big)` *ndarray*) – The output of the operation. Exactly the same as a memory view onto `b` (`b[:n_small]`) as `b` is modified inplace to store the result.

dot_inplace_left

`menpo.math.`**`dot_inplace_left`**(*a*, *b*, *block_size=1000*)

Inplace dot product for memory efficiency. It computes `a * b = c`, where `a` will be replaced inplace with `c`.

Parameters

- **a** (`(n_big, k)` *ndarray*) – First array to dot - assumed to be large. Will be damaged by this function call as it is used to store the output inplace.
- **b** (`(k, n_small)` *ndarray*, `n_small <= k`) – The second array to dot - assumed to be small. `n_small` must be smaller than `k` so the result can be stored within the memory space of `a`.
- **block_size** (*int*, optional) – The size of the block of `a` that will be dotted against `b` in each iteration. larger block sizes increase the time performance of the dot product at the cost of a higher memory overhead for the operation.

Returnsc (`(n_big, n_small)` *ndarray*) – The output of the operation. Exactly the same as a memory view onto `a` (`a[:, :n_small]`) as `a` is modified inplace to store the result.

as_matrix

`menpo.math.`**`as_matrix`**(*vectorizables*, *length=None*, *return_template=False*, *verbose=False*)

Create a matrix from a list/generator of `Vectorizable` objects. All the objects in the list **must** be the same size when vectorized.

Consider using a generator if the matrix you are creating is large and passing the length of the generator explicitly.

Parameters

- **vectorizables** (*list* or generator if `Vectorizable` objects) – A list or generator of objects that supports the vectorizable interface
- **length** (*int*, optional) – Length of the vectorizable list. Useful if you are passing a generator with a known length.
- **verbose** (*bool*, optional) – If `True`, will print the progress of building the matrix.

- **return_template** (*bool*, optional) – If `True`, will return the first element of the list/generator, which was used as the template. Useful if you need to map back from the matrix to a list of vectorizable objects.

Returns

- **M** ((length, n_features) *ndarray*) – Every row is an element of the list.
- **template** (`Vectorizable`, optional) – If `return_template == True`, will return the template used to build the matrix *M*.

Raises `ValueError` – `vectorizables` terminates in fewer than `length` iterations

from_matrix

`menpo.math.`**`from_matrix`**(*matrix*, *template*)

Create a generator from a matrix given a template `Vectorizable` objects as a template. The `from_vector` method will be used to reconstruct each object.

If you want a list, warp the returned value in `list()`.

Parameters

- **matrix** ((n_items, n_features) *ndarray*) – A matrix whereby every *row* represents the data of a vectorizable object.
- **template** (`Vectorizable`) – The template object to use to reconstruct each row of the matrix with.

Returns **vectorizables** (generator of `Vectorizable`) – Every row of the matrix becomes an element of the list.

Convolution

log_gabor

`menpo.math.`**`log_gabor`**(*image*, ***kwargs*)

Creates a log-gabor filter bank, including smoothing the images via a low-pass filter at the edges.

To create a 2D filter bank, simply specify the number of phi orientations (orientations in the xy-plane).

To create a 3D filter bank, you must specify both the number of phi (azimuth) and theta (elevation) orientations.

This algorithm is directly derived from work by Peter Kovesi.

Parameters

- **image** (`(M, N, ...)` *ndarray*) – Image to be convolved
- **num_scales** (*int*, optional) – Number of wavelet scales.

Default 2D	4
Default 3D	4

- **num_phi_orientations** (*int*, optional) – Number of filter orientations in the xy-plane

Default 2D	6
Default 3D	6

- **num_theta_orientations** (*int*, optional) – **Only required for 3D**. Number of filter orientations in the z-plane

Default 2D	N/A
Default 3D	4

- **min_wavelength** (*int*, optional) – Wavelength of smallest scale filter.

Default 2D	3
Default 3D	3

- **scaling_constant** (*int*, optional) – Scaling factor between successive filters.

Default 2D	2
Default 3D	2

- **center_sigma** (*float*, optional) – Ratio of the standard deviation of the Gaussian describing the Log Gabor filter's transfer function in the frequency domain to the filter centre frequency.

Default 2D	0.65
Default 3D	0.65

- **d_phi_sigma** (*float*, optional) – Angular bandwidth in xy-plane

Default 2D	1.3
Default 3D	1.5

- **d_theta_sigma** (*float*, optional) – **Only required for 3D**. Angular bandwidth in z-plane

Default 2D	N/A
Default 3D	1.5

Returns

- **complex_conv** (`(num_scales, num_orientations, image.shape)` *ndarray*) – Complex valued convolution results. The real part is the result of convolving with the even symmetric filter, the imaginary part is the result from convolution with the odd symmetric filter.
- **bandpass** (`(num_scales, image.shape)` *ndarray*) – Bandpass images corresponding to each scale *s*
- **S** (`(image.shape,)` *ndarray*) – Convolved image

Examples

Return the magnitude of the convolution over the image at scale *s* and orientation *o*

```
np.abs(complex_conv[s, o, :, :])
```

Return the phase angles

```
np.angle(complex_conv[s, o, :, :])
```

References

menpo.model

Abstract Classes

LinearModel

menpo.model.**LinearModel**
alias of *LinearVectorModel*

LinearVectorModel

class menpo.model.**LinearVectorModel**(*components*)
Bases: *Copyable*

A Linear Model contains a matrix of vector components, each component vector being made up of *features*.

Parameters components ((n_components, n_features) *ndarray*) – The components array.

component(*index*)
A particular component of the model.

Parameters index (*int*) – The component that is to be returned.

Returns component_vector ((n_features,) *ndarray*) – The component vector.

copy()
Generate an efficient copy of this object.

Note that Numpy arrays and other *Copyable* objects on self will be deeply copied. Dictionaries and sets will be shallow copied, and everything else will be assigned (no copy will be made).

Classes that store state other than numpy arrays and immutable types should overwrite this method to ensure all state is copied.

Returns type(self) – A copy of this object

instance(*weights*)
Creates a new vector instance of the model by weighting together the components.

Parameters weights ((n_weights,) *ndarray* or *list*) – The weightings for the first *n_weights* components that should be used.

weights[j] is the linear contribution of the j'th principal component to the instance vector.

Returns vector ((n_features,) *ndarray*) – The instance vector for the weighting provided.

instance_vectors(*weights*)
Creates new vectorized instances of the model using all the components of the linear model.

Parameters weights ((n_vectors, n_weights) *ndarray* or *list* of *lists*) – The weightings for all components of the linear model. All components will be used to produce the instance.

weights[i, j] is the linear contribution of the j'th principal component to the i'th instance vector produced.

Raises ValueError – If n_weights > n_available_components

Returnsvectors ((n_vectors, n_features) *ndarray*) – The instance vectors for the weighting provided.

orthonormalize_against_inplace(*linear_model*)

Enforces that the union of this model's components and another are both mutually orthonormal.

Both models keep its number of components unchanged or else a value error is raised.

Parameterslinear_model (*LinearVectorModel*) – A second linear model to orthonormalize this against.

RaisesValueError – The number of features must be greater or equal than the sum of the number of components in both linear models ({} < {})

orthonormalize_inplace()

Enforces that this model's components are orthonormalized, s.t. `component_vector(i).dot(component_vector(j) = dirac_delta`.

project(*vector*)

Projects the *vector* onto the model, retrieving the optimal linear reconstruction weights.

Parametersvector ((n_features,) *ndarray*) – A vectorized novel instance.

Returnsweights ((n_components,) *ndarray*) – A vector of optimal linear weights.

project_out(*vector*)

Returns a version of *vector* where all the basis of the model have been projected out.

Parametersvector ((n_features,) *ndarray*) – A novel vector.

Returnsprojected_out ((n_features,) *ndarray*) – A copy of *vector* with all basis of the model projected out.

project_out_vectors(*vectors*)

Returns a version of *vectors* where all the basis of the model have been projected out.

Parametersvectors ((n_vectors, n_features) *ndarray*) – A matrix of novel vectors.

Returnsprojected_out ((n_vectors, n_features) *ndarray*) – A copy of *vectors* with all basis of the model projected out.

project_vectors(*vectors*)

Projects each of the *vectors* onto the model, retrieving the optimal linear reconstruction weights for each instance.

Parametersvectors ((n_samples, n_features) *ndarray*) – Array of vectorized novel instances.

Returnsweights ((n_samples, n_components) *ndarray*) – The matrix of optimal linear weights.

reconstruct(*vector*)

Project a *vector* onto the linear space and rebuild from the weights found.

Parametersvector ((n_features,) *ndarray*) – A vectorized novel instance to project.

Returnsreconstructed ((n_features,) *ndarray*) – The reconstructed vector.

reconstruct_vectors(*vectors*)

Projects the *vectors* onto the linear space and rebuilds vectors from the weights found.

Parametersvectors ((n_vectors, n_features) *ndarray*) – A set of vectors to project.

Returnsreconstructed ((n_vectors, n_features) *ndarray*) – The reconstructed vectors.

components
The components matrix of the linear model.

Type (n_available_components, n_features) *ndarray*

n_components
The number of bases of the model.

Type *int*

n_features
The number of elements in each linear component.

Type *int*

MeanLinearModel

menpo.model.**MeanLinearModel**
alias of *MeanLinearVectorModel*

MeanLinearVectorModel

class menpo.model.**MeanLinearVectorModel**(*components*, *mean*)
Bases: LinearVectorModel

A Linear Model containing a matrix of vector components, each component vector being made up of *features*. The model additionally has a mean component which is handled accordingly when either:

1. A component of the model is selected
2. A projection operation is performed

Parameters

- **components** ((n_components, n_features) *ndarray*) – The components array.
- **mean** ((n_features,) *ndarray*) – The mean vector.

component(*index*, *with_mean=True*, *scale=1.0*)
A particular component of the model, in vectorized form.

Parameters

- **index** (*int*) – The component that is to be returned
- **with_mean** (*bool*, optional) – If True, the component will be blended with the mean vector before being returned. If not, the component is returned on it's own.
- **scale** (*float*, optional) – A scale factor that should be directly applied to the component. Only valid in the case where with_mean == True.

Returns **component_vector** ((n_features,) *ndarray*) – The component vector.

copy()
Generate an efficient copy of this object.

Note that Numpy arrays and other *Copyable* objects on self will be deeply copied. Dictionaries and sets will be shallow copied, and everything else will be assigned (no copy will be made).

Classes that store state other than numpy arrays and immutable types should overwrite this method to ensure all state is copied.

Returns `type(self)` – A copy of this object

instance(*weights*)

Creates a new vector instance of the model by weighting together the components.

Parameters **weights** (`(n_weights,)` *ndarray* or *list*) – The weightings for the first *n_weights* components that should be used.

`weights[j]` is the linear contribution of the j'th principal component to the instance vector.

Returns **vector** (`(n_features,)` *ndarray*) – The instance vector for the weighting provided.

instance_vectors(*weights*)

Creates new vectorized instances of the model using all the components of the linear model.

Parameters **weights** (`(n_vectors, n_weights)` *ndarray* or *list* of *lists*) – The weightings for all components of the linear model. All components will be used to produce the instance.

`weights[i, j]` is the linear contribution of the j'th principal component to the i'th instance vector produced.

Raises `ValueError` – If n_weights > n_available_components

Returns **vectors** (`(n_vectors, n_features)` *ndarray*) – The instance vectors for the weighting provided.

mean()

Return the mean of the model.

Type *ndarray*

orthonormalize_against_inplace(*linear_model*)

Enforces that the union of this model's components and another are both mutually orthonormal.

Both models keep its number of components unchanged or else a value error is raised.

Parameters **linear_model** (*LinearVectorModel*) – A second linear model to orthonormalize this against.

Raises `ValueError` – The number of features must be greater or equal than the sum of the number of components in both linear models ({} < {})

orthonormalize_inplace()

Enforces that this model's components are orthonormalized, s.t. `component_vector(i).dot(component_vector(j) = dirac_delta`.

project(*vector*)

Projects the *vector* onto the model, retrieving the optimal linear reconstruction weights.

Parameters **vector** (`(n_features,)` *ndarray*) – A vectorized novel instance.

Returns **weights** (`(n_components,)` *ndarray*) – A vector of optimal linear weights.

project_out(*vector*)

Returns a version of *vector* where all the basis of the model have been projected out.

Parameters **vector** (`(n_features,)` *ndarray*) – A novel vector.

Returns **projected_out** (`(n_features,)` *ndarray*) – A copy of *vector* with all basis of the model projected out.

project_out_vectors(*vectors*)

Returns a version of *vectors* where all the bases of the model have been projected out.

Parameters
vectors ((n_vectors, n_features) *ndarray*) – A matrix of novel vectors.

Returns
projected_out ((n_vectors, n_features) *ndarray*) – A copy of *vectors* with all bases of the model projected out.

project_vectors(*vectors*)
Projects each of the *vectors* onto the model, retrieving the optimal linear reconstruction weights for each instance.

Parameters
vectors ((n_samples, n_features) *ndarray*) – Array of vectorized novel instances.

Returns
projected ((n_samples, n_components) *ndarray*) – The matrix of optimal linear weights.

reconstruct(*vector*)
Project a *vector* onto the linear space and rebuild from the weights found.

Parameters
vector ((n_features,) *ndarray*) – A vectorized novel instance to project.

Returns
reconstructed ((n_features,) *ndarray*) – The reconstructed vector.

reconstruct_vectors(*vectors*)
Projects the *vectors* onto the linear space and rebuilds vectors from the weights found.

Parameters
vectors ((n_vectors, n_features) *ndarray*) – A set of vectors to project.

Returns
reconstructed ((n_vectors, n_features) *ndarray*) – The reconstructed vectors.

components
The components matrix of the linear model.

Type (n_available_components, n_features) *ndarray*

n_components
The number of bases of the model.

Type *int*

n_features
The number of elements in each linear component.

Type *int*

Principal Component Analysis

PCAModel

class menpo.model.**PCAModel**(*samples*, *centre=True*, *n_samples=None*, *max_n_components=None*, *inplace=True*, *verbose=False*)
Bases: VectorizableBackedModel, PCAVectorModel

A MeanLinearModel where components are Principal Components and the components are vectorized instances.

Principal Component Analysis (PCA) by eigenvalue decomposition of the data's scatter matrix. For details of the implementation of PCA, see *pca*.

Parameters

- **samples** (*list* or *iterable* of *Vectorizable*) – List or iterable of samples to build the model from.

- **centre** (*bool*, optional) – When `True` (default) PCA is performed after mean centering the data. If `False` the data is assumed to be centred, and the mean will be `0`.
- **n_samples** (*int*, optional) – If provided then `samples` must be an iterator that yields `n_samples`. If not provided then samples has to be a *list* (so we know how large the data matrix needs to be).
- **max_n_components** (*int*, optional) – The maximum number of components to keep in the model. Any components above and beyond this one are discarded.
- **inplace** (*bool*, optional) – If `True` the data matrix is modified in place. Otherwise, the data matrix is copied.
- **verbose** (*bool*, optional) – Whether to print building information or not.

component(*index*, *with_mean=True*, *scale=1.0*)

Return a particular component of the linear model.

Parameters

- **index** (*int*) – The component that is to be returned
- **with_mean** (*bool*, optional) – If `True`, the component will be blended with the mean vector before being returned. If not, the component is returned on it's own.
- **scale** (*float*, optional) – A scale factor that should be applied to the component. Only valid in the case where `with_mean == True`. See *component_vector()* for how this scale factor is interpreted.

Returnscomponent (*type(self.template_instance)*) – The requested component instance.

component_vector(**args*, ***kwargs*)

A particular component of the model.

Parametersindex (*int*) – The component that is to be returned.

Returnscomponent (*type(self.template_instance)*) – The component instance.

copy()

Generate an efficient copy of this object.

Note that Numpy arrays and other *Copyable* objects on `self` will be deeply copied. Dictionaries and sets will be shallow copied, and everything else will be assigned (no copy will be made).

Classes that store state other than numpy arrays and immutable types should overwrite this method to ensure all state is copied.

Returns`type(self)` – A copy of this object

eigenvalues_cumulative_ratio()

Returns the cumulative ratio between the variance captured by the active components and the total amount of variance present on the original samples.

Returnseigenvalues_cumulative_ratio (`(n_active_components,)` *ndarray*) – Array of cumulative eigenvalues.

eigenvalues_ratio()

Returns the ratio between the variance captured by each active component and the total amount of variance present on the original samples.

Returnseigenvalues_ratio (`(n_active_components,)` *ndarray*) – The active eigenvalues array scaled by the original variance.

increment(*samples*, *n_samples=None*, *forgetting_factor=1.0*, *verbose=False*)

Update the eigenvectors, eigenvalues and mean vector of this model by performing incremental PCA on the given samples.

Parameters

- **samples** (*list* of `Vectorizable`) – List of new samples to update the model from.
- **n_samples** (*int*, optional) – If provided then `samples` must be an iterator that yields `n_samples`. If not provided then samples has to be a list (so we know how large the data matrix needs to be).
- **forgetting_factor** (`[0.0, 1.0]` *float*, optional) – Forgetting factor that weights the relative contribution of new samples vs old samples. If 1.0, all samples are weighted equally and, hence, the results is the exact same as performing batch PCA on the concatenated list of old and new simples. If <1.0, more emphasis is put on the new samples. See [1] for details.

References

---

classmethod init_from_components(*components*, *eigenvalues*, *mean*, *n_samples*, *centred*, *max_n_components=None*)

Build the Principal Component Analysis (PCA) using the provided components (eigenvectors) and eigenvalues.

Parameters

- **components** (`(n_components, n_features)` *ndarray*) – The eigenvectors to be used.
- **eigenvalues** (`(n_components, )` *ndarray*) – The corresponding eigenvalues.
- **mean** (`Vectorizable`) – The mean instance. It must be a `Vectorizable` and *not* an *ndarray*.
- **n_samples** (*int*) – The number of samples used to generate the eigenvectors.
- **centred** (*bool*, optional) – When `True` we assume that the data were centered before computing the eigenvectors.
- **max_n_components** (*int*, optional) – The maximum number of components to keep in the model. Any components above and beyond this one are discarded.

classmethod init_from_covariance_matrix(*C*, *mean*, *n_samples*, *centred=True*, *is_inverse=False*, *max_n_components=None*)

Build the Principal Component Analysis (PCA) by eigenvalue decomposition of the provided covariance/scatter matrix. For details of the implementation of PCA, see `pcacov`.

Parameters

- **C** (`(n_features, n_features)` *ndarray* or *scipy.sparse*) – The Covariance/Scatter matrix. If it is a precision matrix (inverse covariance), then set *is_inverse=True*.
- **mean** (`Vectorizable`) – The mean instance. It must be a `Vectorizable` and *not* an *ndarray*.
- **n_samples** (*int*) – The number of samples used to generate the covariance matrix.
- **centred** (*bool*, optional) – When `True` we assume that the data were centered before computing the covariance matrix.

- **is_inverse** (*bool*, optional) – It `True`, then it is assumed that *C* is a precision matrix (inverse covariance). Thus, the eigenvalues will be inverted. If `False`, then it is assumed that *C* is a covariance matrix.
- **max_n_components** (*int*, optional) – The maximum number of components to keep in the model. Any components above and beyond this one are discarded.

instance(*weights*, *normalized_weights=False*)

Creates a new instance of the model using the first `len(weights)` components.

Parameters

- **weights** (`(n_weights,)` *ndarray* or *list*) – `weights[i]` is the linear contribution of the i'th component to the instance vector.
- **normalized_weights** (*bool*, optional) – If `True`, the weights are assumed to be normalized w.r.t the eigenvalues. This can be easier to create unique instances by making the weights more interpretable.

Raises `ValueError` – If n_weights > n_components

Returns **instance** (*type(self.template_instance)*) – An instance of the model.

instance_vector(**args*, ***kwargs*)

Creates a new instance of the model using the first `len(weights)` components.

Parameters **weights** (`(n_weights,)` *ndarray* or *list*) – `weights[i]` is the linear contribution of the i'th component to the instance vector.

Raises `ValueError` – If n_weights > n_components

Returns **instance** (*type(self.template_instance)*) – An instance of the model.

instance_vectors(*weights*, *normalized_weights=False*)

Creates new vectorized instances of the model using the first components in a particular weighting.

Parameters

- **weights** (`(n_vectors, n_weights)` *ndarray* or *list* of *lists*) – The weightings for the first *n_weights* components that should be used per instance that is to be produced

  `weights[i, j]` is the linear contribution of the j'th principal component to the i'th instance vector produced. Note that if `n_weights < n_components`, only the first `n_weight` components are used in the reconstruction (i.e. unspecified weights are implicitly `0`).
- **normalized_weights** (*bool*, optional) – If `True`, the weights are assumed to be normalized w.r.t the eigenvalues. This can be easier to create unique instances by making the weights more interpretable.

Returns **vectors** (`(n_vectors, n_features)` *ndarray*) – The instance vectors for the weighting provided.

Raises `ValueError` – If n_weights > n_components

inverse_noise_variance()

Returns the inverse of the noise variance.

Returns **inverse_noise_variance** (*float*) – Inverse of the noise variance.

Raises `ValueError` – If `noise_variance() == 0`

mean()

Return the mean of the model.

Type *Vectorizable*

noise_variance()

Returns the average variance captured by the inactive components, i.e. the sample noise assumed in a Probabilistic PCA formulation.

If all components are active, then `noise_variance == 0.0`.

Returns **noise_variance** (*float*) – The mean variance of the inactive components.

noise_variance_ratio()

Returns the ratio between the noise variance and the total amount of variance present on the original samples.

Returns **noise_variance_ratio** (*float*) – The ratio between the noise variance and the variance present in the original samples.

original_variance()

Returns the total amount of variance captured by the original model, i.e. the amount of variance present on the original samples.

Returns **optional_variance** (*float*) – The variance captured by the model.

orthonormalize_against_inplace(*linear_model*)

Enforces that the union of this model's components and another are both mutually orthonormal.

Note that the model passed in is guaranteed to not have it's number of available components changed. This model, however, may loose some dimensionality due to reaching a degenerate state.

The removed components will always be trimmed from the end of components (i.e. the components which capture the least variance). If trimming is performed, *n_components* and *n_available_components* would be altered - see *trim_components()* for details.

Parameters **linear_model** (`LinearModel`) – A second linear model to orthonormalize this against.

orthonormalize_inplace()

Enforces that this model's components are orthonormalized, s.t. `component_vector(i).dot(component_vector(j) = dirac_delta`.

plot_eigenvalues(*figure_id=None*, *new_figure=False*, *render_lines=True*, *line_colour='b'*, *line_style='-'*, *line_width=2*, *render_markers=True*, *marker_style='o'*, *marker_size=6*, *marker_face_colour='b'*, *marker_edge_colour='k'*, *marker_edge_width=1.0*, *render_axes=True*, *axes_font_name='sans-serif'*, *axes_font_size=10*, *axes_font_style='normal'*, *axes_font_weight='normal'*, *figure_size=(10, 6)*, *render_grid=True*, *grid_line_style='–'*, *grid_line_width=0.5*)

Plot of the eigenvalues.

Parameters

- **figure_id** (*object*, optional) – The id of the figure to be used.
- **new_figure** (*bool*, optional) – If `True`, a new figure is created.
- **render_lines** (*bool*, optional) – If `True`, the line will be rendered.
- **line_colour** (*See Below, optional*) – The colour of the lines. Example options

```
{``r``, ``g``, ``b``, ``c``, ``m``, ``k``, ``w``}
or
``(3, )`` `ndarray`
```

```
or
`list` of length ``3``
```

- **line_style** ({-, --, -., :}, optional) – The style of the lines.
- **line_width** (*float*, optional) – The width of the lines.
- **render_markers** (*bool*, optional) – If `True`, the markers will be rendered.
- **marker_style** (*See Below, optional*) – The style of the markers. Example options

```
{``.``, ``,``, ``o``, ``v``, ``^``, ``<``, ``>``, ``+``,
 ``x``, ``D``, ``d``, ``s``, ``p``, ``*``, ``h``, ``H``,
 ``1``, ``2``, ``3``, ``4``, ``8``}
```

- **marker_size** (*int*, optional) – The size of the markers in points.
- **marker_face_colour** (*See Below, optional*) – The face (filling) colour of the markers. Example options

```
{``r``, ``g``, ``b``, ``c``, ``m``, ``k``, ``w``}
or
``(3, )`` `ndarray`
or
`list` of length ``3``
```

- **marker_edge_colour** (*See Below, optional*) – The edge colour of the markers. Example options

```
{``r``, ``g``, ``b``, ``c``, ``m``, ``k``, ``w``}
or
``(3, )`` `ndarray`
or
`list` of length ``3``
```

- **marker_edge_width** (*float*, optional) – The width of the markers' edge.
- **render_axes** (*bool*, optional) – If `True`, the axes will be rendered.
- **axes_font_name** (*See Below, optional*) – The font of the axes. Example options

```
{``serif``, ``sans-serif``, ``cursive``, ``fantasy``,
 ``monospace``}
```

- **axes_font_size** (*int*, optional) – The font size of the axes.
- **axes_font_style** ({`normal`, `italic`, `oblique`}, optional) – The font style of the axes.
- **axes_font_weight** (*See Below, optional*) – The font weight of the axes. Example options

```
{``ultralight``, ``light``, ``normal``, ``regular``,
 ``book``, ``medium``, ``roman``, ``semibold``,
 ``demibold``, ``demi``, ``bold``, ``heavy``,
 ``extra bold``, ``black``}
```

- **figure_size** ((*float*, *float*) or `None`, optional) – The size of the figure in inches.

- **render_grid** (*bool*, optional) – If `True`, the grid will be rendered.
- **grid_line_style** ({`-`, `--`, `-.`, `:`}, optional) – The style of the grid lines.
- **grid_line_width** (*float*, optional) – The width of the grid lines.

Returns **viewer** (`MatplotlibRenderer`) – The viewer object.

plot_eigenvalues_cumulative_ratio(*figure_id=None, new_figure=False, render_lines=True, line_colour='b', line_style='-', line_width=2, render_markers=True, marker_style='o', marker_size=6, marker_face_colour='b', marker_edge_colour='k', marker_edge_width=1.0, render_axes=True, axes_font_name='sans-serif', axes_font_size=10, axes_font_style='normal', axes_font_weight='normal', figure_size=(10, 6), render_grid=True, grid_line_style='–', grid_line_width=0.5*)

Plot of the cumulative variance ratio captured by the eigenvalues.

Parameters

- **figure_id** (*object*, optional) – The id of the figure to be used.
- **new_figure** (*bool*, optional) – If `True`, a new figure is created.
- **render_lines** (*bool*, optional) – If `True`, the line will be rendered.
- **line_colour** (*See Below, optional*) – The colour of the lines. Example options

```
{``r``, ``g``, ``b``, ``c``, ``m``, ``k``, ``w``}
or
``(3, )`` `ndarray`
or
`list` of length ``3``
```

- **line_style** ({`-`, `--`, `-.`, `:`}, optional) – The style of the lines.
- **line_width** (*float*, optional) – The width of the lines.
- **render_markers** (*bool*, optional) – If `True`, the markers will be rendered.
- **marker_style** (*See Below, optional*) – The style of the markers. Example options

```
{``.``, ``,``, ``o``, ``v``, ``^``, ``<``, ``>``, ``+``,
 ``x``, ``D``, ``d``, ``s``, ``p``, ``*``, ``h``, ``H``,
 ``1``, ``2``, ``3``, ``4``, ``8``}
```

- **marker_size** (*int*, optional) – The size of the markers in points.
- **marker_face_colour** (*See Below, optional*) – The face (filling) colour of the markers. Example options

```
{``r``, ``g``, ``b``, ``c``, ``m``, ``k``, ``w``}
or
``(3, )`` `ndarray`
or
`list` of length ``3``
```

- **marker_edge_colour** (*See Below, optional*) – The edge colour of the markers. Example options

```
{``r``, ``g``, ``b``, ``c``, ``m``, ``k``, ``w``}
or
``(3, )`` `ndarray`
or
`list` of length ``3``
```

- **marker_edge_width** (*float*, optional) – The width of the markers' edge.
- **render_axes** (*bool*, optional) – If `True`, the axes will be rendered.
- **axes_font_name** (*See Below, optional*) – The font of the axes. Example options

```
{``serif``, ``sans-serif``, ``cursive``, ``fantasy``,
 ``monospace``}
```

- **axes_font_size** (*int*, optional) – The font size of the axes.
- **axes_font_style** ({`normal`, `italic`, `oblique`}, optional) – The font style of the axes.
- **axes_font_weight** (*See Below, optional*) – The font weight of the axes. Example options

```
{``ultralight``, ``light``, ``normal``, ``regular``,
 ``book``, ``medium``, ``roman``, ``semibold``,
 ``demibold``, ``demi``, ``bold``, ``heavy``,
 ``extra bold``, ``black``}
```

- **figure_size** ((*float*, *float*) or *None*, optional) – The size of the figure in inches.
- **render_grid** (*bool*, optional) – If `True`, the grid will be rendered.
- **grid_line_style** ({`-`, `--`, `-.`, `:`}, optional) – The style of the grid lines.
- **grid_line_width** (*float*, optional) – The width of the grid lines.

Returns **viewer** (*MatplotlibRenderer*) – The viewer object.

plot_eigenvalues_cumulative_ratio_widget (*figure_size=(10, 6), style='coloured'*)

Plot of the cumulative variance ratio captured by the eigenvalues using an interactive widget.

Parameters

- **figure_size** ((*float*, *float*) or `None`, optional) – The size of the figure in inches.
- **style** ({`'coloured'`, `'minimal'`}, optional) – If `'coloured'`, then the style of the widget will be coloured. If `minimal`, then the style is simple using black and white colours.

plot_eigenvalues_ratio (*figure_id=None, new_figure=False, render_lines=True, line_colour='b', line_style='-', line_width=2, render_markers=True, marker_style='o', marker_size=6, marker_face_colour='b', marker_edge_colour='k', marker_edge_width=1.0, render_axes=True, axes_font_name='sans-serif', axes_font_size=10, axes_font_style='normal', axes_font_weight='normal', figure_size=(10, 6), render_grid=True, grid_line_style='–', grid_line_width=0.5*)

Plot of the variance ratio captured by the eigenvalues.

Parameters

- **figure_id** (*object*, optional) – The id of the figure to be used.
- **new_figure** (*bool*, optional) – If `True`, a new figure is created.
- **render_lines** (*bool*, optional) – If `True`, the line will be rendered.
- **line_colour** (*See Below, optional*) – The colour of the lines. Example options

```
{``r``, ``g``, ``b``, ``c``, ``m``, ``k``, ``w``}
or
``(3, )`` `ndarray`
or
`list` of length ``3``
```

- **line_style** ({`-`, `--`, `-.`, `:`}, optional) – The style of the lines.
- **line_width** (*float*, optional) – The width of the lines.
- **render_markers** (*bool*, optional) – If `True`, the markers will be rendered.
- **marker_style** (*See Below, optional*) – The style of the markers. Example options

```
{``.``, ``,``, ``o``, ``v``, ``^``, ``<``, ``>``, ``+``,
 ``x``, ``D``, ``d``, ``s``, ``p``, ``*``, ``h``, ``H``,
 ``1``, ``2``, ``3``, ``4``, ``8``}
```

- **marker_size** (*int*, optional) – The size of the markers in points.
- **marker_face_colour** (*See Below, optional*) – The face (filling) colour of the markers. Example options

```
{``r``, ``g``, ``b``, ``c``, ``m``, ``k``, ``w``}
or
``(3, )`` `ndarray`
or
`list` of length ``3``
```

- **marker_edge_colour** (*See Below, optional*) – The edge colour of the markers. Example options

```
{``r``, ``g``, ``b``, ``c``, ``m``, ``k``, ``w``}
or
``(3, )`` `ndarray`
or
`list` of length ``3``
```

- **marker_edge_width** (*float*, optional) – The width of the markers' edge.
- **render_axes** (*bool*, optional) – If `True`, the axes will be rendered.
- **axes_font_name** (*See Below, optional*) – The font of the axes. Example options

```
{``serif``, ``sans-serif``, ``cursive``, ``fantasy``,
 ``monospace``}
```

- **axes_font_size** (*int*, optional) – The font size of the axes.

- **axes_font_style** ({normal, italic, oblique}, optional) – The font style of the axes.
- **axes_font_weight** (*See Below, optional*) – The font weight of the axes. Example options

```
{``ultralight``, ``light``, ``normal``, ``regular``,
 ``book``, ``medium``, ``roman``, ``semibold``,
 ``demibold``, ``demi``, ``bold``, ``heavy``,
 ``extra bold``, ``black``}
```

- **figure_size** ((*float*, *float*) or *None*, optional) – The size of the figure in inches.
- **render_grid** (*bool*, optional) – If True, the grid will be rendered.
- **grid_line_style** ({-, --, -., :}, optional) – The style of the grid lines.
- **grid_line_width** (*float*, optional) – The width of the grid lines.

Returns **viewer** (*MatplotlibRenderer*) – The viewer object.

plot_eigenvalues_ratio_widget (*figure_size=(10, 6)*, *style='coloured'*)

Plot of the variance ratio captured by the eigenvalues using an interactive widget.

Parameters

- **figure_size** ((*float*, *float*) or None, optional) – The size of the figure in inches.
- **style** ({'coloured', 'minimal'}, optional) – If 'coloured', then the style of the widget will be coloured. If minimal, then the style is simple using black and white colours.

plot_eigenvalues_widget (*figure_size=(10, 6)*, *style='coloured'*)

Plot of the eigenvalues using an interactive widget.

Parameters

- **figure_size** ((*float*, *float*) or None, optional) – The size of the figure in inches.
- **style** ({'coloured', 'minimal'}, optional) – If 'coloured', then the style of the widget will be coloured. If minimal, then the style is simple using black and white colours.

project (*instance*)

Projects the *instance* onto the model, retrieving the optimal linear weightings.

Parameters **instance** (*Vectorizable*) – A novel instance.

Returns **projected** ((n_components,) *ndarray*) – A vector of optimal linear weightings.

project_out (*instance*)

Returns a version of *instance* where all the basis of the model have been projected out.

Parameters **instance** (Vectorizable) – A novel instance of Vectorizable.

Returns **projected_out** (*self.instance_class*) – A copy of *instance*, with all basis of the model projected out.

project_out_vector (**args*, ***kwargs*)

Returns a version of *instance* where all the basis of the model have been projected out.

Parameters **instance** (Vectorizable) – A novel instance of Vectorizable.

Returns **projected_out** (*self.instance_class*) – A copy of *instance*, with all basis of the model projected out.

project_out_vectors(*vectors*)

Returns a version of *vectors* where all the bases of the model have been projected out.

Parameters **vectors** ((n_vectors, n_features) *ndarray*) – A matrix of novel vectors.

Returns **projected_out** ((n_vectors, n_features) *ndarray*) – A copy of *vectors* with all bases of the model projected out.

project_vector(**args*, ***kwargs*)

Projects the *instance* onto the model, retrieving the optimal linear weightings.

Parameters **instance** (Vectorizable) – A novel instance.

Returns **projected** ((n_components,) *ndarray*) – A vector of optimal linear weightings.

project_vectors(*vectors*)

Projects each of the *vectors* onto the model, retrieving the optimal linear reconstruction weights for each instance.

Parameters **vectors** ((n_samples, n_features) *ndarray*) – Array of vectorized novel instances.

Returns **projected** ((n_samples, n_components) *ndarray*) – The matrix of optimal linear weights.

project_whitened(*instance*)

Projects the *instance* onto the whitened components, retrieving the whitened linear weightings.

Parameters **instance** (Vectorizable) – A novel instance.

Returns **projected** (*(n_components,)*) – A vector of whitened linear weightings

project_whitened_vector(**args*, ***kwargs*)

Projects the *vector_instance* onto the whitened components, retrieving the whitened linear weightings.

Parameters **vector_instance** ((n_features,) *ndarray*) – A novel vector.

Returns **projected** ((n_features,) *ndarray*) – A vector of whitened linear weightings

reconstruct(*instance*)

Projects a *instance* onto the linear space and rebuilds from the weights found.

Syntactic sugar for:

```
instance(project(instance))
```

but faster, as it avoids the conversion that takes place each time.

Parameters **instance** (Vectorizable) – A novel instance of Vectorizable.

Returns **reconstructed** (*self.instance_class*) – The reconstructed object.

reconstruct_vector(**args*, ***kwargs*)

Projects a *instance* onto the linear space and rebuilds from the weights found.

Syntactic sugar for:

```
instance(project(instance))
```

but faster, as it avoids the conversion that takes place each time.

Parameters **instance** (Vectorizable) – A novel instance of Vectorizable.

Returns **reconstructed** (*self.instance_class*) – The reconstructed object.

reconstruct_vectors(*vectors*)

Projects the *vectors* onto the linear space and rebuilds vectors from the weights found.

Parametersvectors ((n_vectors, n_features) *ndarray*) – A set of vectors to project.

Returnsreconstructed ((n_vectors, n_features) *ndarray*) – The reconstructed vectors.

trim_components(*n_components=None*)

Permanently trims the components down to a certain amount. The number of active components will be automatically reset to this particular value.

This will reduce *self.n_components* down to *n_components* (if None, *self.n_active_components* will be used), freeing up memory in the process.

Once the model is trimmed, the trimmed components cannot be recovered.

Parametersn_components (*int* >= 1 or *float* > 0.0 or None, optional) – The number of components that are kept or else the amount (ratio) of variance that is kept. If None, *self.n_active_components* is used.

Notes

In case *n_components* is greater than the total number of components or greater than the amount of variance currently kept, this method does not perform any action.

---

variance()

Returns the total amount of variance retained by the active components.

Returnsvariance (*float*) – Total variance captured by the active components.

variance_ratio()

Returns the ratio between the amount of variance retained by the active components and the total amount of variance present on the original samples.

Returnsvariance_ratio (*float*) – Ratio of active components variance and total variance present in original samples.

view_widget (*figure_size=(7, 7)*)

Visualizes the model using an interactive widget. It only works if it is a 2D/3D shape or appearance model.

Parametersfigure_size ((*int*, *int*), optional) – The initial size of the rendered figure.

whitened_components()

Returns the active components of the model, whitened.

Returnswhitened_components ((n_active_components, n_features) *ndarray*) – The whitened components.

components

Returns the active components of the model.

Type (n_active_components, n_features) *ndarray*

eigenvalues

Returns the eigenvalues associated with the active components of the model, i.e. the amount of variance captured by each active component, sorted form largest to smallest.

Type (n_active_components,) *ndarray*

mean_vector

Return the mean of the model as a 1D vector.

Type*ndarray*

n_active_components
The number of components currently in use on this model.

Type*int*

n_components
The number of bases of the model.

Type*int*

n_features
The number of elements in each linear component.

Type*int*

PCAVectorModel

class `menpo.model.`**`PCAVectorModel`**(*samples*, *centre=True*, *n_samples=None*, *max_n_components=None*, *inplace=True*)

Bases: `MeanLinearVectorModel`

A `MeanLinearModel` where components are Principal Components.

Principal Component Analysis (PCA) by eigenvalue decomposition of the data's scatter matrix. For details of the implementation of PCA, see *`pca`*.

Parameters

- **samples** (*ndarray* or *list* or *iterable* of *ndarray*) – List or iterable of numpy arrays to build the model from, or an existing data matrix.
- **centre** (*bool*, optional) – When `True` (default) PCA is performed after mean centering the data. If `False` the data is assumed to be centred, and the mean will be `0`.
- **n_samples** (*int*, optional) – If provided then `samples` must be an iterator that yields `n_samples`. If not provided then samples has to be a *list* (so we know how large the data matrix needs to be).
- **max_n_components** (*int*, optional) – The maximum number of components to keep in the model. Any components above and beyond this one are discarded.
- **inplace** (*bool*, optional) – If `True` the data matrix is modified in place. Otherwise, the data matrix is copied.

component(*index*, *with_mean=True*, *scale=1.0*)
A particular component of the model, in vectorized form.

Parameters

- **index** (*int*) – The component that is to be returned
- **with_mean** (*bool*, optional) – If `True`, the component will be blended with the mean vector before being returned. If not, the component is returned on it's own.
- **scale** (*float*, optional) – A scale factor that should be applied to the component. Only valid in the case where with_mean is `True`. The scale is applied in units of standard deviations (so a scale of `1.0` *with_mean* visualizes the mean plus `1` std. dev of the component in question).

Returnscomponent_vector (`(n_features,)` *ndarray*) – The component vector of the given index.

copy()

Generate an efficient copy of this object.

Note that Numpy arrays and other `Copyable` objects on `self` will be deeply copied. Dictionaries and sets will be shallow copied, and everything else will be assigned (no copy will be made).

Classes that store state other than numpy arrays and immutable types should overwrite this method to ensure all state is copied.

Returns `type(self)` – A copy of this object

eigenvalues_cumulative_ratio()

Returns the cumulative ratio between the variance captured by the active components and the total amount of variance present on the original samples.

Returns **eigenvalues_cumulative_ratio** (`(n_active_components,)` *ndarray*) – Array of cumulative eigenvalues.

eigenvalues_ratio()

Returns the ratio between the variance captured by each active component and the total amount of variance present on the original samples.

Returns **eigenvalues_ratio** (`(n_active_components,)` *ndarray*) – The active eigenvalues array scaled by the original variance.

increment(*data*, *n_samples=None*, *forgetting_factor=1.0*, *verbose=False*)

Update the eigenvectors, eigenvalues and mean vector of this model by performing incremental PCA on the given samples.

Parameters

- **samples** (*list* of `Vectorizable`) – List of new samples to update the model from.
- **n_samples** (*int*, optional) – If provided then `samples` must be an iterator that yields `n_samples`. If not provided then samples has to be a list (so we know how large the data matrix needs to be).
- **forgetting_factor** (`[0.0, 1.0]` *float*, optional) – Forgetting factor that weights the relative contribution of new samples vs old samples. If 1.0, all samples are weighted equally and, hence, the results is the exact same as performing batch PCA on the concatenated list of old and new simples. If <1.0, more emphasis is put on the new samples. See [1] for details.

References

---

classmethod **init_from_components**(*components*, *eigenvalues*, *mean*, *n_samples*, *centred*, *max_n_components=None*)

Build the Principal Component Analysis (PCA) using the provided components (eigenvectors) and eigenvalues.

Parameters

- **components** (`(n_components, n_features)` *ndarray*) – The eigenvectors to be used.
- **eigenvalues** (`(n_components, )` *ndarray*) – The corresponding eigenvalues.
- **mean** (`(n_features, )` *ndarray*) – The mean vector.
- **n_samples** (*int*) – The number of samples used to generate the eigenvectors.

- **centred** (*bool*) – When `True` we assume that the data were centered before computing the eigenvectors.
- **max_n_components** (*int*, optional) – The maximum number of components to keep in the model. Any components above and beyond this one are discarded.

classmethod init_from_covariance_matrix(*C*, *mean*, *n_samples*, *centred=True*, *is_inverse=False*, *max_n_components=None*)

Build the Principal Component Analysis (PCA) by eigenvalue decomposition of the provided covariance/scatter matrix. For details of the implementation of PCA, see `pcacov`.

Parameters

- **C** (`(n_features, n_features)` *ndarray* or *scipy.sparse*) – The Covariance/Scatter matrix. If it is a precision matrix (inverse covariance), then set *is_inverse=True*.
- **mean** (`(n_features, )` *ndarray*) – The mean vector.
- **n_samples** (*int*) – The number of samples used to generate the covariance matrix.
- **centred** (*bool*, optional) – When `True` we assume that the data were centered before computing the covariance matrix.
- **is_inverse** (*bool*, optional) – It `True`, then it is assumed that *C* is a precision matrix (inverse covariance). Thus, the eigenvalues will be inverted. If `False`, then it is assumed that *C* is a covariance matrix.
- **max_n_components** (*int*, optional) – The maximum number of components to keep in the model. Any components above and beyond this one are discarded.

instance(*weights*, *normalized_weights=False*)

Creates a new vector instance of the model by weighting together the components.

Parameters

- **weights** (`(n_weights,)` *ndarray* or *list*) – The weightings for the first *n_weights* components that should be used.

  `weights[j]` is the linear contribution of the j'th principal component to the instance vector.
- **normalized_weights** (*bool*, optional) – If `True`, the weights are assumed to be normalized w.r.t the eigenvalues. This can be easier to create unique instances by making the weights more interpretable.

Returnsvector (`(n_features,)` *ndarray*) – The instance vector for the weighting provided.

instance_vectors(*weights*, *normalized_weights=False*)

Creates new vectorized instances of the model using the first components in a particular weighting.

Parameters

- **weights** (`(n_vectors, n_weights)` *ndarray* or *list* of *lists*) – The weightings for the first *n_weights* components that should be used per instance that is to be produced

  `weights[i, j]` is the linear contribution of the j'th principal component to the i'th instance vector produced. Note that if `n_weights < n_components`, only the first `n_weight` components are used in the reconstruction (i.e. unspecified weights are implicitly `0`).
- **normalized_weights** (*bool*, optional) – If `True`, the weights are assumed to be normalized w.r.t the eigenvalues. This can be easier to create unique instances by making the weights more interpretable.

Returnsvectors ((n_vectors, n_features) *ndarray*) – The instance vectors for the weighting provided.

RaisesValueError – If n_weights > n_components

inverse_noise_variance()

Returns the inverse of the noise variance.

Returnsinverse_noise_variance (*float*) – Inverse of the noise variance.

RaisesValueError – If noise_variance() == 0

mean()

Return the mean of the model.

Type*ndarray*

noise_variance()

Returns the average variance captured by the inactive components, i.e. the sample noise assumed in a Probabilistic PCA formulation.

If all components are active, then noise_variance == 0.0.

Returnsnoise_variance (*float*) – The mean variance of the inactive components.

noise_variance_ratio()

Returns the ratio between the noise variance and the total amount of variance present on the original samples.

Returnsnoise_variance_ratio (*float*) – The ratio between the noise variance and the variance present in the original samples.

original_variance()

Returns the total amount of variance captured by the original model, i.e. the amount of variance present on the original samples.

Returnsoptional_variance (*float*) – The variance captured by the model.

orthonormalize_against_inplace(*linear_model*)

Enforces that the union of this model's components and another are both mutually orthonormal.

Note that the model passed in is guaranteed to not have it's number of available components changed. This model, however, may loose some dimensionality due to reaching a degenerate state.

The removed components will always be trimmed from the end of components (i.e. the components which capture the least variance). If trimming is performed, *n_components* and *n_available_components* would be altered - see *trim_components()* for details.

Parameterslinear_model (LinearModel) – A second linear model to orthonormalize this against.

orthonormalize_inplace()

Enforces that this model's components are orthonormalized, s.t. component_vector(i).dot(component_vector(j) = dirac_delta.

plot_eigenvalues(*figure_id=None*, *new_figure=False*, *render_lines=True*, *line_colour='b'*, *line_style='-'*, *line_width=2*, *render_markers=True*, *marker_style='o'*, *marker_size=6*, *marker_face_colour='b'*, *marker_edge_colour='k'*, *marker_edge_width=1.0*, *render_axes=True*, *axes_font_name='sans-serif'*, *axes_font_size=10*, *axes_font_style='normal'*, *axes_font_weight='normal'*, *figure_size=(10, 6)*, *render_grid=True*, *grid_line_style='–'*, *grid_line_width=0.5*)

Plot of the eigenvalues.

Parameters

- **figure_id** (*object*, optional) – The id of the figure to be used.
- **new_figure** (*bool*, optional) – If `True`, a new figure is created.
- **render_lines** (*bool*, optional) – If `True`, the line will be rendered.
- **line_colour** (*See Below, optional*) – The colour of the lines. Example options

```
{``r``, ``g``, ``b``, ``c``, ``m``, ``k``, ``w``}
or
``(3, )`` `ndarray`
or
`list` of length ``3``
```

- **line_style** ({`-`, `--`, `-.`, `:`}, optional) – The style of the lines.
- **line_width** (*float*, optional) – The width of the lines.
- **render_markers** (*bool*, optional) – If `True`, the markers will be rendered.
- **marker_style** (*See Below, optional*) – The style of the markers. Example options

```
{``.``, ``,``, ``o``, ``v``, ``^``, ``<``, ``>``, ``+``,
 ``x``, ``D``, ``d``, ``s``, ``p``, ``*``, ``h``, ``H``,
 ``1``, ``2``, ``3``, ``4``, ``8``}
```

- **marker_size** (*int*, optional) – The size of the markers in points.
- **marker_face_colour** (*See Below, optional*) – The face (filling) colour of the markers. Example options

```
{``r``, ``g``, ``b``, ``c``, ``m``, ``k``, ``w``}
or
``(3, )`` `ndarray`
or
`list` of length ``3``
```

- **marker_edge_colour** (*See Below, optional*) – The edge colour of the markers. Example options

```
{``r``, ``g``, ``b``, ``c``, ``m``, ``k``, ``w``}
or
``(3, )`` `ndarray`
or
`list` of length ``3``
```

- **marker_edge_width** (*float*, optional) – The width of the markers' edge.
- **render_axes** (*bool*, optional) – If `True`, the axes will be rendered.
- **axes_font_name** (*See Below, optional*) – The font of the axes. Example options

```
{``serif``, ``sans-serif``, ``cursive``, ``fantasy``,
 ``monospace``}
```

- **axes_font_size** (*int*, optional) – The font size of the axes.
- **axes_font_style** ({`normal`, `italic`, `oblique`}, optional) – The font style of the axes.

- **axes_font_weight** (*See Below, optional*) – The font weight of the axes. Example options

```
{``ultralight``, ``light``, ``normal``, ``regular``,
 ``book``, ``medium``, ``roman``, ``semibold``,
 ``demibold``, ``demi``, ``bold``, ``heavy``,
 ``extra bold``, ``black``}
```

- **figure_size** ((*float*, *float*) or `None`, optional) – The size of the figure in inches.
- **render_grid** (*bool*, optional) – If `True`, the grid will be rendered.
- **grid_line_style** ({`-`, `--`, `-.`, `:`}, optional) – The style of the grid lines.
- **grid_line_width** (*float*, optional) – The width of the grid lines.

Returns **viewer** (`MatplotlibRenderer`) – The viewer object.

plot_eigenvalues_cumulative_ratio(*figure_id=None, new_figure=False, render_lines=True, line_colour='b', line_style='-', line_width=2, render_markers=True, marker_style='o', marker_size=6, marker_face_colour='b', marker_edge_colour='k', marker_edge_width=1.0, render_axes=True, axes_font_name='sans-serif', axes_font_size=10, axes_font_style='normal', axes_font_weight='normal', figure_size=(10, 6), render_grid=True, grid_line_style='–', grid_line_width=0.5*)

Plot of the cumulative variance ratio captured by the eigenvalues.

Parameters

- **figure_id** (*object*, optional) – The id of the figure to be used.
- **new_figure** (*bool*, optional) – If `True`, a new figure is created.
- **render_lines** (*bool*, optional) – If `True`, the line will be rendered.
- **line_colour** (*See Below, optional*) – The colour of the lines. Example options

```
{``r``, ``g``, ``b``, ``c``, ``m``, ``k``, ``w``}
or
``(3, )`` `ndarray`
or
`list` of length ``3``
```

- **line_style** ({`-`, `--`, `-.`, `:`}, optional) – The style of the lines.
- **line_width** (*float*, optional) – The width of the lines.
- **render_markers** (*bool*, optional) – If `True`, the markers will be rendered.
- **marker_style** (*See Below, optional*) – The style of the markers. Example options

```
{``.``, ``,``, ``o``, ``v``, ``^``, ``<``, ``>``, ``+``,
 ``x``, ``D``, ``d``, ``s``, ``p``, ``*``, ``h``, ``H``,
 ``1``, ``2``, ``3``, ``4``, ``8``}
```

- **marker_size** (*int*, optional) – The size of the markers in points.

- **marker_face_colour** (*See Below, optional*) – The face (filling) colour of the markers. Example options

```
{``r``, ``g``, ``b``, ``c``, ``m``, ``k``, ``w``}
or
``(3, )`` `ndarray`
or
`list` of length ``3``
```

- **marker_edge_colour** (*See Below, optional*) – The edge colour of the markers. Example options

```
{``r``, ``g``, ``b``, ``c``, ``m``, ``k``, ``w``}
or
``(3, )`` `ndarray`
or
`list` of length ``3``
```

- **marker_edge_width** (*float*, optional) – The width of the markers' edge.
- **render_axes** (*bool*, optional) – If `True`, the axes will be rendered.
- **axes_font_name** (*See Below, optional*) – The font of the axes. Example options

```
{``serif``, ``sans-serif``, ``cursive``, ``fantasy``,
 ``monospace``}
```

- **axes_font_size** (*int*, optional) – The font size of the axes.
- **axes_font_style** ({`normal`, `italic`, `oblique`}, optional) – The font style of the axes.
- **axes_font_weight** (*See Below, optional*) – The font weight of the axes. Example options

```
{``ultralight``, ``light``, ``normal``, ``regular``,
 ``book``, ``medium``, ``roman``, ``semibold``,
 ``demibold``, ``demi``, ``bold``, ``heavy``,
 ``extra bold``, ``black``}
```

- **figure_size** ((*float*, *float*) or *None*, optional) – The size of the figure in inches.
- **render_grid** (*bool*, optional) – If `True`, the grid will be rendered.
- **grid_line_style** ({`-`, `--`, `-.`, `:`}, optional) – The style of the grid lines.
- **grid_line_width** (*float*, optional) – The width of the grid lines.

Returns **viewer** (*`MatplotlibRenderer`*) – The viewer object.

plot_eigenvalues_cumulative_ratio_widget(*figure_size=(10, 6)*, *style='coloured'*)

Plot of the cumulative variance ratio captured by the eigenvalues using an interactive widget.

Parameters

- **figure_size** ((*float*, *float*) or `None`, optional) – The size of the figure in inches.
- **style** ({`'coloured'`, `'minimal'`}, optional) – If `'coloured'`, then the style of the widget will be coloured. If `minimal`, then the style is simple using black and white colours.

plot_eigenvalues_ratio(*figure_id=None*, *new_figure=False*, *render_lines=True*, *line_colour='b'*, *line_style='-'*, *line_width=2*, *render_markers=True*, *marker_style='o'*, *marker_size=6*, *marker_face_colour='b'*, *marker_edge_colour='k'*, *marker_edge_width=1.0*, *render_axes=True*, *axes_font_name='sans-serif'*, *axes_font_size=10*, *axes_font_style='normal'*, *axes_font_weight='normal'*, *figure_size=(10, 6)*, *render_grid=True*, *grid_line_style='–'*, *grid_line_width=0.5*)

Plot of the variance ratio captured by the eigenvalues.

Parameters

- **figure_id** (*object*, optional) – The id of the figure to be used.
- **new_figure** (*bool*, optional) – If `True`, a new figure is created.
- **render_lines** (*bool*, optional) – If `True`, the line will be rendered.
- **line_colour** (*See Below, optional*) – The colour of the lines. Example options

```
{``r``, ``g``, ``b``, ``c``, ``m``, ``k``, ``w``}
or
``(3, )`` `ndarray`
or
`list` of length ``3``
```

- **line_style** ({`-`, `--`, `-.`, `:`}, optional) – The style of the lines.
- **line_width** (*float*, optional) – The width of the lines.
- **render_markers** (*bool*, optional) – If `True`, the markers will be rendered.
- **marker_style** (*See Below, optional*) – The style of the markers. Example options

```
{``.``, ``,``, ``o``, ``v``, ``^``, ``<``, ``>``, ``+``,
 ``x``, ``D``, ``d``, ``s``, ``p``, ``*``, ``h``, ``H``,
 ``1``, ``2``, ``3``, ``4``, ``8``}
```

- **marker_size** (*int*, optional) – The size of the markers in points.
- **marker_face_colour** (*See Below, optional*) – The face (filling) colour of the markers. Example options

```
{``r``, ``g``, ``b``, ``c``, ``m``, ``k``, ``w``}
or
``(3, )`` `ndarray`
or
`list` of length ``3``
```

- **marker_edge_colour** (*See Below, optional*) – The edge colour of the markers. Example options

```
{``r``, ``g``, ``b``, ``c``, ``m``, ``k``, ``w``}
or
``(3, )`` `ndarray`
or
`list` of length ``3``
```

- **marker_edge_width** (*float*, optional) – The width of the markers' edge.

- **render_axes** (*bool*, optional) – If `True`, the axes will be rendered.
- **axes_font_name** (*See Below, optional*) – The font of the axes. Example options

```
{``serif``, ``sans-serif``, ``cursive``, ``fantasy``,
 ``monospace``}
```

- **axes_font_size** (*int*, optional) – The font size of the axes.
- **axes_font_style** ({`normal`, `italic`, `oblique`}, optional) – The font style of the axes.
- **axes_font_weight** (*See Below, optional*) – The font weight of the axes. Example options

```
{``ultralight``, ``light``, ``normal``, ``regular``,
 ``book``, ``medium``, ``roman``, ``semibold``,
 ``demibold``, ``demi``, ``bold``, ``heavy``,
 ``extra bold``, ``black``}
```

- **figure_size** ((*float*, *float*) or *None*, optional) – The size of the figure in inches.
- **render_grid** (*bool*, optional) – If `True`, the grid will be rendered.
- **grid_line_style** ({`-`, `--`, `-.`, `:`}, optional) – The style of the grid lines.
- **grid_line_width** (*float*, optional) – The width of the grid lines.

Returnsviewer (*MatplotlibRenderer*) – The viewer object.

plot_eigenvalues_ratio_widget (*figure_size=(10, 6)*, *style='coloured'*)

Plot of the variance ratio captured by the eigenvalues using an interactive widget.

Parameters

- **figure_size** ((*float*, *float*) or `None`, optional) – The size of the figure in inches.
- **style** ({`'coloured'`, `'minimal'`}, optional) – If `'coloured'`, then the style of the widget will be coloured. If `minimal`, then the style is simple using black and white colours.

plot_eigenvalues_widget (*figure_size=(10, 6)*, *style='coloured'*)

Plot of the eigenvalues using an interactive widget.

Parameters

- **figure_size** ((*float*, *float*) or `None`, optional) – The size of the figure in inches.
- **style** ({`'coloured'`, `'minimal'`}, optional) – If `'coloured'`, then the style of the widget will be coloured. If `minimal`, then the style is simple using black and white colours.

project (*vector*)

Projects the *vector* onto the model, retrieving the optimal linear reconstruction weights.

Parametersvector (`(n_features,)` *ndarray*) – A vectorized novel instance.

Returnsweights (`(n_components,)` *ndarray*) – A vector of optimal linear weights.

project_out (*vector*)

Returns a version of *vector* where all the basis of the model have been projected out.

Parametersvector (`(n_features,)` *ndarray*) – A novel vector.

Returnsprojected_out ((n_features,) *ndarray*) – A copy of *vector* with all basis of the model projected out.

project_out_vectors(*vectors*)

Returns a version of *vectors* where all the bases of the model have been projected out.

Parametersvectors ((n_vectors, n_features) *ndarray*) – A matrix of novel vectors.

Returnsprojected_out ((n_vectors, n_features) *ndarray*) – A copy of *vectors* with all bases of the model projected out.

project_vectors(*vectors*)

Projects each of the *vectors* onto the model, retrieving the optimal linear reconstruction weights for each instance.

Parametersvectors ((n_samples, n_features) *ndarray*) – Array of vectorized novel instances.

Returnsprojected ((n_samples, n_components) *ndarray*) – The matrix of optimal linear weights.

project_whitened(*vector_instance*)

Projects the *vector_instance* onto the whitened components, retrieving the whitened linear weightings.

Parametersvector_instance ((n_features,) *ndarray*) – A novel vector.

Returnsprojected ((n_features,) *ndarray*) – A vector of whitened linear weightings

reconstruct(*vector*)

Project a *vector* onto the linear space and rebuild from the weights found.

Parametersvector ((n_features,) *ndarray*) – A vectorized novel instance to project.

Returnsreconstructed ((n_features,) *ndarray*) – The reconstructed vector.

reconstruct_vectors(*vectors*)

Projects the *vectors* onto the linear space and rebuilds vectors from the weights found.

Parametersvectors ((n_vectors, n_features) *ndarray*) – A set of vectors to project.

Returnsreconstructed ((n_vectors, n_features) *ndarray*) – The reconstructed vectors.

trim_components(*n_components=None*)

Permanently trims the components down to a certain amount. The number of active components will be automatically reset to this particular value.

This will reduce *self.n_components* down to *n_components* (if None, *self.n_active_components* will be used), freeing up memory in the process.

Once the model is trimmed, the trimmed components cannot be recovered.

Parametersn_components (*int* >= 1 or *float* > 0.0 or None, optional) – The number of components that are kept or else the amount (ratio) of variance that is kept. If None, *self.n_active_components* is used.

Notes

In case *n_components* is greater than the total number of components or greater than the amount of variance currently kept, this method does not perform any action.

---

variance()

Returns the total amount of variance retained by the active components.

Returnsvariance (*float*) – Total variance captured by the active components.

variance_ratio()

Returns the ratio between the amount of variance retained by the active components and the total amount of variance present on the original samples.

Returnsvariance_ratio (*float*) – Ratio of active components variance and total variance present in original samples.

whitened_components()

Returns the active components of the model, whitened.

Returnswhitened_components ((n_active_components, n_features) *ndarray*) – The whitened components.

components

Returns the active components of the model.

Type (n_active_components, n_features) *ndarray*

eigenvalues

Returns the eigenvalues associated with the active components of the model, i.e. the amount of variance captured by each active component, sorted form largest to smallest.

Type (n_active_components,) *ndarray*

n_active_components

The number of components currently in use on this model.

Type*int*

n_components

The number of bases of the model.

Type*int*

n_features

The number of elements in each linear component.

Type*int*

Gaussian Markov Random Field

GMRFModel

class menpo.model.**GMRFModel**(*samples*, *graph*, *mode='concatenation'*, *n_components=None*, *dtype=<type 'numpy.float64'>*, *sparse=True*, *n_samples=None*, *bias=0*, *incremental=False*, *verbose=False*)

Bases: GMRFVectorModel

Trains a Gaussian Markov Random Field (GMRF).

Parameters

- **samples** (*list* or *iterable* of Vectorizable) – List or iterable of samples to build the model from.
- **graph** (UndirectedGraph or DirectedGraph or Tree) – The graph that defines the relations between the features.
- **n_samples** (*int*, optional) – If provided then samples must be an iterator that yields n_samples. If not provided then samples has to be a *list* (so we know how large the data matrix needs to be).

- **mode** ({'concatenation', 'subtraction'}, optional) – Defines the feature vector of each edge. Assuming that $\mathbf{x}_i$ and $\mathbf{x}_j$ are the feature vectors of two adjacent vertices $(i, j : (v_i, v_j) \in E)$, then the edge's feature vector in the case of 'concatenation' is

$$\left[\mathbf{x}_i{}^T, \mathbf{x}_j{}^T\right]^T$$

and in the case of 'subtraction'

$$\mathbf{x}_i - \mathbf{x}_j$$

- **n_components** (*int* or None, optional) – When None (default), the covariance matrix of each edge is inverted using *np.linalg.inv*. If *int*, it is inverted using truncated SVD using the specified number of compnents.
- **dtype** (*numpy.dtype*, optional) – The data type of the GMRF's precision matrix. For example, it can be set to *numpy.float32* for single precision or to *numpy.float64* for double precision. Depending on the size of the precision matrix, this option can you a lot of memory.
- **sparse** (*bool*, optional) – When True, the GMRF's precision matrix has type *scipy.sparse.bsr_matrix*, otherwise it is a *numpy.array*.
- **bias** (*int*, optional) – Default normalization is by (N - 1), where N is the number of observations given (unbiased estimate). If *bias* is 1, then normalization is by N. These values can be overridden by using the keyword ddof in numpy versions >= 1.5.
- **incremental** (*bool*, optional) – This argument must be set to True in case the user wants to incrementally update the GMRF. Note that if True, the model occupies 2x memory.
- **verbose** (*bool*, optional) – If True, the progress of the model's training is printed.

Notes

Let us denote a graph as $G = (V, E)$, where $V = \{v_i, v_2, \ldots, v_{|V|}\}$ is the set of $|V|$ vertices and there is an edge $(v_i, v_j) \in E$ for each pair of connected vertices. Let us also assume that we have a set of random variables $X = \{X_i\}, \forall i : v_i \in V$, which represent an abstract feature vector of length k extracted from each vertex v_i, i.e. $\mathbf{x}_i, i : v_i \in V$.

A GMRF is described by an undirected graph, where the vertexes stand for random variables and the edges impose statistical constraints on these random variables. Thus, the GMRF models the set of random variables with a multivariate normal distribution

$$p(X = \mathbf{x}|G) \sim \mathcal{N}(\boldsymbol{\mu}, \boldsymbol{\Sigma})$$

We denote by $\mathbf{Q}$ the block-sparse precision matrix that is the inverse of the covariance matrix $\boldsymbol{\Sigma}$, i.e. $\mathbf{Q} = \boldsymbol{\Sigma}^{-1}$. By applying the GMRF we make the assumption that the random variables satisfy the three Markov properties (pairwise, local and global) and that the blocks of the precision matrix that correspond to disjoint vertexes are zero, i.e.

$$\mathbf{Q}_{ij} = \mathbf{0}_{k \times k}, \forall i, j : (v_i, v_j) \notin E$$

References

increment(*samples*, *n_samples=None*, *verbose=False*)

Update the mean and precision matrix of the GMRF by updating the distributions of all the edges.

Parameters

- **samples** (*list* or *iterable* of `Vectorizable`) – List or iterable of samples to build the model from.
- **n_samples** (*int*, optional) – If provided then `samples` must be an iterator that yields `n_samples`. If not provided then samples has to be a list (so we know how large the data matrix needs to be).
- **verbose** (*bool*, optional) – If `True`, the progress of the model's incremental update is printed.

mahalanobis_distance(*samples*, *subtract_mean=True*, *square_root=False*)

Compute the mahalanobis distance given a sample $\mathbf{x}$ or an array of samples $\mathbf{X}$, i.e.

$$\sqrt{(\mathbf{x}-\boldsymbol{\mu})^T\mathbf{Q}(\mathbf{x}-\boldsymbol{\mu})} \text{ or } \sqrt{(\mathbf{X}-\boldsymbol{\mu})^T\mathbf{Q}(\mathbf{X}-\boldsymbol{\mu})}$$

Parameters

- **samples** (`Vectorizable` or *list* of `Vectorizable`) – The new data sample or a list of samples.
- **subtract_mean** (*bool*, optional) – When `True`, the mean vector is subtracted from the data vector.
- **square_root** (*bool*, optional) – If `False`, the mahalanobis distance gets squared.

mean()

Return the mean of the model.

Type `Vectorizable`

principal_components_analysis(*max_n_components=None*)

Returns a `PCAModel` with the Principal Components.

Note that the eigenvalue decomposition is applied directly on the precision matrix and then the eigenvalues are inverted.

Parameters **max_n_components** (*int* or `None`, optional) – The maximum number of principal components. If `None`, all the components are returned.

Returns **pca** (`PCAModel`) – The PCA model.

GMRFVectorModel

class `menpo.model.`**GMRFVectorModel**(*samples*, *graph*, *n_samples=None*, *mode='concatenation'*, *n_components=None*, *dtype=<type 'numpy.float64'>*, *sparse=True*, *bias=0*, *incremental=False*, *verbose=False*)

Bases: `object`

Trains a Gaussian Markov Random Field (GMRF).

Parameters

- **samples** (*ndarray* or *list* or *iterable* of *ndarray*) – List or iterable of numpy arrays to build the model from, or an existing data matrix.
- **graph** (`UndirectedGraph` or `DirectedGraph` or `Tree`) – The graph that defines the relations between the features.
- **n_samples** (*int*, optional) – If provided then `samples` must be an iterator that yields `n_samples`. If not provided then samples has to be a *list* (so we know how large the data matrix needs to be).

- **mode** ({'concatenation', 'subtraction'}, optional) – Defines the feature vector of each edge. Assuming that $\mathbf{x}_i$ and $\mathbf{x}_j$ are the feature vectors of two adjacent vertices $(i, j : (v_i, v_j) \in E)$, then the edge's feature vector in the case of 'concatenation' is

$$\left[\mathbf{x}_i{}^T, \mathbf{x}_j{}^T\right]^T$$

and in the case of 'subtraction'

$$\mathbf{x}_i - \mathbf{x}_j$$

- **n_components** (*int* or None, optional) – When None (default), the covariance matrix of each edge is inverted using *np.linalg.inv*. If *int*, it is inverted using truncated SVD using the specified number of compnents.
- **dtype** (*numpy.dtype*, optional) – The data type of the GMRF's precision matrix. For example, it can be set to *numpy.float32* for single precision or to *numpy.float64* for double precision. Depending on the size of the precision matrix, this option can you a lot of memory.
- **sparse** (*bool*, optional) – When True, the GMRF's precision matrix has type *scipy.sparse.bsr_matrix*, otherwise it is a *numpy.array*.
- **bias** (*int*, optional) – Default normalization is by (N - 1), where N is the number of observations given (unbiased estimate). If *bias* is 1, then normalization is by N. These values can be overridden by using the keyword ddof in numpy versions >= 1.5.
- **incremental** (*bool*, optional) – This argument must be set to True in case the user wants to incrementally update the GMRF. Note that if True, the model occupies 2x memory.
- **verbose** (*bool*, optional) – If True, the progress of the model's training is printed.

Notes

Let us denote a graph as $G = (V, E)$, where $V = \{v_i, v_2, \ldots, v_{|V|}\}$ is the set of $|V|$ vertices and there is an edge $(v_i, v_j) \in E$ for each pair of connected vertices. Let us also assume that we have a set of random variables $X = \{X_i\}, \forall i : v_i \in V$, which represent an abstract feature vector of length k extracted from each vertex v_i, i.e. $\mathbf{x}_i, i : v_i \in V$.

A GMRF is described by an undirected graph, where the vertexes stand for random variables and the edges impose statistical constraints on these random variables. Thus, the GMRF models the set of random variables with a multivariate normal distribution

$$p(X = \mathbf{x}|G) \sim \mathcal{N}(\boldsymbol{\mu}, \boldsymbol{\Sigma})$$

We denote by $\mathbf{Q}$ the block-sparse precision matrix that is the inverse of the covariance matrix $\boldsymbol{\Sigma}$, i.e. $\mathbf{Q} = \boldsymbol{\Sigma}^{-1}$. By applying the GMRF we make the assumption that the random variables satisfy the three Markov properties (pairwise, local and global) and that the blocks of the precision matrix that correspond to disjoint vertexes are zero, i.e.

$$\mathbf{Q}_{ij} = \mathbf{0}_{k \times k}, \forall i, j : (v_i, v_j) \notin E$$

References

increment(*samples*, *n_samples=None*, *verbose=False*)

Update the mean and precision matrix of the GMRF by updating the distributions of all the edges.

Parameters

- **samples** (*ndarray* or *list* or *iterable* of *ndarray*) – List or iterable of numpy arrays to build the model from, or an existing data matrix.
- **n_samples** (*int*, optional) – If provided then `samples` must be an iterator that yields `n_samples`. If not provided then samples has to be a list (so we know how large the data matrix needs to be).
- **verbose** (*bool*, optional) – If `True`, the progress of the model's incremental update is printed.

mahalanobis_distance(*samples*, *subtract_mean=True*, *square_root=False*)

Compute the mahalanobis distance given a sample $\mathbf{x}$ or an array of samples $\mathbf{X}$, i.e.

$$\sqrt{(\mathbf{x}-\boldsymbol{\mu})^T\mathbf{Q}(\mathbf{x}-\boldsymbol{\mu})} \text{ or } \sqrt{(\mathbf{X}-\boldsymbol{\mu})^T\mathbf{Q}(\mathbf{X}-\boldsymbol{\mu})}$$

Parameters

- **samples** (*ndarray*) – A single data vector or an array of multiple data vectors.
- **subtract_mean** (*bool*, optional) – When `True`, the mean vector is subtracted from the data vector.
- **square_root** (*bool*, optional) – If `False`, the mahalanobis distance gets squared.

mean()

Return the mean of the model. For this model, returns the same result as `mean_vector`.

Type*ndarray*

principal_components_analysis(*max_n_components=None*)

Returns a `PCAVectorModel` with the Principal Components.

Note that the eigenvalue decomposition is applied directly on the precision matrix and then the eigenvalues are inverted.

Parametersmax_n_components (*int* or `None`, optional) – The maximum number of principal components. If `None`, all the components are returned.

Returnspca (`PCAVectorModel`) – The PCA model.

menpo.shape

Base Class

Shape

class menpo.shape.base.**Shape**

Bases: *Vectorizable*, *Transformable*, `Landmarkable`, `LandmarkableViewable`, `Viewable`

Abstract representation of shape. Shapes are *Transformable*, *Vectorizable*, *Landmarkable*, *LandmarkableViewable* and *Viewable*. This base class handles transforming landmarks when the shape is transformed. Therefore, implementations of `Shape` have to implement the abstract `_transform_self_inplace()` method that handles transforming the `Shape` itself.

as_vector(***kwargs*)

Returns a flattened representation of the object as a single vector.

Returnsvector (*(N,) ndarray*) – The core representation of the object, flattened into a single vector. Note that this is always a view back on to the original object, but is not writable.

copy()

Generate an efficient copy of this object.

Note that Numpy arrays and other `Copyable` objects on `self` will be deeply copied. Dictionaries and sets will be shallow copied, and everything else will be assigned (no copy will be made).

Classes that store state other than numpy arrays and immutable types should overwrite this method to ensure all state is copied.

Returns`type(self)` – A copy of this object

from_vector(*vector*)

Build a new instance of the object from it's vectorized state.

`self` is used to fill out the missing state required to rebuild a full object from it's standardized flattened state. This is the default implementation, which is which is a `deepcopy` of the object followed by a call to `from_vector_inplace()`. This method can be overridden for a performance benefit if desired.

Parametersvector (`(n_parameters,)` *ndarray*) – Flattened representation of the object.

Returnsobject (`type(self)`) – An new instance of this class.

from_vector_inplace(*vector*)

Deprecated. Use the non-mutating API, `from_vector`.

For internal usage in performance-sensitive spots, see *_from_vector_inplace()*

Parametersvector (`(n_parameters,)` *ndarray*) – Flattened representation of this object

has_nan_values()

Tests if the vectorized form of the object contains `nan` values or not. This is particularly useful for objects with unknown values that have been mapped to `nan` values.

Returnshas_nan_values (*bool*) – If the vectorized object contains `nan` values.

n_dims()

The total number of dimensions.

Type*int*

has_landmarks

Whether the object has landmarks.

Type*bool*

landmarks

The landmarks object.

Type`LandmarkManager`

n_landmark_groups

The number of landmark groups on this object.

Type*int*

n_parameters

The length of the vector that this object produces.

Type*int*

PointCloud

PointCloud

class `menpo.shape.PointCloud`(*points*, *copy=True*)

Bases: *Shape*

An N-dimensional point cloud. This is internally represented as an *ndarray* of shape `(n_points, n_dims)`. This class is important for dealing with complex functionality such as viewing and representing metadata such as landmarks.

Currently only 2D and 3D pointclouds are viewable.

Parameters

- **points** (`(n_points, n_dims)` *ndarray*) – The array representing the points.
- **copy** (*bool*, optional) – If `False`, the points will not be copied on assignment. Note that this will miss out on additional checks. Further note that we still demand that the array is C-contiguous - if it isn't, a copy will be generated anyway. In general this should only be used if you know what you are doing.

_view_2d(*figure_id=None*, *new_figure=False*, *image_view=True*, *render_markers=True*, *marker_style='o'*, *marker_size=5*, *marker_face_colour='r'*, *marker_edge_colour='k'*, *marker_edge_width=1.0*, *render_numbering=False*, *numbers_horizontal_align='center'*, *numbers_vertical_align='bottom'*, *numbers_font_name='sans-serif'*, *numbers_font_size=10*, *numbers_font_style='normal'*, *numbers_font_weight='normal'*, *numbers_font_colour='k'*, *render_axes=True*, *axes_font_name='sans-serif'*, *axes_font_size=10*, *axes_font_style='normal'*, *axes_font_weight='normal'*, *axes_x_limits=None*, *axes_y_limits=None*, *axes_x_ticks=None*, *axes_y_ticks=None*, *figure_size=(7, 7)*, *label=None*, ***kwargs*)

Visualization of the PointCloud in 2D.

Returns

- **figure_id** (*object*, optional) – The id of the figure to be used.
- **new_figure** (*bool*, optional) – If `True`, a new figure is created.
- **image_view** (*bool*, optional) – If `True` the PointCloud will be viewed as if it is in the image coordinate system.
- **render_markers** (*bool*, optional) – If `True`, the markers will be rendered.
- **marker_style** (*See Below, optional*) –

  The style of the markers. Example options

```
{., ,, o, v, ^, <, >, +, x, D, d, s, p, *, h, H, 1, 2, 3, 4, 8}
```

- **marker_size** (*int*, optional) – The size of the markers in points.
- **marker_face_colour** (*See Below, optional*) – The face (filling) colour of the markers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **marker_edge_colour** (*See Below, optional*) – The edge colour of the markers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

•**marker_edge_width** (*float*, optional) – The width of the markers' edge.

•**render_numbering** (*bool*, optional) – If `True`, the landmarks will be numbered.

•**numbers_horizontal_align** (`{center, right, left}`, optional) – The horizontal alignment of the numbers' texts.

•**numbers_vertical_align** (`{center, top, bottom, baseline}`, optional) – The vertical alignment of the numbers' texts.

•**numbers_font_name** (*See Below, optional*) –

The font of the numbers. Example options

```
{serif, sans-serif, cursive, fantasy, monospace}
```

•**numbers_font_size** (*int*, optional) – The font size of the numbers.

•**numbers_font_style** (`{normal, italic, oblique}`, optional) – The font style of the numbers.

•**numbers_font_weight** (*See Below, optional*) – The font weight of the numbers. Example options

```
{ultralight, light, normal, regular, book, medium, roman,
semibold, demibold, demi, bold, heavy, extra bold, black}
```

•**numbers_font_colour** (*See Below, optional*) – The font colour of the numbers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

•**render_axes** (*bool*, optional) – If `True`, the axes will be rendered.

•**axes_font_name** (*See Below, optional*) – The font of the axes. Example options

```
{serif, sans-serif, cursive, fantasy, monospace}
```

•**axes_font_size** (*int*, optional) – The font size of the axes.

•**axes_font_style** (`{normal, italic, oblique}`, optional) – The font style of the axes.

•**axes_font_weight** (*See Below, optional*) – The font weight of the axes. Example options

```
{ultralight, light, normal, regular, book, medium, roman,
semibold, demibold, demi, bold, heavy, extra bold, black}
```

•**axes_x_limits** (*float* or (*float*, *float*) or `None`, optional) – The limits of the x axis. If *float*, then it sets padding on the right and left of the PointCloud as a percentage of the PointCloud's width. If *tuple* or *list*, then it defines the axis limits. If `None`, then the limits are set automatically.

•**axes_y_limits** ((*float*, *float*) *tuple* or `None`, optional) – The limits of the y axis. If *float*, then it sets padding on the top and bottom of the PointCloud as a percentage of the Point-

Cloud's height. If *tuple* or *list*, then it defines the axis limits. If `None`, then the limits are set automatically.

- **axes_x_ticks** (*list* or *tuple* or `None`, optional) – The ticks of the x axis.
- **axes_y_ticks** (*list* or *tuple* or `None`, optional) – The ticks of the y axis.
- **figure_size** ((*float*, *float*) *tuple* or `None`, optional) – The size of the figure in inches.
- **label** (*str*, optional) – The name entry in case of a legend.

Returns **viewer** (`PointGraphViewer2d`) – The viewer object.

_view_landmarks_2d(*group=None*, *with_labels=None*, *without_labels=None*, *figure_id=None*, *new_figure=False*, *image_view=True*, *render_markers=True*, *marker_style='s'*, *marker_size=7*, *marker_face_colour='k'*, *marker_edge_colour='k'*, *marker_edge_width=1.0*, *render_lines_lms=True*, *line_colour_lms=None*, *line_style_lms='-'*, *line_width_lms=1*, *render_markers_lms=True*, *marker_style_lms='o'*, *marker_size_lms=5*, *marker_face_colour_lms=None*, *marker_edge_colour_lms=None*, *marker_edge_width_lms=1.0*, *render_numbering=False*, *numbers_horizontal_align='center'*, *numbers_vertical_align='bottom'*, *numbers_font_name='sans-serif'*, *numbers_font_size=10*, *numbers_font_style='normal'*, *numbers_font_weight='normal'*, *numbers_font_colour='k'*, *render_legend=False*, *legend_title=''*, *legend_font_name='sans-serif'*, *legend_font_style='normal'*, *legend_font_size=10*, *legend_font_weight='normal'*, *legend_marker_scale=None*, *legend_location=2*, *legend_bbox_to_anchor=(1.05, 1.0)*, *legend_border_axes_pad=None*, *legend_n_columns=1*, *legend_horizontal_spacing=None*, *legend_vertical_spacing=None*, *legend_border=True*, *legend_border_padding=None*, *legend_shadow=False*, *legend_rounded_corners=False*, *render_axes=False*, *axes_font_name='sans-serif'*, *axes_font_size=10*, *axes_font_style='normal'*, *axes_font_weight='normal'*, *axes_x_limits=None*, *axes_y_limits=None*, *axes_x_ticks=None*, *axes_y_ticks=None*, *figure_size=(7, 7)*)

Visualize the landmarks. This method will appear on the *PointCloud* as `view_landmarks`.

Parameters

- **group** (*str* or''None'' optional) – The landmark group to be visualized. If `None` and there are more than one landmark groups, an error is raised.
- **with_labels** (`None` or *str* or *list* of *str*, optional) – If not `None`, only show the given label(s). Should **not** be used with the `without_labels` kwarg.
- **without_labels** (`None` or *str* or *list* of *str*, optional) – If not `None`, show all except the given label(s). Should **not** be used with the `with_labels` kwarg.
- **figure_id** (*object*, optional) – The id of the figure to be used.
- **new_figure** (*bool*, optional) – If `True`, a new figure is created.
- **image_view** (*bool*, optional) – If `True` the PointCloud will be viewed as if it is in the image coordinate system.
- **render_markers** (*bool*, optional) – If `True`, the markers will be rendered.
- **marker_style** (*See Below, optional*) – The style of the markers. Example options

```
{., ,, o, v, ^, <, >, +, x, D, d, s, p, *, h, H, 1, 2, 3, 4, 8}
```

- **marker_size** (*int*, optional) – The size of the markers in points.
- **marker_face_colour** (*See Below, optional*) – The face (filling) colour of the markers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **marker_edge_colour** (*See Below, optional*) – The edge colour of the markers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **marker_edge_width** (*float*, optional) – The width of the markers' edge.
- **render_lines_lms** (*bool*, optional) – If `True`, the edges of the landmarks will be rendered.
- **line_colour_lms** (*See Below, optional*) – The colour of the lines of the landmarks. Example options:

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **line_style_lms** (`{-, --, -., :}`, optional) – The style of the lines of the landmarks.
- **line_width_lms** (*float*, optional) – The width of the lines of the landmarks.
- **render_markers** – If `True`, the markers of the landmarks will be rendered.
- **marker_style** – The style of the markers of the landmarks. Example options

```
{., ,, o, v, ^, <, >, +, x, D, d, s, p, *, h, H, 1, 2, 3, 4, 8}
```

- **marker_size** – The size of the markers of the landmarks in points.
- **marker_face_colour** – The face (filling) colour of the markers of the landmarks. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **marker_edge_colour** – The edge colour of the markers of the landmarks. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **marker_edge_width** – The width of the markers' edge of the landmarks.
- **render_numbering** (*bool*, optional) – If `True`, the landmarks will be numbered.

- **numbers_horizontal_align** (`{center, right, left}`, optional) – The horizontal alignment of the numbers' texts.
- **numbers_vertical_align** (`{center, top, bottom, baseline}`, optional) – The vertical alignment of the numbers' texts.
- **numbers_font_name** (*See Below, optional*) – The font of the numbers. Example options

```
{serif, sans-serif, cursive, fantasy, monospace}
```

- **numbers_font_size** (*int*, optional) – The font size of the numbers.
- **numbers_font_style** (`{normal, italic, oblique}`, optional) – The font style of the numbers.
- **numbers_font_weight** (*See Below, optional*) – The font weight of the numbers. Example options

```
{ultralight, light, normal, regular, book, medium, roman,
semibold, demibold, demi, bold, heavy, extra bold, black}
```

- **numbers_font_colour** (*See Below, optional*) – The font colour of the numbers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **render_legend** (*bool*, optional) – If `True`, the legend will be rendered.
- **legend_title** (*str*, optional) – The title of the legend.
- **legend_font_name** (*See below, optional*) – The font of the legend. Example options

```
{serif, sans-serif, cursive, fantasy, monospace}
```

- **legend_font_style** (`{normal, italic, oblique}`, optional) – The font style of the legend.
- **legend_font_size** (*int*, optional) – The font size of the legend.
- **legend_font_weight** (*See Below, optional*) – The font weight of the legend. Example options

```
{ultralight, light, normal, regular, book, medium, roman,
semibold, demibold, demi, bold, heavy, extra bold, black}
```

- **legend_marker_scale** (*float*, optional) – The relative size of the legend markers with respect to the original
- **legend_location** (*int*, optional) – The location of the legend. The predefined values are:

'best'	0
'upper right'	1
'upper left'	2
'lower left'	3
'lower right'	4
'right'	5
'center left'	6
'center right'	7
'lower center'	8
'upper center'	9
'center'	10

- **legend_bbox_to_anchor** ((*float*, *float*) *tuple*, optional) – The bbox that the legend will be anchored.
- **legend_border_axes_pad** (*float*, optional) – The pad between the axes and legend border.
- **legend_n_columns** (*int*, optional) – The number of the legend's columns.
- **legend_horizontal_spacing** (*float*, optional) – The spacing between the columns.
- **legend_vertical_spacing** (*float*, optional) – The vertical space between the legend entries.
- **legend_border** (*bool*, optional) – If `True`, a frame will be drawn around the legend.
- **legend_border_padding** (*float*, optional) – The fractional whitespace inside the legend border.
- **legend_shadow** (*bool*, optional) – If `True`, a shadow will be drawn behind legend.
- **legend_rounded_corners** (*bool*, optional) – If `True`, the frame's corners will be rounded (fancybox).
- **render_axes** (*bool*, optional) – If `True`, the axes will be rendered.
- **axes_font_name** (*See Below, optional*) – The font of the axes. Example options

```
{serif, sans-serif, cursive, fantasy, monospace}
```

- **axes_font_size** (*int*, optional) – The font size of the axes.
- **axes_font_style** (`{normal, italic, oblique}`, optional) – The font style of the axes.
- **axes_font_weight** (*See Below, optional*) – The font weight of the axes. Example options

```
{ultralight, light, normal, regular, book, medium, roman,
semibold,demibold, demi, bold, heavy, extra bold, black}
```

- **axes_x_limits** (*float* or (*float*, *float*) or `None`, optional) – The limits of the x axis. If *float*, then it sets padding on the right and left of the PointCloud as a percentage of the PointCloud's width. If *tuple* or *list*, then it defines the axis limits. If `None`, then the limits are set automatically.
- **axes_y_limits** ((*float*, *float*) *tuple* or `None`, optional) – The limits of the y axis. If *float*, then it sets padding on the top and bottom of the PointCloud as a percentage of the

PointCloud's height. If *tuple* or *list*, then it defines the axis limits. If `None`, then the limits are set automatically.

- **axes_x_ticks** (*list* or *tuple* or `None`, optional) – The ticks of the x axis.
- **axes_y_ticks** (*list* or *tuple* or `None`, optional) – The ticks of the y axis.
- **figure_size** ((*float*, *float*) *tuple* or `None` optional) – The size of the figure in inches.

Raises

- `ValueError` – If both `with_labels` and `without_labels` are passed.
- `ValueError` – If the landmark manager doesn't contain the provided group label.

as_vector(***kwargs*)

Returns a flattened representation of the object as a single vector.

Returnsvector (*(N,) ndarray*) – The core representation of the object, flattened into a single vector. Note that this is always a view back on to the original object, but is not writable.

bounding_box()

Return a bounding box from two corner points as a directed graph. In the case of a 2D pointcloud, first point (0) should be nearest the origin. In the case of an image, this ordering would appear as:

```
0<--3
|   ^
|   |
v   |
1-->2
```

In the case of a pointcloud, the ordering will appear as:

```
3<--2
|   ^
|   |
v   |
0-->1
```

In the case of a 3D pointcloud, the first point (0) should be the near closest to the origin and the second point is the far opposite corner.

Returnsbounding_box (`PointDirectedGraph`) – The axis aligned bounding box of the PointCloud.

bounds(*boundary=0*)

The minimum to maximum extent of the PointCloud. An optional boundary argument can be provided to expand the bounds by a constant margin.

Parametersboundary (*float*) – A optional padding distance that is added to the bounds. Default is `0`, meaning the max/min of tightest possible containing square/cube/hypercube is returned.

Returns

- **min_b** (`(n_dims,)` *ndarray*) – The minimum extent of the `PointCloud` and boundary along each dimension
- **max_b** (`(n_dims,)` *ndarray*) – The maximum extent of the `PointCloud` and boundary along each dimension

centre()

The mean of all the points in this PointCloud (centre of mass).

Returnscentre (`(n_dims)` *ndarray*) – The mean of this PointCloud's points.

centre_of_bounds()

The centre of the absolute bounds of this PointCloud. Contrast with `centre()`, which is the mean point position.

Returns **centre** (`n_dims` *ndarray*) – The centre of the bounds of this PointCloud.

constrain_to_bounds(*bounds*)

Returns a copy of this PointCloud, constrained to lie exactly within the given bounds. Any points outside the bounds will be 'snapped' to lie *exactly* on the boundary.

Parameters **bounds** (`(n_dims, n_dims)` tuple of scalars) – The bounds to constrain this pointcloud within.

Returns **constrained** (`PointCloud`) – The constrained pointcloud.

copy()

Generate an efficient copy of this object.

Note that Numpy arrays and other `Copyable` objects on `self` will be deeply copied. Dictionaries and sets will be shallow copied, and everything else will be assigned (no copy will be made).

Classes that store state other than numpy arrays and immutable types should overwrite this method to ensure all state is copied.

Returns `type(self)` – A copy of this object

distance_to(*pointcloud*, ***kwargs*)

Returns a distance matrix between this PointCloud and another. By default the Euclidean distance is calculated - see *scipy.spatial.distance.cdist* for valid kwargs to change the metric and other properties.

Parameters **pointcloud** (`PointCloud`) – The second pointcloud to compute distances between. This must be of the same dimension as this PointCloud.

Returns **distance_matrix** (`(n_points, n_points)` *ndarray*) – The symmetric pairwise distance matrix between the two PointClouds s.t. `distance_matrix[i, j]` is the distance between the i'th point of this PointCloud and the j'th point of the input PointCloud.

from_mask(*mask*)

A 1D boolean array with the same number of elements as the number of points in the PointCloud. This is then broadcast across the dimensions of the PointCloud and returns a new PointCloud containing only those points that were `True` in the mask.

Parameters **mask** (`(n_points,)` *ndarray*) – 1D array of booleans

Returns **pointcloud** (`PointCloud`) – A new pointcloud that has been masked.

Raises `ValueError` – Mask must have same number of points as pointcloud.

from_vector(*vector*)

Build a new instance of the object from it's vectorized state.

`self` is used to fill out the missing state required to rebuild a full object from it's standardized flattened state. This is the default implementation, which is which is a `deepcopy` of the object followed by a call to `from_vector_inplace()`. This method can be overridden for a performance benefit if desired.

Parameters **vector** (`(n_parameters,)` *ndarray*) – Flattened representation of the object.

Returns **object** (`type(self)`) – An new instance of this class.

from_vector_inplace(*vector*)

Deprecated. Use the non-mutating API, `from_vector`.

For internal usage in performance-sensitive spots, see *_from_vector_inplace()*

Parameters **vector** (`(n_parameters,)` *ndarray*) – Flattened representation of this object

h_points()

Convert poincloud to a homogeneous array: `(n_dims + 1, n_points)`

Type `type(self)`

has_nan_values()

Tests if the vectorized form of the object contains `nan` values or not. This is particularly useful for objects with unknown values that have been mapped to `nan` values.

Returns **has_nan_values** (*bool*) – If the vectorized object contains `nan` values.

classmethod init_2d_grid(*shape*, *spacing=None*)

Create a pointcloud that exists on a regular 2D grid. The first dimension is the number of rows in the grid and the second dimension of the shape is the number of columns. `spacing` optionally allows the definition of the distance between points (uniform over points). The spacing may be different for rows and columns.

Parameters

- **shape** (*tuple* of 2 *int*) – The size of the grid to create, this defines the number of points across each dimension in the grid. The first element is the number of rows and the second is the number of columns.
- **spacing** (*int* or *tuple* of 2 *int*, optional) – The spacing between points. If a single *int* is provided, this is applied uniformly across each dimension. If a *tuple* is provided, the spacing is applied non-uniformly as defined e.g. `(2, 3)` gives a spacing of 2 for the rows and 3 for the columns.

Returns **shape_cls** (*type(cls)*) – A PointCloud or subclass arranged in a grid.

classmethod init_from_depth_image(*depth_image*)

Return a 3D point cloud from the given depth image. The depth image is assumed to represent height/depth values and the XY coordinates are assumed to unit spaced and represent image coordinates. This is particularly useful for visualising depth values that have been recovered from images.

Parameters **depth_image** (`Image` or subclass) – A single channel image that contains depth values - as commonly returned by RGBD cameras, for example.

Returns **depth_cloud** (`type(cls)`) – A new 3D PointCloud with unit XY coordinates and the given depth values as Z coordinates.

norm(***kwargs*)

Returns the norm of this PointCloud. This is a translation and rotation invariant measure of the point cloud's intrinsic size - in other words, it is always taken around the point cloud's centre.

By default, the Frobenius norm is taken, but this can be changed by setting kwargs - see `numpy.linalg.norm` for valid options.

Returns **norm** (*float*) – The norm of this `PointCloud`

range(*boundary=0*)

The range of the extent of the PointCloud.

Parameters **boundary** (*float*) – A optional padding distance that is used to extend the bounds from which the range is computed. Default is `0`, no extension is performed.

Returns **range** (`(n_dims,)` *ndarray*) – The range of the `PointCloud` extent in each dimension.

tojson()

Convert this `PointCloud` to a dictionary representation suitable for inclusion in the LJSON landmark format.

Returns`json` (*dict*) – Dictionary with `points` keys.

`with_dims` (*dims*)
Return a copy of this shape with only particular dimensions retained.

Parameters`dims` (*`valid numpy array slice`*) – The slice that will be used on the dimensionality axis of the shape under transform. For example, to go from a 3D shape to a 2D one, [0, 1] could be provided or np.array([True, True, False]).

Returns*copy of self, with only the requested dims*

`has_landmarks`
Whether the object has landmarks.

Type*bool*

`landmarks`
The landmarks object.

Type*`LandmarkManager`*

`lms`
Deprecated. Maintained for compatibility, will be removed in a future version. Returns a copy of this object, which previously would have held the 'underlying' *`PointCloud`* subclass.

Typeself

`n_dims`
The number of dimensions in the pointcloud.

Type*int*

`n_landmark_groups`
The number of landmark groups on this object.

Type*int*

`n_parameters`
The length of the vector that this object produces.

Type*int*

`n_points`
The number of points in the pointcloud.

Type*int*

Graphs

UndirectedGraph

class `menpo.shape.`**`UndirectedGraph`** (*adjacency_matrix*, *copy=True*, *skip_checks=False*)
Bases: `Graph`

Class for Undirected Graph definition and manipulation.

Parameters

- **`adjacency_matrix`** (`(n_vertices, n_vertices, )` *ndarray* or *csr_matrix*) – The adjacency matrix of the graph. The non-edges must be represented with zeros and the edges can have a weight value.

  Note`adjacency_matrix` must be symmetric.

- **copy** (*bool*, optional) – If `False`, the `adjacency_matrix` will not be copied on assignment.
- **skip_checks** (*bool*, optional) – If `True`, no checks will be performed.

Raises

- `ValueError` – adjacency_matrix must be either a numpy.ndarray or a scipy.sparse.csr_matrix.
- `ValueError` – Graph must have at least two vertices.
- `ValueError` – adjacency_matrix must be square (n_vertices, n_vertices,), ({adjacency_matrix.shape[0]}, {adjacency_matrix.shape[1]}) given instead.
- `ValueError` – The adjacency matrix of an undirected graph must be symmetric.

Examples

The following undirected graph

```
|---0---|
|       |
|       |
1-------2
|       |
|       |
3-------4
|
|
5
```

can be defined as

```
import numpy as np
adjacency_matrix = np.array([[0, 1, 1, 0, 0, 0],
                             [1, 0, 1, 1, 0, 0],
                             [1, 1, 0, 0, 1, 0],
                             [0, 1, 0, 0, 1, 1],
                             [0, 0, 1, 1, 0, 0],
                             [0, 0, 0, 1, 0, 0]])
graph = UndirectedGraph(adjacency_matrix)
```

or

```
from scipy.sparse import csr_matrix
adjacency_matrix = csr_matrix(
                    ([1] * 14,
                     ([0, 1, 0, 2, 1, 2, 1, 3, 2, 4, 3, 4, 3, 5],
                      [1, 0, 2, 0, 2, 1, 3, 1, 4, 2, 4, 3, 5, 3])),
                    shape=(6, 6))
graph = UndirectedGraph(adjacency_matrix)
```

The adjacency matrix of the following graph with isolated vertices

```
       0---|
           |
           |
   1       2
           |
```

```
            |
   3-------4

5
```

can be defined as

```
import numpy as np
adjacency_matrix = np.array([[0, 0, 1, 0, 0, 0],
                             [0, 0, 0, 0, 0, 0],
                             [1, 0, 0, 0, 1, 0],
                             [0, 0, 0, 0, 1, 0],
                             [0, 0, 1, 1, 0, 0],
                             [0, 0, 0, 0, 0, 0]])
graph = UndirectedGraph(adjacency_matrix)
```

or

```
from scipy.sparse import csr_matrix
adjacency_matrix = csr_matrix(([1] * 6, ([0, 2, 2, 4, 3, 4],
                                          [2, 0, 4, 2, 4, 3])),
                              shape=(6, 6))
graph = UndirectedGraph(adjacency_matrix)
```

find_all_paths (*start*, *end*, *path=[]*)

Returns a list of lists with all the paths (without cycles) found from start vertex to end vertex.

Parameters

- **start** (*int*) – The vertex from which the paths start.
- **end** (*int*) – The vertex from which the paths end.
- **path** (*list*, optional) – An existing path to append to.

Returns **paths** (*list* of *list*) – The list containing all the paths from start to end.

find_all_shortest_paths (*algorithm='auto'*, *unweighted=False*)

Returns the distances and predecessors arrays of the graph's shortest paths.

Parameters

- **algorithm** (*'str', see below, optional*) – The algorithm to be used. Possible options are:

'dijkstra'	Dijkstra's algorithm with Fibonacci heaps
'bellman-ford'	Bellman-Ford algorithm
'johnson'	Johnson's algorithm
'floyd-warshall'	Floyd-Warshall algorithm
'auto'	Select the best among the above

- **unweighted** (*bool*, optional) – If `True`, then find unweighted distances. That is, rather than finding the path between each vertex such that the sum of weights is minimized, find the path such that the number of edges is minimized.

Returns

- **distances** (`(n_vertices, n_vertices,)` *ndarray*) – The matrix of distances between all graph vertices. `distances[i,j]` gives the shortest distance from vertex `i` to vertex `j` along the graph.

- **predecessors** (`(n_vertices, n_vertices,)` *ndarray*) – The matrix of predecessors, which can be used to reconstruct the shortest paths. Each entry `predecessors[i, j]` gives the index of the previous vertex in the path from vertex `i` to vertex `j`. If no path exists between vertices `i` and `j`, then `predecessors[i, j] = -9999`.

find_path(*start*, *end*, *method='bfs'*, *skip_checks=False*)

Returns a *list* with the first path (without cycles) found from the `start` vertex to the `end` vertex. It can employ either depth-first search or breadth-first search.

Parameters

- **start** (*int*) – The vertex from which the path starts.
- **end** (*int*) – The vertex to which the path ends.
- **method** ({`bfs`, `dfs`}, optional) – The method to be used.
- **skip_checks** (*bool*, optional) – If `True`, then input arguments won't pass through checks. Useful for efficiency.

Returnspath (*list*) – The path's vertices.

Raises`ValueError` – Method must be either bfs or dfs.

find_shortest_path(*start*, *end*, *algorithm='auto'*, *unweighted=False*, *skip_checks=False*)

Returns a *list* with the shortest path (without cycles) found from `start` vertex to `end` vertex.

Parameters

- **start** (*int*) – The vertex from which the path starts.
- **end** (*int*) – The vertex to which the path ends.
- **algorithm** (*`'str', see below, optional`*) – The algorithm to be used. Possible options are:

'dijkstra'	Dijkstra's algorithm with Fibonacci heaps
'bellman-ford'	Bellman-Ford algorithm
'johnson'	Johnson's algorithm
'floyd-warshall'	Floyd-Warshall algorithm
'auto'	Select the best among the above

- **unweighted** (*bool*, optional) – If `True`, then find unweighted distances. That is, rather than finding the path such that the sum of weights is minimized, find the path such that the number of edges is minimized.
- **skip_checks** (*bool*, optional) – If `True`, then input arguments won't pass through checks. Useful for efficiency.

Returns

- **path** (*list*) – The shortest path's vertices, including `start` and `end`. If there was not path connecting the vertices, then an empty *list* is returned.
- **distance** (*int* or *float*) – The distance (cost) of the path from `start` to `end`.

get_adjacency_list()

Returns the adjacency list of the graph, i.e. a *list* of length `n_vertices` that for each vertex has a *list* of the vertex neighbours. If the graph is directed, the neighbours are children.

Returnsadjacency_list (*list* of *list* of length `n_vertices`) – The adjacency list of the graph.

has_cycles()

Checks if the graph has at least one cycle.

Returnshas_cycles (*bool*) – `True` if the graph has cycles.

has_isolated_vertices()

Whether the graph has any isolated vertices, i.e. vertices with no edge connections.

Returnshas_isolated_vertices (*bool*) – `True` if the graph has at least one isolated vertex.

classmethod init_from_edges(*edges*, *n_vertices*, *skip_checks=False*)

Initialize graph from edges array.

Parameters

- **edges** (`(n_edges, 2, )` *ndarray*) – The *ndarray* of edges, i.e. all the pairs of vertices that are connected with an edge.
- **n_vertices** (*int*) – The total number of vertices, assuming that the numbering of vertices starts from `0`. `edges` and `n_vertices` can be defined in a way to set isolated vertices.
- **skip_checks** (*bool*, optional) – If `True`, no checks will be performed.

Examples

The following undirected graph

```
|---0---|
|       |
|       |
1-------2
|       |
|       |
3-------4
|
|
5
```

can be defined as

```
from menpo.shape import UndirectedGraph
import numpy as np
edges = np.array([[0, 1], [1, 0], [0, 2], [2, 0], [1, 2], [2, 1],
                  [1, 3], [3, 1], [2, 4], [4, 2], [3, 4], [4, 3],
                  [3, 5], [5, 3]])
graph = UndirectedGraph.init_from_edges(edges, n_vertices=6)
```

Finally, the following graph with isolated vertices

```
       0---|
           |
           |
   1       2
           |
           |
   3-------4

5
```

---

can be defined as

```
from menpo.shape import UndirectedGraph
import numpy as np
edges = np.array([[0, 2], [2, 0], [2, 4], [4, 2], [3, 4], [4, 3]])
graph = UndirectedGraph.init_from_edges(edges, n_vertices=6)
```

is_edge(*vertex_1*, *vertex_2*, *skip_checks=False*)

Whether there is an edge between the provided vertices.

Parameters

- **vertex_1** (*int*) – The first selected vertex. Parent if the graph is directed.
- **vertex_2** (*int*) – The second selected vertex. Child if the graph is directed.
- **skip_checks** (*bool*, optional) – If `False`, the given vertices will be checked.

Returnsis_edge (*bool*) – `True` if there is an edge connecting `vertex_1` and `vertex_2`.

Raises`ValueError` – The vertex must be between 0 and {n_vertices-1}.

is_tree()

Checks if the graph is tree.

Returnsis_true (*bool*) – If the graph is a tree.

isolated_vertices()

Returns the isolated vertices of the graph (if any), i.e. the vertices that have no edge connections.

Returnsisolated_vertices (*list*) – A *list* of the isolated vertices. If there aren't any, it returns an empty *list*.

minimum_spanning_tree(*root_vertex*)

Returns the minimum spanning tree of the graph using Kruskal's algorithm.

Parametersroot_vertex (*int*) – The vertex that will be set as root in the output MST.

Returnsmst (*`Tree`*) – The computed minimum spanning tree.

Raises`ValueError` – Cannot compute minimum spanning tree of a graph with isolated vertices

n_neighbours(*vertex*, *skip_checks=False*)

Returns the number of neighbours of the selected vertex.

Parameters

- **vertex** (*int*) – The selected vertex.
- **skip_checks** (*bool*, optional) – If `False`, the given vertex will be checked.

Returnsn_neighbours (*int*) – The number of neighbours.

Raises`ValueError` – The vertex must be between 0 and {n_vertices-1}.

n_paths(*start*, *end*)

Returns the number of all the paths (without cycles) existing from start vertex to end vertex.

Parameters

- **start** (*int*) – The vertex from which the paths start.
- **end** (*int*) – The vertex from which the paths end.

Returnspaths (*int*) – The paths' numbers.

neighbours(*vertex*, *skip_checks=False*)

Returns the neighbours of the selected vertex.

Parameters

- **vertex** (*int*) – The selected vertex.
- **skip_checks** (*bool*, optional) – If `False`, the given vertex will be checked.

Returnsneighbours (*list*) – The list of neighbours.

Raises`ValueError` – The vertex must be between 0 and {n_vertices-1}.

n_edges

Returns the number of edges.

Type*int*

n_vertices

Returns the number of vertices.

Type*int*

vertices

Returns the *list* of vertices.

Type*list*

DirectedGraph

class `menpo.shape.`**DirectedGraph**(*adjacency_matrix*, *copy=True*, *skip_checks=False*)

Bases: `Graph`

Class for Directed Graph definition and manipulation.

Parameters

- **adjacency_matrix** (`(n_vertices, n_vertices, )` *ndarray* or *csr_matrix*) – The adjacency matrix of the graph in which the rows represent source vertices and columns represent destination vertices. The non-edges must be represented with zeros and the edges can have a weight value.
- **copy** (*bool*, optional) – If `False`, the `adjacency_matrix` will not be copied on assignment.
- **skip_checks** (*bool*, optional) – If `True`, no checks will be performed.

Raises

- `ValueError` – adjacency_matrix must be either a numpy.ndarray or a scipy.sparse.csr_matrix.
- `ValueError` – Graph must have at least two vertices.
- `ValueError` – adjacency_matrix must be square (n_vertices, n_vertices,), ({adjacency_matrix.shape[0]}, {adjacency_matrix.shape[1]}) given instead.

Examples

The following directed graph

```
|-->0<--|
|       |
|       |
1<----->2
|       |
```

```
v        v
3------>4
|
v
5
```

can be defined as

```
import numpy as np
adjacency_matrix = np.array([[0, 0, 0, 0, 0, 0],
                             [1, 0, 1, 1, 0, 0],
                             [1, 1, 0, 0, 1, 0],
                             [0, 0, 0, 0, 1, 1],
                             [0, 0, 0, 0, 0, 0],
                             [0, 0, 0, 0, 0, 0]])
graph = DirectedGraph(adjacency_matrix)
```

or

```
from scipy.sparse import csr_matrix
adjacency_matrix = csr_matrix(([1] * 8, ([1, 2, 1, 2, 1, 2, 3, 3],
                                          [0, 0, 2, 1, 3, 4, 4, 5])),
                              shape=(6, 6))
graph = DirectedGraph(adjacency_matrix)
```

The following graph with isolated vertices

```
       0<--|
           |
           |
   1       2
           |
           v
   3------>4

5
```

---

can be defined as

```
import numpy as np
adjacency_matrix = np.array([[0, 0, 0, 0, 0, 0],
                             [0, 0, 0, 0, 0, 0],
                             [1, 0, 0, 0, 1, 0],
                             [0, 0, 0, 0, 1, 0],
                             [0, 0, 0, 0, 0, 0],
                             [0, 0, 0, 0, 0, 0]])
graph = DirectedGraph(adjacency_matrix)
```

or

```
from scipy.sparse import csr_matrix
adjacency_matrix = csr_matrix(([1] * 3, ([2, 2, 3], [0, 4, 4])),
                              shape=(6, 6))
graph = DirectedGraph(adjacency_matrix)
```

children(*vertex*, *skip_checks=False*)

Returns the children of the selected vertex.

Parameters

- **vertex** (*int*) – The selected vertex.
- **skip_checks** (*bool*, optional) – If `False`, the given vertex will be checked.

Returnschildren (*list*) – The list of children.

Raises`ValueError` – The vertex must be between 0 and {n_vertices-1}.

find_all_paths (*start*, *end*, *path=[]*)

Returns a list of lists with all the paths (without cycles) found from start vertex to end vertex.

Parameters

- **start** (*int*) – The vertex from which the paths start.
- **end** (*int*) – The vertex from which the paths end.
- **path** (*list*, optional) – An existing path to append to.

Returnspaths (*list* of *list*) – The list containing all the paths from start to end.

find_all_shortest_paths (*algorithm='auto'*, *unweighted=False*)

Returns the distances and predecessors arrays of the graph's shortest paths.

Parameters

- **algorithm** (*`'str', see below, optional`*) – The algorithm to be used. Possible options are:

'dijkstra'	Dijkstra's algorithm with Fibonacci heaps
'bellman-ford'	Bellman-Ford algorithm
'johnson'	Johnson's algorithm
'floyd-warshall'	Floyd-Warshall algorithm
'auto'	Select the best among the above

- **unweighted** (*bool*, optional) – If `True`, then find unweighted distances. That is, rather than finding the path between each vertex such that the sum of weights is minimized, find the path such that the number of edges is minimized.

Returns

- **distances** (`(n_vertices, n_vertices,)` *ndarray*) – The matrix of distances between all graph vertices. `distances[i,j]` gives the shortest distance from vertex `i` to vertex `j` along the graph.
- **predecessors** (`(n_vertices, n_vertices,)` *ndarray*) – The matrix of predecessors, which can be used to reconstruct the shortest paths. Each entry `predecessors[i, j]` gives the index of the previous vertex in the path from vertex `i` to vertex `j`. If no path exists between vertices `i` and `j`, then `predecessors[i, j] = -9999`.

find_path (*start*, *end*, *method='bfs'*, *skip_checks=False*)

Returns a *list* with the first path (without cycles) found from the `start` vertex to the `end` vertex. It can employ either depth-first search or breadth-first search.

Parameters

- **start** (*int*) – The vertex from which the path starts.
- **end** (*int*) – The vertex to which the path ends.
- **method** ({`bfs`, `dfs`}, optional) – The method to be used.
- **skip_checks** (*bool*, optional) – If `True`, then input arguments won't pass through checks. Useful for efficiency.

Returnspath (*list*) – The path's vertices.

Raises`ValueError` – Method must be either bfs or dfs.

find_shortest_path(*start*, *end*, *algorithm='auto'*, *unweighted=False*, *skip_checks=False*)

Returns a *list* with the shortest path (without cycles) found from `start` vertex to `end` vertex.

Parameters

- **start** (*int*) – The vertex from which the path starts.
- **end** (*int*) – The vertex to which the path ends.
- **algorithm** (*'str', see below, optional*) – The algorithm to be used. Possible options are:

'dijkstra'	Dijkstra's algorithm with Fibonacci heaps
'bellman-ford'	Bellman-Ford algorithm
'johnson'	Johnson's algorithm
'floyd-warshall'	Floyd-Warshall algorithm
'auto'	Select the best among the above

- **unweighted** (*bool*, optional) – If `True`, then find unweighted distances. That is, rather than finding the path such that the sum of weights is minimized, find the path such that the number of edges is minimized.
- **skip_checks** (*bool*, optional) – If `True`, then input arguments won't pass through checks. Useful for efficiency.

Returns

- **path** (*list*) – The shortest path's vertices, including `start` and `end`. If there was not path connecting the vertices, then an empty *list* is returned.
- **distance** (*int* or *float*) – The distance (cost) of the path from `start` to `end`.

get_adjacency_list()

Returns the adjacency list of the graph, i.e. a *list* of length `n_vertices` that for each vertex has a *list* of the vertex neighbours. If the graph is directed, the neighbours are children.

Returnsadjacency_list (*list* of *list* of length `n_vertices`) – The adjacency list of the graph.

has_cycles()

Checks if the graph has at least one cycle.

Returnshas_cycles (*bool*) – `True` if the graph has cycles.

has_isolated_vertices()

Whether the graph has any isolated vertices, i.e. vertices with no edge connections.

Returnshas_isolated_vertices (*bool*) – `True` if the graph has at least one isolated vertex.

init_from_edges(*edges*, *n_vertices*, *skip_checks=False*)

Initialize graph from edges array.

Parameters

- **edges** (*`(n_edges, 2, )` ndarray*) – The *ndarray* of edges, i.e. all the pairs of vertices that are connected with an edge.
- **n_vertices** (*int*) – The total number of vertices, assuming that the numbering of vertices starts from `0`. `edges` and `n_vertices` can be defined in a way to set isolated vertices.
- **skip_checks** (*bool*, optional) – If `True`, no checks will be performed.

Examples

The following undirected graph

```
|---0---|
|       |
|       |
1-------2
|       |
|       |
3-------4
|
|
5
```

can be defined as

```
from menpo.shape import UndirectedGraph
import numpy as np
edges = np.array([[0, 1], [1, 0], [0, 2], [2, 0], [1, 2], [2, 1],
                  [1, 3], [3, 1], [2, 4], [4, 2], [3, 4], [4, 3],
                  [3, 5], [5, 3]])
graph = UndirectedGraph.init_from_edges(edges, n_vertices=6)
```

The following directed graph

```
|-->0<--|
|       |
|       |
1<----->2
|       |
v       v
3------>4
|
v
5
```

can be represented as

```
from menpo.shape import DirectedGraph
import numpy as np
edges = np.array([[1, 0], [2, 0], [1, 2], [2, 1], [1, 3], [2, 4],
                  [3, 4], [3, 5]])
graph = DirectedGraph.init_from_edges(edges, n_vertices=6)
```

Finally, the following graph with isolated vertices

```
    0---|
        |
        |
1       2
        |
        |
3-------4


5
```

can be defined as

```
from menpo.shape import UndirectedGraph
import numpy as np
edges = np.array([[0, 2], [2, 0], [2, 4], [4, 2], [3, 4], [4, 3]])
graph = UndirectedGraph.init_from_edges(edges, n_vertices=6)
```

is_edge (*vertex_1*, *vertex_2*, *skip_checks=False*)

Whether there is an edge between the provided vertices.

Parameters

- **vertex_1** (*int*) – The first selected vertex. Parent if the graph is directed.
- **vertex_2** (*int*) – The second selected vertex. Child if the graph is directed.
- **skip_checks** (*bool*, optional) – If `False`, the given vertices will be checked.

Returnsis_edge (*bool*) – `True` if there is an edge connecting `vertex_1` and `vertex_2`.

Raises`ValueError` – The vertex must be between 0 and {n_vertices-1}.

is_tree ()

Checks if the graph is tree.

Returnsis_true (*bool*) – If the graph is a tree.

isolated_vertices ()

Returns the isolated vertices of the graph (if any), i.e. the vertices that have no edge connections.

Returnsisolated_vertices (*list*) – A *list* of the isolated vertices. If there aren't any, it returns an empty *list*.

n_children (*vertex*, *skip_checks=False*)

Returns the number of children of the selected vertex.

Parametersvertex (*int*) – The selected vertex.

Returns

- **n_children** (*int*) – The number of children.
- **skip_checks** (*bool*, optional) – If `False`, the given vertex will be checked.

Raises`ValueError` – The vertex must be in the range `[0, n_vertices - 1]`.

n_parents (*vertex*, *skip_checks=False*)

Returns the number of parents of the selected vertex.

Parameters

- **vertex** (*int*) – The selected vertex.
- **skip_checks** (*bool*, optional) – If `False`, the given vertex will be checked.

Returnsn_parents (*int*) – The number of parents.

Raises`ValueError` – The vertex must be in the range `[0, n_vertices - 1]`.

n_paths (*start*, *end*)

Returns the number of all the paths (without cycles) existing from start vertex to end vertex.

Parameters

- **start** (*int*) – The vertex from which the paths start.
- **end** (*int*) – The vertex from which the paths end.

Returnspaths (*int*) – The paths' numbers.

parents (*vertex*, *skip_checks=False*)

Returns the parents of the selected vertex.

Parameters

- **vertex** (*int*) – The selected vertex.
- **skip_checks** (*bool*, optional) – If `False`, the given vertex will be checked.

Returnsparents (*list*) – The list of parents.

Raises`ValueError` – The vertex must be in the range `[0, n_vertices - 1]`.

n_edges

Returns the number of edges.

Type*int*

n_vertices

Returns the number of vertices.

Type*int*

vertices

Returns the *list* of vertices.

Type*list*

Tree

class `menpo.shape.`**Tree** (*adjacency_matrix*, *root_vertex*, *copy=True*, *skip_checks=False*)

Bases: `DirectedGraph`

Class for Tree definitions and manipulation.

Parameters

- **adjacency_matrix** (`(n_vertices, n_vertices, )` *ndarray* or *csr_matrix*) – The adjacency matrix of the tree in which the rows represent parents and columns represent children. The non-edges must be represented with zeros and the edges can have a weight value.

  NoteA tree must not have isolated vertices.
- **root_vertex** (*int*) – The vertex to be set as root.
- **copy** (*bool*, optional) – If `False`, the `adjacency_matrix` will not be copied on assignment.
- **skip_checks** (*bool*, optional) – If `True`, no checks will be performed.

Raises

- `ValueError` – adjacency_matrix must be either a numpy.ndarray or a scipy.sparse.csr_matrix.
- `ValueError` – Graph must have at least two vertices.
- `ValueError` – adjacency_matrix must be square (n_vertices, n_vertices,), ({adjacency_matrix.shape[0]}, {adjacency_matrix.shape[1]}) given instead.
- `ValueError` – The provided edges do not represent a tree.
- `ValueError` – The root_vertex must be in the range `[0, n_vertices - 1]`.

- `ValueError` – The combination of adjacency matrix and root vertex is not valid. BFS returns a different tree.

Examples

The following tree

```
       0
       |
   ____|____
  1        2
  |        |
 _|_       |
3   4      5
|   |      |
|   |      |
6   7      8
```

can be defined as

```
import numpy as np
adjacency_matrix = np.array([[0, 1, 1, 0, 0, 0, 0, 0, 0],
                             [0, 0, 0, 1, 1, 0, 0, 0, 0],
                             [0, 0, 0, 0, 0, 1, 0, 0, 0],
                             [0, 0, 0, 0, 0, 0, 1, 0, 0],
                             [0, 0, 0, 0, 0, 0, 0, 1, 0],
                             [0, 0, 0, 0, 0, 0, 0, 0, 1],
                             [0, 0, 0, 0, 0, 0, 0, 0, 0],
                             [0, 0, 0, 0, 0, 0, 0, 0, 0],
                             [0, 0, 0, 0, 0, 0, 0, 0, 0]])
tree = Tree(adjacency_matrix, root_vertex=0)
```

or

```
from scipy.sparse import csr_matrix
adjacency_matrix = csr_matrix(([1] * 8, ([0, 0, 1, 1, 2, 3, 4, 5],
                                          [1, 2, 3, 4, 5, 6, 7, 8])),
                              shape=(9, 9))
tree = Tree(adjacency_matrix, root_vertex=0)
```

children (*vertex*, *skip_checks=False*)

Returns the children of the selected vertex.

Parameters

- **vertex** (*int*) – The selected vertex.
- **skip_checks** (*bool*, optional) – If `False`, the given vertex will be checked.

Returns **children** (*list*) – The list of children.

Raises `ValueError` – The vertex must be between 0 and {n_vertices-1}.

depth_of_vertex (*vertex*, *skip_checks=False*)

Returns the depth of the specified vertex.

Parameters

- **vertex** (*int*) – The selected vertex.

- **skip_checks** (*bool*, optional) – If `False`, the given vertex will be checked.

Returnsdepth (*int*) – The depth of the selected vertex.

Raises`ValueError` – The vertex must be in the range `[0, n_vertices - 1]`.

find_all_paths(*start*, *end*, *path=[]*)

Returns a list of lists with all the paths (without cycles) found from start vertex to end vertex.

Parameters

- **start** (*int*) – The vertex from which the paths start.
- **end** (*int*) – The vertex from which the paths end.
- **path** (*list*, optional) – An existing path to append to.

Returnspaths (*list* of *list*) – The list containing all the paths from start to end.

find_all_shortest_paths(*algorithm='auto'*, *unweighted=False*)

Returns the distances and predecessors arrays of the graph's shortest paths.

Parameters

- **algorithm** (*`'str', see below, optional`*) – The algorithm to be used. Possible options are:

'dijkstra'	Dijkstra's algorithm with Fibonacci heaps
'bellman-ford'	Bellman-Ford algorithm
'johnson'	Johnson's algorithm
'floyd-warshall'	Floyd-Warshall algorithm
'auto'	Select the best among the above

- **unweighted** (*bool*, optional) – If `True`, then find unweighted distances. That is, rather than finding the path between each vertex such that the sum of weights is minimized, find the path such that the number of edges is minimized.

Returns

- **distances** (`(n_vertices, n_vertices,)` *ndarray*) – The matrix of distances between all graph vertices. `distances[i,j]` gives the shortest distance from vertex `i` to vertex `j` along the graph.
- **predecessors** (`(n_vertices, n_vertices,)` *ndarray*) – The matrix of predecessors, which can be used to reconstruct the shortest paths. Each entry `predecessors[i, j]` gives the index of the previous vertex in the path from vertex `i` to vertex `j`. If no path exists between vertices `i` and `j`, then `predecessors[i, j] = -9999`.

find_path(*start*, *end*, *method='bfs'*, *skip_checks=False*)

Returns a *list* with the first path (without cycles) found from the `start` vertex to the `end` vertex. It can employ either depth-first search or breadth-first search.

Parameters

- **start** (*int*) – The vertex from which the path starts.
- **end** (*int*) – The vertex to which the path ends.
- **method** (`{bfs, dfs}`, optional) – The method to be used.
- **skip_checks** (*bool*, optional) – If `True`, then input arguments won't pass through checks. Useful for efficiency.

Returnspath (*list*) – The path's vertices.

Raises`ValueError` – Method must be either bfs or dfs.

find_shortest_path(*start*, *end*, *algorithm='auto'*, *unweighted=False*, *skip_checks=False*)

Returns a *list* with the shortest path (without cycles) found from `start` vertex to `end` vertex.

Parameters

- **start** (*int*) – The vertex from which the path starts.
- **end** (*int*) – The vertex to which the path ends.
- **algorithm** (*'str', see below, optional*) – The algorithm to be used. Possible options are:

'dijkstra'	Dijkstra's algorithm with Fibonacci heaps
'bellman-ford'	Bellman-Ford algorithm
'johnson'	Johnson's algorithm
'floyd-warshall'	Floyd-Warshall algorithm
'auto'	Select the best among the above

- **unweighted** (*bool*, optional) – If `True`, then find unweighted distances. That is, rather than finding the path such that the sum of weights is minimized, find the path such that the number of edges is minimized.
- **skip_checks** (*bool*, optional) – If `True`, then input arguments won't pass through checks. Useful for efficiency.

Returns

- **path** (*list*) – The shortest path's vertices, including `start` and `end`. If there was not path connecting the vertices, then an empty *list* is returned.
- **distance** (*int* or *float*) – The distance (cost) of the path from `start` to `end`.

get_adjacency_list()

Returns the adjacency list of the graph, i.e. a *list* of length `n_vertices` that for each vertex has a *list* of the vertex neighbours. If the graph is directed, the neighbours are children.

Returnsadjacency_list (*list* of *list* of length `n_vertices`) – The adjacency list of the graph.

has_cycles()

Checks if the graph has at least one cycle.

Returnshas_cycles (*bool*) – `True` if the graph has cycles.

has_isolated_vertices()

Whether the graph has any isolated vertices, i.e. vertices with no edge connections.

Returnshas_isolated_vertices (*bool*) – `True` if the graph has at least one isolated vertex.

classmethod init_from_edges(*edges*, *n_vertices*, *root_vertex*, *copy=True*, *skip_checks=False*)

Construct a *`Tree`* from edges array.

Parameters

- **edges** (*`(n_edges, 2, )` ndarray*) – The *ndarray* of edges, i.e. all the pairs of vertices that are connected with an edge.
- **n_vertices** (*int*) – The total number of vertices, assuming that the numbering of vertices starts from `0`. `edges` and `n_vertices` can be defined in a way to set isolated vertices.
- **root_vertex** (*int*) – That vertex that will be set as root.
- **copy** (*bool*, optional) – If `False`, the `adjacency_matrix` will not be copied on assignment.

- **skip_checks** (*bool*, optional) – If `True`, no checks will be performed.

Examples

The following tree

```
       0
       |
   ____|____
  1        2
  |        |
 _|_       |
3   4      5
|   |      |
|   |      |
6   7      8
```

can be defined as

```
from menpo.shape import PointTree
import numpy as np
points = np.array([[30, 30], [10, 20], [50, 20], [0, 10], [20, 10],
                   [50, 10], [0, 0], [20, 0], [50, 0]])
edges = np.array([[0, 1], [0, 2], [1, 3], [1, 4], [2, 5], [3, 6],
                  [4, 7], [5, 8]])
tree = PointTree.init_from_edges(points, edges, root_vertex=0)
```

is_edge (*vertex_1*, *vertex_2*, *skip_checks=False*)

Whether there is an edge between the provided vertices.

Parameters

- **vertex_1** (*int*) – The first selected vertex. Parent if the graph is directed.
- **vertex_2** (*int*) – The second selected vertex. Child if the graph is directed.
- **skip_checks** (*bool*, optional) – If `False`, the given vertices will be checked.

Returnsis_edge (*bool*) – `True` if there is an edge connecting `vertex_1` and `vertex_2`.

Raises`ValueError` – The vertex must be between 0 and {n_vertices-1}.

is_leaf (*vertex*, *skip_checks=False*)

Whether the vertex is a leaf.

Parameters

- **vertex** (*int*) – The selected vertex.
- **skip_checks** (*bool*, optional) – If `False`, the given vertex will be checked.

Returnsis_leaf (*bool*) – If `True`, then selected vertex is a leaf.

Raises`ValueError` – The vertex must be in the range `[0, n_vertices - 1]`.

is_tree ()

Checks if the graph is tree.

Returnsis_true (*bool*) – If the graph is a tree.

isolated_vertices ()

Returns the isolated vertices of the graph (if any), i.e. the vertices that have no edge connections.

Returnsisolated_vertices (*list*) – A *list* of the isolated vertices. If there aren't any, it returns an empty *list*.

n_children (*vertex*, *skip_checks=False*)
Returns the number of children of the selected vertex.

Parametersvertex (*int*) – The selected vertex.

Returns

- **n_children** (*int*) – The number of children.
- **skip_checks** (*bool*, optional) – If `False`, the given vertex will be checked.

Raises`ValueError` – The vertex must be in the range `[0, n_vertices - 1]`.

n_parents (*vertex*, *skip_checks=False*)
Returns the number of parents of the selected vertex.

Parameters

- **vertex** (*int*) – The selected vertex.
- **skip_checks** (*bool*, optional) – If `False`, the given vertex will be checked.

Returnsn_parents (*int*) – The number of parents.

Raises`ValueError` – The vertex must be in the range `[0, n_vertices - 1]`.

n_paths (*start*, *end*)
Returns the number of all the paths (without cycles) existing from start vertex to end vertex.

Parameters

- **start** (*int*) – The vertex from which the paths start.
- **end** (*int*) – The vertex from which the paths end.

Returnspaths (*int*) – The paths' numbers.

n_vertices_at_depth (*depth*)
Returns the number of vertices at the specified depth.

Parametersdepth (*int*) – The selected depth.

Returnsn_vertices (*int*) – The number of vertices that lie in the specified depth.

parent (*vertex*, *skip_checks=False*)
Returns the parent of the selected vertex.

Parameters

- **vertex** (*int*) – The selected vertex.
- **skip_checks** (*bool*, optional) – If `False`, the given vertex will be checked.

Returnsparent (*int*) – The parent vertex.

Raises`ValueError` – The vertex must be in the range `[0, n_vertices - 1]`.

parents (*vertex*, *skip_checks=False*)
Returns the parents of the selected vertex.

Parameters

- **vertex** (*int*) – The selected vertex.
- **skip_checks** (*bool*, optional) – If `False`, the given vertex will be checked.

Returnsparents (*list*) – The list of parents.

Raises`ValueError` – The vertex must be in the range `[0, n_vertices - 1]`.

vertices_at_depth(*depth*)

Returns a list of vertices at the specified depth.

Parametersdepth (*int*) – The selected depth.

Returnsvertices (*list*) – The vertices that lie in the specified depth.

leaves

Returns a *list* with the all leaves of the tree.

Type*list*

maximum_depth

Returns the maximum depth of the tree.

Type*int*

n_edges

Returns the number of edges.

Type*int*

n_leaves

Returns the number of leaves of the tree.

Type*int*

n_vertices

Returns the number of vertices.

Type*int*

vertices

Returns the *list* of vertices.

Type*list*

PointGraphs

Mix-ins of Graphs and `PointCloud` for graphs with geometry.

PointUndirectedGraph

class `menpo.shape.`**PointUndirectedGraph**(*points*, *adjacency_matrix*, *copy=True*, *skip_checks=False*)

Bases: `PointGraph`, `UndirectedGraph`

Class for defining an Undirected Graph with geometry.

Parameters

- **points** (`(n_vertices, n_dims, )` *ndarray*) – The array of point locations.
- **adjacency_matrix** (`(n_vertices, n_vertices, )` *ndarray* or *csr_matrix*) – The adjacency matrix of the graph. The non-edges must be represented with zeros and the edges can have a weight value.

  Note`adjacency_matrix` must be symmetric.

- **copy** (*bool*, optional) – If `False`, the `adjacency_matrix` will not be copied on assignment.
- **skip_checks** (*bool*, optional) – If `True`, no checks will be performed.

Raises

- `ValueError` – A point for each graph vertex needs to be passed. Got `n_points` points instead of `n_vertices`.
- `ValueError` – adjacency_matrix must be either a numpy.ndarray or a scipy.sparse.csr_matrix.
- `ValueError` – Graph must have at least two vertices.
- `ValueError` – adjacency_matrix must be square (n_vertices, n_vertices,), ({adjacency_matrix.shape[0]}, {adjacency_matrix.shape[1]}) given instead.
- `ValueError` – The adjacency matrix of an undirected graph must be symmetric.

Examples

The following undirected graph

```
|---0---|
|       |
|       |
1-------2
|       |
|       |
3-------4
|
|
5
```

can be defined as

```
import numpy as np
adjacency_matrix = np.array([[0, 1, 1, 0, 0, 0],
                             [1, 0, 1, 1, 0, 0],
                             [1, 1, 0, 0, 1, 0],
                             [0, 1, 0, 0, 1, 1],
                             [0, 0, 1, 1, 0, 0],
                             [0, 0, 0, 1, 0, 0]])
points = np.array([[10, 30], [0, 20], [20, 20], [0, 10], [20, 10],
                   [0, 0]])
graph = PointUndirectedGraph(points, adjacency_matrix)
```

or

```
from scipy.sparse import csr_matrix
adjacency_matrix = csr_matrix(
                    ([1] * 14,
                     ([0, 1, 0, 2, 1, 2, 1, 3, 2, 4, 3, 4, 3, 5],
                      [1, 0, 2, 0, 2, 1, 3, 1, 4, 2, 4, 3, 5, 3])),
                    shape=(6, 6))
points = np.array([[10, 30], [0, 20], [20, 20], [0, 10], [20, 10],
                   [0, 0]])
graph = PointUndirectedGraph(points, adjacency_matrix)
```

The adjacency matrix of the following graph with isolated vertices

```
       0---|
           |
           |
   1       2
           |
           |
   3-------4

5
```

---

can be defined as

```
import numpy as np
adjacency_matrix = np.array([[0, 0, 1, 0, 0, 0],
                             [0, 0, 0, 0, 0, 0],
                             [1, 0, 0, 0, 1, 0],
                             [0, 0, 0, 0, 1, 0],
                             [0, 0, 1, 1, 0, 0],
                             [0, 0, 0, 0, 0, 0]])
points = np.array([[10, 30], [0, 20], [20, 20], [0, 10], [20, 10],
                   [0, 0]])
graph = PointUndirectedGraph(points, adjacency_matrix)
```

or

```
from scipy.sparse import csr_matrix
adjacency_matrix = csr_matrix(([1] * 6, ([0, 2, 2, 4, 3, 4],
                                          [2, 0, 4, 2, 4, 3])),
                              shape=(6, 6))
points = np.array([[10, 30], [0, 20], [20, 20], [0, 10], [20, 10],
                   [0, 0]])
graph = PointUndirectedGraph(points, adjacency_matrix)
```

_view_2d(*figure_id=None*, *new_figure=False*, *image_view=True*, *render_lines=True*, *line_colour='r'*, *line_style='-'*, *line_width=1.0*, *render_markers=True*, *marker_style='o'*, *marker_size=5*, *marker_face_colour='k'*, *marker_edge_colour='k'*, *marker_edge_width=1.0*, *render_numbering=False*, *numbers_horizontal_align='center'*, *numbers_vertical_align='bottom'*, *numbers_font_name='sans-serif'*, *numbers_font_size=10*, *numbers_font_style='normal'*, *numbers_font_weight='normal'*, *numbers_font_colour='k'*, *render_axes=True*, *axes_font_name='sans-serif'*, *axes_font_size=10*, *axes_font_style='normal'*, *axes_font_weight='normal'*, *axes_x_limits=None*, *axes_y_limits=None*, *axes_x_ticks=None*, *axes_y_ticks=None*, *figure_size=(7, 7)*, *label=None*, ***kwargs*)

Visualization of the PointGraph in 2D.

Returns

- **figure_id** (*object*, optional) – The id of the figure to be used.
- **new_figure** (*bool*, optional) – If `True`, a new figure is created.
- **image_view** (*bool*, optional) – If `True` the PointGraph will be viewed as if it is in the image coordinate system.
- **render_lines** (*bool*, optional) – If `True`, the edges will be rendered.
- **line_colour** (*See Below, optional*) – The colour of the lines. Example options:

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

•**line_style** ({'-', '--', '-.', ':'}, optional) – The style of the lines.

•**line_width** (*float*, optional) – The width of the lines.

•**render_markers** (*bool*, optional) – If `True`, the markers will be rendered.

•**marker_style** (*See Below, optional*) –

The style of the markers. Example options

```
{., ,, o, v, ^, <, >, +, x, D, d, s, p, *, h, H, 1, 2, 3, 4, 8}
```

•**marker_size** (*int*, optional) – The size of the markers in points.

•**marker_face_colour** (*See Below, optional*) – The face (filling) colour of the markers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

•**marker_edge_colour** (*See Below, optional*) – The edge colour of the markers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

•**marker_edge_width** (*float*, optional) – The width of the markers' edge.

•**render_numbering** (*bool*, optional) – If `True`, the landmarks will be numbered.

•**numbers_horizontal_align** ({center, right, left}, optional) – The horizontal alignment of the numbers' texts.

•**numbers_vertical_align** ({center, top, bottom, baseline}, optional) – The vertical alignment of the numbers' texts.

•**numbers_font_name** (*See Below, optional*) –

The font of the numbers. Example options

```
{serif, sans-serif, cursive, fantasy, monospace}
```

•**numbers_font_size** (*int*, optional) – The font size of the numbers.

•**numbers_font_style** ({normal, italic, oblique}, optional) – The font style of the numbers.

•**numbers_font_weight** (*See Below, optional*) – The font weight of the numbers. Example options

```
{ultralight, light, normal, regular, book, medium, roman,
semibold, demibold, demi, bold, heavy, extra bold, black}
```

•**numbers_font_colour** (*See Below, optional*) – The font colour of the numbers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

•**render_axes** (*bool*, optional) – If `True`, the axes will be rendered.

•**axes_font_name** (*See Below, optional*) – The font of the axes. Example options

```
{serif, sans-serif, cursive, fantasy, monospace}
```

•**axes_font_size** (*int*, optional) – The font size of the axes.

•**axes_font_style** ({`normal`, `italic`, `oblique`}, optional) – The font style of the axes.

•**axes_font_weight** (*See Below, optional*) – The font weight of the axes. Example options

```
{ultralight, light, normal, regular, book, medium, roman,
semibold, demibold, demi, bold, heavy, extra bold, black}
```

•**axes_x_limits** (*float* or (*float*, *float*) or `None`, optional) – The limits of the x axis. If *float*, then it sets padding on the right and left of the PointGraph as a percentage of the PointGraph's width. If *tuple* or *list*, then it defines the axis limits. If `None`, then the limits are set automatically.

•**axes_y_limits** ((*float*, *float*) *tuple* or `None`, optional) – The limits of the y axis. If *float*, then it sets padding on the top and bottom of the PointGraph as a percentage of the PointGraph's height. If *tuple* or *list*, then it defines the axis limits. If `None`, then the limits are set automatically.

•**axes_x_ticks** (*list* or *tuple* or `None`, optional) – The ticks of the x axis.

•**axes_y_ticks** (*list* or *tuple* or `None`, optional) – The ticks of the y axis.

•**figure_size** ((*float*, *float*) *tuple* or `None`, optional) – The size of the figure in inches.

•**label** (*str*, optional) – The name entry in case of a legend.

Returnsviewer (`PointGraphViewer2d`) – The viewer object.

_view_landmarks_2d(*group=None*, *with_labels=None*, *without_labels=None*, *figure_id=None*, *new_figure=False*, *image_view=True*, *render_lines=True*, *line_colour='k'*, *line_style='-'*, *line_width=2*, *render_markers=True*, *marker_style='s'*, *marker_size=7*, *marker_face_colour='k'*, *marker_edge_colour='k'*, *marker_edge_width=1.0*, *render_lines_lms=True*, *line_colour_lms=None*, *line_style_lms='-'*, *line_width_lms=1*, *render_markers_lms=True*, *marker_style_lms='o'*, *marker_size_lms=5*, *marker_face_colour_lms=None*, *marker_edge_colour_lms=None*, *marker_edge_width_lms=1.0*, *render_numbering=False*, *numbers_horizontal_align='center'*, *numbers_vertical_align='bottom'*, *numbers_font_name='sans-serif'*, *numbers_font_size=10*, *numbers_font_style='normal'*, *numbers_font_weight='normal'*, *numbers_font_colour='k'*, *render_legend=False*, *legend_title=''*, *legend_font_name='sans-serif'*, *legend_font_style='normal'*, *legend_font_size=10*, *legend_font_weight='normal'*, *legend_marker_scale=None*, *legend_location=2*, *legend_bbox_to_anchor=(1.05, 1.0)*, *legend_border_axes_pad=None*, *legend_n_columns=1*, *legend_horizontal_spacing=None*, *legend_vertical_spacing=None*, *legend_border=True*, *legend_border_padding=None*, *legend_shadow=False*, *legend_rounded_corners=False*, *render_axes=False*, *axes_font_name='sans-serif'*, *axes_font_size=10*, *axes_font_style='normal'*, *axes_font_weight='normal'*, *axes_x_limits=None*, *axes_y_limits=None*, *axes_x_ticks=None*, *axes_y_ticks=None*, *figure_size=(7, 7)*)

Visualize the landmarks. This method will appear on the *PointGraph* as `view_landmarks`.

Parameters

- **group** (*str* or''None'' optional) – The landmark group to be visualized. If `None` and there are more than one landmark groups, an error is raised.
- **with_labels** (`None` or *str* or *list* of *str*, optional) – If not `None`, only show the given label(s). Should **not** be used with the `without_labels` kwarg.
- **without_labels** (`None` or *str* or *list* of *str*, optional) – If not `None`, show all except the given label(s). Should **not** be used with the `with_labels` kwarg.
- **figure_id** (*object*, optional) – The id of the figure to be used.
- **new_figure** (*bool*, optional) – If `True`, a new figure is created.
- **image_view** (*bool*, optional) – If `True` the PointCloud will be viewed as if it is in the image coordinate system.
- **render_lines** (*bool*, optional) – If `True`, the edges will be rendered.
- **line_colour** (*See Below, optional*) – The colour of the lines. Example options:

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **line_style** (`{-, --, -., :}`, optional) – The style of the lines.
- **line_width** (*float*, optional) – The width of the lines.
- **render_markers** (*bool*, optional) – If `True`, the markers will be rendered.
- **marker_style** (*See Below, optional*) – The style of the markers. Example options

```
{., ,, o, v, ^, <, >, +, x, D, d, s, p, *, h, H, 1, 2, 3, 4, 8}
```

- **marker_size** (*int*, optional) – The size of the markers in points.
- **marker_face_colour** (*See Below, optional*) – The face (filling) colour of the markers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **marker_edge_colour** (*See Below, optional*) – The edge colour of the markers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **marker_edge_width** (*float*, optional) – The width of the markers' edge.
- **render_lines_lms** (*bool*, optional) – If `True`, the edges of the landmarks will be rendered.
- **line_colour_lms** (*See Below, optional*) – The colour of the lines of the landmarks. Example options:

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **line_style_lms** (`{-, --, -., :}`, optional) – The style of the lines of the landmarks.
- **line_width_lms** (*float*, optional) – The width of the lines of the landmarks.
- **render_markers** – If `True`, the markers of the landmarks will be rendered.
- **marker_style** – The style of the markers of the landmarks. Example options

```
{., ,, o, v, ^, <, >, +, x, D, d, s, p, *, h, H, 1, 2, 3, 4, 8}
```

- **marker_size** – The size of the markers of the landmarks in points.
- **marker_face_colour** – The face (filling) colour of the markers of the landmarks. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **marker_edge_colour** – The edge colour of the markers of the landmarks. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **marker_edge_width** – The width of the markers' edge of the landmarks.
- **render_numbering** (*bool*, optional) – If `True`, the landmarks will be numbered.

- **numbers_horizontal_align** (`{center, right, left}`, optional) – The horizontal alignment of the numbers' texts.
- **numbers_vertical_align** (`{center, top, bottom, baseline}`, optional) – The vertical alignment of the numbers' texts.
- **numbers_font_name** (*See Below, optional*) – The font of the numbers. Example options

```
{serif, sans-serif, cursive, fantasy, monospace}
```

- **numbers_font_size** (*int*, optional) – The font size of the numbers.
- **numbers_font_style** (`{normal, italic, oblique}`, optional) – The font style of the numbers.
- **numbers_font_weight** (*See Below, optional*) – The font weight of the numbers. Example options

```
{ultralight, light, normal, regular, book, medium, roman,
semibold, demibold, demi, bold, heavy, extra bold, black}
```

- **numbers_font_colour** (*See Below, optional*) – The font colour of the numbers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **render_legend** (*bool*, optional) – If `True`, the legend will be rendered.
- **legend_title** (*str*, optional) – The title of the legend.
- **legend_font_name** (*See below, optional*) – The font of the legend. Example options

```
{serif, sans-serif, cursive, fantasy, monospace}
```

- **legend_font_style** (`{normal, italic, oblique}`, optional) – The font style of the legend.
- **legend_font_size** (*int*, optional) – The font size of the legend.
- **legend_font_weight** (*See Below, optional*) – The font weight of the legend. Example options

```
{ultralight, light, normal, regular, book, medium, roman,
semibold, demibold, demi, bold, heavy, extra bold, black}
```

- **legend_marker_scale** (*float*, optional) – The relative size of the legend markers with respect to the original
- **legend_location** (*int*, optional) – The location of the legend. The predefined values are:

'best'	0
'upper right'	1
'upper left'	2
'lower left'	3
'lower right'	4
'right'	5
'center left'	6
'center right'	7
'lower center'	8
'upper center'	9
'center'	10

- **legend_bbox_to_anchor** ((*float*, *float*) *tuple*, optional) – The bbox that the legend will be anchored.
- **legend_border_axes_pad** (*float*, optional) – The pad between the axes and legend border.
- **legend_n_columns** (*int*, optional) – The number of the legend's columns.
- **legend_horizontal_spacing** (*float*, optional) – The spacing between the columns.
- **legend_vertical_spacing** (*float*, optional) – The vertical space between the legend entries.
- **legend_border** (*bool*, optional) – If `True`, a frame will be drawn around the legend.
- **legend_border_padding** (*float*, optional) – The fractional whitespace inside the legend border.
- **legend_shadow** (*bool*, optional) – If `True`, a shadow will be drawn behind legend.
- **legend_rounded_corners** (*bool*, optional) – If `True`, the frame's corners will be rounded (fancybox).
- **render_axes** (*bool*, optional) – If `True`, the axes will be rendered.
- **axes_font_name** (*See Below, optional*) – The font of the axes. Example options

```
{serif, sans-serif, cursive, fantasy, monospace}
```

- **axes_font_size** (*int*, optional) – The font size of the axes.
- **axes_font_style** (`{normal, italic, oblique}`, optional) – The font style of the axes.
- **axes_font_weight** (*See Below, optional*) – The font weight of the axes. Example options

```
{ultralight, light, normal, regular, book, medium, roman,
semibold,demibold, demi, bold, heavy, extra bold, black}
```

- **axes_x_limits** (*float* or (*float*, *float*) or `None`, optional) – The limits of the x axis. If *float*, then it sets padding on the right and left of the PointCloud as a percentage of the PointCloud's width. If *tuple* or *list*, then it defines the axis limits. If `None`, then the limits are set automatically.
- **axes_y_limits** ((*float*, *float*) *tuple* or `None`, optional) – The limits of the y axis. If *float*, then it sets padding on the top and bottom of the PointCloud as a percentage of the

PointCloud's height. If *tuple* or *list*, then it defines the axis limits. If `None`, then the limits are set automatically.

- **axes_x_ticks** (*list* or *tuple* or `None`, optional) – The ticks of the x axis.
- **axes_y_ticks** (*list* or *tuple* or `None`, optional) – The ticks of the y axis.
- **figure_size** ((*float*, *float*) *tuple* or `None` optional) – The size of the figure in inches.

Raises

- `ValueError` – If both `with_labels` and `without_labels` are passed.
- `ValueError` – If the landmark manager doesn't contain the provided group label.

as_vector(***kwargs*)

Returns a flattened representation of the object as a single vector.

Returnsvector (*(N,) ndarray*) – The core representation of the object, flattened into a single vector. Note that this is always a view back on to the original object, but is not writable.

bounding_box()

Return a bounding box from two corner points as a directed graph. In the case of a 2D pointcloud, first point (0) should be nearest the origin. In the case of an image, this ordering would appear as:

```
0<--3
|   ^
|   |
v   |
1-->2
```

In the case of a pointcloud, the ordering will appear as:

```
3<--2
|   ^
|   |
v   |
0-->1
```

In the case of a 3D pointcloud, the first point (0) should be the near closest to the origin and the second point is the far opposite corner.

Returnsbounding_box (`PointDirectedGraph`) – The axis aligned bounding box of the PointCloud.

bounds(*boundary=0*)

The minimum to maximum extent of the PointCloud. An optional boundary argument can be provided to expand the bounds by a constant margin.

Parametersboundary (*float*) – A optional padding distance that is added to the bounds. Default is `0`, meaning the max/min of tightest possible containing square/cube/hypercube is returned.

Returns

- **min_b** (`(n_dims,)` *ndarray*) – The minimum extent of the `PointCloud` and boundary along each dimension
- **max_b** (`(n_dims,)` *ndarray*) – The maximum extent of the `PointCloud` and boundary along each dimension

centre()

The mean of all the points in this PointCloud (centre of mass).

Returnscentre (`(n_dims)` *ndarray*) – The mean of this PointCloud's points.

centre_of_bounds()

The centre of the absolute bounds of this PointCloud. Contrast with `centre()`, which is the mean point position.

Returns **centre** (`n_dims` *ndarray*) – The centre of the bounds of this PointCloud.

constrain_to_bounds(*bounds*)

Returns a copy of this PointCloud, constrained to lie exactly within the given bounds. Any points outside the bounds will be 'snapped' to lie *exactly* on the boundary.

Parameters **bounds** (`(n_dims, n_dims)` tuple of scalars) – The bounds to constrain this pointcloud within.

Returns **constrained** (`PointCloud`) – The constrained pointcloud.

copy()

Generate an efficient copy of this object.

Note that Numpy arrays and other `Copyable` objects on `self` will be deeply copied. Dictionaries and sets will be shallow copied, and everything else will be assigned (no copy will be made).

Classes that store state other than numpy arrays and immutable types should overwrite this method to ensure all state is copied.

Returns `type(self)` – A copy of this object

distance_to(*pointcloud*, ***kwargs*)

Returns a distance matrix between this PointCloud and another. By default the Euclidean distance is calculated - see *scipy.spatial.distance.cdist* for valid kwargs to change the metric and other properties.

Parameters **pointcloud** (`PointCloud`) – The second pointcloud to compute distances between. This must be of the same dimension as this PointCloud.

Returns **distance_matrix** (`(n_points, n_points)` *ndarray*) – The symmetric pairwise distance matrix between the two PointClouds s.t. `distance_matrix[i, j]` is the distance between the i'th point of this PointCloud and the j'th point of the input PointCloud.

find_all_paths(*start*, *end*, *path=[]*)

Returns a list of lists with all the paths (without cycles) found from start vertex to end vertex.

Parameters

- **start** (*int*) – The vertex from which the paths start.
- **end** (*int*) – The vertex from which the paths end.
- **path** (*list*, optional) – An existing path to append to.

Returns **paths** (*list* of *list*) – The list containing all the paths from start to end.

find_all_shortest_paths(*algorithm='auto'*, *unweighted=False*)

Returns the distances and predecessors arrays of the graph's shortest paths.

Parameters

- **algorithm** (`'str', see below, optional`) – The algorithm to be used. Possible options are:

'dijkstra'	Dijkstra's algorithm with Fibonacci heaps
'bellman-ford'	Bellman-Ford algorithm
'johnson'	Johnson's algorithm
'floyd-warshall'	Floyd-Warshall algorithm
'auto'	Select the best among the above

- **unweighted** (*bool*, optional) – If `True`, then find unweighted distances. That is, rather than finding the path between each vertex such that the sum of weights is minimized, find the path such that the number of edges is minimized.

Returns

- **distances** (`(n_vertices, n_vertices,)` *ndarray*) – The matrix of distances between all graph vertices. `distances[i, j]` gives the shortest distance from vertex `i` to vertex `j` along the graph.
- **predecessors** (`(n_vertices, n_vertices,)` *ndarray*) – The matrix of predecessors, which can be used to reconstruct the shortest paths. Each entry `predecessors[i, j]` gives the index of the previous vertex in the path from vertex `i` to vertex `j`. If no path exists between vertices `i` and `j`, then `predecessors[i, j] = -9999`.

find_path(*start*, *end*, *method='bfs'*, *skip_checks=False*)

Returns a *list* with the first path (without cycles) found from the `start` vertex to the `end` vertex. It can employ either depth-first search or breadth-first search.

Parameters

- **start** (*int*) – The vertex from which the path starts.
- **end** (*int*) – The vertex to which the path ends.
- **method** ({`bfs`, `dfs`}, optional) – The method to be used.
- **skip_checks** (*bool*, optional) – If `True`, then input arguments won't pass through checks. Useful for efficiency.

Returnspath (*list*) – The path's vertices.

Raises`ValueError` – Method must be either bfs or dfs.

find_shortest_path(*start*, *end*, *algorithm='auto'*, *unweighted=False*, *skip_checks=False*)

Returns a *list* with the shortest path (without cycles) found from `start` vertex to `end` vertex.

Parameters

- **start** (*int*) – The vertex from which the path starts.
- **end** (*int*) – The vertex to which the path ends.
- **algorithm** (*`'str', see below, optional`*) – The algorithm to be used. Possible options are:

'dijkstra'	Dijkstra's algorithm with Fibonacci heaps
'bellman-ford'	Bellman-Ford algorithm
'johnson'	Johnson's algorithm
'floyd-warshall'	Floyd-Warshall algorithm
'auto'	Select the best among the above

- **unweighted** (*bool*, optional) – If `True`, then find unweighted distances. That is, rather than finding the path such that the sum of weights is minimized, find the path such that the number of edges is minimized.
- **skip_checks** (*bool*, optional) – If `True`, then input arguments won't pass through checks. Useful for efficiency.

Returns

- **path** (*list*) – The shortest path's vertices, including `start` and `end`. If there was not path connecting the vertices, then an empty *list* is returned.
- **distance** (*int* or *float*) – The distance (cost) of the path from `start` to `end`.

from_mask(*mask*)

A 1D boolean array with the same number of elements as the number of points in the *PointUndirectedGraph*. This is then broadcast across the dimensions of the *PointUndirectedGraph* and returns a new *PointUndirectedGraph* containing only those points that were `True` in the mask.

Parameters: **mask** (`(n_vertices,)` *ndarray*) – 1D array of booleans

Returns: **pointgraph** (`PointUndirectedGraph`) – A new pointgraph that has been masked.

Raises: `ValueError` – Mask must be a 1D boolean array of the same number of entries as points in this PointUndirectedGraph.

from_vector(*vector*)

Build a new instance of the object from it's vectorized state.

`self` is used to fill out the missing state required to rebuild a full object from it's standardized flattened state. This is the default implementation, which is which is a `deepcopy` of the object followed by a call to `from_vector_inplace()`. This method can be overridden for a performance benefit if desired.

Parameters: **vector** (`(n_parameters,)` *ndarray*) – Flattened representation of the object.

Returns: **object** (`type(self)`) – An new instance of this class.

from_vector_inplace(*vector*)

Deprecated. Use the non-mutating API, `from_vector`.

For internal usage in performance-sensitive spots, see *_from_vector_inplace()*

Parameters: **vector** (`(n_parameters,)` *ndarray*) – Flattened representation of this object

get_adjacency_list()

Returns the adjacency list of the graph, i.e. a *list* of length `n_vertices` that for each vertex has a *list* of the vertex neighbours. If the graph is directed, the neighbours are children.

Returns: **adjacency_list** (*list* of *list* of length `n_vertices`) – The adjacency list of the graph.

h_points()

Convert poincloud to a homogeneous array: `(n_dims + 1, n_points)`

Type: `type(self)`

has_cycles()

Checks if the graph has at least one cycle.

Returns: **has_cycles** (*bool*) – `True` if the graph has cycles.

has_isolated_vertices()

Whether the graph has any isolated vertices, i.e. vertices with no edge connections.

Returns: **has_isolated_vertices** (*bool*) – `True` if the graph has at least one isolated vertex.

has_nan_values()

Tests if the vectorized form of the object contains `nan` values or not. This is particularly useful for objects with unknown values that have been mapped to `nan` values.

Returns: **has_nan_values** (*bool*) – If the vectorized object contains `nan` values.

init_2d_grid(*shape*, *spacing=None*, *adjacency_matrix=None*, *skip_checks=False*)

Create a PointGraph that exists on a regular 2D grid. The first dimension is the number of rows in the grid and the second dimension of the shape is the number of columns. `spacing` optionally allows the definition of the distance between points (uniform over points). The spacing may be different for rows and columns.

If no adjacency matrix is provided, the default connectivity will be a 4-connected lattice.

Parameters

- **shape** (*tuple* of 2 *int*) – The size of the grid to create, this defines the number of points across each dimension in the grid. The first element is the number of rows and the second is the number of columns.
- **spacing** (*int* or *tuple* of 2 *int*, optional) – The spacing between points. If a single *int* is provided, this is applied uniformly across each dimension. If a *tuple* is provided, the spacing is applied non-uniformly as defined e.g. `(2, 3)` gives a spacing of 2 for the rows and 3 for the columns.
- **adjacency_matrix** (`(n_vertices, n_vertices)` *ndarray* or *csr_matrix*, optional) – The adjacency matrix of the graph in which the rows represent source vertices and columns represent destination vertices. The non-edges must be represented with zeros and the edges can have a weight value.

  The adjacency matrix of an undirected graph must be symmetric.
- **skip_checks** (*bool*, optional) – If `True`, no checks will be performed. Only considered if no adjacency matrix is provided.

Returnspgraph (*PointGraph*) – A pointgraph arranged in a grid.

init_from_depth_image(*depth_image*, *spacing=None*, *adjacency_matrix=None*, *skip_checks=False*)

Return a 3D point graph from the given depth image. The depth image is assumed to represent height/depth values and the XY coordinates are assumed to unit spaced and represent image coordinates. This is particularly useful for visualising depth values that have been recovered from images.

If no adjacency matrix is provided, the default connectivity will be a 4-connected lattice.

Parameters

- **depth_image** (`Image` or subclass) – A single channel image that contains depth values - as commonly returned by RGBD cameras, for example.
- **spacing** (*int* or *tuple* of 2 *int*, optional) – The spacing between points. If a single *int* is provided, this is applied uniformly across each dimension. If a *tuple* is provided, the spacing is applied non-uniformly as defined e.g. `(2, 3)` gives a spacing of 2 for the rows and 3 for the columns.
- **adjacency_matrix** (`(n_vertices, n_vertices)` *ndarray* or *csr_matrix*, optional) – The adjacency matrix of the graph in which the rows represent source vertices and columns represent destination vertices. The non-edges must be represented with zeros and the edges can have a weight value.

  The adjacency matrix of an undirected graph must be symmetric.
- **skip_checks** (*bool*, optional) – If `True`, no checks will be performed. Only considered if no adjacency matrix is provided.

Returnsdepth_cloud (`type(cls)`) – A new 3D PointGraph with unit XY coordinates and the given depth values as Z coordinates.

classmethod init_from_edges(*points*, *edges*, *copy=True*, *skip_checks=False*)

Construct a `PointUndirectedGraph` from edges array.

Parameters

- **points** (`(n_vertices, n_dims, )` *ndarray*) – The array of point locations.
- **edges** (`(n_edges, 2, )` *ndarray*) – The *ndarray* of edges, i.e. all the pairs of vertices that are connected with an edge.

- **copy** (*bool*, optional) – If `False`, the `adjacency_matrix` will not be copied on assignment.
- **skip_checks** (*bool*, optional) – If `True`, no checks will be performed.

Examples

The following undirected graph

```
|---0---|
|       |
|       |
1-------2
|       |
|       |
3-------4
|
|
5
```

can be defined as

```
from menpo.shape import PointUndirectedGraph
import numpy as np
points = np.array([[10, 30], [0, 20], [20, 20], [0, 10], [20, 10],
                   [0, 0]])
edges = np.array([[0, 1], [1, 0], [0, 2], [2, 0], [1, 2], [2, 1],
                  [1, 3], [3, 1], [2, 4], [4, 2], [3, 4], [4, 3],
                  [3, 5], [5, 3]])
graph = PointUndirectedGraph.init_from_edges(points, edges)
```

Finally, the following graph with isolated vertices

```
    0---|
        |
        |
1       2
        |
        |
3-------4


5
```

can be defined as

```
from menpo.shape import PointUndirectedGraph
import numpy as np
points = np.array([[10, 30], [0, 20], [20, 20], [0, 10], [20, 10],
                   [0, 0]])
edges = np.array([[0, 2], [2, 0], [2, 4], [4, 2], [3, 4], [4, 3]])
graph = PointUndirectedGraph.init_from_edges(points, edges)
```

is_edge(*vertex_1*, *vertex_2*, *skip_checks=False*)

Whether there is an edge between the provided vertices.

Parameters

- **vertex_1** (*int*) – The first selected vertex. Parent if the graph is directed.
- **vertex_2** (*int*) – The second selected vertex. Child if the graph is directed.
- **skip_checks** (*bool*, optional) – If `False`, the given vertices will be checked.

Returnsis_edge (*bool*) – `True` if there is an edge connecting `vertex_1` and `vertex_2`.

Raises`ValueError` – The vertex must be between 0 and {n_vertices-1}.

is_tree()

Checks if the graph is tree.

Returnsis_true (*bool*) – If the graph is a tree.

isolated_vertices()

Returns the isolated vertices of the graph (if any), i.e. the vertices that have no edge connections.

Returnsisolated_vertices (*list*) – A *list* of the isolated vertices. If there aren't any, it returns an empty *list*.

minimum_spanning_tree(*root_vertex*)

Returns the minimum spanning tree of the graph using Kruskal's algorithm.

Parametersroot_vertex (*int*) – The vertex that will be set as root in the output MST.

Returnsmst (`PointTree`) – The computed minimum spanning tree with the *points* of *self*.

Raises`ValueError` – Cannot compute minimum spanning tree of a graph with isolated vertices

n_neighbours(*vertex*, *skip_checks=False*)

Returns the number of neighbours of the selected vertex.

Parameters

- **vertex** (*int*) – The selected vertex.
- **skip_checks** (*bool*, optional) – If `False`, the given vertex will be checked.

Returnsn_neighbours (*int*) – The number of neighbours.

Raises`ValueError` – The vertex must be between 0 and {n_vertices-1}.

n_paths(*start*, *end*)

Returns the number of all the paths (without cycles) existing from start vertex to end vertex.

Parameters

- **start** (*int*) – The vertex from which the paths start.
- **end** (*int*) – The vertex from which the paths end.

Returnspaths (*int*) – The paths' numbers.

neighbours(*vertex*, *skip_checks=False*)

Returns the neighbours of the selected vertex.

Parameters

- **vertex** (*int*) – The selected vertex.
- **skip_checks** (*bool*, optional) – If `False`, the given vertex will be checked.

Returnsneighbours (*list*) – The list of neighbours.

Raises`ValueError` – The vertex must be between 0 and {n_vertices-1}.

norm(***kwargs*)

Returns the norm of this PointCloud. This is a translation and rotation invariant measure of the point cloud's intrinsic size - in other words, it is always taken around the point cloud's centre.

By default, the Frobenius norm is taken, but this can be changed by setting kwargs - see `numpy.linalg.norm` for valid options.

Returnsnorm (*float*) – The norm of this `PointCloud`

range(*boundary=0*)

The range of the extent of the PointCloud.

Parametersboundary (*float*) – A optional padding distance that is used to extend the bounds from which the range is computed. Default is `0`, no extension is performed.

Returnsrange (`(n_dims,)` *ndarray*) – The range of the `PointCloud` extent in each dimension.

tojson()

Convert this PointGraph to a dictionary representation suitable for inclusion in the LJSON landmark format.

Returnsjson (*dict*) – Dictionary with `points` and `connectivity` keys.

with_dims(*dims*)

Return a copy of this shape with only particular dimensions retained.

Parametersdims (*`valid numpy array slice`*) – The slice that will be used on the dimensionality axis of the shape under transform. For example, to go from a 3D shape to a 2D one, [0, 1] could be provided or np.array([True, True, False]).

Returns*copy of self, with only the requested dims*

has_landmarks

Whether the object has landmarks.

Type*bool*

landmarks

The landmarks object.

Type`LandmarkManager`

lms

Deprecated. Maintained for compatibility, will be removed in a future version. Returns a copy of this object, which previously would have held the 'underlying' `PointCloud` subclass.

Typeself

n_dims

The number of dimensions in the pointcloud.

Type*int*

n_edges

Returns the number of edges.

Type*int*

n_landmark_groups

The number of landmark groups on this object.

Type*int*

n_parameters
The length of the vector that this object produces.

Type *int*

n_points
The number of points in the pointcloud.

Type *int*

n_vertices
Returns the number of vertices.

Type *int*

vertices
Returns the *list* of vertices.

Type *list*

PointDirectedGraph

class `menpo.shape.`**`PointDirectedGraph`**(*points*, *adjacency_matrix*, *copy=True*, *skip_checks=False*)
Bases: `PointGraph`, `DirectedGraph`

Class for defining a directed graph with geometry.

Parameters

- **points** (`(n_vertices, n_dims)` *ndarray*) – The array representing the points.
- **adjacency_matrix** (`(n_vertices, n_vertices, )` *ndarray* or *csr_matrix*) – The adjacency matrix of the graph in which the rows represent source vertices and columns represent destination vertices. The non-edges must be represented with zeros and the edges can have a weight value.
- **copy** (*bool*, optional) – If `False`, the `adjacency_matrix` will not be copied on assignment.
- **skip_checks** (*bool*, optional) – If `True`, no checks will be performed.

Raises

- `ValueError` – A point for each graph vertex needs to be passed. Got {n_points} points instead of {n_vertices}.
- `ValueError` – adjacency_matrix must be either a numpy.ndarray or a scipy.sparse.csr_matrix.
- `ValueError` – Graph must have at least two vertices.
- `ValueError` – adjacency_matrix must be square (n_vertices, n_vertices,), ({adjacency_matrix.shape[0]}, {adjacency_matrix.shape[1]}) given instead.

Examples

The following directed graph

```
|-->0<--|
|       |
|       |
1<----->2
|       |
```

```
v       v
3------>4
|
v
5
```

can be defined as

```
import numpy as np
adjacency_matrix = np.array([[0, 0, 0, 0, 0, 0],
                             [1, 0, 1, 1, 0, 0],
                             [1, 1, 0, 0, 1, 0],
                             [0, 0, 0, 0, 1, 1],
                             [0, 0, 0, 0, 0, 0],
                             [0, 0, 0, 0, 0, 0]])
points = np.array([[10, 30], [0, 20], [20, 20], [0, 10], [20, 10],
                   [0, 0]])
graph = PointDirectedGraph(points, adjacency_matrix)
```

or

```
from scipy.sparse import csr_matrix
adjacency_matrix = csr_matrix(([1] * 8, ([1, 2, 1, 2, 1, 2, 3, 3],
                                          [0, 0, 2, 1, 3, 4, 4, 5])),
                              shape=(6, 6))
points = np.array([[10, 30], [0, 20], [20, 20], [0, 10], [20, 10],
                   [0, 0]])
graph = PointDirectedGraph(points, adjacency_matrix)
```

The following graph with isolated vertices

```
       0<--|
           |
           |
   1       2
           |
           v
   3------>4

5
```

---

can be defined as

```
import numpy as np
adjacency_matrix = np.array([[0, 0, 0, 0, 0, 0],
                             [0, 0, 0, 0, 0, 0],
                             [1, 0, 0, 0, 1, 0],
                             [0, 0, 0, 0, 1, 0],
                             [0, 0, 0, 0, 0, 0],
                             [0, 0, 0, 0, 0, 0]])
points = np.array([[10, 30], [0, 20], [20, 20], [0, 10], [20, 10],
                   [0, 0]])
graph = PointDirectedGraph(points, adjacency_matrix)
```

or

```
from scipy.sparse import csr_matrix
adjacency_matrix = csr_matrix(([1] * 3, ([2, 2, 3], [0, 4, 4])),
                              shape=(6, 6))
points = np.array([[10, 30], [0, 20], [20, 20], [0, 10], [20, 10],
                   [0, 0]])
graph = PointDirectedGraph(points, adjacency_matrix)
```

_view_2d(*figure_id=None*, *new_figure=False*, *image_view=True*, *render_lines=True*, *line_colour='r'*, *line_style='-'*, *line_width=1.0*, *render_markers=True*, *marker_style='o'*, *marker_size=5*, *marker_face_colour='k'*, *marker_edge_colour='k'*, *marker_edge_width=1.0*, *render_numbering=False*, *numbers_horizontal_align='center'*, *numbers_vertical_align='bottom'*, *numbers_font_name='sans-serif'*, *numbers_font_size=10*, *numbers_font_style='normal'*, *numbers_font_weight='normal'*, *numbers_font_colour='k'*, *render_axes=True*, *axes_font_name='sans-serif'*, *axes_font_size=10*, *axes_font_style='normal'*, *axes_font_weight='normal'*, *axes_x_limits=None*, *axes_y_limits=None*, *axes_x_ticks=None*, *axes_y_ticks=None*, *figure_size=(7, 7)*, *label=None*, ***kwargs*)

Visualization of the PointGraph in 2D.

Returns

- **figure_id** (*object*, optional) – The id of the figure to be used.
- **new_figure** (*bool*, optional) – If `True`, a new figure is created.
- **image_view** (*bool*, optional) – If `True` the PointGraph will be viewed as if it is in the image coordinate system.
- **render_lines** (*bool*, optional) – If `True`, the edges will be rendered.
- **line_colour** (*See Below, optional*) – The colour of the lines. Example options:

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **line_style** (`{'-', '--', '-.', ':'}`, optional) – The style of the lines.
- **line_width** (*float*, optional) – The width of the lines.
- **render_markers** (*bool*, optional) – If `True`, the markers will be rendered.
- **marker_style** (*See Below, optional*) –

  The style of the markers. Example options

```
{., ,, o, v, ^, <, >, +, x, D, d, s, p, *, h, H, 1, 2, 3, 4, 8}
```

- **marker_size** (*int*, optional) – The size of the markers in points.
- **marker_face_colour** (*See Below, optional*) – The face (filling) colour of the markers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **marker_edge_colour** (*See Below, optional*) – The edge colour of the markers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

•**marker_edge_width** (*float*, optional) – The width of the markers' edge.

•**render_numbering** (*bool*, optional) – If `True`, the landmarks will be numbered.

•**numbers_horizontal_align** (`{center, right, left}`, optional) – The horizontal alignment of the numbers' texts.

•**numbers_vertical_align** (`{center, top, bottom, baseline}`, optional) – The vertical alignment of the numbers' texts.

•**numbers_font_name** (*See Below, optional*) –

The font of the numbers. Example options

```
{serif, sans-serif, cursive, fantasy, monospace}
```

•**numbers_font_size** (*int*, optional) – The font size of the numbers.

•**numbers_font_style** (`{normal, italic, oblique}`, optional) – The font style of the numbers.

•**numbers_font_weight** (*See Below, optional*) – The font weight of the numbers. Example options

```
{ultralight, light, normal, regular, book, medium, roman,
semibold, demibold, demi, bold, heavy, extra bold, black}
```

•**numbers_font_colour** (*See Below, optional*) – The font colour of the numbers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

•**render_axes** (*bool*, optional) – If `True`, the axes will be rendered.

•**axes_font_name** (*See Below, optional*) – The font of the axes. Example options

```
{serif, sans-serif, cursive, fantasy, monospace}
```

•**axes_font_size** (*int*, optional) – The font size of the axes.

•**axes_font_style** (`{normal, italic, oblique}`, optional) – The font style of the axes.

•**axes_font_weight** (*See Below, optional*) – The font weight of the axes. Example options

```
{ultralight, light, normal, regular, book, medium, roman,
semibold, demibold, demi, bold, heavy, extra bold, black}
```

•**axes_x_limits** (*float* or (*float*, *float*) or `None`, optional) – The limits of the x axis. If *float*, then it sets padding on the right and left of the PointGraph as a percentage of the PointGraph's width. If *tuple* or *list*, then it defines the axis limits. If `None`, then the limits are set automatically.

•**axes_y_limits** ((*float*, *float*) *tuple* or `None`, optional) – The limits of the y axis. If *float*, then it sets padding on the top and bottom of the PointGraph as a percentage of the Point-

Graph's height. If *tuple* or *list*, then it defines the axis limits. If `None`, then the limits are set automatically.

- **axes_x_ticks** (*list* or *tuple* or `None`, optional) – The ticks of the x axis.
- **axes_y_ticks** (*list* or *tuple* or `None`, optional) – The ticks of the y axis.
- **figure_size** ((*float*, *float*) *tuple* or `None`, optional) – The size of the figure in inches.
- **label** (*str*, optional) – The name entry in case of a legend.

Returns **viewer** (`PointGraphViewer2d`) – The viewer object.

_view_landmarks_2d(*group=None*, *with_labels=None*, *without_labels=None*, *figure_id=None*, *new_figure=False*, *image_view=True*, *render_lines=True*, *line_colour='k'*, *line_style='-'*, *line_width=2*, *render_markers=True*, *marker_style='s'*, *marker_size=7*, *marker_face_colour='k'*, *marker_edge_colour='k'*, *marker_edge_width=1.0*, *render_lines_lms=True*, *line_colour_lms=None*, *line_style_lms='-'*, *line_width_lms=1*, *render_markers_lms=True*, *marker_style_lms='o'*, *marker_size_lms=5*, *marker_face_colour_lms=None*, *marker_edge_colour_lms=None*, *marker_edge_width_lms=1.0*, *render_numbering=False*, *numbers_horizontal_align='center'*, *numbers_vertical_align='bottom'*, *numbers_font_name='sans-serif'*, *numbers_font_size=10*, *numbers_font_style='normal'*, *numbers_font_weight='normal'*, *numbers_font_colour='k'*, *render_legend=False*, *legend_title=''*, *legend_font_name='sans-serif'*, *legend_font_style='normal'*, *legend_font_size=10*, *legend_font_weight='normal'*, *legend_marker_scale=None*, *legend_location=2*, *legend_bbox_to_anchor=(1.05, 1.0)*, *legend_border_axes_pad=None*, *legend_n_columns=1*, *legend_horizontal_spacing=None*, *legend_vertical_spacing=None*, *legend_border=True*, *legend_border_padding=None*, *legend_shadow=False*, *legend_rounded_corners=False*, *render_axes=False*, *axes_font_name='sans-serif'*, *axes_font_size=10*, *axes_font_style='normal'*, *axes_font_weight='normal'*, *axes_x_limits=None*, *axes_y_limits=None*, *axes_x_ticks=None*, *axes_y_ticks=None*, *figure_size=(7, 7)*)

Visualize the landmarks. This method will appear on the *PointGraph* as `view_landmarks`.

Parameters

- **group** (*str* or''None'' optional) – The landmark group to be visualized. If `None` and there are more than one landmark groups, an error is raised.
- **with_labels** (`None` or *str* or *list* of *str*, optional) – If not `None`, only show the given label(s). Should **not** be used with the `without_labels` kwarg.
- **without_labels** (`None` or *str* or *list* of *str*, optional) – If not `None`, show all except the given label(s). Should **not** be used with the `with_labels` kwarg.
- **figure_id** (*object*, optional) – The id of the figure to be used.
- **new_figure** (*bool*, optional) – If `True`, a new figure is created.
- **image_view** (*bool*, optional) – If `True` the PointCloud will be viewed as if it is in the image coordinate system.
- **render_lines** (*bool*, optional) – If `True`, the edges will be rendered.
- **line_colour** (*See Below, optional*) – The colour of the lines. Example options:

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **line_style** ({-, --, -., :}, optional) – The style of the lines.
- **line_width** (*float*, optional) – The width of the lines.
- **render_markers** (*bool*, optional) – If True, the markers will be rendered.
- **marker_style** (*See Below, optional*) – The style of the markers. Example options

```
{., ,, o, v, ^, <, >, +, x, D, d, s, p, *, h, H, 1, 2, 3, 4, 8}
```

- **marker_size** (*int*, optional) – The size of the markers in points.
- **marker_face_colour** (*See Below, optional*) – The face (filling) colour of the markers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **marker_edge_colour** (*See Below, optional*) – The edge colour of the markers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **marker_edge_width** (*float*, optional) – The width of the markers' edge.
- **render_lines_lms** (*bool*, optional) – If True, the edges of the landmarks will be rendered.
- **line_colour_lms** (*See Below, optional*) – The colour of the lines of the landmarks. Example options:

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **line_style_lms** ({-, --, -., :}, optional) – The style of the lines of the landmarks.
- **line_width_lms** (*float*, optional) – The width of the lines of the landmarks.
- **render_markers** – If True, the markers of the landmarks will be rendered.
- **marker_style** – The style of the markers of the landmarks. Example options

```
{., ,, o, v, ^, <, >, +, x, D, d, s, p, *, h, H, 1, 2, 3, 4, 8}
```

- **marker_size** – The size of the markers of the landmarks in points.
- **marker_face_colour** – The face (filling) colour of the markers of the landmarks. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

•**marker_edge_colour** – The edge colour of the markers of the landmarks. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

•**marker_edge_width** – The width of the markers' edge of the landmarks.

•**render_numbering** (*bool*, optional) – If `True`, the landmarks will be numbered.

•**numbers_horizontal_align** (`{center, right, left}`, optional) – The horizontal alignment of the numbers' texts.

•**numbers_vertical_align** (`{center, top, bottom, baseline}`, optional) – The vertical alignment of the numbers' texts.

•**numbers_font_name** (*See Below, optional*) – The font of the numbers. Example options

```
{serif, sans-serif, cursive, fantasy, monospace}
```

•**numbers_font_size** (*int*, optional) – The font size of the numbers.

•**numbers_font_style** (`{normal, italic, oblique}`, optional) – The font style of the numbers.

•**numbers_font_weight** (*See Below, optional*) – The font weight of the numbers. Example options

```
{ultralight, light, normal, regular, book, medium, roman,
semibold, demibold, demi, bold, heavy, extra bold, black}
```

•**numbers_font_colour** (*See Below, optional*) – The font colour of the numbers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

•**render_legend** (*bool*, optional) – If `True`, the legend will be rendered.

•**legend_title** (*str*, optional) – The title of the legend.

•**legend_font_name** (*See below, optional*) – The font of the legend. Example options

```
{serif, sans-serif, cursive, fantasy, monospace}
```

•**legend_font_style** (`{normal, italic, oblique}`, optional) – The font style of the legend.

•**legend_font_size** (*int*, optional) – The font size of the legend.

•**legend_font_weight** (*See Below, optional*) – The font weight of the legend. Example options

```
{ultralight, light, normal, regular, book, medium, roman,
semibold, demibold, demi, bold, heavy, extra bold, black}
```

- **legend_marker_scale** (*float*, optional) – The relative size of the legend markers with respect to the original
- **legend_location** (*int*, optional) – The location of the legend. The predefined values are:

'best'	0
'upper right'	1
'upper left'	2
'lower left'	3
'lower right'	4
'right'	5
'center left'	6
'center right'	7
'lower center'	8
'upper center'	9
'center'	10

- **legend_bbox_to_anchor** ((*float*, *float*) *tuple*, optional) – The bbox that the legend will be anchored.
- **legend_border_axes_pad** (*float*, optional) – The pad between the axes and legend border.
- **legend_n_columns** (*int*, optional) – The number of the legend's columns.
- **legend_horizontal_spacing** (*float*, optional) – The spacing between the columns.
- **legend_vertical_spacing** (*float*, optional) – The vertical space between the legend entries.
- **legend_border** (*bool*, optional) – If `True`, a frame will be drawn around the legend.
- **legend_border_padding** (*float*, optional) – The fractional whitespace inside the legend border.
- **legend_shadow** (*bool*, optional) – If `True`, a shadow will be drawn behind legend.
- **legend_rounded_corners** (*bool*, optional) – If `True`, the frame's corners will be rounded (fancybox).
- **render_axes** (*bool*, optional) – If `True`, the axes will be rendered.
- **axes_font_name** (*See Below, optional*) – The font of the axes. Example options

```
{serif, sans-serif, cursive, fantasy, monospace}
```

- **axes_font_size** (*int*, optional) – The font size of the axes.
- **axes_font_style** (`{normal, italic, oblique}`, optional) – The font style of the axes.
- **axes_font_weight** (*See Below, optional*) – The font weight of the axes. Example options

```
{ultralight, light, normal, regular, book, medium, roman,
semibold,demibold, demi, bold, heavy, extra bold, black}
```

- **axes_x_limits** (*float* or (*float*, *float*) or `None`, optional) – The limits of the x axis. If *float*, then it sets padding on the right and left of the PointCloud as a percentage of the PointCloud's width. If *tuple* or *list*, then it defines the axis limits. If `None`, then the limits are set automatically.
- **axes_y_limits** ((*float*, *float*) *tuple* or `None`, optional) – The limits of the y axis. If *float*, then it sets padding on the top and bottom of the PointCloud as a percentage of the PointCloud's height. If *tuple* or *list*, then it defines the axis limits. If `None`, then the limits are set automatically.
- **axes_x_ticks** (*list* or *tuple* or `None`, optional) – The ticks of the x axis.
- **axes_y_ticks** (*list* or *tuple* or `None`, optional) – The ticks of the y axis.
- **figure_size** ((*float*, *float*) *tuple* or `None` optional) – The size of the figure in inches.

Raises

- `ValueError` – If both `with_labels` and `without_labels` are passed.
- `ValueError` – If the landmark manager doesn't contain the provided group label.

as_vector(***kwargs*)

Returns a flattened representation of the object as a single vector.

Returnsvector (*(N,) ndarray*) – The core representation of the object, flattened into a single vector. Note that this is always a view back on to the original object, but is not writable.

bounding_box()

Return a bounding box from two corner points as a directed graph. In the case of a 2D pointcloud, first point (0) should be nearest the origin. In the case of an image, this ordering would appear as:

```
0<--3
|   ^
|   |
v   |
1-->2
```

In the case of a pointcloud, the ordering will appear as:

```
3<--2
|   ^
|   |
v   |
0-->1
```

In the case of a 3D pointcloud, the first point (0) should be the near closest to the origin and the second point is the far opposite corner.

Returnsbounding_box (*PointDirectedGraph*) – The axis aligned bounding box of the PointCloud.

bounds(*boundary=0*)

The minimum to maximum extent of the PointCloud. An optional boundary argument can be provided to expand the bounds by a constant margin.

Parametersboundary (*float*) – A optional padding distance that is added to the bounds. Default is `0`, meaning the max/min of tightest possible containing square/cube/hypercube is returned.

Returns

- **min_b** (`(n_dims,)` *ndarray*) – The minimum extent of the *PointCloud* and boundary along each dimension

- **max_b** ((n_dims,) *ndarray*) – The maximum extent of the `PointCloud` and boundary along each dimension

centre()

The mean of all the points in this PointCloud (centre of mass).

Returns **centre** ((n_dims) *ndarray*) – The mean of this PointCloud's points.

centre_of_bounds()

The centre of the absolute bounds of this PointCloud. Contrast with `centre()`, which is the mean point position.

Returns **centre** (n_dims *ndarray*) – The centre of the bounds of this PointCloud.

children(*vertex*, *skip_checks=False*)

Returns the children of the selected vertex.

Parameters

- **vertex** (*int*) – The selected vertex.
- **skip_checks** (*bool*, optional) – If `False`, the given vertex will be checked.

Returns **children** (*list*) – The list of children.

Raises `ValueError` – The vertex must be between 0 and {n_vertices-1}.

constrain_to_bounds(*bounds*)

Returns a copy of this PointCloud, constrained to lie exactly within the given bounds. Any points outside the bounds will be 'snapped' to lie *exactly* on the boundary.

Parameters **bounds** ((n_dims, n_dims) tuple of scalars) – The bounds to constrain this pointcloud within.

Returns **constrained** (`PointCloud`) – The constrained pointcloud.

copy()

Generate an efficient copy of this object.

Note that Numpy arrays and other `Copyable` objects on `self` will be deeply copied. Dictionaries and sets will be shallow copied, and everything else will be assigned (no copy will be made).

Classes that store state other than numpy arrays and immutable types should overwrite this method to ensure all state is copied.

Returns `type(self)` – A copy of this object

distance_to(*pointcloud*, ***kwargs*)

Returns a distance matrix between this PointCloud and another. By default the Euclidean distance is calculated - see *scipy.spatial.distance.cdist* for valid kwargs to change the metric and other properties.

Parameters **pointcloud** (`PointCloud`) – The second pointcloud to compute distances between. This must be of the same dimension as this PointCloud.

Returns **distance_matrix** ((n_points, n_points) *ndarray*) – The symmetric pairwise distance matrix between the two PointClouds s.t. `distance_matrix[i, j]` is the distance between the i'th point of this PointCloud and the j'th point of the input PointCloud.

find_all_paths(*start*, *end*, *path=[]*)

Returns a list of lists with all the paths (without cycles) found from start vertex to end vertex.

Parameters

- **start** (*int*) – The vertex from which the paths start.
- **end** (*int*) – The vertex from which the paths end.

- **path** (*list*, optional) – An existing path to append to.

Returnspaths (*list* of *list*) – The list containing all the paths from start to end.

find_all_shortest_paths(*algorithm='auto'*, *unweighted=False*)

Returns the distances and predecessors arrays of the graph's shortest paths.

Parameters

- **algorithm** (*'str', see below, optional*) – The algorithm to be used. Possible options are:

'dijkstra'	Dijkstra's algorithm with Fibonacci heaps
'bellman-ford'	Bellman-Ford algorithm
'johnson'	Johnson's algorithm
'floyd-warshall'	Floyd-Warshall algorithm
'auto'	Select the best among the above

- **unweighted** (*bool*, optional) – If `True`, then find unweighted distances. That is, rather than finding the path between each vertex such that the sum of weights is minimized, find the path such that the number of edges is minimized.

Returns

- **distances** (`(n_vertices, n_vertices,)` *ndarray*) – The matrix of distances between all graph vertices. `distances[i,j]` gives the shortest distance from vertex `i` to vertex `j` along the graph.
- **predecessors** (`(n_vertices, n_vertices,)` *ndarray*) – The matrix of predecessors, which can be used to reconstruct the shortest paths. Each entry `predecessors[i, j]` gives the index of the previous vertex in the path from vertex `i` to vertex `j`. If no path exists between vertices `i` and `j`, then `predecessors[i, j] = -9999`.

find_path(*start*, *end*, *method='bfs'*, *skip_checks=False*)

Returns a *list* with the first path (without cycles) found from the `start` vertex to the `end` vertex. It can employ either depth-first search or breadth-first search.

Parameters

- **start** (*int*) – The vertex from which the path starts.
- **end** (*int*) – The vertex to which the path ends.
- **method** (`{bfs, dfs}`, optional) – The method to be used.
- **skip_checks** (*bool*, optional) – If `True`, then input arguments won't pass through checks. Useful for efficiency.

Returnspath (*list*) – The path's vertices.

Raises`ValueError` – Method must be either bfs or dfs.

find_shortest_path(*start*, *end*, *algorithm='auto'*, *unweighted=False*, *skip_checks=False*)

Returns a *list* with the shortest path (without cycles) found from `start` vertex to `end` vertex.

Parameters

- **start** (*int*) – The vertex from which the path starts.
- **end** (*int*) – The vertex to which the path ends.
- **algorithm** (*'str', see below, optional*) – The algorithm to be used. Possible options are:

'dijkstra'	Dijkstra's algorithm with Fibonacci heaps
'bellman-ford'	Bellman-Ford algorithm
'johnson'	Johnson's algorithm
'floyd-warshall'	Floyd-Warshall algorithm
'auto'	Select the best among the above

- **unweighted** (*bool*, optional) – If `True`, then find unweighted distances. That is, rather than finding the path such that the sum of weights is minimized, find the path such that the number of edges is minimized.
- **skip_checks** (*bool*, optional) – If `True`, then input arguments won't pass through checks. Useful for efficiency.

Returns

- **path** (*list*) – The shortest path's vertices, including `start` and `end`. If there was not path connecting the vertices, then an empty *list* is returned.
- **distance** (*int* or *float*) – The distance (cost) of the path from `start` to `end`.

from_mask(*mask*)

A 1D boolean array with the same number of elements as the number of points in the *PointDirectedGraph*. This is then broadcast across the dimensions of the *PointDirectedGraph* and returns a new *PointDirectedGraph* containing only those points that were `True` in the mask.

Parameters **mask** (`(n_points,)` *ndarray*) – 1D array of booleans

Returns **pointgraph** (`PointDirectedGraph`) – A new pointgraph that has been masked.

Raises `ValueError` – Mask must be a 1D boolean array of the same number of entries as points in this PointDirectedGraph.

from_vector(*vector*)

Build a new instance of the object from it's vectorized state.

`self` is used to fill out the missing state required to rebuild a full object from it's standardized flattened state. This is the default implementation, which is which is a `deepcopy` of the object followed by a call to `from_vector_inplace()`. This method can be overridden for a performance benefit if desired.

Parameters **vector** (`(n_parameters,)` *ndarray*) – Flattened representation of the object.

Returns **object** (`type(self)`) – An new instance of this class.

from_vector_inplace(*vector*)

Deprecated. Use the non-mutating API, `from_vector`.

For internal usage in performance-sensitive spots, see *_from_vector_inplace()*

Parameters **vector** (`(n_parameters,)` *ndarray*) – Flattened representation of this object

get_adjacency_list()

Returns the adjacency list of the graph, i.e. a *list* of length `n_vertices` that for each vertex has a *list* of the vertex neighbours. If the graph is directed, the neighbours are children.

Returns **adjacency_list** (*list* of *list* of length `n_vertices`) – The adjacency list of the graph.

h_points()

Convert poincloud to a homogeneous array: `(n_dims + 1, n_points)`

Type `type(self)`

has_cycles()

Checks if the graph has at least one cycle.

Returns **has_cycles** (*bool*) – `True` if the graph has cycles.

has_isolated_vertices()

Whether the graph has any isolated vertices, i.e. vertices with no edge connections.

Returnshas_isolated_vertices (*bool*) – `True` if the graph has at least one isolated vertex.

has_nan_values()

Tests if the vectorized form of the object contains `nan` values or not. This is particularly useful for objects with unknown values that have been mapped to `nan` values.

Returnshas_nan_values (*bool*) – If the vectorized object contains `nan` values.

init_2d_grid(*shape*, *spacing=None*, *adjacency_matrix=None*, *skip_checks=False*)

Create a PointGraph that exists on a regular 2D grid. The first dimension is the number of rows in the grid and the second dimension of the shape is the number of columns. `spacing` optionally allows the definition of the distance between points (uniform over points). The spacing may be different for rows and columns.

If no adjacency matrix is provided, the default connectivity will be a 4-connected lattice.

Parameters

- **shape** (*tuple* of 2 *int*) – The size of the grid to create, this defines the number of points across each dimension in the grid. The first element is the number of rows and the second is the number of columns.
- **spacing** (*int* or *tuple* of 2 *int*, optional) – The spacing between points. If a single *int* is provided, this is applied uniformly across each dimension. If a *tuple* is provided, the spacing is applied non-uniformly as defined e.g. `(2, 3)` gives a spacing of 2 for the rows and 3 for the columns.
- **adjacency_matrix** (`(n_vertices, n_vertices)` *ndarray* or *csr_matrix*, optional) – The adjacency matrix of the graph in which the rows represent source vertices and columns represent destination vertices. The non-edges must be represented with zeros and the edges can have a weight value.

  The adjacency matrix of an undirected graph must be symmetric.
- **skip_checks** (*bool*, optional) – If `True`, no checks will be performed. Only considered if no adjacency matrix is provided.

Returnspgraph (*PointGraph*) – A pointgraph arranged in a grid.

init_from_depth_image(*depth_image*, *spacing=None*, *adjacency_matrix=None*, *skip_checks=False*)

Return a 3D point graph from the given depth image. The depth image is assumed to represent height/depth values and the XY coordinates are assumed to unit spaced and represent image coordinates. This is particularly useful for visualising depth values that have been recovered from images.

If no adjacency matrix is provided, the default connectivity will be a 4-connected lattice.

Parameters

- **depth_image** (`Image` or subclass) – A single channel image that contains depth values - as commonly returned by RGBD cameras, for example.
- **spacing** (*int* or *tuple* of 2 *int*, optional) – The spacing between points. If a single *int* is provided, this is applied uniformly across each dimension. If a *tuple* is provided, the spacing is applied non-uniformly as defined e.g. `(2, 3)` gives a spacing of 2 for the rows and 3 for the columns.
- **adjacency_matrix** (`(n_vertices, n_vertices)` *ndarray* or *csr_matrix*, optional) – The adjacency matrix of the graph in which the rows represent source vertices

and columns represent destination vertices. The non-edges must be represented with zeros and the edges can have a weight value.

The adjacency matrix of an undirected graph must be symmetric.

- **skip_checks** (*bool*, optional) – If `True`, no checks will be performed. Only considered if no adjacency matrix is provided.

Returnsdepth_cloud (`type(cls)`) – A new 3D PointGraph with unit XY coordinates and the given depth values as Z coordinates.

init_from_edges(*points*, *edges*, *copy=True*, *skip_checks=False*)

Construct a PointGraph from edges array.

Parameters

- **points** (`(n_vertices, n_dims, )` *ndarray*) – The array of point locations.
- **edges** (`(n_edges, 2, )` *ndarray*) – The *ndarray* of edges, i.e. all the pairs of vertices that are connected with an edge.
- **copy** (*bool*, optional) – If `False`, the `adjacency_matrix` will not be copied on assignment.
- **skip_checks** (*bool*, optional) – If `True`, no checks will be performed.

Examples

The following undirected graph

```
|---0---|
|       |
|       |
1-------2
|       |
|       |
3-------4
|
|
5
```

can be defined as

```
from menpo.shape import PointUndirectedGraph
import numpy as np
points = np.array([[10, 30], [0, 20], [20, 20], [0, 10], [20, 10],
                   [0, 0]])
edges = np.array([[0, 1], [1, 0], [0, 2], [2, 0], [1, 2], [2, 1],
                  [1, 3], [3, 1], [2, 4], [4, 2], [3, 4], [4, 3],
                  [3, 5], [5, 3]])
graph = PointUndirectedGraph.init_from_edges(points, edges)
```

The following directed graph

```
|-->0<--|
|       |
|       |
1<----->2
|       |
v       v
```

```
3------>4
|
v
5
```

can be represented as

```
from menpo.shape import PointDirectedGraph
import numpy as np
points = np.array([[10, 30], [0, 20], [20, 20], [0, 10], [20, 10],
                   [0, 0]])
edges = np.array([[1, 0], [2, 0], [1, 2], [2, 1], [1, 3], [2, 4],
                  [3, 4], [3, 5]])
graph = PointDirectedGraph.init_from_edges(points, edges)
```

Finally, the following graph with isolated vertices

```
    0---|
        |
        |
1       2
        |
        |
3-------4


5
```

can be defined as

```
from menpo.shape import PointUndirectedGraph
import numpy as np
points = np.array([[10, 30], [0, 20], [20, 20], [0, 10], [20, 10],
                   [0, 0]])
edges = np.array([[0, 2], [2, 0], [2, 4], [4, 2], [3, 4], [4, 3]])
graph = PointUndirectedGraph.init_from_edges(points, edges)
```

is_edge (*vertex_1*, *vertex_2*, *skip_checks=False*)

Whether there is an edge between the provided vertices.

Parameters

- **vertex_1** (*int*) – The first selected vertex. Parent if the graph is directed.
- **vertex_2** (*int*) – The second selected vertex. Child if the graph is directed.
- **skip_checks** (*bool*, optional) – If `False`, the given vertices will be checked.

Returnsis_edge (*bool*) – `True` if there is an edge connecting `vertex_1` and `vertex_2`.

Raises`ValueError` – The vertex must be between 0 and {n_vertices-1}.

is_tree ()

Checks if the graph is tree.

Returnsis_true (*bool*) – If the graph is a tree.

isolated_vertices ()

Returns the isolated vertices of the graph (if any), i.e. the vertices that have no edge connections.

Returnsisolated_vertices (*list*) – A *list* of the isolated vertices. If there aren't any, it returns an empty *list*.

n_children (*vertex*, *skip_checks=False*)

Returns the number of children of the selected vertex.

Parametersvertex (*int*) – The selected vertex.

Returns

- **n_children** (*int*) – The number of children.
- **skip_checks** (*bool*, optional) – If `False`, the given vertex will be checked.

Raises`ValueError` – The vertex must be in the range `[0, n_vertices - 1]`.

n_parents (*vertex*, *skip_checks=False*)

Returns the number of parents of the selected vertex.

Parameters

- **vertex** (*int*) – The selected vertex.
- **skip_checks** (*bool*, optional) – If `False`, the given vertex will be checked.

Returnsn_parents (*int*) – The number of parents.

Raises`ValueError` – The vertex must be in the range `[0, n_vertices - 1]`.

n_paths (*start*, *end*)

Returns the number of all the paths (without cycles) existing from start vertex to end vertex.

Parameters

- **start** (*int*) – The vertex from which the paths start.
- **end** (*int*) – The vertex from which the paths end.

Returnspaths (*int*) – The paths' numbers.

norm (***kwargs*)

Returns the norm of this PointCloud. This is a translation and rotation invariant measure of the point cloud's intrinsic size - in other words, it is always taken around the point cloud's centre.

By default, the Frobenius norm is taken, but this can be changed by setting kwargs - see `numpy.linalg.norm` for valid options.

Returnsnorm (*float*) – The norm of this *`PointCloud`*

parents (*vertex*, *skip_checks=False*)

Returns the parents of the selected vertex.

Parameters

- **vertex** (*int*) – The selected vertex.
- **skip_checks** (*bool*, optional) – If `False`, the given vertex will be checked.

Returnsparents (*list*) – The list of parents.

Raises`ValueError` – The vertex must be in the range `[0, n_vertices - 1]`.

range (*boundary=0*)

The range of the extent of the PointCloud.

Parametersboundary (*float*) – A optional padding distance that is used to extend the bounds from which the range is computed. Default is `0`, no extension is performed.

Returnsrange ((n_dims,) *ndarray*) – The range of the `PointCloud` extent in each dimension.

relative_location_edge(*parent*, *child*)

Returns the relative location between the provided vertices. That is if vertex j is the parent and vertex i is its child and vector l denotes the coordinates of a vertex, then

```
l_i - l_j = [[x_i], [y_i]] - [[x_j], [y_j]] =
          = [[x_i - x_j], [y_i - y_j]]
```

Parameters

- **parent** (*int*) – The first selected vertex which is considered as the parent.
- **child** (*int*) – The second selected vertex which is considered as the child.

Returnsrelative_location ((2,) *ndarray*) – The relative location vector.

Raises`ValueError` – Vertices `parent` and `child` are not connected with an edge.

relative_locations()

Returns the relative location between the vertices of each edge. If vertex j is the parent and vertex i is its child and vector l denotes the coordinates of a vertex, then:

```
l_i - l_j = [[x_i], [y_i]] - [[x_j], [y_j]] =
          = [[x_i - x_j], [y_i - y_j]]
```

Returnsrelative_locations ((n_vertexes, 2) *ndarray*) – The relative locations vector.

tojson()

Convert this PointGraph to a dictionary representation suitable for inclusion in the LJSON landmark format.

Returnsjson (*dict*) – Dictionary with `points` and `connectivity` keys.

with_dims(*dims*)

Return a copy of this shape with only particular dimensions retained.

Parametersdims (*valid numpy array slice*) – The slice that will be used on the dimensionality axis of the shape under transform. For example, to go from a 3D shape to a 2D one, [0, 1] could be provided or np.array([True, True, False]).

Returns*copy of self, with only the requested dims*

has_landmarks

Whether the object has landmarks.

Type*bool*

landmarks

The landmarks object.

Type`LandmarkManager`

lms

Deprecated. Maintained for compatibility, will be removed in a future version. Returns a copy of this object, which previously would have held the 'underlying' `PointCloud` subclass.

Typeself

n_dims

The number of dimensions in the pointcloud.

Type*int*

n_edges
Returns the number of edges.

Type*int*

n_landmark_groups
The number of landmark groups on this object.

Type*int*

n_parameters
The length of the vector that this object produces.

Type*int*

n_points
The number of points in the pointcloud.

Type*int*

n_vertices
Returns the number of vertices.

Type*int*

vertices
Returns the *list* of vertices.

Type*list*

PointTree

class `menpo.shape.`**`PointTree`**(*points*, *adjacency_matrix*, *root_vertex*, *copy=True*, *skip_checks=False*)
Bases: `PointDirectedGraph`, `Tree`

Class for defining a Tree with geometry.

Parameters

- **points** (`(n_vertices, n_dims)` *ndarray*) – The array representing the points.
- **adjacency_matrix** (`(n_vertices, n_vertices)` *ndarray* or *csr_matrix*) – The adjacency matrix of the tree in which the rows represent parents and columns represent children. The non-edges must be represented with zeros and the edges can have a weight value.

  NoteA tree must not have isolated vertices.
- **root_vertex** (*int*) – The vertex to be set as root.
- **copy** (*bool*, optional) – If `False`, the `adjacency_matrix` will not be copied on assignment.
- **skip_checks** (*bool*, optional) – If `True`, no checks will be performed.

Raises

- `ValueError` – A point for each graph vertex needs to be passed. Got {n_points} points instead of {n_vertices}.
- `ValueError` – adjacency_matrix must be either a numpy.ndarray or a scipy.sparse.csr_matrix.

- `ValueError` – Graph must have at least two vertices.
- `ValueError` – adjacency_matrix must be square (n_vertices, n_vertices,), ({adjacency_matrix.shape[0]}, {adjacency_matrix.shape[1]}) given instead.
- `ValueError` – The provided edges do not represent a tree.
- `ValueError` – The root_vertex must be in the range `[0, n_vertices - 1]`.
- `ValueError` – The combination of adjacency matrix and root vertex is not valid. BFS returns a different tree.

Examples

The following tree

```
       0
       |
   ____|____
  1        2
  |        |
 _|_       |
3   4      5
|   |      |
|   |      |
6   7      8
```

can be defined as

```
import numpy as np
adjacency_matrix = np.array([[0, 1, 1, 0, 0, 0, 0, 0, 0],
                             [0, 0, 0, 1, 1, 0, 0, 0, 0],
                             [0, 0, 0, 0, 0, 1, 0, 0, 0],
                             [0, 0, 0, 0, 0, 0, 1, 0, 0],
                             [0, 0, 0, 0, 0, 0, 0, 1, 0],
                             [0, 0, 0, 0, 0, 0, 0, 0, 1],
                             [0, 0, 0, 0, 0, 0, 0, 0, 0],
                             [0, 0, 0, 0, 0, 0, 0, 0, 0],
                             [0, 0, 0, 0, 0, 0, 0, 0, 0]])
points = np.array([[30, 30], [10, 20], [50, 20], [0, 10], [20, 10],
                   [50, 10], [0, 0], [20, 0], [50, 0]])
tree = PointTree(points, adjacency_matrix, root_vertex=0)
```

or

```
from scipy.sparse import csr_matrix
adjacency_matrix = csr_matrix(([1] * 8, ([0, 0, 1, 1, 2, 3, 4, 5],
                                         [1, 2, 3, 4, 5, 6, 7, 8])),
                              shape=(9, 9))
points = np.array([[30, 30], [10, 20], [50, 20], [0, 10], [20, 10],
                   [50, 10], [0, 0], [20, 0], [50, 0]])
tree = PointTree(points, adjacency_matrix, root_vertex=0)
```

_view_2d(*figure_id=None*, *new_figure=False*, *image_view=True*, *render_lines=True*, *line_colour='r'*, *line_style='-'*, *line_width=1.0*, *render_markers=True*, *marker_style='o'*, *marker_size=5*, *marker_face_colour='k'*, *marker_edge_colour='k'*, *marker_edge_width=1.0*, *render_numbering=False*, *numbers_horizontal_align='center'*, *numbers_vertical_align='bottom'*, *numbers_font_name='sans-serif'*, *numbers_font_size=10*, *numbers_font_style='normal'*, *numbers_font_weight='normal'*, *numbers_font_colour='k'*, *render_axes=True*, *axes_font_name='sans-serif'*, *axes_font_size=10*, *axes_font_style='normal'*, *axes_font_weight='normal'*, *axes_x_limits=None*, *axes_y_limits=None*, *axes_x_ticks=None*, *axes_y_ticks=None*, *figure_size=(7, 7)*, *label=None*, ***kwargs*)

Visualization of the PointGraph in 2D.

Returns

- **figure_id** (*object*, optional) – The id of the figure to be used.
- **new_figure** (*bool*, optional) – If `True`, a new figure is created.
- **image_view** (*bool*, optional) – If `True` the PointGraph will be viewed as if it is in the image coordinate system.
- **render_lines** (*bool*, optional) – If `True`, the edges will be rendered.
- **line_colour** (*See Below, optional*) – The colour of the lines. Example options:

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **line_style** (`{'-', '--', '-.', ':'}`, optional) – The style of the lines.
- **line_width** (*float*, optional) – The width of the lines.
- **render_markers** (*bool*, optional) – If `True`, the markers will be rendered.
- **marker_style** (*See Below, optional*) –

  The style of the markers. Example options

```
{., ,, o, v, ^, <, >, +, x, D, d, s, p, *, h, H, 1, 2, 3, 4, 8}
```

- **marker_size** (*int*, optional) – The size of the markers in points.
- **marker_face_colour** (*See Below, optional*) – The face (filling) colour of the markers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **marker_edge_colour** (*See Below, optional*) – The edge colour of the markers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **marker_edge_width** (*float*, optional) – The width of the markers' edge.
- **render_numbering** (*bool*, optional) – If `True`, the landmarks will be numbered.

- **numbers_horizontal_align** (`{center, right, left}`, optional) – The horizontal alignment of the numbers' texts.
- **numbers_vertical_align** (`{center, top, bottom, baseline}`, optional) – The vertical alignment of the numbers' texts.
- **numbers_font_name** (*See Below, optional*) –

  The font of the numbers. Example options

```
{serif, sans-serif, cursive, fantasy, monospace}
```

- **numbers_font_size** (*int*, optional) – The font size of the numbers.
- **numbers_font_style** (`{normal, italic, oblique}`, optional) – The font style of the numbers.
- **numbers_font_weight** (*See Below, optional*) – The font weight of the numbers. Example options

```
{ultralight, light, normal, regular, book, medium, roman,
semibold, demibold, demi, bold, heavy, extra bold, black}
```

- **numbers_font_colour** (*See Below, optional*) – The font colour of the numbers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **render_axes** (*bool*, optional) – If `True`, the axes will be rendered.
- **axes_font_name** (*See Below, optional*) – The font of the axes. Example options

```
{serif, sans-serif, cursive, fantasy, monospace}
```

- **axes_font_size** (*int*, optional) – The font size of the axes.
- **axes_font_style** ({`normal`, `italic`, `oblique`}, optional) – The font style of the axes.
- **axes_font_weight** (*See Below, optional*) – The font weight of the axes. Example options

```
{ultralight, light, normal, regular, book, medium, roman,
semibold, demibold, demi, bold, heavy, extra bold, black}
```

- **axes_x_limits** (*float* or (*float*, *float*) or `None`, optional) – The limits of the x axis. If *float*, then it sets padding on the right and left of the PointGraph as a percentage of the PointGraph's width. If *tuple* or *list*, then it defines the axis limits. If `None`, then the limits are set automatically.
- **axes_y_limits** ((*float*, *float*) *tuple* or `None`, optional) – The limits of the y axis. If *float*, then it sets padding on the top and bottom of the PointGraph as a percentage of the PointGraph's height. If *tuple* or *list*, then it defines the axis limits. If `None`, then the limits are set automatically.
- **axes_x_ticks** (*list* or *tuple* or `None`, optional) – The ticks of the x axis.
- **axes_y_ticks** (*list* or *tuple* or `None`, optional) – The ticks of the y axis.
- **figure_size** ((*float*, *float*) *tuple* or `None`, optional) – The size of the figure in inches.
- **label** (*str*, optional) – The name entry in case of a legend.

Returns **viewer** (`PointGraphViewer2d`) – The viewer object.

_view_landmarks_2d(*group=None*, *with_labels=None*, *without_labels=None*, *figure_id=None*, *new_figure=False*, *image_view=True*, *render_lines=True*, *line_colour='k'*, *line_style='-'*, *line_width=2*, *render_markers=True*, *marker_style='s'*, *marker_size=7*, *marker_face_colour='k'*, *marker_edge_colour='k'*, *marker_edge_width=1.0*, *render_lines_lms=True*, *line_colour_lms=None*, *line_style_lms='-'*, *line_width_lms=1*, *render_markers_lms=True*, *marker_style_lms='o'*, *marker_size_lms=5*, *marker_face_colour_lms=None*, *marker_edge_colour_lms=None*, *marker_edge_width_lms=1.0*, *render_numbering=False*, *numbers_horizontal_align='center'*, *numbers_vertical_align='bottom'*, *numbers_font_name='sans-serif'*, *numbers_font_size=10*, *numbers_font_style='normal'*, *numbers_font_weight='normal'*, *numbers_font_colour='k'*, *render_legend=False*, *legend_title=''*, *legend_font_name='sans-serif'*, *legend_font_style='normal'*, *legend_font_size=10*, *legend_font_weight='normal'*, *legend_marker_scale=None*, *legend_location=2*, *legend_bbox_to_anchor=(1.05, 1.0)*, *legend_border_axes_pad=None*, *legend_n_columns=1*, *legend_horizontal_spacing=None*, *legend_vertical_spacing=None*, *legend_border=True*, *legend_border_padding=None*, *legend_shadow=False*, *legend_rounded_corners=False*, *render_axes=False*, *axes_font_name='sans-serif'*, *axes_font_size=10*, *axes_font_style='normal'*, *axes_font_weight='normal'*, *axes_x_limits=None*, *axes_y_limits=None*, *axes_x_ticks=None*, *axes_y_ticks=None*, *figure_size=(7, 7)*)

Visualize the landmarks. This method will appear on the *PointGraph* as `view_landmarks`.

Parameters

- **group** (*str* or''None'' optional) – The landmark group to be visualized. If `None` and there are more than one landmark groups, an error is raised.
- **with_labels** (`None` or *str* or *list* of *str*, optional) – If not `None`, only show the given label(s). Should **not** be used with the `without_labels` kwarg.
- **without_labels** (`None` or *str* or *list* of *str*, optional) – If not `None`, show all except the given label(s). Should **not** be used with the `with_labels` kwarg.
- **figure_id** (*object*, optional) – The id of the figure to be used.
- **new_figure** (*bool*, optional) – If `True`, a new figure is created.
- **image_view** (*bool*, optional) – If `True` the PointCloud will be viewed as if it is in the image coordinate system.
- **render_lines** (*bool*, optional) – If `True`, the edges will be rendered.
- **line_colour** (*See Below, optional*) – The colour of the lines. Example options:

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **line_style** (`{-, --, -., :}`, optional) – The style of the lines.
- **line_width** (*float*, optional) – The width of the lines.
- **render_markers** (*bool*, optional) – If `True`, the markers will be rendered.

- **marker_style** (*See Below, optional*) – The style of the markers. Example options

```
{., ,, o, v, ^, <, >, +, x, D, d, s, p, *, h, H, 1, 2, 3, 4, 8}
```

- **marker_size** (*int*, optional) – The size of the markers in points.
- **marker_face_colour** (*See Below, optional*) – The face (filling) colour of the markers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **marker_edge_colour** (*See Below, optional*) – The edge colour of the markers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **marker_edge_width** (*float*, optional) – The width of the markers' edge.
- **render_lines_lms** (*bool*, optional) – If `True`, the edges of the landmarks will be rendered.
- **line_colour_lms** (*See Below, optional*) – The colour of the lines of the landmarks. Example options:

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **line_style_lms** (`{-, --, -., :}`, optional) – The style of the lines of the landmarks.
- **line_width_lms** (*float*, optional) – The width of the lines of the landmarks.
- **render_markers** – If `True`, the markers of the landmarks will be rendered.
- **marker_style** – The style of the markers of the landmarks. Example options

```
{., ,, o, v, ^, <, >, +, x, D, d, s, p, *, h, H, 1, 2, 3, 4, 8}
```

- **marker_size** – The size of the markers of the landmarks in points.
- **marker_face_colour** – The face (filling) colour of the markers of the landmarks. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **marker_edge_colour** – The edge colour of the markers of the landmarks. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **marker_edge_width** – The width of the markers' edge of the landmarks.
- **render_numbering** (*bool*, optional) – If `True`, the landmarks will be numbered.
- **numbers_horizontal_align** (`{center, right, left}`, optional) – The horizontal alignment of the numbers' texts.
- **numbers_vertical_align** (`{center, top, bottom, baseline}`, optional) – The vertical alignment of the numbers' texts.
- **numbers_font_name** (*See Below, optional*) – The font of the numbers. Example options

```
{serif, sans-serif, cursive, fantasy, monospace}
```

- **numbers_font_size** (*int*, optional) – The font size of the numbers.
- **numbers_font_style** (`{normal, italic, oblique}`, optional) – The font style of the numbers.
- **numbers_font_weight** (*See Below, optional*) – The font weight of the numbers. Example options

```
{ultralight, light, normal, regular, book, medium, roman,
semibold, demibold, demi, bold, heavy, extra bold, black}
```

- **numbers_font_colour** (*See Below, optional*) – The font colour of the numbers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **render_legend** (*bool*, optional) – If `True`, the legend will be rendered.
- **legend_title** (*str*, optional) – The title of the legend.
- **legend_font_name** (*See below, optional*) – The font of the legend. Example options

```
{serif, sans-serif, cursive, fantasy, monospace}
```

- **legend_font_style** (`{normal, italic, oblique}`, optional) – The font style of the legend.
- **legend_font_size** (*int*, optional) – The font size of the legend.
- **legend_font_weight** (*See Below, optional*) – The font weight of the legend. Example options

```
{ultralight, light, normal, regular, book, medium, roman,
semibold, demibold, demi, bold, heavy, extra bold, black}
```

- **legend_marker_scale** (*float*, optional) – The relative size of the legend markers with respect to the original
- **legend_location** (*int*, optional) – The location of the legend. The predefined values are:

'best'	0
'upper right'	1
'upper left'	2
'lower left'	3
'lower right'	4
'right'	5
'center left'	6
'center right'	7
'lower center'	8
'upper center'	9
'center'	10

- **legend_bbox_to_anchor** ((*float*, *float*) *tuple*, optional) – The bbox that the legend will be anchored.
- **legend_border_axes_pad** (*float*, optional) – The pad between the axes and legend border.
- **legend_n_columns** (*int*, optional) – The number of the legend's columns.
- **legend_horizontal_spacing** (*float*, optional) – The spacing between the columns.
- **legend_vertical_spacing** (*float*, optional) – The vertical space between the legend entries.
- **legend_border** (*bool*, optional) – If `True`, a frame will be drawn around the legend.
- **legend_border_padding** (*float*, optional) – The fractional whitespace inside the legend border.
- **legend_shadow** (*bool*, optional) – If `True`, a shadow will be drawn behind legend.
- **legend_rounded_corners** (*bool*, optional) – If `True`, the frame's corners will be rounded (fancybox).
- **render_axes** (*bool*, optional) – If `True`, the axes will be rendered.
- **axes_font_name** (*See Below, optional*) – The font of the axes. Example options

```
{serif, sans-serif, cursive, fantasy, monospace}
```

- **axes_font_size** (*int*, optional) – The font size of the axes.
- **axes_font_style** (`{normal, italic, oblique}`, optional) – The font style of the axes.
- **axes_font_weight** (*See Below, optional*) – The font weight of the axes. Example options

```
{ultralight, light, normal, regular, book, medium, roman,
semibold,demibold, demi, bold, heavy, extra bold, black}
```

- **axes_x_limits** (*float* or (*float*, *float*) or `None`, optional) – The limits of the x axis. If *float*, then it sets padding on the right and left of the PointCloud as a percentage of the PointCloud's width. If *tuple* or *list*, then it defines the axis limits. If `None`, then the limits are set automatically.
- **axes_y_limits** ((*float*, *float*) *tuple* or `None`, optional) – The limits of the y axis. If *float*, then it sets padding on the top and bottom of the PointCloud as a percentage of the

PointCloud's height. If *tuple* or *list*, then it defines the axis limits. If `None`, then the limits are set automatically.

- **axes_x_ticks** (*list* or *tuple* or `None`, optional) – The ticks of the x axis.
- **axes_y_ticks** (*list* or *tuple* or `None`, optional) – The ticks of the y axis.
- **figure_size** ((*float*, *float*) *tuple* or `None` optional) – The size of the figure in inches.

Raises

- `ValueError` – If both `with_labels` and `without_labels` are passed.
- `ValueError` – If the landmark manager doesn't contain the provided group label.

as_vector(***kwargs*)

Returns a flattened representation of the object as a single vector.

Returnsvector (*(N,) ndarray*) – The core representation of the object, flattened into a single vector. Note that this is always a view back on to the original object, but is not writable.

bounding_box()

Return a bounding box from two corner points as a directed graph. In the case of a 2D pointcloud, first point (0) should be nearest the origin. In the case of an image, this ordering would appear as:

```
0<--3
|   ^
|   |
v   |
1-->2
```

In the case of a pointcloud, the ordering will appear as:

```
3<--2
|   ^
|   |
v   |
0-->1
```

In the case of a 3D pointcloud, the first point (0) should be the near closest to the origin and the second point is the far opposite corner.

Returnsbounding_box (`PointDirectedGraph`) – The axis aligned bounding box of the PointCloud.

bounds(*boundary=0*)

The minimum to maximum extent of the PointCloud. An optional boundary argument can be provided to expand the bounds by a constant margin.

Parametersboundary (*float*) – A optional padding distance that is added to the bounds. Default is `0`, meaning the max/min of tightest possible containing square/cube/hypercube is returned.

Returns

- **min_b** (`(n_dims,)` *ndarray*) – The minimum extent of the `PointCloud` and boundary along each dimension
- **max_b** (`(n_dims,)` *ndarray*) – The maximum extent of the `PointCloud` and boundary along each dimension

centre()

The mean of all the points in this PointCloud (centre of mass).

Returnscentre (`(n_dims)` *ndarray*) – The mean of this PointCloud's points.

centre_of_bounds()

The centre of the absolute bounds of this PointCloud. Contrast with `centre()`, which is the mean point position.

Returns **centre** (`n_dims` *ndarray*) – The centre of the bounds of this PointCloud.

children(*vertex*, *skip_checks=False*)

Returns the children of the selected vertex.

Parameters

- **vertex** (*int*) – The selected vertex.
- **skip_checks** (*bool*, optional) – If `False`, the given vertex will be checked.

Returns **children** (*list*) – The list of children.

Raises `ValueError` – The vertex must be between 0 and {n_vertices-1}.

constrain_to_bounds(*bounds*)

Returns a copy of this PointCloud, constrained to lie exactly within the given bounds. Any points outside the bounds will be 'snapped' to lie *exactly* on the boundary.

Parameters **bounds** (`(n_dims, n_dims)` tuple of scalars) – The bounds to constrain this pointcloud within.

Returns **constrained** (`PointCloud`) – The constrained pointcloud.

copy()

Generate an efficient copy of this object.

Note that Numpy arrays and other `Copyable` objects on `self` will be deeply copied. Dictionaries and sets will be shallow copied, and everything else will be assigned (no copy will be made).

Classes that store state other than numpy arrays and immutable types should overwrite this method to ensure all state is copied.

Returns `type(self)` – A copy of this object

depth_of_vertex(*vertex*, *skip_checks=False*)

Returns the depth of the specified vertex.

Parameters

- **vertex** (*int*) – The selected vertex.
- **skip_checks** (*bool*, optional) – If `False`, the given vertex will be checked.

Returns **depth** (*int*) – The depth of the selected vertex.

Raises `ValueError` – The vertex must be in the range `[0, n_vertices - 1]`.

distance_to(*pointcloud*, ***kwargs*)

Returns a distance matrix between this PointCloud and another. By default the Euclidean distance is calculated - see *scipy.spatial.distance.cdist* for valid kwargs to change the metric and other properties.

Parameters **pointcloud** (`PointCloud`) – The second pointcloud to compute distances between. This must be of the same dimension as this PointCloud.

Returns **distance_matrix** (`(n_points, n_points)` *ndarray*) – The symmetric pairwise distance matrix between the two PointClouds s.t. `distance_matrix[i, j]` is the distance between the i'th point of this PointCloud and the j'th point of the input PointCloud.

find_all_paths(*start*, *end*, *path=[]*)

Returns a list of lists with all the paths (without cycles) found from start vertex to end vertex.

Parameters

- **start** (*int*) – The vertex from which the paths start.
- **end** (*int*) – The vertex from which the paths end.
- **path** (*list*, optional) – An existing path to append to.

Returnspaths (*list* of *list*) – The list containing all the paths from start to end.

find_all_shortest_paths (*algorithm='auto'*, *unweighted=False*)

Returns the distances and predecessors arrays of the graph's shortest paths.

Parameters

- **algorithm** (*'str', see below, optional*) – The algorithm to be used. Possible options are:

'dijkstra'	Dijkstra's algorithm with Fibonacci heaps
'bellman-ford'	Bellman-Ford algorithm
'johnson'	Johnson's algorithm
'floyd-warshall'	Floyd-Warshall algorithm
'auto'	Select the best among the above

- **unweighted** (*bool*, optional) – If `True`, then find unweighted distances. That is, rather than finding the path between each vertex such that the sum of weights is minimized, find the path such that the number of edges is minimized.

Returns

- **distances** (`(n_vertices, n_vertices,)` *ndarray*) – The matrix of distances between all graph vertices. `distances[i,j]` gives the shortest distance from vertex `i` to vertex `j` along the graph.
- **predecessors** (`(n_vertices, n_vertices,)` *ndarray*) – The matrix of predecessors, which can be used to reconstruct the shortest paths. Each entry `predecessors[i, j]` gives the index of the previous vertex in the path from vertex `i` to vertex `j`. If no path exists between vertices `i` and `j`, then `predecessors[i, j] = -9999`.

find_path (*start*, *end*, *method='bfs'*, *skip_checks=False*)

Returns a *list* with the first path (without cycles) found from the `start` vertex to the `end` vertex. It can employ either depth-first search or breadth-first search.

Parameters

- **start** (*int*) – The vertex from which the path starts.
- **end** (*int*) – The vertex to which the path ends.
- **method** ({`bfs`, `dfs`}, optional) – The method to be used.
- **skip_checks** (*bool*, optional) – If `True`, then input arguments won't pass through checks. Useful for efficiency.

Returnspath (*list*) – The path's vertices.

Raises`ValueError` – Method must be either bfs or dfs.

find_shortest_path (*start*, *end*, *algorithm='auto'*, *unweighted=False*, *skip_checks=False*)

Returns a *list* with the shortest path (without cycles) found from `start` vertex to `end` vertex.

Parameters

- **start** (*int*) – The vertex from which the path starts.
- **end** (*int*) – The vertex to which the path ends.

- **algorithm** (*'str', see below, optional*) – The algorithm to be used. Possible options are:

'dijkstra'	Dijkstra's algorithm with Fibonacci heaps
'bellman-ford'	Bellman-Ford algorithm
'johnson'	Johnson's algorithm
'floyd-warshall'	Floyd-Warshall algorithm
'auto'	Select the best among the above

- **unweighted** (*bool*, optional) – If `True`, then find unweighted distances. That is, rather than finding the path such that the sum of weights is minimized, find the path such that the number of edges is minimized.
- **skip_checks** (*bool*, optional) – If `True`, then input arguments won't pass through checks. Useful for efficiency.

Returns

- **path** (*list*) – The shortest path's vertices, including `start` and `end`. If there was not path connecting the vertices, then an empty *list* is returned.
- **distance** (*int* or *float*) – The distance (cost) of the path from `start` to `end`.

from_mask(*mask*)

A 1D boolean array with the same number of elements as the number of points in the *PointTree*. This is then broadcast across the dimensions of the *PointTree* and returns a new *PointTree* containing only those points that were `True` in the mask.

Parametersmask (`(n_points,)` *ndarray*) – 1D array of booleans

Returnspointtree (*`PointTree`*) – A new pointtree that has been masked.

Raises

- `ValueError` – Mask must be a 1D boolean array of the same number of entries as points in this PointTree.
- `ValueError` – Cannot remove root vertex.

from_vector(*vector*)

Build a new instance of the object from it's vectorized state.

`self` is used to fill out the missing state required to rebuild a full object from it's standardized flattened state. This is the default implementation, which is which is a `deepcopy` of the object followed by a call to *`from_vector_inplace()`*. This method can be overridden for a performance benefit if desired.

Parametersvector (`(n_parameters,)` *ndarray*) – Flattened representation of the object.

Returnsobject (`type(self)`) – An new instance of this class.

from_vector_inplace(*vector*)

Deprecated. Use the non-mutating API, *`from_vector`*.

For internal usage in performance-sensitive spots, see *_from_vector_inplace()*

Parametersvector (`(n_parameters,)` *ndarray*) – Flattened representation of this object

get_adjacency_list()

Returns the adjacency list of the graph, i.e. a *list* of length `n_vertices` that for each vertex has a *list* of the vertex neighbours. If the graph is directed, the neighbours are children.

Returnsadjacency_list (*list* of *list* of length `n_vertices`) – The adjacency list of the graph.

h_points()

Convert poincloud to a homogeneous array: `(n_dims + 1, n_points)`

Type`type(self)`

has_cycles()

Checks if the graph has at least one cycle.

Returnshas_cycles (*bool*) – `True` if the graph has cycles.

has_isolated_vertices()

Whether the graph has any isolated vertices, i.e. vertices with no edge connections.

Returnshas_isolated_vertices (*bool*) – `True` if the graph has at least one isolated vertex.

has_nan_values()

Tests if the vectorized form of the object contains `nan` values or not. This is particularly useful for objects with unknown values that have been mapped to `nan` values.

Returnshas_nan_values (*bool*) – If the vectorized object contains `nan` values.

classmethod init_2d_grid(*shape*, *spacing=None*, *adjacency_matrix=None*, *root_vertex=None*, *skip_checks=False*)

Create a pointtree that exists on a regular 2D grid. The first dimension is the number of rows in the grid and the second dimension of the shape is the number of columns. `spacing` optionally allows the definition of the distance between points (uniform over points). The spacing may be different for rows and columns.

The default connectivity is the minimum spanning tree formed from a triangulation of the grid. The default root will be the centre of the grid.

Parameters

- **shape** (*tuple* of 2 *int*) – The size of the grid to create, this defines the number of points across each dimension in the grid. The first element is the number of rows and the second is the number of columns.
- **spacing** (*int* or *tuple* of 2 *int*, optional) – The spacing between points. If a single *int* is provided, this is applied uniformly across each dimension. If a *tuple* is provided, the spacing is applied non-uniformly as defined e.g. `(2, 3)` gives a spacing of 2 for the rows and 3 for the columns.
- **adjacency_matrix** (`(n_vertices, n_vertices)` *ndarray* or *csr_matrix*, optional) – The adjacency matrix of the tree in which the rows represent parents and columns represent children. The non-edges must be represented with zeros and the edges can have a weight value.

  NoteA tree must not have isolated vertices.
- **root_vertex** (*int*) – The vertex to be set as root.
- **skip_checks** (*bool*, optional) – If `True`, no checks will be performed. Only considered if an adjacency matrix is provided.

Returnsshape_cls (*type(cls)*) – A PointCloud or subclass arranged in a grid.

classmethod init_from_depth_image(*depth_image*, *spacing=None*, *adjacency_matrix=None*, *root_vertex=None*, *skip_checks=False*)

Return a 3D point cloud from the given depth image. The depth image is assumed to represent height/depth values and the XY coordinates are assumed to unit spaced and represent image coordinates. This is particularly useful for visualising depth values that have been recovered from images.

The default connectivity is the minimum spanning tree formed from a triangulation of the grid. The default root will be the centre of the grid (for an unmasked image), otherwise it will be the first pixel in the masked are of the image.

Parameters

- **depth_image** (*Image* or subclass) – A single channel image that contains depth values - as commonly returned by RGBD cameras, for example.
- **spacing** (*int* or *tuple* of 2 *int*, optional) – The spacing between points. If a single *int* is provided, this is applied uniformly across each dimension. If a *tuple* is provided, the spacing is applied non-uniformly as defined e.g. `(2, 3)` gives a spacing of 2 for the rows and 3 for the columns.
- **adjacency_matrix** (`(n_vertices, n_vertices)` *ndarray* or *csr_matrix*, optional) – The adjacency matrix of the tree in which the rows represent parents and columns represent children. The non-edges must be represented with zeros and the edges can have a weight value.

  NoteA tree must not have isolated vertices.
- **root_vertex** (*int*) – The vertex to be set as root.
- **skip_checks** (*bool*, optional) – If `True`, no checks will be performed. Only considered if an adjacency matrix is provided.

Returnsdepth_cloud (`type(cls)`) – A new 3D PointCloud with unit XY coordinates and the given depth values as Z coordinates.

classmethod init_from_edges(*points*, *edges*, *root_vertex*, *copy=True*, *skip_checks=False*)

Construct a *PointTree* from edges array.

Parameters

- **points** (`(n_vertices, n_dims, )` *ndarray*) – The array of point locations.
- **edges** (`(n_edges, 2, )` *ndarray*) – The *ndarray* of edges, i.e. all the pairs of vertices that are connected with an edge.
- **root_vertex** (*int*) – That vertex that will be set as root.
- **copy** (*bool*, optional) – If `False`, the `adjacency_matrix` will not be copied on assignment.
- **skip_checks** (*bool*, optional) – If `True`, no checks will be performed.

Examples

The following tree

```
       0
       |
   ____|____
  1        2
  |        |
 _|_       |
3   4      5
|   |      |
|   |      |
6   7      8
```

can be defined as

```
from menpo.shape import PointTree
import numpy as np
points = np.array([[30, 30], [10, 20], [50, 20], [0, 10], [20, 10],
                   [50, 10], [0, 0], [20, 0], [50, 0]])
edges = np.array([[0, 1], [0, 2], [1, 3], [1, 4], [2, 5], [3, 6],
```

```
                    [4, 7], [5, 8]])
tree = PointTree.init_from_edges(points, edges, root_vertex=0)
```

is_edge (*vertex_1*, *vertex_2*, *skip_checks=False*)

Whether there is an edge between the provided vertices.

Parameters

- **vertex_1** (*int*) – The first selected vertex. Parent if the graph is directed.
- **vertex_2** (*int*) – The second selected vertex. Child if the graph is directed.
- **skip_checks** (*bool*, optional) – If `False`, the given vertices will be checked.

Returnsis_edge (*bool*) – `True` if there is an edge connecting `vertex_1` and `vertex_2`.

Raises`ValueError` – The vertex must be between 0 and {n_vertices-1}.

is_leaf (*vertex*, *skip_checks=False*)

Whether the vertex is a leaf.

Parameters

- **vertex** (*int*) – The selected vertex.
- **skip_checks** (*bool*, optional) – If `False`, the given vertex will be checked.

Returnsis_leaf (*bool*) – If `True`, then selected vertex is a leaf.

Raises`ValueError` – The vertex must be in the range `[0, n_vertices - 1]`.

is_tree ()

Checks if the graph is tree.

Returnsis_true (*bool*) – If the graph is a tree.

isolated_vertices ()

Returns the isolated vertices of the graph (if any), i.e. the vertices that have no edge connections.

Returnsisolated_vertices (*list*) – A *list* of the isolated vertices. If there aren't any, it returns an empty *list*.

n_children (*vertex*, *skip_checks=False*)

Returns the number of children of the selected vertex.

Parametersvertex (*int*) – The selected vertex.

Returns

- **n_children** (*int*) – The number of children.
- **skip_checks** (*bool*, optional) – If `False`, the given vertex will be checked.

Raises`ValueError` – The vertex must be in the range `[0, n_vertices - 1]`.

n_parents (*vertex*, *skip_checks=False*)

Returns the number of parents of the selected vertex.

Parameters

- **vertex** (*int*) – The selected vertex.
- **skip_checks** (*bool*, optional) – If `False`, the given vertex will be checked.

Returnsn_parents (*int*) – The number of parents.

Raises `ValueError` – The vertex must be in the range `[0, n_vertices - 1]`.

n_paths (*start*, *end*)

Returns the number of all the paths (without cycles) existing from start vertex to end vertex.

Parameters

- **start** (*int*) – The vertex from which the paths start.
- **end** (*int*) – The vertex from which the paths end.

Returns **paths** (*int*) – The paths' numbers.

n_vertices_at_depth (*depth*)

Returns the number of vertices at the specified depth.

Parameters **depth** (*int*) – The selected depth.

Returns **n_vertices** (*int*) – The number of vertices that lie in the specified depth.

norm (***kwargs*)

Returns the norm of this PointCloud. This is a translation and rotation invariant measure of the point cloud's intrinsic size - in other words, it is always taken around the point cloud's centre.

By default, the Frobenius norm is taken, but this can be changed by setting kwargs - see `numpy.linalg.norm` for valid options.

Returns **norm** (*float*) – The norm of this `PointCloud`

parent (*vertex*, *skip_checks=False*)

Returns the parent of the selected vertex.

Parameters

- **vertex** (*int*) – The selected vertex.
- **skip_checks** (*bool*, optional) – If `False`, the given vertex will be checked.

Returns **parent** (*int*) – The parent vertex.

Raises `ValueError` – The vertex must be in the range `[0, n_vertices - 1]`.

parents (*vertex*, *skip_checks=False*)

Returns the parents of the selected vertex.

Parameters

- **vertex** (*int*) – The selected vertex.
- **skip_checks** (*bool*, optional) – If `False`, the given vertex will be checked.

Returns **parents** (*list*) – The list of parents.

Raises `ValueError` – The vertex must be in the range `[0, n_vertices - 1]`.

range (*boundary=0*)

The range of the extent of the PointCloud.

Parameters **boundary** (*float*) – A optional padding distance that is used to extend the bounds from which the range is computed. Default is `0`, no extension is performed.

Returns **range** (`(n_dims,)` *ndarray*) – The range of the `PointCloud` extent in each dimension.

relative_location_edge (*parent*, *child*)

Returns the relative location between the provided vertices. That is if vertex j is the parent and vertex i is its child and vector l denotes the coordinates of a vertex, then

```
l_i - l_j = [[x_i], [y_i]] - [[x_j], [y_j]] =
          = [[x_i - x_j], [y_i - y_j]]
```

Parameters

- **parent** (*int*) – The first selected vertex which is considered as the parent.
- **child** (*int*) – The second selected vertex which is considered as the child.

Returnsrelative_location (`(2,)` *ndarray*) – The relative location vector.

Raises`ValueError` – Vertices `parent` and `child` are not connected with an edge.

relative_locations()

Returns the relative location between the vertices of each edge. If vertex j is the parent and vertex i is its child and vector l denotes the coordinates of a vertex, then:

```
l_i - l_j = [[x_i], [y_i]] - [[x_j], [y_j]] =
          = [[x_i - x_j], [y_i - y_j]]
```

Returnsrelative_locations (`(n_vertexes, 2)` *ndarray*) – The relative locations vector.

tojson()

Convert this PointGraph to a dictionary representation suitable for inclusion in the LJSON landmark format.

Returnsjson (*dict*) – Dictionary with `points` and `connectivity` keys.

vertices_at_depth(*depth*)

Returns a list of vertices at the specified depth.

Parametersdepth (*int*) – The selected depth.

Returnsvertices (*list*) – The vertices that lie in the specified depth.

with_dims(*dims*)

Return a copy of this shape with only particular dimensions retained.

Parametersdims (*valid numpy array slice*) – The slice that will be used on the dimensionality axis of the shape under transform. For example, to go from a 3D shape to a 2D one, [0, 1] could be provided or np.array([True, True, False]).

Returns*copy of self, with only the requested dims*

has_landmarks

Whether the object has landmarks.

Type*bool*

landmarks

The landmarks object.

Type*LandmarkManager*

leaves

Returns a *list* with the all leaves of the tree.

Type*list*

lms

Deprecated. Maintained for compatibility, will be removed in a future version. Returns a copy of this object, which previously would have held the 'underlying' *PointCloud* subclass.

Typeself

maximum_depth
Returns the maximum depth of the tree.

Type*int*

n_dims
The number of dimensions in the pointcloud.

Type*int*

n_edges
Returns the number of edges.

Type*int*

n_landmark_groups
The number of landmark groups on this object.

Type*int*

n_leaves
Returns the number of leaves of the tree.

Type*int*

n_parameters
The length of the vector that this object produces.

Type*int*

n_points
The number of points in the pointcloud.

Type*int*

n_vertices
Returns the number of vertices.

Type*int*

vertices
Returns the *list* of vertices.

Type*list*

LabelledPointGraph

A subclass of `PointUndirectedGraph` that allows the attaching of *labels* associated with semantic parts of the object.

LabelledPointUndirectedGraph

class `menpo.shape.`**`LabelledPointUndirectedGraph`**(*points*, *adjacency_matrix*, *labels_to_masks*, *copy=True*, *skip_checks=False*)

Bases: `PointUndirectedGraph`

A subclass of `PointUndirectedGraph` that allows the attaching of 'labels' associated with semantic parts of an object. For example, for a face the semantic parts might be the eyes, nose and mouth. These 'labels' are defined as a dictionary of string keys that map to boolean mask arrays that define which of the underlying points belong to a given label.

The labels to masks must be within an *OrderedDict* so that semantic ordering can be maintained.

Parameters

- **points** (*ndarray*) – The points representing the landmarks.
- **adjacency_matrix** ((n_vertices, n_vertices,) *ndarray* or *csr_matrix*) – The adjacency matrix of the graph. The non-edges must be represented with zeros and the edges can have a weight value.

  Note adjacency_matrix must be symmetric.
- **labels_to_masks** (*ordereddict* {*str* -> *bool ndarray*}) – For each label, the mask that specifies the indices in to the points that belong to the label.
- **copy** (*bool*, optional) – If True, a copy of the data is stored.

Raises

- ValueError – If *dict* passed instead of *OrderedDict*
- ValueError – If no set of label masks is passed.
- ValueError – If any of the label masks differs in size to the points.
- ValueError – If there exists any point in the points that is not covered by a label.

_view_2d(*with_labels=None*, *without_labels=None*, *group='group'*, *figure_id=None*, *new_figure=False*, *image_view=True*, *render_lines=True*, *line_colour=None*, *line_style='-'*, *line_width=1*, *render_markers=True*, *marker_style='o'*, *marker_size=5*, *marker_face_colour=None*, *marker_edge_colour=None*, *marker_edge_width=1.0*, *render_numbering=False*, *numbers_horizontal_align='center'*, *numbers_vertical_align='bottom'*, *numbers_font_name='sans-serif'*, *numbers_font_size=10*, *numbers_font_style='normal'*, *numbers_font_weight='normal'*, *numbers_font_colour='k'*, *render_legend=True*, *legend_title=''*, *legend_font_name='sans-serif'*, *legend_font_style='normal'*, *legend_font_size=10*, *legend_font_weight='normal'*, *legend_marker_scale=None*, *legend_location=2*, *legend_bbox_to_anchor=(1.05, 1.0)*, *legend_border_axes_pad=None*, *legend_n_columns=1*, *legend_horizontal_spacing=None*, *legend_vertical_spacing=None*, *legend_border=True*, *legend_border_padding=None*, *legend_shadow=False*, *legend_rounded_corners=False*, *render_axes=True*, *axes_font_name='sans-serif'*, *axes_font_size=10*, *axes_font_style='normal'*, *axes_font_weight='normal'*, *axes_x_limits=None*, *axes_y_limits=None*, *axes_x_ticks=None*, *axes_y_ticks=None*, *figure_size=(10, 8)*)

Visualize the labelled point undirected graph.

Parameters

- **with_labels** (None or *str* or *list* of *str*, optional) – If not None, only show the given label(s). Should **not** be used with the without_labels kwarg.
- **without_labels** (None or *str* or *list* of *str*, optional) – If not None, show all except the given label(s). Should **not** be used with the with_labels kwarg.
- **group** (*str* or *None*, optional) – The name of the labelled point undirected graph. It is used in the legend.
- **figure_id** (*object*, optional) – The id of the figure to be used.
- **new_figure** (*bool*, optional) – If True, a new figure is created.
- **image_view** (*bool*, optional) – If True, the x and y axes are flipped.
- **render_lines** (*bool*, optional) – If True, the edges will be rendered.

- **line_colour** (*See Below, optional*) – The colour of the lines. Example options:

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

It can either be one of the above or a *list* of those defining a value per label.

- **line_style** ({'-', '--', '-.', ':'}, optional) – The style of the lines.
- **line_width** (*float*, optional) – The width of the lines.
- **render_markers** (*bool*, optional) – If `True`, the markers will be rendered.
- **marker_style** (*See Below, optional*) – The style of the markers. Example options

```
{., ,, o, v, ^, <, >, +, x, D, d, s, p, *, h, H, 1, 2, 3, 4, 8}
```

- **marker_size** (*int*, optional) – The size of the markers in points.
- **marker_face_colour** (*See Below, optional*) – The face (filling) colour of the markers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

It can either be one of the above or a *list* of those defining a value per label.

- **marker_edge_colour** (*See Below, optional*) – The edge colour of the markers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

It can either be one of the above or a *list* of those defining a value per label.

- **marker_edge_width** (*float*, optional) – The width of the markers' edge.
- **render_numbering** (*bool*, optional) – If `True`, the landmarks will be numbered.
- **numbers_horizontal_align** ({center, right, left}, optional) – The horizontal alignment of the numbers' texts.
- **numbers_vertical_align** ({center, top, bottom, baseline}, optional) – The vertical alignment of the numbers' texts.
- **numbers_font_name** (*See Below, optional*) – The font of the numbers. Example options

```
{serif, sans-serif, cursive, fantasy, monospace}
```

- **numbers_font_size** (*int*, optional) – The font size of the numbers.
- **numbers_font_style** ({normal, italic, oblique}, optional) – The font style of the numbers.
- **numbers_font_weight** (*See Below, optional*) – The font weight of the numbers. Example options

```
{ultralight, light, normal, regular, book, medium, roman,
semibold, demibold, demi, bold, heavy, extra bold, black}
```

- **numbers_font_colour** (*See Below, optional*) – The font colour of the numbers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **render_legend** (*bool*, optional) – If `True`, the legend will be rendered.
- **legend_title** (*str*, optional) – The title of the legend.
- **legend_font_name** (*See Below, optional*) – The font of the legend. Possible options

```
{serif, sans-serif, cursive, fantasy, monospace}
```

- **legend_font_style** ({`normal`, `italic`, `oblique`}, optional) – The font style of the legend.
- **legend_font_size** (*int*, optional) – The font size of the legend.
- **legend_font_weight** (*See Below, optional*) – The font weight of the legend. Possible options

```
{ultralight, light, normal, regular, book, medium, roman,
 semibold, demibold, demi, bold, heavy, extra bold, black}
```

- **legend_marker_scale** (*float*, optional) – The relative size of the legend markers with respect to the original
- **legend_location** (*int*, optional) – The location of the legend. The predefined values are:

'best'	0
'upper right'	1
'upper left'	2
'lower left'	3
'lower right'	4
'right'	5
'center left'	6
'center right'	7
'lower center'	8
'upper center'	9
'center'	10

- **legend_bbox_to_anchor** ((*float*, *float*), optional) – The bbox that the legend will be anchored.
- **legend_border_axes_pad** (*float*, optional) – The pad between the axes and legend border.
- **legend_n_columns** (*int*, optional) – The number of the legend's columns.
- **legend_horizontal_spacing** (*float*, optional) – The spacing between the columns.
- **legend_vertical_spacing** (*float*, optional) – The vertical space between the legend entries.

- **legend_border** (*bool*, optional) – If `True`, a frame will be drawn around the legend.
- **legend_border_padding** (*float*, optional) – The fractional whitespace inside the legend border.
- **legend_shadow** (*bool*, optional) – If `True`, a shadow will be drawn behind legend.
- **legend_rounded_corners** (*bool*, optional) – If `True`, the frame's corners will be rounded (fancybox).
- **render_axes** (*bool*, optional) – If `True`, the axes will be rendered.
- **axes_font_name** (*See Below, optional*) – The font of the axes. Example options

```
{serif, sans-serif, cursive, fantasy, monospace}
```

- **axes_font_size** (*int*, optional) – The font size of the axes.
- **axes_font_style** ({`normal`, `italic`, `oblique`}, optional) – The font style of the axes.
- **axes_font_weight** (*See Below, optional*) – The font weight of the axes. Example options

```
{ultralight, light, normal, regular, book, medium, roman,
semibold, demibold, demi, bold, heavy, extra bold, black}
```

- **axes_x_limits** (*float* or (*float*, *float*) or `None`, optional) – The limits of the x axis. If *float*, then it sets padding on the right and left of the LabelledPointUndirectedGraph as a percentage of the LabelledPointUndirectedGraph's width. If *tuple* or *list*, then it defines the axis limits. If `None`, then the limits are set automatically.
- **axes_y_limits** ((*float*, *float*) *tuple* or `None`, optional) – The limits of the y axis. If *float*, then it sets padding on the top and bottom of the LabelledPointUndirectedGraph as a percentage of the LabelledPointUndirectedGraph's height. If *tuple* or *list*, then it defines the axis limits. If `None`, then the limits are set automatically.
- **axes_x_ticks** (*list* or *tuple* or `None`, optional) – The ticks of the x axis.
- **axes_y_ticks** (*list* or *tuple* or `None`, optional) – The ticks of the y axis.
- **figure_size** ((*float*, *float*) or *None*, optional) – The size of the figure in inches.

Raises `ValueError` – If both `with_labels` and `without_labels` are passed.

_view_landmarks_2d(*group=None*, *with_labels=None*, *without_labels=None*, *figure_id=None*, *new_figure=False*, *image_view=True*, *render_lines=True*, *line_colour='k'*, *line_style='-'*, *line_width=2*, *render_markers=True*, *marker_style='s'*, *marker_size=7*, *marker_face_colour='k'*, *marker_edge_colour='k'*, *marker_edge_width=1.0*, *render_lines_lms=True*, *line_colour_lms=None*, *line_style_lms='-'*, *line_width_lms=1*, *render_markers_lms=True*, *marker_style_lms='o'*, *marker_size_lms=5*, *marker_face_colour_lms=None*, *marker_edge_colour_lms=None*, *marker_edge_width_lms=1.0*, *render_numbering=False*, *numbers_horizontal_align='center'*, *numbers_vertical_align='bottom'*, *numbers_font_name='sans-serif'*, *numbers_font_size=10*, *numbers_font_style='normal'*, *numbers_font_weight='normal'*, *numbers_font_colour='k'*, *render_legend=False*, *legend_title=''*, *legend_font_name='sans-serif'*, *legend_font_style='normal'*, *legend_font_size=10*, *legend_font_weight='normal'*, *legend_marker_scale=None*, *legend_location=2*, *legend_bbox_to_anchor=(1.05, 1.0)*, *legend_border_axes_pad=None*, *legend_n_columns=1*, *legend_horizontal_spacing=None*, *legend_vertical_spacing=None*, *legend_border=True*, *legend_border_padding=None*, *legend_shadow=False*, *legend_rounded_corners=False*, *render_axes=False*, *axes_font_name='sans-serif'*, *axes_font_size=10*, *axes_font_style='normal'*, *axes_font_weight='normal'*, *axes_x_limits=None*, *axes_y_limits=None*, *axes_x_ticks=None*, *axes_y_ticks=None*, *figure_size=(7, 7)*)

Visualize the landmarks. This method will appear on the *PointGraph* as `view_landmarks`.

Parameters

- **group** (*str* or''None'' optional) – The landmark group to be visualized. If `None` and there are more than one landmark groups, an error is raised.
- **with_labels** (`None` or *str* or *list* of *str*, optional) – If not `None`, only show the given label(s). Should **not** be used with the `without_labels` kwarg.
- **without_labels** (`None` or *str* or *list* of *str*, optional) – If not `None`, show all except the given label(s). Should **not** be used with the `with_labels` kwarg.
- **figure_id** (*object*, optional) – The id of the figure to be used.
- **new_figure** (*bool*, optional) – If `True`, a new figure is created.
- **image_view** (*bool*, optional) – If `True` the PointCloud will be viewed as if it is in the image coordinate system.
- **render_lines** (*bool*, optional) – If `True`, the edges will be rendered.
- **line_colour** (*See Below, optional*) – The colour of the lines. Example options:

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **line_style** (`{-, --, -., :}`, optional) – The style of the lines.
- **line_width** (*float*, optional) – The width of the lines.
- **render_markers** (*bool*, optional) – If `True`, the markers will be rendered.
- **marker_style** (*See Below, optional*) – The style of the markers. Example options

```
{., ,, o, v, ^, <, >, +, x, D, d, s, p, *, h, H, 1, 2, 3, 4, 8}
```

- **marker_size** (*int*, optional) – The size of the markers in points.
- **marker_face_colour** (*See Below, optional*) – The face (filling) colour of the markers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **marker_edge_colour** (*See Below, optional*) – The edge colour of the markers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **marker_edge_width** (*float*, optional) – The width of the markers' edge.
- **render_lines_lms** (*bool*, optional) – If `True`, the edges of the landmarks will be rendered.
- **line_colour_lms** (*See Below, optional*) – The colour of the lines of the landmarks. Example options:

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **line_style_lms** (`{-, --, -., :}`, optional) – The style of the lines of the landmarks.
- **line_width_lms** (*float*, optional) – The width of the lines of the landmarks.
- **render_markers** – If `True`, the markers of the landmarks will be rendered.
- **marker_style** – The style of the markers of the landmarks. Example options

```
{., ,, o, v, ^, <, >, +, x, D, d, s, p, *, h, H, 1, 2, 3, 4, 8}
```

- **marker_size** – The size of the markers of the landmarks in points.
- **marker_face_colour** – The face (filling) colour of the markers of the landmarks. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **marker_edge_colour** – The edge colour of the markers of the landmarks. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **marker_edge_width** – The width of the markers' edge of the landmarks.
- **render_numbering** (*bool*, optional) – If `True`, the landmarks will be numbered.

- **numbers_horizontal_align** (`{center, right, left}`, optional) – The horizontal alignment of the numbers' texts.
- **numbers_vertical_align** (`{center, top, bottom, baseline}`, optional) – The vertical alignment of the numbers' texts.
- **numbers_font_name** (*See Below, optional*) – The font of the numbers. Example options

```
{serif, sans-serif, cursive, fantasy, monospace}
```

- **numbers_font_size** (*int*, optional) – The font size of the numbers.
- **numbers_font_style** (`{normal, italic, oblique}`, optional) – The font style of the numbers.
- **numbers_font_weight** (*See Below, optional*) – The font weight of the numbers. Example options

```
{ultralight, light, normal, regular, book, medium, roman,
semibold, demibold, demi, bold, heavy, extra bold, black}
```

- **numbers_font_colour** (*See Below, optional*) – The font colour of the numbers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **render_legend** (*bool*, optional) – If `True`, the legend will be rendered.
- **legend_title** (*str*, optional) – The title of the legend.
- **legend_font_name** (*See below, optional*) – The font of the legend. Example options

```
{serif, sans-serif, cursive, fantasy, monospace}
```

- **legend_font_style** (`{normal, italic, oblique}`, optional) – The font style of the legend.
- **legend_font_size** (*int*, optional) – The font size of the legend.
- **legend_font_weight** (*See Below, optional*) – The font weight of the legend. Example options

```
{ultralight, light, normal, regular, book, medium, roman,
semibold, demibold, demi, bold, heavy, extra bold, black}
```

- **legend_marker_scale** (*float*, optional) – The relative size of the legend markers with respect to the original
- **legend_location** (*int*, optional) – The location of the legend. The predefined values are:

'best'	0
'upper right'	1
'upper left'	2
'lower left'	3
'lower right'	4
'right'	5
'center left'	6
'center right'	7
'lower center'	8
'upper center'	9
'center'	10

- **legend_bbox_to_anchor** ((*float*, *float*) *tuple*, optional) – The bbox that the legend will be anchored.
- **legend_border_axes_pad** (*float*, optional) – The pad between the axes and legend border.
- **legend_n_columns** (*int*, optional) – The number of the legend's columns.
- **legend_horizontal_spacing** (*float*, optional) – The spacing between the columns.
- **legend_vertical_spacing** (*float*, optional) – The vertical space between the legend entries.
- **legend_border** (*bool*, optional) – If `True`, a frame will be drawn around the legend.
- **legend_border_padding** (*float*, optional) – The fractional whitespace inside the legend border.
- **legend_shadow** (*bool*, optional) – If `True`, a shadow will be drawn behind legend.
- **legend_rounded_corners** (*bool*, optional) – If `True`, the frame's corners will be rounded (fancybox).
- **render_axes** (*bool*, optional) – If `True`, the axes will be rendered.
- **axes_font_name** (*See Below, optional*) – The font of the axes. Example options

```
{serif, sans-serif, cursive, fantasy, monospace}
```

- **axes_font_size** (*int*, optional) – The font size of the axes.
- **axes_font_style** (`{normal, italic, oblique}`, optional) – The font style of the axes.
- **axes_font_weight** (*See Below, optional*) – The font weight of the axes. Example options

```
{ultralight, light, normal, regular, book, medium, roman,
semibold,demibold, demi, bold, heavy, extra bold, black}
```

- **axes_x_limits** (*float* or (*float*, *float*) or `None`, optional) – The limits of the x axis. If *float*, then it sets padding on the right and left of the PointCloud as a percentage of the PointCloud's width. If *tuple* or *list*, then it defines the axis limits. If `None`, then the limits are set automatically.
- **axes_y_limits** ((*float*, *float*) *tuple* or `None`, optional) – The limits of the y axis. If *float*, then it sets padding on the top and bottom of the PointCloud as a percentage of the

PointCloud's height. If *tuple* or *list*, then it defines the axis limits. If `None`, then the limits are set automatically.

- **axes_x_ticks** (*list* or *tuple* or `None`, optional) – The ticks of the x axis.
- **axes_y_ticks** (*list* or *tuple* or `None`, optional) – The ticks of the y axis.
- **figure_size** ((*float*, *float*) *tuple* or `None` optional) – The size of the figure in inches.

Raises

- `ValueError` – If both `with_labels` and `without_labels` are passed.
- `ValueError` – If the landmark manager doesn't contain the provided group label.

add_label(*label*, *indices*)

Add a new label by creating a new mask over the points. A new `LabelledPointUndirectedGraph` is returned.

Parameters

- **label** (*string*) – Label of landmark.
- **indices** (`(K,)` *ndarray*) – Array of indices in to the points. Each index implies membership to the label.

Returnslabelled_pointgraph (`LabelledPointUndirectedGraph`) – A new labelled pointgraph with the new label specified by indices.

as_vector(***kwargs*)

Returns a flattened representation of the object as a single vector.

Returnsvector (*(N,) ndarray*) – The core representation of the object, flattened into a single vector. Note that this is always a view back on to the original object, but is not writable.

bounding_box()

Return a bounding box from two corner points as a directed graph. In the case of a 2D pointcloud, first point (0) should be nearest the origin. In the case of an image, this ordering would appear as:

```
0<--3
|   ^
|   |
v   |
1-->2
```

In the case of a pointcloud, the ordering will appear as:

```
3<--2
|   ^
|   |
v   |
0-->1
```

In the case of a 3D pointcloud, the first point (0) should be the near closest to the origin and the second point is the far opposite corner.

Returnsbounding_box (`PointDirectedGraph`) – The axis aligned bounding box of the PointCloud.

bounds(*boundary=0*)

The minimum to maximum extent of the PointCloud. An optional boundary argument can be provided to expand the bounds by a constant margin.

Parameters`boundary` (*float*) – A optional padding distance that is added to the bounds. Default is `0`, meaning the max/min of tightest possible containing square/cube/hypercube is returned.

Returns

- **min_b** (`(n_dims,)` *ndarray*) – The minimum extent of the `PointCloud` and boundary along each dimension
- **max_b** (`(n_dims,)` *ndarray*) – The maximum extent of the `PointCloud` and boundary along each dimension

centre()

The mean of all the points in this PointCloud (centre of mass).

Returnscentre (`(n_dims)` *ndarray*) – The mean of this PointCloud's points.

centre_of_bounds()

The centre of the absolute bounds of this PointCloud. Contrast with `centre()`, which is the mean point position.

Returnscentre (`n_dims` *ndarray*) – The centre of the bounds of this PointCloud.

constrain_to_bounds(*bounds*)

Returns a copy of this PointCloud, constrained to lie exactly within the given bounds. Any points outside the bounds will be 'snapped' to lie *exactly* on the boundary.

Parameters`bounds` (`(n_dims, n_dims)` tuple of scalars) – The bounds to constrain this pointcloud within.

Returnsconstrained (`PointCloud`) – The constrained pointcloud.

copy()

Generate an efficient copy of this `LabelledPointUndirectedGraph`.

Returns`type(self)` – A copy of this object

distance_to(*pointcloud*, ***kwargs*)

Returns a distance matrix between this PointCloud and another. By default the Euclidean distance is calculated - see *scipy.spatial.distance.cdist* for valid kwargs to change the metric and other properties.

Parameters`pointcloud` (`PointCloud`) – The second pointcloud to compute distances between. This must be of the same dimension as this PointCloud.

Returnsdistance_matrix (`(n_points, n_points)` *ndarray*) – The symmetric pairwise distance matrix between the two PointClouds s.t. `distance_matrix[i, j]` is the distance between the i'th point of this PointCloud and the j'th point of the input PointCloud.

find_all_paths(*start*, *end*, *path=[]*)

Returns a list of lists with all the paths (without cycles) found from start vertex to end vertex.

Parameters

- **start** (*int*) – The vertex from which the paths start.
- **end** (*int*) – The vertex from which the paths end.
- **path** (*list*, optional) – An existing path to append to.

Returnspaths (*list* of *list*) – The list containing all the paths from start to end.

find_all_shortest_paths(*algorithm='auto'*, *unweighted=False*)

Returns the distances and predecessors arrays of the graph's shortest paths.

Parameters

- **algorithm** (*'str', see below, optional*) – The algorithm to be used. Possible options are:

'dijkstra'	Dijkstra's algorithm with Fibonacci heaps
'bellman-ford'	Bellman-Ford algorithm
'johnson'	Johnson's algorithm
'floyd-warshall'	Floyd-Warshall algorithm
'auto'	Select the best among the above

- **unweighted** (*bool*, optional) – If `True`, then find unweighted distances. That is, rather than finding the path between each vertex such that the sum of weights is minimized, find the path such that the number of edges is minimized.

Returns

- **distances** (`(n_vertices, n_vertices,)` *ndarray*) – The matrix of distances between all graph vertices. `distances[i,j]` gives the shortest distance from vertex `i` to vertex `j` along the graph.
- **predecessors** (`(n_vertices, n_vertices,)` *ndarray*) – The matrix of predecessors, which can be used to reconstruct the shortest paths. Each entry `predecessors[i, j]` gives the index of the previous vertex in the path from vertex `i` to vertex `j`. If no path exists between vertices `i` and `j`, then `predecessors[i, j] = -9999`.

find_path(*start*, *end*, *method='bfs'*, *skip_checks=False*)

Returns a *list* with the first path (without cycles) found from the `start` vertex to the `end` vertex. It can employ either depth-first search or breadth-first search.

Parameters

- **start** (*int*) – The vertex from which the path starts.
- **end** (*int*) – The vertex to which the path ends.
- **method** (`{bfs, dfs}`, optional) – The method to be used.
- **skip_checks** (*bool*, optional) – If `True`, then input arguments won't pass through checks. Useful for efficiency.

Returnspath (*list*) – The path's vertices.

Raises`ValueError` – Method must be either bfs or dfs.

find_shortest_path(*start*, *end*, *algorithm='auto'*, *unweighted=False*, *skip_checks=False*)

Returns a *list* with the shortest path (without cycles) found from `start` vertex to `end` vertex.

Parameters

- **start** (*int*) – The vertex from which the path starts.
- **end** (*int*) – The vertex to which the path ends.
- **algorithm** (*'str', see below, optional*) – The algorithm to be used. Possible options are:

'dijkstra'	Dijkstra's algorithm with Fibonacci heaps
'bellman-ford'	Bellman-Ford algorithm
'johnson'	Johnson's algorithm
'floyd-warshall'	Floyd-Warshall algorithm
'auto'	Select the best among the above

- **unweighted** (*bool*, optional) – If `True`, then find unweighted distances. That is, rather than finding the path such that the sum of weights is minimized, find the path such that the number of edges is minimized.

- **skip_checks** (*bool*, optional) – If `True`, then input arguments won't pass through checks. Useful for efficiency.

Returns

- **path** (*list*) – The shortest path's vertices, including `start` and `end`. If there was not path connecting the vertices, then an empty *list* is returned.
- **distance** (*int* or *float*) – The distance (cost) of the path from `start` to `end`.

from_mask(*mask*)

A 1D boolean array with the same number of elements as the number of points in the *PointUndirectedGraph*. This is then broadcast across the dimensions of the *PointUndirectedGraph* and returns a new *PointUndirectedGraph* containing only those points that were `True` in the mask.

Parameters **mask** (`(n_vertices,)` *ndarray*) – 1D array of booleans

Returns **pointgraph** (`PointUndirectedGraph`) – A new pointgraph that has been masked.

Raises `ValueError` – Mask must be a 1D boolean array of the same number of entries as points in this PointUndirectedGraph.

from_vector(*vector*)

Build a new instance of the object from it's vectorized state.

`self` is used to fill out the missing state required to rebuild a full object from it's standardized flattened state. This is the default implementation, which is which is a `deepcopy` of the object followed by a call to `from_vector_inplace()`. This method can be overridden for a performance benefit if desired.

Parameters **vector** (`(n_parameters,)` *ndarray*) – Flattened representation of the object.

Returns **object** (`type(self)`) – An new instance of this class.

from_vector_inplace(*vector*)

Deprecated. Use the non-mutating API, `from_vector`.

For internal usage in performance-sensitive spots, see *_from_vector_inplace()*

Parameters **vector** (`(n_parameters,)` *ndarray*) – Flattened representation of this object

get_adjacency_list()

Returns the adjacency list of the graph, i.e. a *list* of length `n_vertices` that for each vertex has a *list* of the vertex neighbours. If the graph is directed, the neighbours are children.

Returns **adjacency_list** (*list* of *list* of length `n_vertices`) – The adjacency list of the graph.

get_label(*label*)

Returns a new `PointUndirectedGraph` that contains the subset of points that this label represents.

Parameters **label** (*string*) – Label to filter on.

Returns **graph** (`PointUndirectedGraph`) – The PointUndirectedGraph containing the subset of points that this label masks. Will be a subset of the entire group's points.

h_points()

Convert poincloud to a homogeneous array: `(n_dims + 1, n_points)`

Type `type(self)`

has_cycles()

Checks if the graph has at least one cycle.

Returns **has_cycles** (*bool*) – `True` if the graph has cycles.

has_isolated_vertices()

Whether the graph has any isolated vertices, i.e. vertices with no edge connections.

Returnshas_isolated_vertices (*bool*) – `True` if the graph has at least one isolated vertex.

has_nan_values()

Tests if the vectorized form of the object contains `nan` values or not. This is particularly useful for objects with unknown values that have been mapped to `nan` values.

Returnshas_nan_values (*bool*) – If the vectorized object contains `nan` values.

init_2d_grid(*shape*, *spacing=None*, *adjacency_matrix=None*, *skip_checks=False*)

Create a PointGraph that exists on a regular 2D grid. The first dimension is the number of rows in the grid and the second dimension of the shape is the number of columns. `spacing` optionally allows the definition of the distance between points (uniform over points). The spacing may be different for rows and columns.

If no adjacency matrix is provided, the default connectivity will be a 4-connected lattice.

Parameters

- **shape** (*tuple* of 2 *int*) – The size of the grid to create, this defines the number of points across each dimension in the grid. The first element is the number of rows and the second is the number of columns.
- **spacing** (*int* or *tuple* of 2 *int*, optional) – The spacing between points. If a single *int* is provided, this is applied uniformly across each dimension. If a *tuple* is provided, the spacing is applied non-uniformly as defined e.g. `(2, 3)` gives a spacing of 2 for the rows and 3 for the columns.
- **adjacency_matrix** (`(n_vertices, n_vertices)` *ndarray* or *csr_matrix*, optional) – The adjacency matrix of the graph in which the rows represent source vertices and columns represent destination vertices. The non-edges must be represented with zeros and the edges can have a weight value.

  The adjacency matrix of an undirected graph must be symmetric.
- **skip_checks** (*bool*, optional) – If `True`, no checks will be performed. Only considered if no adjacency matrix is provided.

Returnsspgraph (*PointGraph*) – A pointgraph arranged in a grid.

init_from_depth_image(*depth_image*, *spacing=None*, *adjacency_matrix=None*, *skip_checks=False*)

Return a 3D point graph from the given depth image. The depth image is assumed to represent height/depth values and the XY coordinates are assumed to unit spaced and represent image coordinates. This is particularly useful for visualising depth values that have been recovered from images.

If no adjacency matrix is provided, the default connectivity will be a 4-connected lattice.

Parameters

- **depth_image** (`Image` or subclass) – A single channel image that contains depth values - as commonly returned by RGBD cameras, for example.
- **spacing** (*int* or *tuple* of 2 *int*, optional) – The spacing between points. If a single *int* is provided, this is applied uniformly across each dimension. If a *tuple* is provided, the spacing is applied non-uniformly as defined e.g. `(2, 3)` gives a spacing of 2 for the rows and 3 for the columns.
- **adjacency_matrix** (`(n_vertices, n_vertices)` *ndarray* or *csr_matrix*, optional) – The adjacency matrix of the graph in which the rows represent source vertices and columns represent destination vertices. The non-edges must be represented with zeros and the edges can have a weight value.

  The adjacency matrix of an undirected graph must be symmetric.

- **skip_checks** (*bool*, optional) – If `True`, no checks will be performed. Only considered if no adjacency matrix is provided.

Returnsdepth_cloud (`type(cls)`) – A new 3D PointGraph with unit XY coordinates and the given depth values as Z coordinates.

classmethod init_from_edges(*points*, *edges*, *labels_to_masks*, *copy=True*, *skip_checks=False*)

Construct a `LabelledPointUndirectedGraph` from an edges array.

See `PointUndirectedGraph` for more information.

Parameters

- **points** (`(n_vertices, n_dims, )` *ndarray*) – The array of point locations.
- **edges** (`(n_edges, 2, )` *ndarray* or `None`) – The *ndarray* of edges, i.e. all the pairs of vertices that are connected with an edge. If `None`, then an empty adjacency matrix is created.
- **labels_to_masks** (*ordereddict {str -> bool ndarray}*) – For each label, the mask that specifies the indices in to the points that belong to the label.
- **copy** (*bool*, optional) – If `False`, the *adjacency_matrix* will not be copied on assignment.
- **skip_checks** (*bool*, optional) – If `True`, no checks will be performed.

classmethod init_from_indices_mapping(*points*, *adjacency*, *labels_to_indices*, *copy=True*)

Static constructor to create a `LabelledPointUndirectedGraph` from an ordered dictionary that maps a set of indices .

Parameters

- **points** (`PointCloud`) – The points representing the landmarks.
- **adjacency** (`(n_vertices, n_vertices, )` *ndarray*, *csr_matrix* or *list* of edges) – The adjacency matrix of the graph, or a list of edges representing adjacency.
- **labels_to_indices** (*ordereddict* {*str -> int ndarray*}) – For each label, the indices in to the points that belong to the label.
- **copy** (*boolean*, optional) – If `True`, a copy of the data is stored on the group.

Returnslabelled_pointgraph (`LabelledPointUndirectedGraph`) – Labelled point undirected graph wrapping the given points with the given semantic labels applied.

Raises

- `ValueError` – If *dict* passed instead of *OrderedDict*
- `ValueError` – If any of the label masks differs in size to the points.
- `ValueError` – If there exists any point in the points that is not covered by a label.

classmethod init_with_all_label(*points*, *adjacency_matrix*, *copy=True*)

Static constructor to create a `LabelledPointUndirectedGraph` with a single default 'all' label that covers all points.

Parameters

- **points** (*ndarray*) – The points representing the landmarks.
- **adjacency_matrix** (`(n_vertices, n_vertices, )` *ndarray* or *csr_matrix*) – The adjacency matrix of the graph. The non-edges must be represented with zeros and the edges can have a weight value.

Note`adjacency_matrix` must be symmetric.

- **copy** (*bool*, optional) – If `True`, a copy of data is stored on the group.

Returnslabelled_pointgraph (*LabelledPointUndirectedGraph*) – Labelled pointgraph wrapping the given points with a single label called 'all' that is `True` for all points.

is_edge(*vertex_1*, *vertex_2*, *skip_checks=False*)

Whether there is an edge between the provided vertices.

Parameters

- **vertex_1** (*int*) – The first selected vertex. Parent if the graph is directed.
- **vertex_2** (*int*) – The second selected vertex. Child if the graph is directed.
- **skip_checks** (*bool*, optional) – If `False`, the given vertices will be checked.

Returnsis_edge (*bool*) – `True` if there is an edge connecting `vertex_1` and `vertex_2`.

Raises`ValueError` – The vertex must be between 0 and {n_vertices-1}.

is_tree()

Checks if the graph is tree.

Returnsis_true (*bool*) – If the graph is a tree.

isolated_vertices()

Returns the isolated vertices of the graph (if any), i.e. the vertices that have no edge connections.

Returnsisolated_vertices (*list*) – A *list* of the isolated vertices. If there aren't any, it returns an empty *list*.

minimum_spanning_tree(*root_vertex*)

Returns the minimum spanning tree of the graph using Kruskal's algorithm.

Parametersroot_vertex (*int*) – The vertex that will be set as root in the output MST.

Returnsmst (*PointTree*) – The computed minimum spanning tree with the *points* of *self*.

Raises`ValueError` – Cannot compute minimum spanning tree of a graph with isolated vertices

n_neighbours(*vertex*, *skip_checks=False*)

Returns the number of neighbours of the selected vertex.

Parameters

- **vertex** (*int*) – The selected vertex.
- **skip_checks** (*bool*, optional) – If `False`, the given vertex will be checked.

Returnsn_neighbours (*int*) – The number of neighbours.

Raises`ValueError` – The vertex must be between 0 and {n_vertices-1}.

n_paths(*start*, *end*)

Returns the number of all the paths (without cycles) existing from start vertex to end vertex.

Parameters

- **start** (*int*) – The vertex from which the paths start.
- **end** (*int*) – The vertex from which the paths end.

Returnspaths (*int*) – The paths' numbers.

neighbours(*vertex*, *skip_checks=False*)

Returns the neighbours of the selected vertex.

Parameters

- **vertex** (*int*) – The selected vertex.
- **skip_checks** (*bool*, optional) – If `False`, the given vertex will be checked.

Returnsneighbours (*list*) – The list of neighbours.

Raises`ValueError` – The vertex must be between 0 and {n_vertices-1}.

norm(***kwargs*)

Returns the norm of this PointCloud. This is a translation and rotation invariant measure of the point cloud's intrinsic size - in other words, it is always taken around the point cloud's centre.

By default, the Frobenius norm is taken, but this can be changed by setting kwargs - see `numpy.linalg.norm` for valid options.

Returnsnorm (*float*) – The norm of this `PointCloud`

range(*boundary=0*)

The range of the extent of the PointCloud.

Parametersboundary (*float*) – A optional padding distance that is used to extend the bounds from which the range is computed. Default is `0`, no extension is performed.

Returnsrange (`(n_dims,)` *ndarray*) – The range of the `PointCloud` extent in each dimension.

remove_label(*label*)

Returns a new `LabelledPointUndirectedGraph` that does not contain the given label.

Note: You cannot delete a semantic label and leave the labelled point graph partially unlabelled. Labelled point graphs must contain labels for **every point**.

Parameterslabel (*string*) – The label to remove.

Raises`ValueError` – If deleting the label would leave some points unlabelled.

tojson()

Convert this *LabelledPointUndirectedGraph* to a dictionary JSON representation.

Returnsjson (`dict`) – Dictionary conforming to the LJSON v2 specification.

with_dims(*dims*)

Return a copy of this shape with only particular dimensions retained.

Parametersdims (`valid numpy array slice`) – The slice that will be used on the dimensionality axis of the shape under transform. For example, to go from a 3D shape to a 2D one, [0, 1] could be provided or np.array([True, True, False]).

Returns*copy of self, with only the requested dims*

with_labels(*labels*)

A new labelled point undirected graph that contains only the given labels.

Parameterslabels (*str* or *list* of *str*) – Label(s) that should be kept in the returned labelled point graph.

Returnslabelled_pointgraph (`LabelledPointUndirectedGraph`) – A new labelled point undirected graph with the same group label but containing only the given label(s).

without_labels(*labels*)

A new labelled point undirected graph that excludes certain labels.

Parameters **labels** (*str* or *list* of *str*) – Label(s) that should be excluded in the returned labelled point graph.

Returns **labelled_pointgraph** (*LabelledPointUndirectedGraph*) – A new labelled point undirected graph with the same group label but containing all labels except the given label.

has_landmarks

Whether the object has landmarks.

Type *bool*

labels

The list of labels that belong to this group.

Type *list* of *str*

landmarks

The landmarks object.

Type *LandmarkManager*

lms

Deprecated. Maintained for compatibility, will be removed in a future version. Returns a copy of this object, which previously would have held the 'underlying' *PointCloud* subclass.

Type self

n_dims

The number of dimensions in the pointcloud.

Type *int*

n_edges

Returns the number of edges.

Type *int*

n_labels

Number of labels in the group.

Type *int*

n_landmark_groups

The number of landmark groups on this object.

Type *int*

n_landmarks

The total number of points in the group.

Type *int*

n_parameters

The length of the vector that this object produces.

Type *int*

n_points

The number of points in the pointcloud.

Type *int*

n_vertices
Returns the number of vertices.

Type*int*

vertices
Returns the *list* of vertices.

Type*list*

Predefined Graphs

empty_graph

`menpo.shape.`**`empty_graph`**(*shape*, *return_pointgraph=True*)
Returns an empty graph given the landmarks configuration of a shape instance.

Parameters

- **shape** (`PointCloud` or subclass) – The shape instance that defines the landmarks configuration based on which the graph will be created.
- **return_pointgraph** (*bool*, optional) – If `True`, then a `PointUndirectedGraph` instance will be returned. If `False`, then an `UndirectedGraph` instance will be returned.

Returnsgraph (`UndirectedGraph` or `PointUndirectedGraph`) – The generated graph.

star_graph

`menpo.shape.`**`star_graph`**(*shape*, *root_vertex*, *graph_cls=<class 'menpo.shape.graph.PointTree'>*)
Returns a star graph given the landmarks configuration of a shape instance.

Parameters

- **shape** (`PointCloud` or subclass) – The shape instance that defines the landmarks configuration based on which the graph will be created.
- **root_vertex** (*int*) – The root of the star tree.
- **graph_cls** (*Graph* or *PointGraph* subclass) – The output graph type. Possible options are

```
{:map:`UndirectedGraph`, :map:`DirectedGraph`, :map:`Tree`,
 :map:`PointUndirectedGraph`, :map:`PointDirectedGraph`,
 :map:`PointTree`}
```

Returnsgraph (*Graph* or *PointGraph* subclass) – The generated graph.

Raises`ValueError` – graph_cls must be UndirectedGraph, DirectedGraph, Tree, PointUndirectedGraph, PointDirectedGraph or PointTree.

complete_graph

`menpo.shape.`**`complete_graph`**(*shape*, *graph_cls=<class 'menpo.shape.graph.PointUndirectedGraph'>*)
Returns a complete graph given the landmarks configuration of a shape instance.

Parameters

- **shape** (*PointCloud* or subclass) – The shape instance that defines the landmarks configuration based on which the graph will be created.
- **graph_cls** (*Graph* or *PointGraph* subclass) – The output graph type. Possible options are

```
{:map:`UndirectedGraph`, :map:`DirectedGraph`,
 :map:`PointUndirectedGraph`, :map:`PointDirectedGraph`}
```

Returns **graph** (*Graph* or *PointGraph* subclass) – The generated graph.

Raises `ValueError` – graph_cls must be UndirectedGraph, DirectedGraph, PointUndirectedGraph or PointDirectedGraph.

chain_graph

`menpo.shape.`**`chain_graph`**(*shape*, *graph_cls=<class 'menpo.shape.graph.PointDirectedGraph'>*, *closed=False*)

Returns a chain graph given the landmarks configuration of a shape instance.

Parameters

- **shape** (*PointCloud* or subclass) – The shape instance that defines the landmarks configuration based on which the graph will be created.
- **graph_cls** (*Graph* or *PointGraph* subclass) – The output graph type. Possible options are

```
{:map:`UndirectedGraph`, :map:`DirectedGraph`, :map:`Tree`,
 :map:`PointUndirectedGraph`, :map:`PointDirectedGraph`,
 :map:`PointTree`}
```

- **closed** (*bool*, optional) – If `True`, then the chain will be closed (i.e. edge between the first and last vertices).

Returns **graph** (*Graph* or *PointGraph* subclass) – The generated graph.

Raises

- `ValueError` – A closed chain graph cannot be a Tree or PointTree instance.
- `ValueError` – graph_cls must be UndirectedGraph, DirectedGraph, Tree, PointUndirectedGraph, PointDirectedGraph or PointTree.

delaunay_graph

`menpo.shape.`**`delaunay_graph`**(*shape*, *return_pointgraph=True*)

Returns a graph with the edges being generated by Delaunay triangulation.

Parameters

- **shape** (*PointCloud* or subclass) – The shape instance that defines the landmarks configuration based on which the graph will be created.
- **return_pointgraph** (*bool*, optional) – If `True`, then a *PointUndirectedGraph* instance will be returned. If `False`, then an *UndirectedGraph* instance will be returned.

Returns **graph** (*UndirectedGraph* or *PointUndirectedGraph*) – The generated graph.

stencil_grid

`menpo.shape.stencil_grid(stencil, shape, dtype=None, format=None)`

Construct a sparse matrix form a local matrix stencil

This function is useful for building sparse adjacency matrices according to a specific connectivity pattern.

This function is borrowed from the PyAMG project, under the permission of the MIT license:

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The original version of this file can be found here:

https://github.com/pyamg/pyamg/blob/621d63411895898660e5ea078840118905bec061/pyamg/gallery/stencil.py

This file has been modified to fit the style standards of the Menpo project.

Parameters

- **S** (*ndarray*) – Matrix stencil stored in N-d array
- **grid** (*tuple*) – Tuple containing the N shape dimensions (shape)
- **dtype** (*np.dtype*, optional) – Numpy data type of the result
- **format** (*str*, optional) – Sparse matrix format to return, e.g. "csr", "coo", etc.

ReturnsA (*sparse matrix*) – Sparse matrix which represents the operator given by applying stencil stencil at each vertex of a regular shape with given dimensions.

Notes

The shape vertices are enumerated as `arange(prod(shape)).reshape(shape)`. This implies that the last shape dimension cycles fastest, while the first dimension cycles slowest. For example, if `shape=(2,3)` then the shape vertices are ordered as `(0,0), (0,1), (0,2), (1,0), (1,1), (1,2)`.

This coincides with the ordering used by the NumPy functions `ndenumerate()` and `mgrid()`.

Raises

- `ValueError` – If the stencil shape is not odd.
- `ValueError` – If the stencil dimension does not equal the number of shape dimensions
- `ValueError` – If the shape dimensions are not all positive

Examples

```
>>> import numpy as np
>>> from menpo.shape import stencil_grid
>>> stencil = [[0,-1,0],[-1,4,-1],[0,-1,0]]  # 2D Poisson stencil
>>> shape = (3, 3)                           # 2D shape with shape 3x3
>>> A = stencil_grid(stencil, shape, dtype=np.float, format='csr')
>>> A.todense()
matrix([[ 4., -1.,  0., -1.,  0.,  0.,  0.,  0.,  0.],
        [-1.,  4., -1.,  0., -1.,  0.,  0.,  0.,  0.],
        [ 0., -1.,  4.,  0.,  0., -1.,  0.,  0.,  0.],
        [-1.,  0.,  0.,  4., -1.,  0., -1.,  0.,  0.],
        [ 0., -1.,  0., -1.,  4., -1.,  0., -1.,  0.],
        [ 0.,  0., -1.,  0., -1.,  4.,  0.,  0., -1.],
        [ 0.,  0.,  0., -1.,  0.,  0.,  4., -1.,  0.],
        [ 0.,  0.,  0.,  0., -1.,  0., -1.,  4., -1.],
        [ 0.,  0.,  0.,  0.,  0., -1.,  0., -1.,  4.]])
```

```
>>> stencil = [[0,1,0],[1,0,1],[0,1,0]]  # 2D Lattice Connectivity
>>> shape = (3, 3)                       # 2D shape with shape 3x3
>>> A = stencil_grid(stencil, shape, dtype=np.float, format='csr')
>>> A.todense()
matrix([[ 0.,  1.,  0.,  1.,  0.,  0.,  0.,  0.,  0.],
        [ 1.,  0.,  1.,  0.,  1.,  0.,  0.,  0.,  0.],
        [ 0.,  1.,  0.,  0.,  0.,  1.,  0.,  0.,  0.],
        [ 1.,  0.,  0.,  0.,  1.,  0.,  1.,  0.,  0.],
        [ 0.,  1.,  0.,  1.,  0.,  1.,  0.,  1.,  0.],
        [ 0.,  0.,  1.,  0.,  1.,  0.,  0.,  0.,  1.],
        [ 0.,  0.,  0.,  1.,  0.,  0.,  0.,  1.,  0.],
        [ 0.,  0.,  0.,  0.,  1.,  0.,  1.,  0.,  1.],
        [ 0.,  0.,  0.,  0.,  0.,  1.,  0.,  1.,  0.]])
```

Triangular Meshes

TriMesh

class `menpo.shape.`**`TriMesh`**(*points*, *trilist=None*, *copy=True*)

Bases: `PointCloud`

A *`PointCloud`* with a connectivity defined by a triangle list. These are designed to be explicitly 2D or 3D.

Parameters

- **`points`** (`(n_points, n_dims)` *ndarray*) – The array representing the points.
- **`trilist`** (`(M, 3)` *ndarray* or `None`, optional) – The triangle list. If *None*, a Delaunay triangulation of the points will be used instead.
- **`copy`** (*bool*, optional) – If `False`, the points will not be copied on assignment. Any trilist will also not be copied. In general this should only be used if you know what you are doing.

_view_2d(*figure_id=None*, *new_figure=False*, *image_view=True*, *render_lines=True*, *line_colour='r'*, *line_style='-'*, *line_width=1.0*, *render_markers=True*, *marker_style='o'*, *marker_size=5*, *marker_face_colour='k'*, *marker_edge_colour='k'*, *marker_edge_width=1.0*, *render_numbering=False*, *numbers_horizontal_align='center'*, *numbers_vertical_align='bottom'*, *numbers_font_name='sans-serif'*, *numbers_font_size=10*, *numbers_font_style='normal'*, *numbers_font_weight='normal'*, *numbers_font_colour='k'*, *render_axes=True*, *axes_font_name='sans-serif'*, *axes_font_size=10*, *axes_font_style='normal'*, *axes_font_weight='normal'*, *axes_x_limits=None*, *axes_y_limits=None*, *axes_x_ticks=None*, *axes_y_ticks=None*, *figure_size=(7, 7)*, *label=None*, ***kwargs*)

Visualization of the TriMesh in 2D.

Returns

- **figure_id** (*object*, optional) – The id of the figure to be used.
- **new_figure** (*bool*, optional) – If `True`, a new figure is created.
- **image_view** (*bool*, optional) – If `True` the TriMesh will be viewed as if it is in the image coordinate system.
- **render_lines** (*bool*, optional) – If `True`, the edges will be rendered.
- **line_colour** (*See Below, optional*) – The colour of the lines. Example options:

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **line_style** (`{-, --, -., :}`, optional) – The style of the lines.
- **line_width** (*float*, optional) – The width of the lines.
- **render_markers** (*bool*, optional) – If `True`, the markers will be rendered.
- **marker_style** (*See Below, optional*) –

  The style of the markers. Example options

```
{., ,, o, v, ^, <, >, +, x, D, d, s, p, *, h, H, 1, 2, 3, 4, 8}
```

- **marker_size** (*int*, optional) – The size of the markers in points.
- **marker_face_colour** (*See Below, optional*) – The face (filling) colour of the markers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **marker_edge_colour** (*See Below, optional*) – The edge colour of the markers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **marker_edge_width** (*float*, optional) – The width of the markers' edge.
- **render_numbering** (*bool*, optional) – If `True`, the landmarks will be numbered.

•**numbers_horizontal_align** (`{center, right, left}`, optional) – The horizontal alignment of the numbers' texts.

•**numbers_vertical_align** (`{center, top, bottom, baseline}`, optional) – The vertical alignment of the numbers' texts.

•**numbers_font_name** (*See Below, optional*) –

The font of the numbers. Example options

```
{serif, sans-serif, cursive, fantasy, monospace}
```

•**numbers_font_size** (*int*, optional) – The font size of the numbers.

•**numbers_font_style** (`{normal, italic, oblique}`, optional) – The font style of the numbers.

•**numbers_font_weight** (*See Below, optional*) – The font weight of the numbers. Example options

```
{ultralight, light, normal, regular, book, medium, roman,
semibold, demibold, demi, bold, heavy, extra bold, black}
```

•**numbers_font_colour** (*See Below, optional*) – The font colour of the numbers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

•**render_axes** (*bool*, optional) – If `True`, the axes will be rendered.

•**axes_font_name** (*See Below, optional*) – The font of the axes. Example options

```
{serif, sans-serif, cursive, fantasy, monospace}
```

•**axes_font_size** (*int*, optional) – The font size of the axes.

•**axes_font_style** ({`normal`, `italic`, `oblique`}, optional) – The font style of the axes.

•**axes_font_weight** (*See Below, optional*) – The font weight of the axes. Example options

```
{ultralight, light, normal, regular, book, medium, roman,
semibold, demibold, demi, bold, heavy, extra bold, black}
```

•**axes_x_limits** (*float* or (*float*, *float*) or `None`, optional) – The limits of the x axis. If *float*, then it sets padding on the right and left of the TriMesh as a percentage of the TriMesh's width. If *tuple* or *list*, then it defines the axis limits. If `None`, then the limits are set automatically.

•**axes_y_limits** ((*float*, *float*) *tuple* or `None`, optional) – The limits of the y axis. If *float*, then it sets padding on the top and bottom of the TriMesh as a percentage of the TriMesh's height. If *tuple* or *list*, then it defines the axis limits. If `None`, then the limits are set automatically.

•**axes_x_ticks** (*list* or *tuple* or `None`, optional) – The ticks of the x axis.

•**axes_y_ticks** (*list* or *tuple* or `None`, optional) – The ticks of the y axis.

•**figure_size** ((*float*, *float*) *tuple* or `None`, optional) – The size of the figure in inches.

•**label** (*str*, optional) – The name entry in case of a legend.

Returns **viewer** (`PointGraphViewer2d`) – The viewer object.

_view_landmarks_2d(*group=None*, *with_labels=None*, *without_labels=None*, *figure_id=None*, *new_figure=False*, *image_view=True*, *render_lines=True*, *line_colour='k'*, *line_style='-'*, *line_width=2*, *render_markers=True*, *marker_style='s'*, *marker_size=7*, *marker_face_colour='k'*, *marker_edge_colour='k'*, *marker_edge_width=1.0*, *render_lines_lms=True*, *line_colour_lms=None*, *line_style_lms='-'*, *line_width_lms=1*, *render_markers_lms=True*, *marker_style_lms='o'*, *marker_size_lms=5*, *marker_face_colour_lms=None*, *marker_edge_colour_lms=None*, *marker_edge_width_lms=1.0*, *render_numbering=False*, *numbers_horizontal_align='center'*, *numbers_vertical_align='bottom'*, *numbers_font_name='sans-serif'*, *numbers_font_size=10*, *numbers_font_style='normal'*, *numbers_font_weight='normal'*, *numbers_font_colour='k'*, *render_legend=False*, *legend_title=''*, *legend_font_name='sans-serif'*, *legend_font_style='normal'*, *legend_font_size=10*, *legend_font_weight='normal'*, *legend_marker_scale=None*, *legend_location=2*, *legend_bbox_to_anchor=(1.05, 1.0)*, *legend_border_axes_pad=None*, *legend_n_columns=1*, *legend_horizontal_spacing=None*, *legend_vertical_spacing=None*, *legend_border=True*, *legend_border_padding=None*, *legend_shadow=False*, *legend_rounded_corners=False*, *render_axes=False*, *axes_font_name='sans-serif'*, *axes_font_size=10*, *axes_font_style='normal'*, *axes_font_weight='normal'*, *axes_x_limits=None*, *axes_y_limits=None*, *axes_x_ticks=None*, *axes_y_ticks=None*, *figure_size=(7, 7)*)

Visualize the landmarks. This method will appear on the *TriMesh* as `view_landmarks`.

Parameters

- **group** (*str* or''None'' optional) – The landmark group to be visualized. If `None` and there are more than one landmark groups, an error is raised.
- **with_labels** (`None` or *str* or *list* of *str*, optional) – If not `None`, only show the given label(s). Should **not** be used with the `without_labels` kwarg.
- **without_labels** (`None` or *str* or *list* of *str*, optional) – If not `None`, show all except the given label(s). Should **not** be used with the `with_labels` kwarg.
- **figure_id** (*object*, optional) – The id of the figure to be used.
- **new_figure** (*bool*, optional) – If `True`, a new figure is created.
- **image_view** (*bool*, optional) – If `True` the PointCloud will be viewed as if it is in the image coordinate system.
- **render_lines** (*bool*, optional) – If `True`, the edges will be rendered.
- **line_colour** (*See Below, optional*) – The colour of the lines. Example options:

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **line_style** (`{-, --, -., :}`, optional) – The style of the lines.
- **line_width** (*float*, optional) – The width of the lines.
- **render_markers** (*bool*, optional) – If `True`, the markers will be rendered.

- **marker_style** (*See Below, optional*) – The style of the markers. Example options

```
{., ,, o, v, ^, <, >, +, x, D, d, s, p, *, h, H, 1, 2, 3, 4, 8}
```

- **marker_size** (*int*, optional) – The size of the markers in points.
- **marker_face_colour** (*See Below, optional*) – The face (filling) colour of the markers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **marker_edge_colour** (*See Below, optional*) – The edge colour of the markers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **marker_edge_width** (*float*, optional) – The width of the markers' edge.
- **render_lines_lms** (*bool*, optional) – If `True`, the edges of the landmarks will be rendered.
- **line_colour_lms** (*See Below, optional*) – The colour of the lines of the landmarks. Example options:

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **line_style_lms** (`{-, --, -., :}`, optional) – The style of the lines of the landmarks.
- **line_width_lms** (*float*, optional) – The width of the lines of the landmarks.
- **render_markers** – If `True`, the markers of the landmarks will be rendered.
- **marker_style** – The style of the markers of the landmarks. Example options

```
{., ,, o, v, ^, <, >, +, x, D, d, s, p, *, h, H, 1, 2, 3, 4, 8}
```

- **marker_size** – The size of the markers of the landmarks in points.
- **marker_face_colour** – The face (filling) colour of the markers of the landmarks. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **marker_edge_colour** – The edge colour of the markers of the landmarks. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **marker_edge_width** – The width of the markers' edge of the landmarks.
- **render_numbering** (*bool*, optional) – If `True`, the landmarks will be numbered.
- **numbers_horizontal_align** (`{center, right, left}`, optional) – The horizontal alignment of the numbers' texts.
- **numbers_vertical_align** (`{center, top, bottom, baseline}`, optional) – The vertical alignment of the numbers' texts.
- **numbers_font_name** (*See Below, optional*) – The font of the numbers. Example options

```
{serif, sans-serif, cursive, fantasy, monospace}
```

- **numbers_font_size** (*int*, optional) – The font size of the numbers.
- **numbers_font_style** (`{normal, italic, oblique}`, optional) – The font style of the numbers.
- **numbers_font_weight** (*See Below, optional*) – The font weight of the numbers. Example options

```
{ultralight, light, normal, regular, book, medium, roman,
semibold, demibold, demi, bold, heavy, extra bold, black}
```

- **numbers_font_colour** (*See Below, optional*) – The font colour of the numbers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **render_legend** (*bool*, optional) – If `True`, the legend will be rendered.
- **legend_title** (*str*, optional) – The title of the legend.
- **legend_font_name** (*See below, optional*) – The font of the legend. Example options

```
{serif, sans-serif, cursive, fantasy, monospace}
```

- **legend_font_style** (`{normal, italic, oblique}`, optional) – The font style of the legend.
- **legend_font_size** (*int*, optional) – The font size of the legend.
- **legend_font_weight** (*See Below, optional*) – The font weight of the legend. Example options

```
{ultralight, light, normal, regular, book, medium, roman,
semibold, demibold, demi, bold, heavy, extra bold, black}
```

- **legend_marker_scale** (*float*, optional) – The relative size of the legend markers with respect to the original
- **legend_location** (*int*, optional) – The location of the legend. The predefined values are:

'best'	0
'upper right'	1
'upper left'	2
'lower left'	3
'lower right'	4
'right'	5
'center left'	6
'center right'	7
'lower center'	8
'upper center'	9
'center'	10

- **legend_bbox_to_anchor** ((*float*, *float*) *tuple*, optional) – The bbox that the legend will be anchored.
- **legend_border_axes_pad** (*float*, optional) – The pad between the axes and legend border.
- **legend_n_columns** (*int*, optional) – The number of the legend's columns.
- **legend_horizontal_spacing** (*float*, optional) – The spacing between the columns.
- **legend_vertical_spacing** (*float*, optional) – The vertical space between the legend entries.
- **legend_border** (*bool*, optional) – If `True`, a frame will be drawn around the legend.
- **legend_border_padding** (*float*, optional) – The fractional whitespace inside the legend border.
- **legend_shadow** (*bool*, optional) – If `True`, a shadow will be drawn behind legend.
- **legend_rounded_corners** (*bool*, optional) – If `True`, the frame's corners will be rounded (fancybox).
- **render_axes** (*bool*, optional) – If `True`, the axes will be rendered.
- **axes_font_name** (*See Below, optional*) – The font of the axes. Example options

```
{serif, sans-serif, cursive, fantasy, monospace}
```

- **axes_font_size** (*int*, optional) – The font size of the axes.
- **axes_font_style** (`{normal, italic, oblique}`, optional) – The font style of the axes.
- **axes_font_weight** (*See Below, optional*) – The font weight of the axes. Example options

```
{ultralight, light, normal, regular, book, medium, roman,
semibold,demibold, demi, bold, heavy, extra bold, black}
```

- **axes_x_limits** (*float* or (*float*, *float*) or `None`, optional) – The limits of the x axis. If *float*, then it sets padding on the right and left of the PointCloud as a percentage of the PointCloud's width. If *tuple* or *list*, then it defines the axis limits. If `None`, then the limits are set automatically.
- **axes_y_limits** ((*float*, *float*) *tuple* or `None`, optional) – The limits of the y axis. If *float*, then it sets padding on the top and bottom of the PointCloud as a percentage of the

PointCloud's height. If *tuple* or *list*, then it defines the axis limits. If `None`, then the limits are set automatically.

- **axes_x_ticks** (*list* or *tuple* or `None`, optional) – The ticks of the x axis.
- **axes_y_ticks** (*list* or *tuple* or `None`, optional) – The ticks of the y axis.
- **figure_size** ((*float*, *float*) *tuple* or `None` optional) – The size of the figure in inches.

Raises

- `ValueError` – If both `with_labels` and `without_labels` are passed.
- `ValueError` – If the landmark manager doesn't contain the provided group label.

as_pointgraph(*copy=True*, *skip_checks=False*)

Converts the TriMesh to a `PointUndirectedGraph`.

Parameters

- **copy** (*bool*, optional) – If `True`, the graph will be a copy.
- **skip_checks** (*bool*, optional) – If `True`, no checks will be performed.

Returns **pointgraph** (`PointUndirectedGraph`) – The point graph.

as_vector(***kwargs*)

Returns a flattened representation of the object as a single vector.

Returns **vector** (*(N,) ndarray*) – The core representation of the object, flattened into a single vector. Note that this is always a view back on to the original object, but is not writable.

boundary_tri_index()

Boolean index into triangles that are at the edge of the TriMesh

Returns **boundary_tri_index** (`(n_tris,)` *ndarray*) – For each triangle (ABC), returns whether any of it's edges is not also an edge of another triangle (and so this triangle exists on the boundary of the TriMesh)

bounding_box()

Return a bounding box from two corner points as a directed graph. In the case of a 2D pointcloud, first point (0) should be nearest the origin. In the case of an image, this ordering would appear as:

```
0<--3
|   ^
|   |
v   |
1-->2
```

In the case of a pointcloud, the ordering will appear as:

```
3<--2
|   ^
|   |
v   |
0-->1
```

In the case of a 3D pointcloud, the first point (0) should be the near closest to the origin and the second point is the far opposite corner.

Returns **bounding_box** (`PointDirectedGraph`) – The axis aligned bounding box of the PointCloud.

bounds (*boundary=0*)

The minimum to maximum extent of the PointCloud. An optional boundary argument can be provided to expand the bounds by a constant margin.

Parameters **boundary** (*float*) – A optional padding distance that is added to the bounds. Default is `0`, meaning the max/min of tightest possible containing square/cube/hypercube is returned.

Returns

- **min_b** (`(n_dims,)` *ndarray*) – The minimum extent of the `PointCloud` and boundary along each dimension
- **max_b** (`(n_dims,)` *ndarray*) – The maximum extent of the `PointCloud` and boundary along each dimension

centre ()

The mean of all the points in this PointCloud (centre of mass).

Returns **centre** (`(n_dims)` *ndarray*) – The mean of this PointCloud's points.

centre_of_bounds ()

The centre of the absolute bounds of this PointCloud. Contrast with `centre()`, which is the mean point position.

Returns **centre** (`n_dims` *ndarray*) – The centre of the bounds of this PointCloud.

constrain_to_bounds (*bounds*)

Returns a copy of this PointCloud, constrained to lie exactly within the given bounds. Any points outside the bounds will be 'snapped' to lie *exactly* on the boundary.

Parameters **bounds** (`(n_dims, n_dims)` tuple of scalars) – The bounds to constrain this pointcloud within.

Returns **constrained** (`PointCloud`) – The constrained pointcloud.

copy ()

Generate an efficient copy of this object.

Note that Numpy arrays and other `Copyable` objects on `self` will be deeply copied. Dictionaries and sets will be shallow copied, and everything else will be assigned (no copy will be made).

Classes that store state other than numpy arrays and immutable types should overwrite this method to ensure all state is copied.

Returns `type(self)` – A copy of this object

distance_to (*pointcloud*, ***kwargs*)

Returns a distance matrix between this PointCloud and another. By default the Euclidean distance is calculated - see *scipy.spatial.distance.cdist* for valid kwargs to change the metric and other properties.

Parameters **pointcloud** (`PointCloud`) – The second pointcloud to compute distances between. This must be of the same dimension as this PointCloud.

Returns **distance_matrix** (`(n_points, n_points)` *ndarray*) – The symmetric pairwise distance matrix between the two PointClouds s.t. `distance_matrix[i, j]` is the distance between the i'th point of this PointCloud and the j'th point of the input PointCloud.

edge_indices ()

An unordered index into points that rebuilds the edges of this `TriMesh`.

Note that there will be two edges present in cases where two triangles 'share' an edge. Consider `unique_edge_indices()` for a single index for each physical edge on the `TriMesh`.

Returnsedge_indices ((n_tris * 3, 2) *ndarray*) – For each triangle (ABC), returns the pair of point indices that rebuild AB, AC, BC. All edge indices are concatenated for a total of n_tris * 3 edge_indices. The ordering is done so that all AB vectors are first in the returned list, followed by BC, then CA.

edge_lengths()

The length of each edge in this *TriMesh*.

Note that there will be two edges present in cases where two triangles 'share' an edge. Consider *unique_edge_indices()* for a single index for each physical edge on the *TriMesh*. The ordering matches the case for edges and edge_indices.

Returnsedge_lengths ((n_tris * 3,) *ndarray*) – Scalar euclidean lengths for each edge in this *TriMesh*.

edge_vectors()

A vector of edges of each triangle face.

Note that there will be two edges present in cases where two triangles 'share' an edge. Consider *unique_edge_vectors()* for a single vector for each physical edge on the *TriMesh*.

Returnsedges ((n_tris * 3, n_dims) *ndarray*) – For each triangle (ABC), returns the edge vectors AB, BC, CA. All edges are concatenated for a total of n_tris * 3 edges. The ordering is done so that all AB vectors are first in the returned list, followed by BC, then CA.

from_mask(*mask*)

A 1D boolean array with the same number of elements as the number of points in the TriMesh. This is then broadcast across the dimensions of the mesh and returns a new mesh containing only those points that were True in the mask.

Parametersmask ((n_points,) *ndarray*) – 1D array of booleans

Returnsmesh (*TriMesh*) – A new mesh that has been masked.

from_tri_mask(*tri_mask*)

A 1D boolean array with the same number of elements as the number of triangles in the TriMesh. This is then broadcast across the dimensions of the mesh and returns a new mesh containing only those triangles that were True in the mask.

Parametersmask ((n_tris,) *ndarray*) – 1D array of booleans

Returnsmesh (*TriMesh*) – A new mesh that has been masked by triangles.

from_vector(*vector*)

Build a new instance of the object from it's vectorized state.

self is used to fill out the missing state required to rebuild a full object from it's standardized flattened state. This is the default implementation, which is which is a deepcopy of the object followed by a call to *from_vector_inplace()*. This method can be overridden for a performance benefit if desired.

Parametersvector ((n_parameters,) *ndarray*) – Flattened representation of the object.

Returnsobject (type(self)) – An new instance of this class.

from_vector_inplace(*vector*)

Deprecated. Use the non-mutating API, *from_vector*.

For internal usage in performance-sensitive spots, see *_from_vector_inplace()*

Parametersvector ((n_parameters,) *ndarray*) – Flattened representation of this object

h_points()

Convert poincloud to a homogeneous array: (n_dims + 1, n_points)

Type`type(self)`

has_nan_values()

Tests if the vectorized form of the object contains `nan` values or not. This is particularly useful for objects with unknown values that have been mapped to `nan` values.

Returnshas_nan_values (*bool*) – If the vectorized object contains `nan` values.

classmethod **init_2d_grid**(*shape*, *spacing=None*)

Create a TriMesh that exists on a regular 2D grid. The first dimension is the number of rows in the grid and the second dimension of the shape is the number of columns. `spacing` optionally allows the definition of the distance between points (uniform over points). The spacing may be different for rows and columns.

The triangulation will be right-handed and the diagonal will go from the top left to the bottom right of a square on the grid.

Parameters

- **shape** (*tuple* of 2 *int*) – The size of the grid to create, this defines the number of points across each dimension in the grid. The first element is the number of rows and the second is the number of columns.
- **spacing** (*int* or *tuple* of 2 *int*, optional) – The spacing between points. If a single *int* is provided, this is applied uniformly across each dimension. If a *tuple* is provided, the spacing is applied non-uniformly as defined e.g. `(2, 3)` gives a spacing of 2 for the rows and 3 for the columns.

Returnstrimesh (*`TriMesh`*) – A TriMesh arranged in a grid.

classmethod **init_from_depth_image**(*depth_image*)

Return a 3D triangular mesh from the given depth image. The depth image is assumed to represent height/depth values and the XY coordinates are assumed to unit spaced and represent image coordinates. This is particularly useful for visualising depth values that have been recovered from images.

Parametersdepth_image (*`Image`* or subclass) – A single channel image that contains depth values - as commonly returned by RGBD cameras, for example.

Returnsdepth_cloud (`type(cls)`) – A new 3D TriMesh with unit XY coordinates and the given depth values as Z coordinates. The trilist is constructed as in *`init_2d_grid()`*.

mean_edge_length(*unique=True*)

The mean length of each edge in this *`TriMesh`*.

Parametersunique (*bool*, optional) – If `True`, each shared edge will only be counted once towards the average. If false, shared edges will be counted twice.

Returnsmean_edge_length (`float`) – The mean length of each edge in this *`TriMesh`*

mean_tri_area()

The mean area of each triangle face in this *`TriMesh`*.

Returnsmean_tri_area (`float`) – The mean area of each triangle face in this *`TriMesh`*

Raises`ValueError` – If mesh is not 3D

norm(***kwargs*)

Returns the norm of this PointCloud. This is a translation and rotation invariant measure of the point cloud's intrinsic size - in other words, it is always taken around the point cloud's centre.

By default, the Frobenius norm is taken, but this can be changed by setting kwargs - see `numpy.linalg.norm` for valid options.

Returnsnorm (*float*) – The norm of this *`PointCloud`*

range(*boundary=0*)

The range of the extent of the PointCloud.

Parametersboundary (*float*) – A optional padding distance that is used to extend the bounds from which the range is computed. Default is `0`, no extension is performed.

Returnsrange (`(n_dims,)` *ndarray*) – The range of the `PointCloud` extent in each dimension.

tojson()

Convert this `TriMesh` to a dictionary representation suitable for inclusion in the LJSON landmark format. Note that this enforces a simpler representation, and as such is not suitable for a permanent serialization of a `TriMesh` (to be clear, `TriMesh`'s serialized as part of a landmark set will be rebuilt as a `PointUndirectedGraph`).

Returnsjson (*dict*) – Dictionary with `points` and `connectivity` keys.

tri_areas()

The area of each triangle face.

Returnsareas (`(n_tris,)` *ndarray*) – Area of each triangle, ordered as the trilist is

Raises`ValueError` – If mesh is not 2D or 3D

tri_normals()

Compute the triangle face normals from the current set of points and triangle list. Only valid for 3D dimensional meshes.

Returnsnormals (`(n_tris, 3)` *ndarray*) – Normal at each triangle face.

Raises`ValueError` – If mesh is not 3D

unique_edge_indices()

An unordered index into points that rebuilds the unique edges of this `TriMesh`.

Note that each physical edge will only be counted once in this method (i.e. edges shared between neighbouring triangles are only counted once not twice). The ordering should be considered random.

Returnsunique_edge_indices (`(n_unique_edges, 2)` *ndarray*) – Return a point index that rebuilds all edges present in this `TriMesh` only once.

unique_edge_lengths()

The length of each edge in this `TriMesh`.

Note that each physical edge will only be counted once in this method (i.e. edges shared between neighbouring triangles are only counted once not twice). The ordering should be considered random.

Returnsedge_lengths (`(n_tris * 3, )` *ndarray*) – Scalar euclidean lengths for each edge in this `TriMesh`.

unique_edge_vectors()

An unordered vector of unique edges for the whole `TriMesh`.

Note that each physical edge will only be counted once in this method (i.e. edges shared between neighbouring triangles are only counted once not twice). The ordering should be considered random.

Returnsunique_edge_vectors (`(n_unique_edges, n_dims)` *ndarray*) – Vectors for each unique edge in this `TriMesh`.

vertex_normals()

Compute the per-vertex normals from the current set of points and triangle list. Only valid for 3D dimensional meshes.

Returnsnormals (`(n_points, 3)` *ndarray*) – Normal at each point.

Raises `ValueError` – If mesh is not 3D

with_dims (*dims*)
Return a copy of this shape with only particular dimensions retained.

Parameters **dims** (*valid numpy array slice*) – The slice that will be used on the dimensionality axis of the shape under transform. For example, to go from a 3D shape to a 2D one, [0, 1] could be provided or np.array([True, True, False]).

Returns *copy of self, with only the requested dims*

has_landmarks
Whether the object has landmarks.

Type *bool*

landmarks
The landmarks object.

Type *LandmarkManager*

lms
Deprecated. Maintained for compatibility, will be removed in a future version. Returns a copy of this object, which previously would have held the 'underlying' *PointCloud* subclass.

Type self

n_dims
The number of dimensions in the pointcloud.

Type *int*

n_landmark_groups
The number of landmark groups on this object.

Type *int*

n_parameters
The length of the vector that this object produces.

Type *int*

n_points
The number of points in the pointcloud.

Type *int*

n_tris
The number of triangles in the triangle list.

Type *int*

ColouredTriMesh

class `menpo.shape.`**ColouredTriMesh** (*points*, *trilist=None*, *colours=None*, *copy=True*)
Bases: `TriMesh`

Combines a *TriMesh* with a colour per vertex.

Parameters

- **points** (`(n_points, n_dims)` *ndarray*) – The array representing the points.
- **trilist** (`(M, 3)` *ndarray* or `None`, optional) – The triangle list. If *None*, a Delaunay triangulation of the points will be used instead.

- **colours** ((N, 3) *ndarray*, optional) – The floating point RGB colour per vertex. If not given, grey will be assigned to each vertex.
- **copy** (*bool*, optional) – If False, the points, trilist and colours will not be copied on assignment. In general this should only be used if you know what you are doing.

Raises ValueError – If the number of colour values does not match the number of vertices.

_view_2d(*figure_id=None*, *new_figure=False*, *image_view=True*, *render_lines=True*, *line_colour='r'*, *line_style='-'*, *line_width=1.0*, *render_markers=True*, *marker_style='o'*, *marker_size=5*, *marker_face_colour='k'*, *marker_edge_colour='k'*, *marker_edge_width=1.0*, *render_numbering=False*, *numbers_horizontal_align='center'*, *numbers_vertical_align='bottom'*, *numbers_font_name='sans-serif'*, *numbers_font_size=10*, *numbers_font_style='normal'*, *numbers_font_weight='normal'*, *numbers_font_colour='k'*, *render_axes=True*, *axes_font_name='sans-serif'*, *axes_font_size=10*, *axes_font_style='normal'*, *axes_font_weight='normal'*, *axes_x_limits=None*, *axes_y_limits=None*, *axes_x_ticks=None*, *axes_y_ticks=None*, *figure_size=(7, 7)*, *label=None*, ***kwargs*)

Visualization of the TriMesh in 2D. Currently, explicit coloured TriMesh viewing is not supported, and therefore viewing falls back to uncoloured 2D TriMesh viewing.

Returns

- **figure_id** (*object*, optional) – The id of the figure to be used.
- **new_figure** (*bool*, optional) – If True, a new figure is created.
- **image_view** (*bool*, optional) – If True the ColouredTriMesh will be viewed as if it is in the image coordinate system.
- **render_lines** (*bool*, optional) – If True, the edges will be rendered.
- **line_colour** (*See Below, optional*) – The colour of the lines. Example options:

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **line_style** ({-, --, -., :}, optional) – The style of the lines.
- **line_width** (*float*, optional) – The width of the lines.
- **render_markers** (*bool*, optional) – If True, the markers will be rendered.
- **marker_style** (*See Below, optional*) –

  The style of the markers. Example options

```
{., ,, o, v, ^, <, >, +, x, D, d, s, p, *, h, H, 1, 2, 3, 4, 8}
```

- **marker_size** (*int*, optional) – The size of the markers in points.
- **marker_face_colour** (*See Below, optional*) – The face (filling) colour of the markers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **marker_edge_colour** (*See Below, optional*) – The edge colour of the markers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

•**marker_edge_width** (*float*, optional) – The width of the markers' edge.

•**render_numbering** (*bool*, optional) – If `True`, the landmarks will be numbered.

•**numbers_horizontal_align** (`{center, right, left}`, optional) – The horizontal alignment of the numbers' texts.

•**numbers_vertical_align** (`{center, top, bottom, baseline}`, optional) – The vertical alignment of the numbers' texts.

•**numbers_font_name** (*See Below, optional*) –

The font of the numbers. Example options

```
{serif, sans-serif, cursive, fantasy, monospace}
```

•**numbers_font_size** (*int*, optional) – The font size of the numbers.

•**numbers_font_style** (`{normal, italic, oblique}`, optional) – The font style of the numbers.

•**numbers_font_weight** (*See Below, optional*) – The font weight of the numbers. Example options

```
{ultralight, light, normal, regular, book, medium, roman,
semibold, demibold, demi, bold, heavy, extra bold, black}
```

•**numbers_font_colour** (*See Below, optional*) – The font colour of the numbers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

•**render_axes** (*bool*, optional) – If `True`, the axes will be rendered.

•**axes_font_name** (*See Below, optional*) – The font of the axes. Example options

```
{serif, sans-serif, cursive, fantasy, monospace}
```

•**axes_font_size** (*int*, optional) – The font size of the axes.

•**axes_font_style** (`{normal, italic, oblique}`, optional) – The font style of the axes.

•**axes_font_weight** (*See Below, optional*) – The font weight of the axes. Example options

```
{ultralight, light, normal, regular, book, medium, roman,
semibold, demibold, demi, bold, heavy, extra bold, black}
```

•**axes_x_limits** (*float* or (*float*, *float*) or `None`, optional) – The limits of the x axis. If *float*, then it sets padding on the right and left of the TriMesh as a percentage of the TriMesh's width. If *tuple* or *list*, then it defines the axis limits. If `None`, then the limits are set automatically.

•**axes_y_limits** ((*float*, *float*) *tuple* or `None`, optional) – The limits of the y axis. If *float*, then it sets padding on the top and bottom of the TriMesh as a percentage of the TriMesh's

height. If *tuple* or *list*, then it defines the axis limits. If `None`, then the limits are set automatically.

- **axes_x_ticks** (*list* or *tuple* or `None`, optional) – The ticks of the x axis.
- **axes_y_ticks** (*list* or *tuple* or `None`, optional) – The ticks of the y axis.
- **figure_size** ((*float*, *float*) *tuple* or `None`, optional) – The size of the figure in inches.
- **label** (*str*, optional) – The name entry in case of a legend.

Returns **viewer** (`PointGraphViewer2d`) – The viewer object.

Raises `warning` – 2D Viewing of Coloured TriMeshes is not supported, automatically falls back to 2D `TriMesh` viewing.

_view_landmarks_2d(*group=None*, *with_labels=None*, *without_labels=None*, *figure_id=None*, *new_figure=False*, *image_view=True*, *render_lines=True*, *line_colour='k'*, *line_style='-'*, *line_width=2*, *render_markers=True*, *marker_style='s'*, *marker_size=7*, *marker_face_colour='k'*, *marker_edge_colour='k'*, *marker_edge_width=1.0*, *render_lines_lms=True*, *line_colour_lms=None*, *line_style_lms='-'*, *line_width_lms=1*, *render_markers_lms=True*, *marker_style_lms='o'*, *marker_size_lms=5*, *marker_face_colour_lms=None*, *marker_edge_colour_lms=None*, *marker_edge_width_lms=1.0*, *render_numbering=False*, *numbers_horizontal_align='center'*, *numbers_vertical_align='bottom'*, *numbers_font_name='sans-serif'*, *numbers_font_size=10*, *numbers_font_style='normal'*, *numbers_font_weight='normal'*, *numbers_font_colour='k'*, *render_legend=False*, *legend_title=''*, *legend_font_name='sans-serif'*, *legend_font_style='normal'*, *legend_font_size=10*, *legend_font_weight='normal'*, *legend_marker_scale=None*, *legend_location=2*, *legend_bbox_to_anchor=(1.05, 1.0)*, *legend_border_axes_pad=None*, *legend_n_columns=1*, *legend_horizontal_spacing=None*, *legend_vertical_spacing=None*, *legend_border=True*, *legend_border_padding=None*, *legend_shadow=False*, *legend_rounded_corners=False*, *render_axes=False*, *axes_font_name='sans-serif'*, *axes_font_size=10*, *axes_font_style='normal'*, *axes_font_weight='normal'*, *axes_x_limits=None*, *axes_y_limits=None*, *axes_x_ticks=None*, *axes_y_ticks=None*, *figure_size=(7, 7)*)

Visualize the landmarks. This method will appear on the *TriMesh* as `view_landmarks`.

Parameters

- **group** (*str* or''None'' optional) – The landmark group to be visualized. If `None` and there are more than one landmark groups, an error is raised.
- **with_labels** (`None` or *str* or *list* of *str*, optional) – If not `None`, only show the given label(s). Should **not** be used with the `without_labels` kwarg.
- **without_labels** (`None` or *str* or *list* of *str*, optional) – If not `None`, show all except the given label(s). Should **not** be used with the `with_labels` kwarg.
- **figure_id** (*object*, optional) – The id of the figure to be used.
- **new_figure** (*bool*, optional) – If `True`, a new figure is created.
- **image_view** (*bool*, optional) – If `True` the PointCloud will be viewed as if it is in the image coordinate system.
- **render_lines** (*bool*, optional) – If `True`, the edges will be rendered.

- **line_colour** (*See Below, optional*) – The colour of the lines. Example options:

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **line_style** ({-, --, -., :}, optional) – The style of the lines.
- **line_width** (*float*, optional) – The width of the lines.
- **render_markers** (*bool*, optional) – If `True`, the markers will be rendered.
- **marker_style** (*See Below, optional*) – The style of the markers. Example options

```
{., ,, o, v, ^, <, >, +, x, D, d, s, p, *, h, H, 1, 2, 3, 4, 8}
```

- **marker_size** (*int*, optional) – The size of the markers in points.
- **marker_face_colour** (*See Below, optional*) – The face (filling) colour of the markers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **marker_edge_colour** (*See Below, optional*) – The edge colour of the markers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **marker_edge_width** (*float*, optional) – The width of the markers' edge.
- **render_lines_lms** (*bool*, optional) – If `True`, the edges of the landmarks will be rendered.
- **line_colour_lms** (*See Below, optional*) – The colour of the lines of the landmarks. Example options:

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **line_style_lms** ({-, --, -., :}, optional) – The style of the lines of the landmarks.
- **line_width_lms** (*float*, optional) – The width of the lines of the landmarks.
- **render_markers** – If `True`, the markers of the landmarks will be rendered.
- **marker_style** – The style of the markers of the landmarks. Example options

```
{., ,, o, v, ^, <, >, +, x, D, d, s, p, *, h, H, 1, 2, 3, 4, 8}
```

- **marker_size** – The size of the markers of the landmarks in points.
- **marker_face_colour** – The face (filling) colour of the markers of the landmarks. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **marker_edge_colour** – The edge colour of the markers of the landmarks. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **marker_edge_width** – The width of the markers' edge of the landmarks.
- **render_numbering** (*bool*, optional) – If `True`, the landmarks will be numbered.
- **numbers_horizontal_align** (`{center, right, left}`, optional) – The horizontal alignment of the numbers' texts.
- **numbers_vertical_align** (`{center, top, bottom, baseline}`, optional) – The vertical alignment of the numbers' texts.
- **numbers_font_name** (*See Below, optional*) – The font of the numbers. Example options

```
{serif, sans-serif, cursive, fantasy, monospace}
```

- **numbers_font_size** (*int*, optional) – The font size of the numbers.
- **numbers_font_style** (`{normal, italic, oblique}`, optional) – The font style of the numbers.
- **numbers_font_weight** (*See Below, optional*) – The font weight of the numbers. Example options

```
{ultralight, light, normal, regular, book, medium, roman,
semibold, demibold, demi, bold, heavy, extra bold, black}
```

- **numbers_font_colour** (*See Below, optional*) – The font colour of the numbers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **render_legend** (*bool*, optional) – If `True`, the legend will be rendered.
- **legend_title** (*str*, optional) – The title of the legend.
- **legend_font_name** (*See below, optional*) – The font of the legend. Example options

```
{serif, sans-serif, cursive, fantasy, monospace}
```

- **legend_font_style** (`{normal, italic, oblique}`, optional) – The font style of the legend.
- **legend_font_size** (*int*, optional) – The font size of the legend.
- **legend_font_weight** (*See Below, optional*) – The font weight of the legend. Example options

```
{ultralight, light, normal, regular, book, medium, roman,
semibold, demibold, demi, bold, heavy, extra bold, black}
```

- **legend_marker_scale** (*float*, optional) – The relative size of the legend markers with respect to the original
- **legend_location** (*int*, optional) – The location of the legend. The predefined values are:

'best'	0
'upper right'	1
'upper left'	2
'lower left'	3
'lower right'	4
'right'	5
'center left'	6
'center right'	7
'lower center'	8
'upper center'	9
'center'	10

- **legend_bbox_to_anchor** ((*float*, *float*) *tuple*, optional) – The bbox that the legend will be anchored.
- **legend_border_axes_pad** (*float*, optional) – The pad between the axes and legend border.
- **legend_n_columns** (*int*, optional) – The number of the legend's columns.
- **legend_horizontal_spacing** (*float*, optional) – The spacing between the columns.
- **legend_vertical_spacing** (*float*, optional) – The vertical space between the legend entries.
- **legend_border** (*bool*, optional) – If `True`, a frame will be drawn around the legend.
- **legend_border_padding** (*float*, optional) – The fractional whitespace inside the legend border.
- **legend_shadow** (*bool*, optional) – If `True`, a shadow will be drawn behind legend.
- **legend_rounded_corners** (*bool*, optional) – If `True`, the frame's corners will be rounded (fancybox).
- **render_axes** (*bool*, optional) – If `True`, the axes will be rendered.
- **axes_font_name** (*See Below, optional*) – The font of the axes. Example options

```
{serif, sans-serif, cursive, fantasy, monospace}
```

- **axes_font_size** (*int*, optional) – The font size of the axes.
- **axes_font_style** (`{normal, italic, oblique}`, optional) – The font style of the axes.
- **axes_font_weight** (*See Below, optional*) – The font weight of the axes. Example options

```
{ultralight, light, normal, regular, book, medium, roman,
semibold,demibold, demi, bold, heavy, extra bold, black}
```

- **axes_x_limits** (*float* or (*float*, *float*) or `None`, optional) – The limits of the x axis. If *float*, then it sets padding on the right and left of the PointCloud as a percentage of the PointCloud's width. If *tuple* or *list*, then it defines the axis limits. If `None`, then the limits are set automatically.
- **axes_y_limits** ((*float*, *float*) *tuple* or `None`, optional) – The limits of the y axis. If *float*, then it sets padding on the top and bottom of the PointCloud as a percentage of the PointCloud's height. If *tuple* or *list*, then it defines the axis limits. If `None`, then the limits are set automatically.
- **axes_x_ticks** (*list* or *tuple* or `None`, optional) – The ticks of the x axis.
- **axes_y_ticks** (*list* or *tuple* or `None`, optional) – The ticks of the y axis.
- **figure_size** ((*float*, *float*) *tuple* or `None` optional) – The size of the figure in inches.

Raises

- `ValueError` – If both `with_labels` and `without_labels` are passed.
- `ValueError` – If the landmark manager doesn't contain the provided group label.

as_pointgraph(*copy=True*, *skip_checks=False*)

Converts the TriMesh to a `PointUndirectedGraph`.

Parameters

- **copy** (*bool*, optional) – If `True`, the graph will be a copy.
- **skip_checks** (*bool*, optional) – If `True`, no checks will be performed.

Returnspointgraph (`PointUndirectedGraph`) – The point graph.

as_vector(***kwargs*)

Returns a flattened representation of the object as a single vector.

Returnsvector (*(N,) ndarray*) – The core representation of the object, flattened into a single vector. Note that this is always a view back on to the original object, but is not writable.

boundary_tri_index()

Boolean index into triangles that are at the edge of the TriMesh

Returnsboundary_tri_index (`(n_tris,)` *ndarray*) – For each triangle (ABC), returns whether any of it's edges is not also an edge of another triangle (and so this triangle exists on the boundary of the TriMesh)

bounding_box()

Return a bounding box from two corner points as a directed graph. In the case of a 2D pointcloud, first point (0) should be nearest the origin. In the case of an image, this ordering would appear as:

```
0<--3
|   ^
|   |
v   |
1-->2
```

In the case of a pointcloud, the ordering will appear as:

```
3<--2
|   ^
|   |
v   |
0-->1
```

In the case of a 3D pointcloud, the first point (0) should be the near closest to the origin and the second point is the far opposite corner.

Returnsbounding_box (*PointDirectedGraph*) – The axis aligned bounding box of the PointCloud.

bounds(*boundary=0*)

The minimum to maximum extent of the PointCloud. An optional boundary argument can be provided to expand the bounds by a constant margin.

Parametersboundary (*float*) – A optional padding distance that is added to the bounds. Default is `0`, meaning the max/min of tightest possible containing square/cube/hypercube is returned.

Returns

- **min_b** (`(n_dims,)` *ndarray*) – The minimum extent of the *PointCloud* and boundary along each dimension
- **max_b** (`(n_dims,)` *ndarray*) – The maximum extent of the *PointCloud* and boundary along each dimension

centre()

The mean of all the points in this PointCloud (centre of mass).

Returnscentre (`(n_dims)` *ndarray*) – The mean of this PointCloud's points.

centre_of_bounds()

The centre of the absolute bounds of this PointCloud. Contrast with *centre()*, which is the mean point position.

Returnscentre (`n_dims` *ndarray*) – The centre of the bounds of this PointCloud.

clip_texture(*range=(0.0, 1.0)*)

Method that returns a copy of the object with the coloured values clipped in range `(0, 1)`.

Parametersrange (`(float, float)`, optional) – The clipping range.

Returnsself (*ColouredTriMesh*) – A copy of self with its texture clipped.

constrain_to_bounds(*bounds*)

Returns a copy of this PointCloud, constrained to lie exactly within the given bounds. Any points outside the bounds will be 'snapped' to lie *exactly* on the boundary.

Parametersbounds (`(n_dims, n_dims)` tuple of scalars) – The bounds to constrain this pointcloud within.

Returnsconstrained (*PointCloud*) – The constrained pointcloud.

copy()

Generate an efficient copy of this object.

Note that Numpy arrays and other *Copyable* objects on `self` will be deeply copied. Dictionaries and sets will be shallow copied, and everything else will be assigned (no copy will be made).

Classes that store state other than numpy arrays and immutable types should overwrite this method to ensure all state is copied.

Returns`type(self)` – A copy of this object

distance_to(*pointcloud*, ***kwargs*)

Returns a distance matrix between this PointCloud and another. By default the Euclidean distance is calculated - see *scipy.spatial.distance.cdist* for valid kwargs to change the metric and other properties.

Parameterspointcloud (*PointCloud*) – The second pointcloud to compute distances between. This must be of the same dimension as this PointCloud.

Returnsdistance_matrix ((n_points, n_points) *ndarray*) – The symmetric pairwise distance matrix between the two PointClouds s.t. distance_matrix[i, j] is the distance between the i'th point of this PointCloud and the j'th point of the input PointCloud.

edge_indices()

An unordered index into points that rebuilds the edges of this *TriMesh*.

Note that there will be two edges present in cases where two triangles 'share' an edge. Consider *unique_edge_indices()* for a single index for each physical edge on the *TriMesh*.

Returnsedge_indices ((n_tris * 3, 2) *ndarray*) – For each triangle (ABC), returns the pair of point indices that rebuild AB, AC, BC. All edge indices are concatenated for a total of n_tris * 3 edge_indices. The ordering is done so that all AB vectors are first in the returned list, followed by BC, then CA.

edge_lengths()

The length of each edge in this *TriMesh*.

Note that there will be two edges present in cases where two triangles 'share' an edge. Consider *unique_edge_indices()* for a single index for each physical edge on the *TriMesh*. The ordering matches the case for edges and edge_indices.

Returnsedge_lengths ((n_tris * 3,) *ndarray*) – Scalar euclidean lengths for each edge in this *TriMesh*.

edge_vectors()

A vector of edges of each triangle face.

Note that there will be two edges present in cases where two triangles 'share' an edge. Consider *unique_edge_vectors()* for a single vector for each physical edge on the *TriMesh*.

Returnsedges ((n_tris * 3, n_dims) *ndarray*) – For each triangle (ABC), returns the edge vectors AB, BC, CA. All edges are concatenated for a total of n_tris * 3 edges. The ordering is done so that all AB vectors are first in the returned list, followed by BC, then CA.

from_mask(*mask*)

A 1D boolean array with the same number of elements as the number of points in the ColouredTriMesh. This is then broadcast across the dimensions of the mesh and returns a new mesh containing only those points that were True in the mask.

Parametersmask ((n_points,) *ndarray*) – 1D array of booleans

Returnsmesh (*ColouredTriMesh*) – A new mesh that has been masked.

from_tri_mask(*tri_mask*)

A 1D boolean array with the same number of elements as the number of triangles in the TriMesh. This is then broadcast across the dimensions of the mesh and returns a new mesh containing only those triangles that were True in the mask.

Parametersmask ((n_tris,) *ndarray*) – 1D array of booleans

Returnsmesh (*TriMesh*) – A new mesh that has been masked by triangles.

from_vector(*vector*)

Build a new instance of the object from it's vectorized state.

self is used to fill out the missing state required to rebuild a full object from it's standardized flattened state. This is the default implementation, which is which is a deepcopy of the object followed by a call to *from_vector_inplace()*. This method can be overridden for a performance benefit if desired.

Parametersvector ((n_parameters,) *ndarray*) – Flattened representation of the object.

Returnsobject (`type(self)`) – An new instance of this class.

from_vector_inplace(*vector*)

Deprecated. Use the non-mutating API, `from_vector`.

For internal usage in performance-sensitive spots, see *_from_vector_inplace()*

Parametersvector (`(n_parameters,)` *ndarray*) – Flattened representation of this object

h_points()

Convert poincloud to a homogeneous array: `(n_dims + 1, n_points)`

Type`type(self)`

has_nan_values()

Tests if the vectorized form of the object contains `nan` values or not. This is particularly useful for objects with unknown values that have been mapped to `nan` values.

Returnshas_nan_values (*bool*) – If the vectorized object contains `nan` values.

classmethod init_2d_grid(*shape*, *spacing=None*, *colours=None*)

Create a ColouredTriMesh that exists on a regular 2D grid. The first dimension is the number of rows in the grid and the second dimension of the shape is the number of columns. `spacing` optionally allows the definition of the distance between points (uniform over points). The spacing may be different for rows and columns.

The triangulation will be right-handed and the diagonal will go from the top left to the bottom right of a square on the grid.

Parameters

- **shape** (*tuple* of 2 *int*) – The size of the grid to create, this defines the number of points across each dimension in the grid. The first element is the number of rows and the second is the number of columns.
- **spacing** (*int* or *tuple* of 2 *int*, optional) – The spacing between points. If a single *int* is provided, this is applied uniformly across each dimension. If a *tuple* is provided, the spacing is applied non-uniformly as defined e.g. `(2, 3)` gives a spacing of 2 for the rows and 3 for the columns.
- **colours** (`(N, 3)` *ndarray*, optional) – The floating point RGB colour per vertex. If not given, grey will be assigned to each vertex.

Returnstrimesh (`TriMesh`) – A TriMesh arranged in a grid.

classmethod init_from_depth_image(*depth_image*, *colours=None*)

Return a 3D textured triangular mesh from the given depth image. The depth image is assumed to represent height/depth values and the XY coordinates are assumed to unit spaced and represent image coordinates. This is particularly useful for visualising depth values that have been recovered from images.

The optionally passed texture will be textured mapped onto the planar surface using the correct texture coordinates for an image of the same shape as `depth_image`.

Parameters

- **depth_image** (`Image` or subclass) – A single channel image that contains depth values - as commonly returned by RGBD cameras, for example.
- **colours** (`(N, 3)` *ndarray*, optional) – The floating point RGB colour per vertex. If not given, grey will be assigned to each vertex.

Returnsdepth_cloud (`type(cls)`) – A new 3D TriMesh with unit XY coordinates and the given depth values as Z coordinates. The trilist is constructed as in `init_2d_grid()`.

mean_edge_length(*unique=True*)

The mean length of each edge in this `TriMesh`.

Parametersunique (*bool*, optional) – If `True`, each shared edge will only be counted once towards the average. If false, shared edges will be counted twice.

Returnsmean_edge_length (`float`) – The mean length of each edge in this `TriMesh`

mean_tri_area()

The mean area of each triangle face in this `TriMesh`.

Returnsmean_tri_area (`float`) – The mean area of each triangle face in this `TriMesh`

Raises`ValueError` – If mesh is not 3D

norm(***kwargs*)

Returns the norm of this PointCloud. This is a translation and rotation invariant measure of the point cloud's intrinsic size - in other words, it is always taken around the point cloud's centre.

By default, the Frobenius norm is taken, but this can be changed by setting kwargs - see `numpy.linalg.norm` for valid options.

Returnsnorm (*float*) – The norm of this `PointCloud`

range(*boundary=0*)

The range of the extent of the PointCloud.

Parametersboundary (*float*) – A optional padding distance that is used to extend the bounds from which the range is computed. Default is `0`, no extension is performed.

Returnsrange (`(n_dims,)` *ndarray*) – The range of the `PointCloud` extent in each dimension.

rescale_texture(*minimum*, *maximum*, *per_channel=True*)

A copy of this mesh with colours linearly rescaled to fit a range.

Parameters

- **minimum** (*float*) – The minimal value of the rescaled colours
- **maximum** (*float*) – The maximal value of the rescaled colours
- **per_channel** (*boolean*, optional) – If `True`, each channel will be rescaled independently. If `False`, the scaling will be over all channels.

Returnscoloured_mesh (`type(self)`) – A copy of this mesh with colours linearly rescaled to fit in the range provided.

tojson()

Convert this `TriMesh` to a dictionary representation suitable for inclusion in the LJSON landmark format. Note that this enforces a simpler representation, and as such is not suitable for a permanent serialization of a `TriMesh` (to be clear, `TriMesh`'s serialized as part of a landmark set will be rebuilt as a `PointUndirectedGraph`).

Returnsjson (*dict*) – Dictionary with `points` and `connectivity` keys.

tri_areas()

The area of each triangle face.

Returnsareas (`(n_tris,)` *ndarray*) – Area of each triangle, ordered as the trilist is

Raises`ValueError` – If mesh is not 2D or 3D

tri_normals()

Compute the triangle face normals from the current set of points and triangle list. Only valid for 3D dimensional meshes.

Returnsnormals ((n_tris, 3) *ndarray*) – Normal at each triangle face.

RaisesValueError – If mesh is not 3D

unique_edge_indices()

An unordered index into points that rebuilds the unique edges of this *TriMesh*.

Note that each physical edge will only be counted once in this method (i.e. edges shared between neighbouring triangles are only counted once not twice). The ordering should be considered random.

Returnsunique_edge_indices ((n_unique_edges, 2) *ndarray*) – Return a point index that rebuilds all edges present in this *TriMesh* only once.

unique_edge_lengths()

The length of each edge in this *TriMesh*.

Note that each physical edge will only be counted once in this method (i.e. edges shared between neighbouring triangles are only counted once not twice). The ordering should be considered random.

Returnsedge_lengths ((n_tris * 3,) *ndarray*) – Scalar euclidean lengths for each edge in this *TriMesh*.

unique_edge_vectors()

An unordered vector of unique edges for the whole *TriMesh*.

Note that each physical edge will only be counted once in this method (i.e. edges shared between neighbouring triangles are only counted once not twice). The ordering should be considered random.

Returnsunique_edge_vectors ((n_unique_edges, n_dims) *ndarray*) – Vectors for each unique edge in this *TriMesh*.

vertex_normals()

Compute the per-vertex normals from the current set of points and triangle list. Only valid for 3D dimensional meshes.

Returnsnormals ((n_points, 3) *ndarray*) – Normal at each point.

RaisesValueError – If mesh is not 3D

with_dims(*dims*)

Return a copy of this shape with only particular dimensions retained.

Parametersdims (*valid numpy array slice*) – The slice that will be used on the dimensionality axis of the shape under transform. For example, to go from a 3D shape to a 2D one, [0, 1] could be provided or np.array([True, True, False]).

Returns*copy of self, with only the requested dims*

has_landmarks

Whether the object has landmarks.

Type*bool*

landmarks

The landmarks object.

Type*LandmarkManager*

lms

Deprecated. Maintained for compatibility, will be removed in a future version. Returns a copy of this object, which previously would have held the 'underlying' *PointCloud* subclass.

Typeself

n_channels
The number of channels of colour used (e.g. 3 for RGB).

Type*int*

n_dims
The number of dimensions in the pointcloud.

Type*int*

n_landmark_groups
The number of landmark groups on this object.

Type*int*

n_parameters
The length of the vector that this object produces.

Type*int*

n_points
The number of points in the pointcloud.

Type*int*

n_tris
The number of triangles in the triangle list.

Type*int*

TexturedTriMesh

class `menpo.shape.`**`TexturedTriMesh`**(*points*, *tcoords*, *texture*, *trilist=None*, *copy=True*)
Bases: `TriMesh`

Combines a `TriMesh` with a texture. Also encapsulates the texture coordinates required to render the texture on the mesh.

Parameters

- **points** (`(n_points, n_dims)` *ndarray*) – The array representing the points.
- **tcoords** (`(N, 2)` *ndarray*) – The texture coordinates for the mesh.
- **texture** (`Image`) – The texture for the mesh.
- **trilist** (`(M, 3)` *ndarray* or `None`, optional) – The triangle list. If `None`, a Delaunay triangulation of the points will be used instead.
- **copy** (*bool*, optional) – If `False`, the points, trilist and texture will not be copied on assignment. In general this should only be used if you know what you are doing.

_view_2d(*figure_id=None*, *new_figure=False*, *image_view=True*, *render_lines=True*, *line_colour='r'*, *line_style='-'*, *line_width=1.0*, *render_markers=True*, *marker_style='o'*, *marker_size=5*, *marker_face_colour='k'*, *marker_edge_colour='k'*, *marker_edge_width=1.0*, *render_numbering=False*, *numbers_horizontal_align='center'*, *numbers_vertical_align='bottom'*, *numbers_font_name='sans-serif'*, *numbers_font_size=10*, *numbers_font_style='normal'*, *numbers_font_weight='normal'*, *numbers_font_colour='k'*, *render_axes=True*, *axes_font_name='sans-serif'*, *axes_font_size=10*, *axes_font_style='normal'*, *axes_font_weight='normal'*, *axes_x_limits=None*, *axes_y_limits=None*, *axes_x_ticks=None*, *axes_y_ticks=None*, *figure_size=(7, 7)*, *label=None*, ***kwargs*)

Visualization of the TriMesh in 2D. Currently, explicit textured TriMesh viewing is not supported, and therefore viewing falls back to untextured 2D TriMesh viewing.

Returns

- **figure_id** (*object*, optional) – The id of the figure to be used.
- **new_figure** (*bool*, optional) – If `True`, a new figure is created.
- **image_view** (*bool*, optional) – If `True` the TexturedTriMesh will be viewed as if it is in the image coordinate system.
- **render_lines** (*bool*, optional) – If `True`, the edges will be rendered.
- **line_colour** (*See Below, optional*) – The colour of the lines. Example options:

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **line_style** (`{-, --, -., :}`, optional) – The style of the lines.
- **line_width** (*float*, optional) – The width of the lines.
- **render_markers** (*bool*, optional) – If `True`, the markers will be rendered.
- **marker_style** (*See Below, optional*) –

  The style of the markers. Example options

```
{., ,, o, v, ^, <, >, +, x, D, d, s, p, *, h, H, 1, 2, 3, 4, 8}
```

- **marker_size** (*int*, optional) – The size of the markers in points.
- **marker_face_colour** (*See Below, optional*) – The face (filling) colour of the markers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **marker_edge_colour** (*See Below, optional*) – The edge colour of the markers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **marker_edge_width** (*float*, optional) – The width of the markers' edge.
- **render_numbering** (*bool*, optional) – If `True`, the landmarks will be numbered.

- **numbers_horizontal_align** (`{center, right, left}`, optional) – The horizontal alignment of the numbers' texts.
- **numbers_vertical_align** (`{center, top, bottom, baseline}`, optional) – The vertical alignment of the numbers' texts.
- **numbers_font_name** (*See Below, optional*) –

  The font of the numbers. Example options

```
{serif, sans-serif, cursive, fantasy, monospace}
```

- **numbers_font_size** (*int*, optional) – The font size of the numbers.
- **numbers_font_style** (`{normal, italic, oblique}`, optional) – The font style of the numbers.
- **numbers_font_weight** (*See Below, optional*) – The font weight of the numbers. Example options

```
{ultralight, light, normal, regular, book, medium, roman,
semibold, demibold, demi, bold, heavy, extra bold, black}
```

- **numbers_font_colour** (*See Below, optional*) – The font colour of the numbers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **render_axes** (*bool*, optional) – If `True`, the axes will be rendered.
- **axes_font_name** (*See Below, optional*) – The font of the axes. Example options

```
{serif, sans-serif, cursive, fantasy, monospace}
```

- **axes_font_size** (*int*, optional) – The font size of the axes.
- **axes_font_style** ({`normal`, `italic`, `oblique`}, optional) – The font style of the axes.
- **axes_font_weight** (*See Below, optional*) – The font weight of the axes. Example options

```
{ultralight, light, normal, regular, book, medium, roman,
semibold, demibold, demi, bold, heavy, extra bold, black}
```

- **axes_x_limits** (*float* or (*float*, *float*) or `None`, optional) – The limits of the x axis. If *float*, then it sets padding on the right and left of the TriMesh as a percentage of the TriMesh's width. If *tuple* or *list*, then it defines the axis limits. If `None`, then the limits are set automatically.
- **axes_y_limits** ((*float*, *float*) *tuple* or `None`, optional) – The limits of the y axis. If *float*, then it sets padding on the top and bottom of the TriMesh as a percentage of the TriMesh's height. If *tuple* or *list*, then it defines the axis limits. If `None`, then the limits are set automatically.
- **axes_x_ticks** (*list* or *tuple* or `None`, optional) – The ticks of the x axis.
- **axes_y_ticks** (*list* or *tuple* or `None`, optional) – The ticks of the y axis.
- **figure_size** ((*float*, *float*) *tuple* or `None`, optional) – The size of the figure in inches.
- **label** (*str*, optional) – The name entry in case of a legend.

Returnsviewer (`PointGraphViewer2d`) – The viewer object.

Raises`warning` – 2D Viewing of Coloured TriMeshes is not supported, automatically falls back to 2D `TriMesh` viewing.

_view_landmarks_2d(*group=None, with_labels=None, without_labels=None, figure_id=None, new_figure=False, image_view=True, render_lines=True, line_colour='k', line_style='-', line_width=2, render_markers=True, marker_style='s', marker_size=7, marker_face_colour='k', marker_edge_colour='k', marker_edge_width=1.0, render_lines_lms=True, line_colour_lms=None, line_style_lms='-', line_width_lms=1, render_markers_lms=True, marker_style_lms='o', marker_size_lms=5, marker_face_colour_lms=None, marker_edge_colour_lms=None, marker_edge_width_lms=1.0, render_numbering=False, numbers_horizontal_align='center', numbers_vertical_align='bottom', numbers_font_name='sans-serif', numbers_font_size=10, numbers_font_style='normal', numbers_font_weight='normal', numbers_font_colour='k', render_legend=False, legend_title='', legend_font_name='sans-serif', legend_font_style='normal', legend_font_size=10, legend_font_weight='normal', legend_marker_scale=None, legend_location=2, legend_bbox_to_anchor=(1.05, 1.0), legend_border_axes_pad=None, legend_n_columns=1, legend_horizontal_spacing=None, legend_vertical_spacing=None, legend_border=True, legend_border_padding=None, legend_shadow=False, legend_rounded_corners=False, render_axes=False, axes_font_name='sans-serif', axes_font_size=10, axes_font_style='normal', axes_font_weight='normal', axes_x_limits=None, axes_y_limits=None, axes_x_ticks=None, axes_y_ticks=None, figure_size=(7, 7)*)

Visualize the landmarks. This method will appear on the *TriMesh* as `view_landmarks`.

Parameters

- **group** (*str* or''None'' optional) – The landmark group to be visualized. If `None` and there are more than one landmark groups, an error is raised.
- **with_labels** (`None` or *str* or *list* of *str*, optional) – If not `None`, only show the given label(s). Should **not** be used with the `without_labels` kwarg.
- **without_labels** (`None` or *str* or *list* of *str*, optional) – If not `None`, show all except the given label(s). Should **not** be used with the `with_labels` kwarg.
- **figure_id** (*object*, optional) – The id of the figure to be used.
- **new_figure** (*bool*, optional) – If `True`, a new figure is created.
- **image_view** (*bool*, optional) – If `True` the PointCloud will be viewed as if it is in the image coordinate system.
- **render_lines** (*bool*, optional) – If `True`, the edges will be rendered.
- **line_colour** (*See Below, optional*) – The colour of the lines. Example options:

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **line_style** (`{-, --, -., :}`, optional) – The style of the lines.
- **line_width** (*float*, optional) – The width of the lines.

- **render_markers** (*bool*, optional) – If `True`, the markers will be rendered.
- **marker_style** (*See Below, optional*) – The style of the markers. Example options

```
{., ,, o, v, ^, <, >, +, x, D, d, s, p, *, h, H, 1, 2, 3, 4, 8}
```

- **marker_size** (*int*, optional) – The size of the markers in points.
- **marker_face_colour** (*See Below, optional*) – The face (filling) colour of the markers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **marker_edge_colour** (*See Below, optional*) – The edge colour of the markers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **marker_edge_width** (*float*, optional) – The width of the markers' edge.
- **render_lines_lms** (*bool*, optional) – If `True`, the edges of the landmarks will be rendered.
- **line_colour_lms** (*See Below, optional*) – The colour of the lines of the landmarks. Example options:

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **line_style_lms** (`{-, --, -., :}`, optional) – The style of the lines of the landmarks.
- **line_width_lms** (*float*, optional) – The width of the lines of the landmarks.
- **render_markers** – If `True`, the markers of the landmarks will be rendered.
- **marker_style** – The style of the markers of the landmarks. Example options

```
{., ,, o, v, ^, <, >, +, x, D, d, s, p, *, h, H, 1, 2, 3, 4, 8}
```

- **marker_size** – The size of the markers of the landmarks in points.
- **marker_face_colour** – The face (filling) colour of the markers of the landmarks. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **marker_edge_colour** – The edge colour of the markers of the landmarks. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **marker_edge_width** – The width of the markers' edge of the landmarks.
- **render_numbering** (*bool*, optional) – If `True`, the landmarks will be numbered.
- **numbers_horizontal_align** (`{center, right, left}`, optional) – The horizontal alignment of the numbers' texts.
- **numbers_vertical_align** (`{center, top, bottom, baseline}`, optional) – The vertical alignment of the numbers' texts.
- **numbers_font_name** (*See Below, optional*) – The font of the numbers. Example options

```
{serif, sans-serif, cursive, fantasy, monospace}
```

- **numbers_font_size** (*int*, optional) – The font size of the numbers.
- **numbers_font_style** (`{normal, italic, oblique}`, optional) – The font style of the numbers.
- **numbers_font_weight** (*See Below, optional*) – The font weight of the numbers. Example options

```
{ultralight, light, normal, regular, book, medium, roman,
semibold, demibold, demi, bold, heavy, extra bold, black}
```

- **numbers_font_colour** (*See Below, optional*) – The font colour of the numbers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **render_legend** (*bool*, optional) – If `True`, the legend will be rendered.
- **legend_title** (*str*, optional) – The title of the legend.
- **legend_font_name** (*See below, optional*) – The font of the legend. Example options

```
{serif, sans-serif, cursive, fantasy, monospace}
```

- **legend_font_style** (`{normal, italic, oblique}`, optional) – The font style of the legend.
- **legend_font_size** (*int*, optional) – The font size of the legend.
- **legend_font_weight** (*See Below, optional*) – The font weight of the legend. Example options

```
{ultralight, light, normal, regular, book, medium, roman,
semibold, demibold, demi, bold, heavy, extra bold, black}
```

- **legend_marker_scale** (*float*, optional) – The relative size of the legend markers with respect to the original
- **legend_location** (*int*, optional) – The location of the legend. The predefined values are:

'best'	0
'upper right'	1
'upper left'	2
'lower left'	3
'lower right'	4
'right'	5
'center left'	6
'center right'	7
'lower center'	8
'upper center'	9
'center'	10

- **legend_bbox_to_anchor** ((*float*, *float*) *tuple*, optional) – The bbox that the legend will be anchored.
- **legend_border_axes_pad** (*float*, optional) – The pad between the axes and legend border.
- **legend_n_columns** (*int*, optional) – The number of the legend's columns.
- **legend_horizontal_spacing** (*float*, optional) – The spacing between the columns.
- **legend_vertical_spacing** (*float*, optional) – The vertical space between the legend entries.
- **legend_border** (*bool*, optional) – If `True`, a frame will be drawn around the legend.
- **legend_border_padding** (*float*, optional) – The fractional whitespace inside the legend border.
- **legend_shadow** (*bool*, optional) – If `True`, a shadow will be drawn behind legend.
- **legend_rounded_corners** (*bool*, optional) – If `True`, the frame's corners will be rounded (fancybox).
- **render_axes** (*bool*, optional) – If `True`, the axes will be rendered.
- **axes_font_name** (*See Below, optional*) – The font of the axes. Example options

```
{serif, sans-serif, cursive, fantasy, monospace}
```

- **axes_font_size** (*int*, optional) – The font size of the axes.
- **axes_font_style** (`{normal, italic, oblique}`, optional) – The font style of the axes.
- **axes_font_weight** (*See Below, optional*) – The font weight of the axes. Example options

```
{ultralight, light, normal, regular, book, medium, roman,
semibold,demibold, demi, bold, heavy, extra bold, black}
```

- **axes_x_limits** (*float* or (*float*, *float*) or `None`, optional) – The limits of the x axis. If *float*, then it sets padding on the right and left of the PointCloud as a percentage of the PointCloud's width. If *tuple* or *list*, then it defines the axis limits. If `None`, then the limits are set automatically.
- **axes_y_limits** ((*float*, *float*) *tuple* or `None`, optional) – The limits of the y axis. If *float*, then it sets padding on the top and bottom of the PointCloud as a percentage of the

PointCloud's height. If *tuple* or *list*, then it defines the axis limits. If `None`, then the limits are set automatically.

- **axes_x_ticks** (*list* or *tuple* or `None`, optional) – The ticks of the x axis.
- **axes_y_ticks** (*list* or *tuple* or `None`, optional) – The ticks of the y axis.
- **figure_size** ((*float*, *float*) *tuple* or `None` optional) – The size of the figure in inches.

Raises

- `ValueError` – If both `with_labels` and `without_labels` are passed.
- `ValueError` – If the landmark manager doesn't contain the provided group label.

as_pointgraph(*copy=True*, *skip_checks=False*)

Converts the TriMesh to a `PointUndirectedGraph`.

Parameters

- **copy** (*bool*, optional) – If `True`, the graph will be a copy.
- **skip_checks** (*bool*, optional) – If `True`, no checks will be performed.

Returns **pointgraph** (`PointUndirectedGraph`) – The point graph.

as_vector(***kwargs*)

Returns a flattened representation of the object as a single vector.

Returns **vector** (*(N,) ndarray*) – The core representation of the object, flattened into a single vector. Note that this is always a view back on to the original object, but is not writable.

boundary_tri_index()

Boolean index into triangles that are at the edge of the TriMesh

Returns **boundary_tri_index** (`(n_tris,)` *ndarray*) – For each triangle (ABC), returns whether any of it's edges is not also an edge of another triangle (and so this triangle exists on the boundary of the TriMesh)

bounding_box()

Return a bounding box from two corner points as a directed graph. In the case of a 2D pointcloud, first point (0) should be nearest the origin. In the case of an image, this ordering would appear as:

```
0<--3
|   ^
|   |
v   |
1-->2
```

In the case of a pointcloud, the ordering will appear as:

```
3<--2
|   ^
|   |
v   |
0-->1
```

In the case of a 3D pointcloud, the first point (0) should be the near closest to the origin and the second point is the far opposite corner.

Returns **bounding_box** (`PointDirectedGraph`) – The axis aligned bounding box of the PointCloud.

bounds (*boundary=0*)

The minimum to maximum extent of the PointCloud. An optional boundary argument can be provided to expand the bounds by a constant margin.

Parameters **boundary** (*float*) – A optional padding distance that is added to the bounds. Default is `0`, meaning the max/min of tightest possible containing square/cube/hypercube is returned.

Returns

- **min_b** (`(n_dims,)` *ndarray*) – The minimum extent of the `PointCloud` and boundary along each dimension
- **max_b** (`(n_dims,)` *ndarray*) – The maximum extent of the `PointCloud` and boundary along each dimension

centre ()

The mean of all the points in this PointCloud (centre of mass).

Returns **centre** (`(n_dims)` *ndarray*) – The mean of this PointCloud's points.

centre_of_bounds ()

The centre of the absolute bounds of this PointCloud. Contrast with `centre()`, which is the mean point position.

Returns **centre** (`n_dims` *ndarray*) – The centre of the bounds of this PointCloud.

clip_texture (*range=(0.0, 1.0)*)

Method that returns a copy of the object with the texture values clipped in range `(0, 1)`.

Parameters **range** (`(float, float)`, optional) – The clipping range.

Returns **self** (`ColouredTriMesh`) – A copy of self with its texture clipped.

constrain_to_bounds (*bounds*)

Returns a copy of this PointCloud, constrained to lie exactly within the given bounds. Any points outside the bounds will be 'snapped' to lie *exactly* on the boundary.

Parameters **bounds** (`(n_dims, n_dims)` tuple of scalars) – The bounds to constrain this pointcloud within.

Returns **constrained** (`PointCloud`) – The constrained pointcloud.

copy ()

Generate an efficient copy of this object.

Note that Numpy arrays and other `Copyable` objects on `self` will be deeply copied. Dictionaries and sets will be shallow copied, and everything else will be assigned (no copy will be made).

Classes that store state other than numpy arrays and immutable types should overwrite this method to ensure all state is copied.

Returns `type(self)` – A copy of this object

distance_to (*pointcloud*, ***kwargs*)

Returns a distance matrix between this PointCloud and another. By default the Euclidean distance is calculated - see *scipy.spatial.distance.cdist* for valid kwargs to change the metric and other properties.

Parameters **pointcloud** (`PointCloud`) – The second pointcloud to compute distances between. This must be of the same dimension as this PointCloud.

Returns **distance_matrix** (`(n_points, n_points)` *ndarray*) – The symmetric pairwise distance matrix between the two PointClouds s.t. `distance_matrix[i, j]` is the distance between the i'th point of this PointCloud and the j'th point of the input PointCloud.

edge_indices()

An unordered index into points that rebuilds the edges of this *TriMesh*.

Note that there will be two edges present in cases where two triangles 'share' an edge. Consider *unique_edge_indices()* for a single index for each physical edge on the *TriMesh*.

Returns **edge_indices** (`(n_tris * 3, 2)` *ndarray*) – For each triangle (ABC), returns the pair of point indices that rebuild AB, AC, BC. All edge indices are concatenated for a total of `n_tris * 3` edge_indices. The ordering is done so that all AB vectors are first in the returned list, followed by BC, then CA.

edge_lengths()

The length of each edge in this *TriMesh*.

Note that there will be two edges present in cases where two triangles 'share' an edge. Consider *unique_edge_indices()* for a single index for each physical edge on the *TriMesh*. The ordering matches the case for edges and edge_indices.

Returns **edge_lengths** (`(n_tris * 3, )` *ndarray*) – Scalar euclidean lengths for each edge in this *TriMesh*.

edge_vectors()

A vector of edges of each triangle face.

Note that there will be two edges present in cases where two triangles 'share' an edge. Consider *unique_edge_vectors()* for a single vector for each physical edge on the *TriMesh*.

Returns **edges** (`(n_tris * 3, n_dims)` *ndarray*) – For each triangle (ABC), returns the edge vectors AB, BC, CA. All edges are concatenated for a total of `n_tris * 3` edges. The ordering is done so that all AB vectors are first in the returned list, followed by BC, then CA.

from_mask(*mask*)

A 1D boolean array with the same number of elements as the number of points in the TexturedTriMesh. This is then broadcast across the dimensions of the mesh and returns a new mesh containing only those points that were `True` in the mask.

Parameters **mask** (`(n_points,)` *ndarray*) – 1D array of booleans

Returns **mesh** (*TexturedTriMesh*) – A new mesh that has been masked.

from_tri_mask(*tri_mask*)

A 1D boolean array with the same number of elements as the number of triangles in the TriMesh. This is then broadcast across the dimensions of the mesh and returns a new mesh containing only those triangles that were `True` in the mask.

Parameters **mask** (`(n_tris,)` *ndarray*) – 1D array of booleans

Returns **mesh** (*TriMesh*) – A new mesh that has been masked by triangles.

from_vector(*flattened*)

Builds a new *TexturedTriMesh* given the *flattened* 1D vector. Note that the trilist, texture, and tcoords will be drawn from self.

Parameters **flattened** (`(N,)` *ndarray*) – Vector representing a set of points.

Returns **trimesh** (*TriMesh*) – A new trimesh created from the vector with `self` trilist.

from_vector_inplace(*vector*)

Deprecated. Use the non-mutating API, *from_vector*.

For internal usage in performance-sensitive spots, see *_from_vector_inplace()*

Parameters **vector** (`(n_parameters,)` *ndarray*) – Flattened representation of this object

h_points()

Convert poincloud to a homogeneous array: `(n_dims + 1, n_points)`

Type `type(self)`

has_nan_values()

Tests if the vectorized form of the object contains `nan` values or not. This is particularly useful for objects with unknown values that have been mapped to `nan` values.

Returns **has_nan_values** (*bool*) – If the vectorized object contains `nan` values.

classmethod init_2d_grid(*shape*, *spacing=None*, *tcoords=None*, *texture=None*)

Create a TexturedTriMesh that exists on a regular 2D grid. The first dimension is the number of rows in the grid and the second dimension of the shape is the number of columns. `spacing` optionally allows the definition of the distance between points (uniform over points). The spacing may be different for rows and columns.

The triangulation will be right-handed and the diagonal will go from the top left to the bottom right of a square on the grid.

If no texture is passed a blank (black) texture is attached with correct texture coordinates for texture mapping an image of the same size as `shape`.

Parameters

- **shape** (*tuple* of 2 *int*) – The size of the grid to create, this defines the number of points across each dimension in the grid. The first element is the number of rows and the second is the number of columns.
- **spacing** (*int* or *tuple* of 2 *int*, optional) – The spacing between points. If a single *int* is provided, this is applied uniformly across each dimension. If a *tuple* is provided, the spacing is applied non-uniformly as defined e.g. `(2, 3)` gives a spacing of 2 for the rows and 3 for the columns.
- **tcoords** (`(N, 2)` *ndarray*, optional) – The texture coordinates for the mesh.
- **texture** (*Image*, optional) – The texture for the mesh.

Returns **strimesh** (*TriMesh*) – A TriMesh arranged in a grid.

classmethod init_from_depth_image(*depth_image*, *tcoords=None*, *texture=None*)

Return a 3D textured triangular mesh from the given depth image. The depth image is assumed to represent height/depth values and the XY coordinates are assumed to unit spaced and represent image coordinates. This is particularly useful for visualising depth values that have been recovered from images.

The optionally passed texture will be textured mapped onto the planar surface using the correct texture coordinates for an image of the same shape as `depth_image`.

Parameters

- **depth_image** (*Image* or subclass) – A single channel image that contains depth values - as commonly returned by RGBD cameras, for example.
- **tcoords** (`(N, 2)` *ndarray*, optional) – The texture coordinates for the mesh.
- **texture** (*Image*, optional) – The texture for the mesh.

Returns **depth_cloud** (`type(cls)`) – A new 3D TriMesh with unit XY coordinates and the given depth values as Z coordinates. The trilist is constructed as in *init_2d_grid()*.

mean_edge_length(*unique=True*)

The mean length of each edge in this *TriMesh*.

Parametersunique (*bool*, optional) – If `True`, each shared edge will only be counted once towards the average. If false, shared edges will be counted twice.

Returnsmean_edge_length (`float`) – The mean length of each edge in this `TriMesh`

mean_tri_area()

The mean area of each triangle face in this `TriMesh`.

Returnsmean_tri_area (`float`) – The mean area of each triangle face in this `TriMesh`

Raises`ValueError` – If mesh is not 3D

norm(***kwargs*)

Returns the norm of this PointCloud. This is a translation and rotation invariant measure of the point cloud's intrinsic size - in other words, it is always taken around the point cloud's centre.

By default, the Frobenius norm is taken, but this can be changed by setting kwargs - see `numpy.linalg.norm` for valid options.

Returnsnorm (*float*) – The norm of this `PointCloud`

range(*boundary=0*)

The range of the extent of the PointCloud.

Parametersboundary (*float*) – A optional padding distance that is used to extend the bounds from which the range is computed. Default is `0`, no extension is performed.

Returnsrange (`(n_dims,)` *ndarray*) – The range of the `PointCloud` extent in each dimension.

rescale_texture(*minimum*, *maximum*, *per_channel=True*)

A copy of this mesh with texture linearly rescaled to fit a range.

Parameters

- **minimum** (*float*) – The minimal value of the rescaled colours
- **maximum** (*float*) – The maximal value of the rescaled colours
- **per_channel** (*boolean*, optional) – If `True`, each channel will be rescaled independently. If `False`, the scaling will be over all channels.

Returnstextured_mesh (`type(self)`) – A copy of this mesh with texture linearly rescaled to fit in the range provided.

tcoords_pixel_scaled()

Returns a `PointCloud` that is modified to be suitable for directly indexing into the pixels of the texture (e.g. for manual mapping operations). The resulting tcoords behave just like image landmarks do.

The operations that are performed are:

- Flipping the origin from bottom-left to top-left
- Scaling the tcoords by the image shape (denormalising them)
- Permuting the axis so that

Returnstcoords_scaled (`PointCloud`) – A copy of the tcoords that behave like `Image` landmarks

---

Examples

Recovering pixel values for every texture coordinate:

```
>>> texture = texturedtrimesh.texture
>>> tc_ps = texturedtrimesh.tcoords_pixel_scaled()
>>> pixel_values_at_tcs = texture.sample(tc_ps)
```

tojson()

Convert this *TriMesh* to a dictionary representation suitable for inclusion in the LJSON landmark format. Note that this enforces a simpler representation, and as such is not suitable for a permanent serialization of a *TriMesh* (to be clear, *TriMesh*'s serialized as part of a landmark set will be rebuilt as a *PointUndirectedGraph*).

Returnsjson (*dict*) – Dictionary with `points` and `connectivity` keys.

tri_areas()

The area of each triangle face.

Returnsareas (`(n_tris,)` *ndarray*) – Area of each triangle, ordered as the trilist is

Raises`ValueError` – If mesh is not 2D or 3D

tri_normals()

Compute the triangle face normals from the current set of points and triangle list. Only valid for 3D dimensional meshes.

Returnsnormals (`(n_tris, 3)` *ndarray*) – Normal at each triangle face.

Raises`ValueError` – If mesh is not 3D

unique_edge_indices()

An unordered index into points that rebuilds the unique edges of this *TriMesh*.

Note that each physical edge will only be counted once in this method (i.e. edges shared between neighbouring triangles are only counted once not twice). The ordering should be considered random.

Returnsunique_edge_indices (`(n_unique_edges, 2)` *ndarray*) – Return a point index that rebuilds all edges present in this *TriMesh* only once.

unique_edge_lengths()

The length of each edge in this *TriMesh*.

Note that each physical edge will only be counted once in this method (i.e. edges shared between neighbouring triangles are only counted once not twice). The ordering should be considered random.

Returnsedge_lengths (`(n_tris * 3, )` *ndarray*) – Scalar euclidean lengths for each edge in this *TriMesh*.

unique_edge_vectors()

An unordered vector of unique edges for the whole *TriMesh*.

Note that each physical edge will only be counted once in this method (i.e. edges shared between neighbouring triangles are only counted once not twice). The ordering should be considered random.

Returnsunique_edge_vectors (`(n_unique_edges, n_dims)` *ndarray*) – Vectors for each unique edge in this *TriMesh*.

vertex_normals()

Compute the per-vertex normals from the current set of points and triangle list. Only valid for 3D dimensional meshes.

Returnsnormals (`(n_points, 3)` *ndarray*) – Normal at each point.

Raises`ValueError` – If mesh is not 3D

with_dims(*dims*)
Return a copy of this shape with only particular dimensions retained.

Parametersdims (*valid numpy array slice*) – The slice that will be used on the dimensionality axis of the shape under transform. For example, to go from a 3D shape to a 2D one, [0, 1] could be provided or np.array([True, True, False]).

Returns*copy of self, with only the requested dims*

has_landmarks
Whether the object has landmarks.

Type*bool*

landmarks
The landmarks object.

Type*LandmarkManager*

lms
Deprecated. Maintained for compatibility, will be removed in a future version. Returns a copy of this object, which previously would have held the 'underlying' *PointCloud* subclass.

Typeself

n_channels
The number of channels of colour used (e.g. 3 for RGB).

Type*int*

n_dims
The number of dimensions in the pointcloud.

Type*int*

n_landmark_groups
The number of landmark groups on this object.

Type*int*

n_parameters
The length of the vector that this object produces.

Type*int*

n_points
The number of points in the pointcloud.

Type*int*

n_tris
The number of triangles in the triangle list.

Type*int*

Group Operations

mean_pointcloud

menpo.shape.**mean_pointcloud**(*pointclouds*)
Compute the mean of a *list* of *PointCloud* or subclass objects. The list is assumed to be homogeneous i.e all elements of the list are assumed to belong to the same point cloud subclass just as all elements are also assumed to have the same number of points and represent semantically equivalent point clouds.

Parameters`pointclouds` (*list* of `PointCloud` or subclass) – List of point cloud or subclass objects from which we want to compute the mean.

Returns`mean_pointcloud` (`PointCloud` or subclass) – The mean point cloud or subclass.

Shape Building

bounding_box

`menpo.shape.`**`bounding_box`**(*closest_to_origin*, *opposite_corner*)

Return a bounding box from two corner points as a directed graph. The the first point (0) should be nearest the origin. In the case of an image, this ordering would appear as:

```
0<--3
|   ^
|   |
v   |
1-->2
```

In the case of a pointcloud, the ordering will appear as:

```
3<--2
|   ^
|   |
v   |
0-->1
```

Parameters

- **`closest_to_origin`** ((*float*, *float*)) – Two floats representing the coordinates closest to the origin. Represented by (0) in the graph above. For an image, this will be the top left. For a pointcloud, this will be the bottom left.
- **`opposite_corner`** ((*float*, *float*)) – Two floats representing the coordinates opposite the corner closest to the origin. Represented by (2) in the graph above. For an image, this will be the bottom right. For a pointcloud, this will be the top right.

Returns`bounding_box` (`PointDirectedGraph`) – The axis aligned bounding box from the two given corners.

bounding_cuboid

`menpo.shape.`**`bounding_cuboid`**(*near_closest_to_origin*, *far_opposite_corner*)

Return a bounding cuboid from the near closest and far opposite corners as a directed graph.

Parameters

- **`near_closest_to_origin`** ((*float*, *float*, *float*)) – Three floats representing the coordinates of the near corner closest to the origin.
- **`far_opposite_corner`** ((*float*, *float*, *float*)) – Three floats representing the coordinates of the far opposite corner compared to near_closest_to_origin.

Returns`bounding_box` (`PointDirectedGraph`) – The axis aligned bounding cuboid from the two given corners.

menpo.transform

Composite Transforms

rotate_ccw_about_centre

menpo.transform.**rotate_ccw_about_centre**(*obj*, *theta*, *degrees=True*)

Return a Homogeneous Transform that implements rotating an object counter-clockwise about its centre. The given object must be transformable and must implement a method to provide the object centre.

Parameters

- **obj** (*Transformable*) – A transformable object that has the `centre` method.
- **theta** (*float*) – The angle of rotation clockwise about the origin.
- **degrees** (*bool*, optional) – If `True` theta is interpreted as degrees. If `False`, theta is interpreted as radians.

Returnstransform (*Homogeneous*) – A homogeneous transform that implements the rotation.

scale_about_centre

menpo.transform.**scale_about_centre**(*obj*, *scale*)

Return a Homogeneous Transform that implements scaling an object about its centre. The given object must be transformable and must implement a method to provide the object centre.

Parameters

- **obj** (*Transformable*) – A transformable object that has the `centre` method.
- **scale** (*float* or `(n_dims,)` *ndarray*) – The scale factor as defined in the `Scale` documentation.

Returnstransform (*Homogeneous*) – A homogeneous transform that implements the scaling.

shear_about_centre

menpo.transform.**shear_about_centre**(*obj*, *phi*, *psi*, *degrees=True*)

Return an affine transform that implements shearing (distorting) an object about its centre. The given object must be transformable and must implement a method to provide the object centre.

Parameters

- **obj** (*Transformable*) – A transformable object that has the `centre` method.
- **phi** (*float*) – The angle of shearing in the X direction.
- **psi** (*float*) – The angle of shearing in the Y direction.
- **degrees** (*bool*, optional) – If `True`, then phi and psi are interpreted as degrees. If `False` they are interpreted as radians.

Returnstransform (*Affine*) – An affine transform that implements the shearing.

Raises`ValueError` – Shearing can only be applied on 2D objects

transform_about_centre

menpo.transform.**transform_about_centre**(*obj*, *transform*)

Return a Transform that implements transforming an object about its centre. The given object must be transformable and must implement a method to provide the object centre. More precisely, the object will be translated to the origin (according to it's centre), transformed, and then translated back to it's previous position.

Parameters

- **obj** (*Transformable*) – A transformable object that has the `centre` method.
- **transform** (*ComposableTransform*) – A composable transform.

Returnstransform (*Homogeneous*) – A homogeneous transform that implements the scaling.

Homogeneous Transforms

Homogeneous

class menpo.transform.**Homogeneous**(*h_matrix*, *copy=True*, *skip_checks=False*)

Bases: *ComposableTransform*, *Vectorizable*, *VComposable*, *VInvertible*

A simple `n`-dimensional homogeneous transformation.

Adds a unit homogeneous coordinate to points, performs the dot product, re-normalizes by division by the homogeneous coordinate, and returns the result.

Can be composed with another *Homogeneous*, so long as the dimensionality matches.

Parameters

- **h_matrix** (`(n_dims + 1, n_dims + 1)` *ndarray*) – The homogeneous matrix defining this transform.
- **copy** (*bool*, optional) – If `False`, avoid copying `h_matrix`. Useful for performance.
- **skip_checks** (*bool*, optional) – If `True`, avoid sanity checks on the `h_matrix`. Useful for performance.

apply(*x*, *batch_size=None*, ***kwargs*)

Applies this transform to `x`.

If `x` is *Transformable*, `x` will be handed this transform object to transform itself non-destructively (a transformed copy of the object will be returned).

If not, `x` is assumed to be an *ndarray*. The transformation will be non-destructive, returning the transformed version.

Any `kwargs` will be passed to the specific transform `_apply()` method.

Parameters

- **x** (*Transformable* or `(n_points, n_dims)` *ndarray*) – The array or object to be transformed.
- **batch_size** (*int*, optional) – If not `None`, this determines how many items from the numpy array will be passed through the transform at a time. This is useful for operations that require large intermediate matrices to be computed.
- **kwargs** (*dict*) – Passed through to `_apply()`.

Returnstransformed (`type(x)`) – The transformed object or array

apply_inplace(**args*, ***kwargs*)

Deprecated as public supported API, use the non-mutating *apply()* instead.

For internal performance-specific uses, see *_apply_inplace()*.

as_vector(***kwargs*)

Returns a flattened representation of the object as a single vector.

Returnsvector (*(N,) ndarray*) – The core representation of the object, flattened into a single vector. Note that this is always a view back on to the original object, but is not writable.

compose_after(*transform*)

A `Transform` that represents **this** transform composed **after** the given transform:

```
c = a.compose_after(b)
c.apply(p) == a.apply(b.apply(p))
```

`a` and `b` are left unchanged.

This corresponds to the usual mathematical formalism for the compose operator, `o`.

An attempt is made to perform native composition, but will fall back to a `TransformChain` as a last resort. See `composes_with` for a description of how the mode of composition is decided.

Parameterstransform (`Transform`) – Transform to be applied **before** `self`

Returnstransform (`Transform` or `TransformChain`) – If the composition was native, a single new `Transform` will be returned. If not, a `TransformChain` is returned instead.

compose_after_inplace(*transform*)

Update `self` so that it represents **this** transform composed **after** the given transform:

```
a_orig = a.copy()
a.compose_after_inplace(b)
a.apply(p) == a_orig.apply(b.apply(p))
```

`a` is permanently altered to be the result of the composition. `b` is left unchanged.

Parameterstransform (`composes_inplace_with`) – Transform to be applied **before** `self`

Raises`ValueError` – If `transform` isn't an instance of `composes_inplace_with`

compose_before(*transform*)

A `Transform` that represents **this** transform composed **before** the given transform:

```
c = a.compose_before(b)
c.apply(p) == b.apply(a.apply(p))
```

`a` and `b` are left unchanged.

An attempt is made to perform native composition, but will fall back to a `TransformChain` as a last resort. See `composes_with` for a description of how the mode of composition is decided.

Parameterstransform (`Transform`) – Transform to be applied **after** `self`

Returnstransform (`Transform` or `TransformChain`) – If the composition was native, a single new `Transform` will be returned. If not, a `TransformChain` is returned instead.

compose_before_inplace(*transform*)

Update `self` so that it represents **this** transform composed **before** the given transform:

```
a_orig = a.copy()
a.compose_before_inplace(b)
a.apply(p) == b.apply(a_orig.apply(p))
```

`a` is permanently altered to be the result of the composition. `b` is left unchanged.

Parameters`transform` (*composes_inplace_with*) – Transform to be applied **after** `self`

Raises`ValueError` – If `transform` isn't an instance of *composes_inplace_with*

copy()

Generate an efficient copy of this object.

Note that Numpy arrays and other *Copyable* objects on `self` will be deeply copied. Dictionaries and sets will be shallow copied, and everything else will be assigned (no copy will be made).

Classes that store state other than numpy arrays and immutable types should overwrite this method to ensure all state is copied.

Returns`type(self)` – A copy of this object

from_vector(*vector*)

Build a new instance of the object from its vectorized state.

`self` is used to fill out the missing state required to rebuild a full object from it's standardized flattened state. This is the default implementation, which is a `deepcopy` of the object followed by a call to *from_vector_inplace()*. This method can be overridden for a performance benefit if desired.

Parameters`vector` (`(n_parameters,)` *ndarray*) – Flattened representation of the object.

Returns`transform` (*Homogeneous*) – An new instance of this class.

from_vector_inplace(*vector*)

Deprecated. Use the non-mutating API, *from_vector*.

For internal usage in performance-sensitive spots, see *_from_vector_inplace()*

Parameters`vector` (`(n_parameters,)` *ndarray*) – Flattened representation of this object

has_nan_values()

Tests if the vectorized form of the object contains `nan` values or not. This is particularly useful for objects with unknown values that have been mapped to `nan` values.

Returns`has_nan_values` (*bool*) – If the vectorized object contains `nan` values.

classmethod init_identity(*n_dims*)

Creates an identity matrix Homogeneous transform.

Parameters`n_dims` (*int*) – The number of dimensions.

Returns`identity` (*Homogeneous*) – The identity matrix transform.

pseudoinverse()

The pseudoinverse of the transform - that is, the transform that results from swapping *source* and *target*, or more formally, negating the transforms parameters. If the transform has a true inverse this is returned instead.

Type*Homogeneous*

pseudoinverse_vector(*vector*)

The vectorized pseudoinverse of a provided vector instance. Syntactic sugar for:

```
self.from_vector(vector).pseudoinverse().as_vector()
```

Can be much faster than the explict call as object creation can be entirely avoided in some cases.

Parametersvector ((n_parameters,) *ndarray*) – A vectorized version of `self`

Returnspseudoinverse_vector ((n_parameters,) *ndarray*) – The pseudoinverse of the vector provided

set_h_matrix(*value*, *copy=True*, *skip_checks=False*)

Deprecated Deprecated - do not use this method - you are better off just creating a new transform!

Updates `h_matrix`, optionally performing sanity checks.

Note that it won't always be possible to manually specify the `h_matrix` through this method, specifically if changing the `h_matrix` could change the nature of the transform. See *h_matrix_is_mutable* for how you can discover if the `h_matrix` is allowed to be set for a given class.

Parameters

- **value** (*ndarray*) – The new homogeneous matrix to set.
- **copy** (*bool*, optional) – If `False`, do not copy the h_matrix. Useful for performance.
- **skip_checks** (*bool*, optional) – If `True`, skip checking. Useful for performance.

Raises`NotImplementedError` – If *h_matrix_is_mutable* returns `False`.

composes_inplace_with

Homogeneous can swallow composition with any other *Homogeneous*, subclasses will have to override and be more specific.

composes_with

Any Homogeneous can compose with any other Homogeneous.

h_matrix

The homogeneous matrix defining this transform.

Type(n_dims + 1, n_dims + 1) *ndarray*

h_matrix_is_mutable

Deprecated `True` iff *set_h_matrix()* is permitted on this type of transform.

If this returns `False` calls to *set_h_matrix()* will raise a `NotImplementedError`.

Type*bool*

has_true_inverse

The pseudoinverse is an exact inverse.

Type`True`

n_dims

The dimensionality of the data the transform operates on.

Type*int*

n_dims_output

The output of the data from the transform.

Type*int*

n_parameters

The length of the vector that this object produces.

Type*int*

Affine

class menpo.transform.**Affine**(*h_matrix*, *copy=True*, *skip_checks=False*)

Bases: Homogeneous

Base class for all n-dimensional affine transformations. Provides methods to break the transform down into its constituent scale/rotation/translation, to view the homogeneous matrix equivalent, and to chain this transform with other affine transformations.

Parameters

- **h_matrix** ((n_dims + 1, n_dims + 1) *ndarray*) – The homogeneous matrix of the affine transformation.
- **copy** (*bool*, optional) – If False avoid copying h_matrix for performance.
- **skip_checks** (*bool*, optional) – If True avoid sanity checks on h_matrix for performance.

apply(*x*, *batch_size=None*, ***kwargs*)

Applies this transform to x.

If x is *Transformable*, x will be handed this transform object to transform itself non-destructively (a transformed copy of the object will be returned).

If not, x is assumed to be an *ndarray*. The transformation will be non-destructive, returning the transformed version.

Any kwargs will be passed to the specific transform _apply() method.

Parameters

- **x** (*Transformable* or (n_points, n_dims) *ndarray*) – The array or object to be transformed.
- **batch_size** (*int*, optional) – If not None, this determines how many items from the numpy array will be passed through the transform at a time. This is useful for operations that require large intermediate matrices to be computed.
- **kwargs** (*dict*) – Passed through to _apply().

Returnstransformed (type(x)) – The transformed object or array

apply_inplace(**args*, ***kwargs*)

Deprecated as public supported API, use the non-mutating *apply()* instead.

For internal performance-specific uses, see *_apply_inplace()*.

as_vector(***kwargs*)

Returns a flattened representation of the object as a single vector.

Returnsvector (*(N,) ndarray*) – The core representation of the object, flattened into a single vector. Note that this is always a view back on to the original object, but is not writable.

compose_after(*transform*)

A *Transform* that represents **this** transform composed **after** the given transform:

```
c = a.compose_after(b)
c.apply(p) == a.apply(b.apply(p))
```

a and b are left unchanged.

This corresponds to the usual mathematical formalism for the compose operator, o.

An attempt is made to perform native composition, but will fall back to a *TransformChain* as a last resort. See *composes_with* for a description of how the mode of composition is decided.

Parameters **transform** (*Transform*) – Transform to be applied **before** `self`

Returns **transform** (*Transform* or *TransformChain*) – If the composition was native, a single new *Transform* will be returned. If not, a *TransformChain* is returned instead.

compose_after_inplace(*transform*)

Update `self` so that it represents **this** transform composed **after** the given transform:

```
a_orig = a.copy()
a.compose_after_inplace(b)
a.apply(p) == a_orig.apply(b.apply(p))
```

`a` is permanently altered to be the result of the composition. `b` is left unchanged.

Parameters **transform** (*composes_inplace_with*) – Transform to be applied **before** `self`

Raises `ValueError` – If `transform` isn't an instance of *composes_inplace_with*

compose_before(*transform*)

A *Transform* that represents **this** transform composed **before** the given transform:

```
c = a.compose_before(b)
c.apply(p) == b.apply(a.apply(p))
```

`a` and `b` are left unchanged.

An attempt is made to perform native composition, but will fall back to a *TransformChain* as a last resort. See *composes_with* for a description of how the mode of composition is decided.

Parameters **transform** (*Transform*) – Transform to be applied **after** `self`

Returns **transform** (*Transform* or *TransformChain*) – If the composition was native, a single new *Transform* will be returned. If not, a *TransformChain* is returned instead.

compose_before_inplace(*transform*)

Update `self` so that it represents **this** transform composed **before** the given transform:

```
a_orig = a.copy()
a.compose_before_inplace(b)
a.apply(p) == b.apply(a_orig.apply(p))
```

`a` is permanently altered to be the result of the composition. `b` is left unchanged.

Parameters **transform** (*composes_inplace_with*) – Transform to be applied **after** `self`

Raises `ValueError` – If `transform` isn't an instance of *composes_inplace_with*

copy()

Generate an efficient copy of this object.

Note that Numpy arrays and other *Copyable* objects on `self` will be deeply copied. Dictionaries and sets will be shallow copied, and everything else will be assigned (no copy will be made).

Classes that store state other than numpy arrays and immutable types should overwrite this method to ensure all state is copied.

Returns `type(self)` – A copy of this object

decompose()

Decompose this transform into discrete Affine Transforms.

Useful for understanding the effect of a complex composite transform.

Returns

transforms (*list* of `DiscreteAffine`) – Equivalent to this affine transform, such that

```
reduce(lambda x, y: x.chain(y), self.decompose()) == self
```

from_vector(*vector*)

Build a new instance of the object from its vectorized state.

`self` is used to fill out the missing state required to rebuild a full object from it's standardized flattened state. This is the default implementation, which is a `deepcopy` of the object followed by a call to `from_vector_inplace()`. This method can be overridden for a performance benefit if desired.

Parametersvector (`(n_parameters,)` *ndarray*) – Flattened representation of the object.

Returnstransform (`Homogeneous`) – An new instance of this class.

from_vector_inplace(*vector*)

Deprecated. Use the non-mutating API, `from_vector`.

For internal usage in performance-sensitive spots, see *_from_vector_inplace()*

Parametersvector (`(n_parameters,)` *ndarray*) – Flattened representation of this object

has_nan_values()

Tests if the vectorized form of the object contains `nan` values or not. This is particularly useful for objects with unknown values that have been mapped to `nan` values.

Returnshas_nan_values (*bool*) – If the vectorized object contains `nan` values.

classmethod init_from_2d_shear(*phi*, *psi*, *degrees=True*)

Convenience constructor for 2D shear transformations about the origin.

Parameters

- **phi** (*float*) – The angle of shearing in the X direction.
- **psi** (*float*) – The angle of shearing in the Y direction.
- **degrees** (*bool*, optional) – If `True` phi and psi are interpreted as degrees. If `False`, phi and psi are interpreted as radians.

Returnsshear_transform (`Affine`) – A 2D shear transform.

classmethod init_identity(*n_dims*)

Creates an identity matrix Affine transform.

Parametersn_dims (*int*) – The number of dimensions.

Returnsidentity (`Affine`) – The identity matrix transform.

pseudoinverse()

The pseudoinverse of the transform - that is, the transform that results from swapping *source* and *target*, or more formally, negating the transforms parameters. If the transform has a true inverse this is returned instead.

Type`Homogeneous`

pseudoinverse_vector(*vector*)

The vectorized pseudoinverse of a provided vector instance. Syntactic sugar for:

```
self.from_vector(vector).pseudoinverse().as_vector()
```

Can be much faster than the explict call as object creation can be entirely avoided in some cases.

Parametersvector ((n_parameters,) *ndarray*) – A vectorized version of `self`

Returnspseudoinverse_vector ((n_parameters,) *ndarray*) – The pseudoinverse of the vector provided

set_h_matrix(*value*, *copy=True*, *skip_checks=False*)

Deprecated Deprecated - do not use this method - you are better off just creating a new transform!

Updates `h_matrix`, optionally performing sanity checks.

Note that it won't always be possible to manually specify the `h_matrix` through this method, specifically if changing the `h_matrix` could change the nature of the transform. See *h_matrix_is_mutable* for how you can discover if the `h_matrix` is allowed to be set for a given class.

Parameters

- **value** (*ndarray*) – The new homogeneous matrix to set.
- **copy** (*bool*, optional) – If `False`, do not copy the h_matrix. Useful for performance.
- **skip_checks** (*bool*, optional) – If `True`, skip checking. Useful for performance.

Raises`NotImplementedError` – If *h_matrix_is_mutable* returns `False`.

composes_inplace_with

Affine can swallow composition with any other *Affine*.

composes_with

Any Homogeneous can compose with any other Homogeneous.

h_matrix

The homogeneous matrix defining this transform.

Type (n_dims + 1, n_dims + 1) *ndarray*

h_matrix_is_mutable

Deprecated `True` iff *set_h_matrix()* is permitted on this type of transform.

If this returns `False` calls to *set_h_matrix()* will raise a `NotImplementedError`.

Type*bool*

has_true_inverse

The pseudoinverse is an exact inverse.

Type`True`

linear_component

The linear component of this affine transform.

Type (n_dims, n_dims) *ndarray*

n_dims

The dimensionality of the data the transform operates on.

Type*int*

n_dims_output

The output of the data from the transform.

Type*int*

n_parameters

`n_dims * (n_dims + 1)` parameters - every element of the matrix but the homogeneous part.

Type int

Examples

2D Affine: 6 parameters:

```
[p1, p3, p5]
[p2, p4, p6]
```

3D Affine: 12 parameters:

```
[p1, p4, p7, p10]
[p2, p5, p8, p11]
[p3, p6, p9, p12]
```

translation_component

The translation component of this affine transform.

Type `(n_dims,)` *ndarray*

Similarity

class `menpo.transform.`**`Similarity`**(*h_matrix*, *copy=True*, *skip_checks=False*)

Bases: `Affine`

Specialist version of an `Affine` that is guaranteed to be a Similarity transform.

Parameters

- **h_matrix** (`(n_dims + 1, n_dims + 1)` *ndarray*) – The homogeneous matrix of the affine transformation.
- **copy** (*bool*, optional) – If `False` avoid copying `h_matrix` for performance.
- **skip_checks** (*bool*, optional) – If `True` avoid sanity checks on `h_matrix` for performance.

apply(*x*, *batch_size=None*, ***kwargs*)

Applies this transform to `x`.

If `x` is `Transformable`, `x` will be handed this transform object to transform itself non-destructively (a transformed copy of the object will be returned).

If not, `x` is assumed to be an *ndarray*. The transformation will be non-destructive, returning the transformed version.

Any `kwargs` will be passed to the specific transform `_apply()` method.

Parameters

- **x** (`Transformable` or `(n_points, n_dims)` *ndarray*) – The array or object to be transformed.
- **batch_size** (*int*, optional) – If not `None`, this determines how many items from the numpy array will be passed through the transform at a time. This is useful for operations that require large intermediate matrices to be computed.
- **kwargs** (*dict*) – Passed through to `_apply()`.

Returnstransformed (`type(x)`) – The transformed object or array

apply_inplace(**args*, ***kwargs*)

Deprecated as public supported API, use the non-mutating *apply()* instead.

For internal performance-specific uses, see *_apply_inplace()*.

as_vector(***kwargs*)

Returns a flattened representation of the object as a single vector.

Returnsvector (*(N,) ndarray*) – The core representation of the object, flattened into a single vector. Note that this is always a view back on to the original object, but is not writable.

compose_after(*transform*)

A `Transform` that represents **this** transform composed **after** the given transform:

```
c = a.compose_after(b)
c.apply(p) == a.apply(b.apply(p))
```

`a` and `b` are left unchanged.

This corresponds to the usual mathematical formalism for the compose operator, `o`.

An attempt is made to perform native composition, but will fall back to a `TransformChain` as a last resort. See `composes_with` for a description of how the mode of composition is decided.

Parameterstransform (`Transform`) – Transform to be applied **before** `self`

Returnstransform (`Transform` or `TransformChain`) – If the composition was native, a single new `Transform` will be returned. If not, a `TransformChain` is returned instead.

compose_after_inplace(*transform*)

Update `self` so that it represents **this** transform composed **after** the given transform:

```
a_orig = a.copy()
a.compose_after_inplace(b)
a.apply(p) == a_orig.apply(b.apply(p))
```

`a` is permanently altered to be the result of the composition. `b` is left unchanged.

Parameterstransform (`composes_inplace_with`) – Transform to be applied **before** `self`

Raises`ValueError` – If `transform` isn't an instance of `composes_inplace_with`

compose_before(*transform*)

A `Transform` that represents **this** transform composed **before** the given transform:

```
c = a.compose_before(b)
c.apply(p) == b.apply(a.apply(p))
```

`a` and `b` are left unchanged.

An attempt is made to perform native composition, but will fall back to a `TransformChain` as a last resort. See `composes_with` for a description of how the mode of composition is decided.

Parameterstransform (`Transform`) – Transform to be applied **after** `self`

Returnstransform (`Transform` or `TransformChain`) – If the composition was native, a single new `Transform` will be returned. If not, a `TransformChain` is returned instead.

compose_before_inplace(*transform*)

Update `self` so that it represents **this** transform composed **before** the given transform:

```
a_orig = a.copy()
a.compose_before_inplace(b)
a.apply(p) == b.apply(a_orig.apply(p))
```

`a` is permanently altered to be the result of the composition. `b` is left unchanged.

Parameters`transform` (*composes_inplace_with*) – Transform to be applied **after** `self`

Raises`ValueError` – If `transform` isn't an instance of *composes_inplace_with*

copy()

Generate an efficient copy of this object.

Note that Numpy arrays and other *Copyable* objects on `self` will be deeply copied. Dictionaries and sets will be shallow copied, and everything else will be assigned (no copy will be made).

Classes that store state other than numpy arrays and immutable types should overwrite this method to ensure all state is copied.

Returns`type(self)` – A copy of this object

decompose()

Decompose this transform into discrete Affine Transforms.

Useful for understanding the effect of a complex composite transform.

Returns

transforms (*list* of `DiscreteAffine`) – Equivalent to this affine transform, such that

```
reduce(lambda x, y: x.chain(y), self.decompose()) == self
```

from_vector(*vector*)

Build a new instance of the object from its vectorized state.

`self` is used to fill out the missing state required to rebuild a full object from it's standardized flattened state. This is the default implementation, which is a `deepcopy` of the object followed by a call to *from_vector_inplace()*. This method can be overridden for a performance benefit if desired.

Parameters`vector` (`(n_parameters,)` *ndarray*) – Flattened representation of the object.

Returns`transform` (*Homogeneous*) – An new instance of this class.

from_vector_inplace(*vector*)

Deprecated. Use the non-mutating API, *from_vector*.

For internal usage in performance-sensitive spots, see *_from_vector_inplace()*

Parameters`vector` (`(n_parameters,)` *ndarray*) – Flattened representation of this object

has_nan_values()

Tests if the vectorized form of the object contains `nan` values or not. This is particularly useful for objects with unknown values that have been mapped to `nan` values.

Returns`has_nan_values` (*bool*) – If the vectorized object contains `nan` values.

init_from_2d_shear(*phi*, *psi*, *degrees=True*)

Convenience constructor for 2D shear transformations about the origin.

Parameters

- **phi** (*float*) – The angle of shearing in the X direction.
- **psi** (*float*) – The angle of shearing in the Y direction.

- **degrees** (*bool*, optional) – If `True` phi and psi are interpreted as degrees. If `False`, phi and psi are interpreted as radians.

Returnsshear_transform (*Affine*) – A 2D shear transform.

classmethod init_identity(*n_dims*)

Creates an identity transform.

Parametersn_dims (*int*) – The number of dimensions.

Returnsidentity (*Similarity*) – The identity matrix transform.

pseudoinverse()

The pseudoinverse of the transform - that is, the transform that results from swapping *source* and *target*, or more formally, negating the transforms parameters. If the transform has a true inverse this is returned instead.

Type*Homogeneous*

pseudoinverse_vector(*vector*)

The vectorized pseudoinverse of a provided vector instance. Syntactic sugar for:

```
self.from_vector(vector).pseudoinverse().as_vector()
```

Can be much faster than the explict call as object creation can be entirely avoided in some cases.

Parametersvector ((n_parameters,) *ndarray*) – A vectorized version of `self`

Returnspseudoinverse_vector ((n_parameters,) *ndarray*) – The pseudoinverse of the vector provided

set_h_matrix(*value*, *copy=True*, *skip_checks=False*)

Deprecated Deprecated - do not use this method - you are better off just creating a new transform!

Updates `h_matrix`, optionally performing sanity checks.

Note that it won't always be possible to manually specify the `h_matrix` through this method, specifically if changing the `h_matrix` could change the nature of the transform. See *h_matrix_is_mutable* for how you can discover if the `h_matrix` is allowed to be set for a given class.

Parameters

- **value** (*ndarray*) – The new homogeneous matrix to set.
- **copy** (*bool*, optional) – If `False`, do not copy the h_matrix. Useful for performance.
- **skip_checks** (*bool*, optional) – If `True`, skip checking. Useful for performance.

Raises`NotImplementedError` – If *h_matrix_is_mutable* returns `False`.

composes_inplace_with

Affine can swallow composition with any other *Affine*.

composes_with

Any Homogeneous can compose with any other Homogeneous.

h_matrix

The homogeneous matrix defining this transform.

Type(n_dims + 1, n_dims + 1) *ndarray*

h_matrix_is_mutable

Deprecated `True` iff *set_h_matrix()* is permitted on this type of transform.

If this returns `False` calls to *set_h_matrix()* will raise a `NotImplementedError`.

Type *bool*

has_true_inverse
The pseudoinverse is an exact inverse.

Type `True`

linear_component
The linear component of this affine transform.

Type `(n_dims, n_dims)` *ndarray*

n_dims
The dimensionality of the data the transform operates on.

Type *int*

n_dims_output
The output of the data from the transform.

Type *int*

n_parameters
Number of parameters of Similarity

2D Similarity - 4 parameters

```
[(1 + a), -b,      tx]
[b,       (1 + a), ty]
```

3D Similarity: Currently not supported

Returns **n_parameters** (*int*) – The transform parameters

Raises *DimensionalityError, NotImplementedError* – Only 2D transforms are supported.

translation_component
The translation component of this affine transform.

Type `(n_dims,)` *ndarray*

Rotation

class `menpo.transform.`**`Rotation`**(*rotation_matrix*, *skip_checks=False*)
Bases: `DiscreteAffine`, `Similarity`

Abstract *n_dims* rotation transform.

Parameters

- **rotation_matrix** (`(n_dims, n_dims)` *ndarray*) – A valid, square rotation matrix
- **skip_checks** (*bool*, optional) – If `True` avoid sanity checks on `rotation_matrix` for performance.

apply(*x*, *batch_size=None*, ***kwargs*)
Applies this transform to `x`.

If `x` is `Transformable`, `x` will be handed this transform object to transform itself non-destructively (a transformed copy of the object will be returned).

If not, `x` is assumed to be an *ndarray*. The transformation will be non-destructive, returning the transformed version.

Any `kwargs` will be passed to the specific transform `_apply()` method.

Parameters

- **x** (*Transformable* or `(n_points, n_dims)` *ndarray*) – The array or object to be transformed.
- **batch_size** (*int*, optional) – If not `None`, this determines how many items from the numpy array will be passed through the transform at a time. This is useful for operations that require large intermediate matrices to be computed.
- **kwargs** (*dict*) – Passed through to `_apply()`.

Returnstransformed (`type(x)`) – The transformed object or array

apply_inplace(**args*, ***kwargs*)

Deprecated as public supported API, use the non-mutating *apply()* instead.

For internal performance-specific uses, see *_apply_inplace()*.

as_vector(***kwargs*)

Returns a flattened representation of the object as a single vector.

Returnsvector (*(N,) ndarray*) – The core representation of the object, flattened into a single vector. Note that this is always a view back on to the original object, but is not writable.

axis_and_angle_of_rotation()

Abstract method for computing the axis and angle of rotation.

Returns

- **axis** (`(n_dims,)` *ndarray*) – The unit vector representing the axis of rotation
- **angle_of_rotation** (*float*) – The angle in radians of the rotation about the axis. The angle is signed in a right handed sense.

compose_after(*transform*)

A *Transform* that represents **this** transform composed **after** the given transform:

```
c = a.compose_after(b)
c.apply(p) == a.apply(b.apply(p))
```

`a` and `b` are left unchanged.

This corresponds to the usual mathematical formalism for the compose operator, `o`.

An attempt is made to perform native composition, but will fall back to a *TransformChain* as a last resort. See *composes_with* for a description of how the mode of composition is decided.

Parameterstransform (*Transform*) – Transform to be applied **before** `self`

Returnstransform (*Transform* or *TransformChain*) – If the composition was native, a single new *Transform* will be returned. If not, a *TransformChain* is returned instead.

compose_after_inplace(*transform*)

Update `self` so that it represents **this** transform composed **after** the given transform:

```
a_orig = a.copy()
a.compose_after_inplace(b)
a.apply(p) == a_orig.apply(b.apply(p))
```

`a` is permanently altered to be the result of the composition. `b` is left unchanged.

Parameterstransform (*composes_inplace_with*) – Transform to be applied **before** `self`

Raises`ValueError` – If `transform` isn't an instance of *composes_inplace_with*

compose_before(*transform*)

A `Transform` that represents **this** transform composed **before** the given transform:

```
c = a.compose_before(b)
c.apply(p) == b.apply(a.apply(p))
```

`a` and `b` are left unchanged.

An attempt is made to perform native composition, but will fall back to a `TransformChain` as a last resort. See `composes_with` for a description of how the mode of composition is decided.

Parameters`transform` (`Transform`) – Transform to be applied **after** `self`

Returns`transform` (`Transform` or `TransformChain`) – If the composition was native, a single new `Transform` will be returned. If not, a `TransformChain` is returned instead.

compose_before_inplace(*transform*)

Update `self` so that it represents **this** transform composed **before** the given transform:

```
a_orig = a.copy()
a.compose_before_inplace(b)
a.apply(p) == b.apply(a_orig.apply(p))
```

`a` is permanently altered to be the result of the composition. `b` is left unchanged.

Parameters`transform` (`composes_inplace_with`) – Transform to be applied **after** `self`

Raises`ValueError` – If `transform` isn't an instance of `composes_inplace_with`

copy()

Generate an efficient copy of this object.

Note that Numpy arrays and other `Copyable` objects on `self` will be deeply copied. Dictionaries and sets will be shallow copied, and everything else will be assigned (no copy will be made).

Classes that store state other than numpy arrays and immutable types should overwrite this method to ensure all state is copied.

Returns`type(self)` – A copy of this object

decompose()

A `DiscreteAffine` is already maximally decomposed - return a copy of self in a *list*.

Returns`transform` (`DiscreteAffine`) – Deep copy of *self*.

from_vector(*vector*)

Build a new instance of the object from its vectorized state.

`self` is used to fill out the missing state required to rebuild a full object from it's standardized flattened state. This is the default implementation, which is a `deepcopy` of the object followed by a call to `from_vector_inplace()`. This method can be overridden for a performance benefit if desired.

Parameters`vector` (`(n_parameters,)` *ndarray*) – Flattened representation of the object.

Returns`transform` (`Homogeneous`) – An new instance of this class.

from_vector_inplace(*vector*)

Deprecated. Use the non-mutating API, `from_vector`.

For internal usage in performance-sensitive spots, see *_from_vector_inplace()*

Parameters`vector` (`(n_parameters,)` *ndarray*) – Flattened representation of this object

has_nan_values()

Tests if the vectorized form of the object contains `nan` values or not. This is particularly useful for objects with unknown values that have been mapped to `nan` values.

Returnshas_nan_values (*bool*) – If the vectorized object contains `nan` values.

classmethod **init_3d_from_quaternion**(*q*)

Convenience constructor for 3D rotations based on quaternion parameters.

Parametersq ((4,) *ndarray*) – The quaternion parameters.

Returnsrotation (`Rotation`) – A 3D rotation transform.

classmethod **init_from_2d_ccw_angle**(*theta*, *degrees=True*)

Convenience constructor for 2D CCW rotations about the origin.

Parameters

- **theta** (*float*) – The angle of rotation about the origin
- **degrees** (*bool*, optional) – If `True` theta is interpreted as a degree. If `False`, theta is interpreted as radians.

Returnsrotation (`Rotation`) – A 2D rotation transform.

init_from_2d_shear(*phi*, *psi*, *degrees=True*)

Convenience constructor for 2D shear transformations about the origin.

Parameters

- **phi** (*float*) – The angle of shearing in the X direction.
- **psi** (*float*) – The angle of shearing in the Y direction.
- **degrees** (*bool*, optional) – If `True` phi and psi are interpreted as degrees. If `False`, phi and psi are interpreted as radians.

Returnsshear_transform (`Affine`) – A 2D shear transform.

classmethod **init_identity**(*n_dims*)

Creates an identity transform.

Parametersn_dims (*int*) – The number of dimensions.

Returnsidentity (`Rotation`) – The identity matrix transform.

pseudoinverse()

The inverse rotation matrix.

Type`Rotation`

pseudoinverse_vector(*vector*)

The vectorized pseudoinverse of a provided vector instance. Syntactic sugar for:

```
self.from_vector(vector).pseudoinverse().as_vector()
```

Can be much faster than the explict call as object creation can be entirely avoided in some cases.

Parametersvector ((n_parameters,) *ndarray*) – A vectorized version of `self`

Returnspseudoinverse_vector ((n_parameters,) *ndarray*) – The pseudoinverse of the vector provided

set_h_matrix(*value*, *copy=True*, *skip_checks=False*)

Deprecated Deprecated - do not use this method - you are better off just creating a new transform!

Updates `h_matrix`, optionally performing sanity checks.

Note that it won't always be possible to manually specify the `h_matrix` through this method, specifically if changing the `h_matrix` could change the nature of the transform. See *h_matrix_is_mutable* for how you can discover if the `h_matrix` is allowed to be set for a given class.

Parameters

- **value** (*ndarray*) – The new homogeneous matrix to set.
- **copy** (*bool*, optional) – If `False`, do not copy the h_matrix. Useful for performance.
- **skip_checks** (*bool*, optional) – If `True`, skip checking. Useful for performance.

Raises `NotImplementedError` – If *h_matrix_is_mutable* returns `False`.

set_rotation_matrix(*value*, *skip_checks=False*)

Sets the rotation matrix.

Parameters

- **value** (`(n_dims, n_dims)` *ndarray*) – The new rotation matrix.
- **skip_checks** (*bool*, optional) – If `True` avoid sanity checks on `value` for performance.

composes_inplace_with

Rotation can swallow composition with any other *Rotation*.

composes_with

Any Homogeneous can compose with any other Homogeneous.

h_matrix

The homogeneous matrix defining this transform.

Type `(n_dims + 1, n_dims + 1)` *ndarray*

h_matrix_is_mutable

Deprecated `True` iff *set_h_matrix()* is permitted on this type of transform.

If this returns `False` calls to *set_h_matrix()* will raise a `NotImplementedError`.

Type *bool*

has_true_inverse

The pseudoinverse is an exact inverse.

Type `True`

linear_component

The linear component of this affine transform.

Type `(n_dims, n_dims)` *ndarray*

n_dims

The dimensionality of the data the transform operates on.

Type *int*

n_dims_output

The output of the data from the transform.

Type *int*

n_parameters

Number of parameters of Rotation. Only 3D rotations are currently supported.

Returns **n_parameters** (*int*) – The transform parameters. Only 3D rotations are currently supported which are parametrized with quaternions.

Raises*DimensionalityError, NotImplementedError* – Non-3D Rotations are not yet vectorizable

rotation_matrix
The rotation matrix.

Type `(n_dims, n_dims)` *ndarray*

translation_component
The translation component of this affine transform.

Type `(n_dims,)` *ndarray*

Translation

class `menpo.transform.`**`Translation`**(*translation*, *skip_checks=False*)
Bases: `DiscreteAffine`, `Similarity`

An `n_dims`-dimensional translation transform.

Parameters

- **translation** (`(n_dims,)` *ndarray*) – The translation in each axis.
- **skip_checks** (*bool*, optional) – If `True` avoid sanity checks on `h_matrix` for performance.

apply(*x*, *batch_size=None*, ***kwargs*)
Applies this transform to `x`.

If `x` is `Transformable`, `x` will be handed this transform object to transform itself non-destructively (a transformed copy of the object will be returned).

If not, `x` is assumed to be an *ndarray*. The transformation will be non-destructive, returning the transformed version.

Any `kwargs` will be passed to the specific transform `_apply()` method.

Parameters

- **x** (`Transformable` or `(n_points, n_dims)` *ndarray*) – The array or object to be transformed.
- **batch_size** (*int*, optional) – If not `None`, this determines how many items from the numpy array will be passed through the transform at a time. This is useful for operations that require large intermediate matrices to be computed.
- **kwargs** (*dict*) – Passed through to `_apply()`.

Returnstransformed (`type(x)`) – The transformed object or array

apply_inplace(**args*, ***kwargs*)
Deprecated as public supported API, use the non-mutating *apply()* instead.

For internal performance-specific uses, see *_apply_inplace()*.

as_vector(***kwargs*)
Returns a flattened representation of the object as a single vector.

Returnsvector (*(N,) ndarray*) – The core representation of the object, flattened into a single vector. Note that this is always a view back on to the original object, but is not writable.

compose_after(*transform*)
A `Transform` that represents **this** transform composed **after** the given transform:

```
c = a.compose_after(b)
c.apply(p) == a.apply(b.apply(p))
```

a and b are left unchanged.

This corresponds to the usual mathematical formalism for the compose operator, o.

An attempt is made to perform native composition, but will fall back to a *TransformChain* as a last resort. See *composes_with* for a description of how the mode of composition is decided.

Parameters **transform** (*Transform*) – Transform to be applied **before** self

Returns **transform** (*Transform* or *TransformChain*) – If the composition was native, a single new *Transform* will be returned. If not, a *TransformChain* is returned instead.

compose_after_inplace(*transform*)

Update self so that it represents **this** transform composed **after** the given transform:

```
a_orig = a.copy()
a.compose_after_inplace(b)
a.apply(p) == a_orig.apply(b.apply(p))
```

a is permanently altered to be the result of the composition. b is left unchanged.

Parameters **transform** (*composes_inplace_with*) – Transform to be applied **before** self

Raises ValueError – If transform isn't an instance of *composes_inplace_with*

compose_before(*transform*)

A *Transform* that represents **this** transform composed **before** the given transform:

```
c = a.compose_before(b)
c.apply(p) == b.apply(a.apply(p))
```

a and b are left unchanged.

An attempt is made to perform native composition, but will fall back to a *TransformChain* as a last resort. See *composes_with* for a description of how the mode of composition is decided.

Parameters **transform** (*Transform*) – Transform to be applied **after** self

Returns **transform** (*Transform* or *TransformChain*) – If the composition was native, a single new *Transform* will be returned. If not, a *TransformChain* is returned instead.

compose_before_inplace(*transform*)

Update self so that it represents **this** transform composed **before** the given transform:

```
a_orig = a.copy()
a.compose_before_inplace(b)
a.apply(p) == b.apply(a_orig.apply(p))
```

a is permanently altered to be the result of the composition. b is left unchanged.

Parameters **transform** (*composes_inplace_with*) – Transform to be applied **after** self

Raises ValueError – If transform isn't an instance of *composes_inplace_with*

copy()

Generate an efficient copy of this object.

Note that Numpy arrays and other `Copyable` objects on `self` will be deeply copied. Dictionaries and sets will be shallow copied, and everything else will be assigned (no copy will be made).

Classes that store state other than numpy arrays and immutable types should overwrite this method to ensure all state is copied.

Returns `type(self)` – A copy of this object

decompose()

A `DiscreteAffine` is already maximally decomposed - return a copy of self in a *list*.

Returns **transform** (`DiscreteAffine`) – Deep copy of *self*.

from_vector(*vector*)

Build a new instance of the object from its vectorized state.

`self` is used to fill out the missing state required to rebuild a full object from it's standardized flattened state. This is the default implementation, which is a `deepcopy` of the object followed by a call to `from_vector_inplace()`. This method can be overridden for a performance benefit if desired.

Parameters **vector** (`(n_parameters,)` *ndarray*) – Flattened representation of the object.

Returns **transform** (`Homogeneous`) – An new instance of this class.

from_vector_inplace(*vector*)

Deprecated. Use the non-mutating API, `from_vector`.

For internal usage in performance-sensitive spots, see *_from_vector_inplace()*

Parameters **vector** (`(n_parameters,)` *ndarray*) – Flattened representation of this object

has_nan_values()

Tests if the vectorized form of the object contains `nan` values or not. This is particularly useful for objects with unknown values that have been mapped to `nan` values.

Returns **has_nan_values** (*bool*) – If the vectorized object contains `nan` values.

init_from_2d_shear(*phi*, *psi*, *degrees=True*)

Convenience constructor for 2D shear transformations about the origin.

Parameters

- **phi** (*float*) – The angle of shearing in the X direction.
- **psi** (*float*) – The angle of shearing in the Y direction.
- **degrees** (*bool*, optional) – If `True` phi and psi are interpreted as degrees. If `False`, phi and psi are interpreted as radians.

Returns **shear_transform** (`Affine`) – A 2D shear transform.

classmethod init_identity(*n_dims*)

Creates an identity transform.

Parameters **n_dims** (*int*) – The number of dimensions.

Returns **identity** (`Translation`) – The identity matrix transform.

pseudoinverse()

The inverse translation (negated).

Type `Translation`

pseudoinverse_vector(*vector*)

The vectorized pseudoinverse of a provided vector instance. Syntactic sugar for:

```
self.from_vector(vector).pseudoinverse().as_vector()
```

Can be much faster than the explict call as object creation can be entirely avoided in some cases.

Parameters
vector ((n_parameters,) *ndarray*) – A vectorized version of `self`

Returns
pseudoinverse_vector ((n_parameters,) *ndarray*) – The pseudoinverse of the vector provided

set_h_matrix(*value*, *copy=True*, *skip_checks=False*)

Deprecated Deprecated - do not use this method - you are better off just creating a new transform!

Updates `h_matrix`, optionally performing sanity checks.

Note that it won't always be possible to manually specify the `h_matrix` through this method, specifically if changing the `h_matrix` could change the nature of the transform. See *h_matrix_is_mutable* for how you can discover if the `h_matrix` is allowed to be set for a given class.

Parameters

- **value** (*ndarray*) – The new homogeneous matrix to set.
- **copy** (*bool*, optional) – If `False`, do not copy the h_matrix. Useful for performance.
- **skip_checks** (*bool*, optional) – If `True`, skip checking. Useful for performance.

Raises `NotImplementedError` – If *h_matrix_is_mutable* returns `False`.

composes_inplace_with

Affine can swallow composition with any other *Affine*.

composes_with

Any Homogeneous can compose with any other Homogeneous.

h_matrix

The homogeneous matrix defining this transform.

Type (n_dims + 1, n_dims + 1) *ndarray*

h_matrix_is_mutable

Deprecated `True` iff *set_h_matrix()* is permitted on this type of transform.

If this returns `False` calls to *set_h_matrix()* will raise a `NotImplementedError`.

Type *bool*

has_true_inverse

The pseudoinverse is an exact inverse.

Type `True`

linear_component

The linear component of this affine transform.

Type (n_dims, n_dims) *ndarray*

n_dims

The dimensionality of the data the transform operates on.

Type *int*

n_dims_output

The output of the data from the transform.

Type *int*

n_parameters
The number of parameters – n_dims

Type*int*

translation_component
The translation component of this affine transform.

Type (n_dims,) *ndarray*

Scale

menpo.transform.**Scale**(*scale_factor*, *n_dims=None*)
Factory function for producing Scale transforms. Zero scale factors are not permitted.

A *UniformScale* will be produced if:

- A *float* scale_factor and a n_dims *kwarg* are provided
- A *ndarray* scale_factor with shape (n_dims,) is provided with all elements being the same

A *NonUniformScale* will be provided if:

- A *ndarray* scale_factor with shape (n_dims,) is provided with at least two differing scale factors.

Parameters

- **scale_factor** (*float* or (n_dims,) *ndarray*) – Scale for each axis.
- **n_dims** (*int*, optional) – The dimensionality of the output transform.

Returnsscale (*UniformScale* or *NonUniformScale*) – The correct type of scale

RaisesValueError – If any of the scale factors is zero

UniformScale

class menpo.transform.**UniformScale**(*scale*, *n_dims*, *skip_checks=False*)
Bases: *DiscreteAffine*, Similarity

An abstract similarity scale transform, with a single scale component applied to all dimensions. This is abstracted out to remove unnecessary code duplication.

Parameters

- **scale** ((n_dims,) *ndarray*) – A scale for each axis.
- **n_dims** (*int*) – The number of dimensions
- **skip_checks** (*bool*, optional) – If True avoid sanity checks on h_matrix for performance.

apply(*x*, *batch_size=None*, ***kwargs*)
Applies this transform to x.

If x is *Transformable*, x will be handed this transform object to transform itself non-destructively (a transformed copy of the object will be returned).

If not, x is assumed to be an *ndarray*. The transformation will be non-destructive, returning the transformed version.

Any kwargs will be passed to the specific transform _apply() method.

Parameters

- **x** (*Transformable* or `(n_points, n_dims)` *ndarray*) – The array or object to be transformed.
- **batch_size** (*int*, optional) – If not `None`, this determines how many items from the numpy array will be passed through the transform at a time. This is useful for operations that require large intermediate matrices to be computed.
- **kwargs** (*dict*) – Passed through to `_apply()`.

Returnstransformed (`type(x)`) – The transformed object or array

apply_inplace(**args*, ***kwargs*)

Deprecated as public supported API, use the non-mutating *apply()* instead.

For internal performance-specific uses, see *_apply_inplace()*.

as_vector(***kwargs*)

Returns a flattened representation of the object as a single vector.

Returnsvector (*(N,) ndarray*) – The core representation of the object, flattened into a single vector. Note that this is always a view back on to the original object, but is not writable.

compose_after(*transform*)

A *Transform* that represents **this** transform composed **after** the given transform:

```
c = a.compose_after(b)
c.apply(p) == a.apply(b.apply(p))
```

`a` and `b` are left unchanged.

This corresponds to the usual mathematical formalism for the compose operator, `o`.

An attempt is made to perform native composition, but will fall back to a *TransformChain* as a last resort. See *composes_with* for a description of how the mode of composition is decided.

Parameterstransform (*Transform*) – Transform to be applied **before** `self`

Returnstransform (*Transform* or *TransformChain*) – If the composition was native, a single new *Transform* will be returned. If not, a *TransformChain* is returned instead.

compose_after_inplace(*transform*)

Update `self` so that it represents **this** transform composed **after** the given transform:

```
a_orig = a.copy()
a.compose_after_inplace(b)
a.apply(p) == a_orig.apply(b.apply(p))
```

`a` is permanently altered to be the result of the composition. `b` is left unchanged.

Parameterstransform (*composes_inplace_with*) – Transform to be applied **before** `self`

Raises`ValueError` – If `transform` isn't an instance of *composes_inplace_with*

compose_before(*transform*)

A *Transform* that represents **this** transform composed **before** the given transform:

```
c = a.compose_before(b)
c.apply(p) == b.apply(a.apply(p))
```

`a` and `b` are left unchanged.

An attempt is made to perform native composition, but will fall back to a *TransformChain* as a last resort. See *composes_with* for a description of how the mode of composition is decided.

Parameters`transform` (*Transform*) – Transform to be applied **after** `self`

Returns`transform` (*Transform* or *TransformChain*) – If the composition was native, a single new *Transform* will be returned. If not, a *TransformChain* is returned instead.

compose_before_inplace(*transform*)

Update `self` so that it represents **this** transform composed **before** the given transform:

```
a_orig = a.copy()
a.compose_before_inplace(b)
a.apply(p) == b.apply(a_orig.apply(p))
```

`a` is permanently altered to be the result of the composition. `b` is left unchanged.

Parameters`transform` (*composes_inplace_with*) – Transform to be applied **after** `self`

Raises`ValueError` – If `transform` isn't an instance of *composes_inplace_with*

copy()

Generate an efficient copy of this object.

Note that Numpy arrays and other *Copyable* objects on `self` will be deeply copied. Dictionaries and sets will be shallow copied, and everything else will be assigned (no copy will be made).

Classes that store state other than numpy arrays and immutable types should overwrite this method to ensure all state is copied.

Returns`type(self)` – A copy of this object

decompose()

A `DiscreteAffine` is already maximally decomposed - return a copy of self in a *list*.

Returns`transform` (`DiscreteAffine`) – Deep copy of *self*.

from_vector(*vector*)

Build a new instance of the object from its vectorized state.

`self` is used to fill out the missing state required to rebuild a full object from it's standardized flattened state. This is the default implementation, which is a `deepcopy` of the object followed by a call to *from_vector_inplace()*. This method can be overridden for a performance benefit if desired.

Parameters`vector` (`(n_parameters,)` *ndarray*) – Flattened representation of the object.

Returns`transform` (*Homogeneous*) – An new instance of this class.

from_vector_inplace(*vector*)

Deprecated. Use the non-mutating API, *from_vector*.

For internal usage in performance-sensitive spots, see *_from_vector_inplace()*

Parameters`vector` (`(n_parameters,)` *ndarray*) – Flattened representation of this object

has_nan_values()

Tests if the vectorized form of the object contains `nan` values or not. This is particularly useful for objects with unknown values that have been mapped to `nan` values.

Returns`has_nan_values` (*bool*) – If the vectorized object contains `nan` values.

init_from_2d_shear(*phi*, *psi*, *degrees=True*)

Convenience constructor for 2D shear transformations about the origin.

Parameters

- **phi** (*float*) – The angle of shearing in the X direction.

- **psi** (*float*) – The angle of shearing in the Y direction.
- **degrees** (*bool*, optional) – If `True` phi and psi are interpreted as degrees. If `False`, phi and psi are interpreted as radians.

Returns **shear_transform** (*Affine*) – A 2D shear transform.

classmethod init_identity(*n_dims*)

Creates an identity transform.

Parameters **n_dims** (*int*) – The number of dimensions.

Returns **identity** (*UniformScale*) – The identity matrix transform.

pseudoinverse()

The inverse scale.

Type *UniformScale*

pseudoinverse_vector(*vector*)

The vectorized pseudoinverse of a provided vector instance. Syntactic sugar for:

```
self.from_vector(vector).pseudoinverse().as_vector()
```

Can be much faster than the explict call as object creation can be entirely avoided in some cases.

Parameters **vector** (`(n_parameters,)` *ndarray*) – A vectorized version of `self`

Returns **pseudoinverse_vector** (`(n_parameters,)` *ndarray*) – The pseudoinverse of the vector provided

set_h_matrix(*value*, *copy=True*, *skip_checks=False*)

Deprecated Deprecated - do not use this method - you are better off just creating a new transform!

Updates `h_matrix`, optionally performing sanity checks.

Note that it won't always be possible to manually specify the `h_matrix` through this method, specifically if changing the `h_matrix` could change the nature of the transform. See *h_matrix_is_mutable* for how you can discover if the `h_matrix` is allowed to be set for a given class.

Parameters

- **value** (*ndarray*) – The new homogeneous matrix to set.
- **copy** (*bool*, optional) – If `False`, do not copy the h_matrix. Useful for performance.
- **skip_checks** (*bool*, optional) – If `True`, skip checking. Useful for performance.

Raises `NotImplementedError` – If *h_matrix_is_mutable* returns `False`.

composes_inplace_with

UniformScale can swallow composition with any other *UniformScale*.

composes_with

Any Homogeneous can compose with any other Homogeneous.

h_matrix

The homogeneous matrix defining this transform.

Type `(n_dims + 1, n_dims + 1)` *ndarray*

h_matrix_is_mutable

Deprecated `True` iff *set_h_matrix()* is permitted on this type of transform.

If this returns `False` calls to *set_h_matrix()* will raise a `NotImplementedError`.

Type *bool*

has_true_inverse
The pseudoinverse is an exact inverse.

Type `True`

linear_component
The linear component of this affine transform.

Type `(n_dims, n_dims)` *ndarray*

n_dims
The dimensionality of the data the transform operates on.

Type *int*

n_dims_output
The output of the data from the transform.

Type *int*

n_parameters
The number of parameters – 1

Type *int*

scale
The single scale value.

Type *float*

translation_component
The translation component of this affine transform.

Type `(n_dims,)` *ndarray*

NonUniformScale

class `menpo.transform.`**`NonUniformScale`**(*scale*, *skip_checks=False*)
Bases: `DiscreteAffine`, `Affine`

An `n_dims` scale transform, with a scale component for each dimension.

Parameters

- **scale** (`(n_dims,)` *ndarray*) – A scale for each axis.
- **skip_checks** (*bool*, optional) – If `True` avoid sanity checks on `h_matrix` for performance.

apply(*x*, *batch_size=None*, ***kwargs*)
Applies this transform to `x`.

If `x` is `Transformable`, `x` will be handed this transform object to transform itself non-destructively (a transformed copy of the object will be returned).

If not, `x` is assumed to be an *ndarray*. The transformation will be non-destructive, returning the transformed version.

Any `kwargs` will be passed to the specific transform `_apply()` method.

Parameters

- **x** (`Transformable` or `(n_points, n_dims)` *ndarray*) – The array or object to be transformed.

- **batch_size** (*int*, optional) – If not `None`, this determines how many items from the numpy array will be passed through the transform at a time. This is useful for operations that require large intermediate matrices to be computed.
- **kwargs** (*dict*) – Passed through to `_apply()`.

Returnstransformed (`type(x)`) – The transformed object or array

apply_inplace(**args*, ***kwargs*)

Deprecated as public supported API, use the non-mutating *apply()* instead.

For internal performance-specific uses, see *_apply_inplace()*.

as_vector(***kwargs*)

Returns a flattened representation of the object as a single vector.

Returnsvector (*(N,) ndarray*) – The core representation of the object, flattened into a single vector. Note that this is always a view back on to the original object, but is not writable.

compose_after(*transform*)

A `Transform` that represents **this** transform composed **after** the given transform:

```
c = a.compose_after(b)
c.apply(p) == a.apply(b.apply(p))
```

`a` and `b` are left unchanged.

This corresponds to the usual mathematical formalism for the compose operator, `o`.

An attempt is made to perform native composition, but will fall back to a `TransformChain` as a last resort. See `composes_with` for a description of how the mode of composition is decided.

Parameterstransform (`Transform`) – Transform to be applied **before** `self`

Returnstransform (`Transform` or `TransformChain`) – If the composition was native, a single new `Transform` will be returned. If not, a `TransformChain` is returned instead.

compose_after_inplace(*transform*)

Update `self` so that it represents **this** transform composed **after** the given transform:

```
a_orig = a.copy()
a.compose_after_inplace(b)
a.apply(p) == a_orig.apply(b.apply(p))
```

`a` is permanently altered to be the result of the composition. `b` is left unchanged.

Parameterstransform (`composes_inplace_with`) – Transform to be applied **before** `self`

Raises`ValueError` – If `transform` isn't an instance of `composes_inplace_with`

compose_before(*transform*)

A `Transform` that represents **this** transform composed **before** the given transform:

```
c = a.compose_before(b)
c.apply(p) == b.apply(a.apply(p))
```

`a` and `b` are left unchanged.

An attempt is made to perform native composition, but will fall back to a `TransformChain` as a last resort. See `composes_with` for a description of how the mode of composition is decided.

Parameterstransform (`Transform`) – Transform to be applied **after** `self`

Returnstransform (*Transform* or *TransformChain*) – If the composition was native, a single new *Transform* will be returned. If not, a *TransformChain* is returned instead.

compose_before_inplace(*transform*)

Update `self` so that it represents **this** transform composed **before** the given transform:

```
a_orig = a.copy()
a.compose_before_inplace(b)
a.apply(p) == b.apply(a_orig.apply(p))
```

`a` is permanently altered to be the result of the composition. `b` is left unchanged.

Parameterstransform (*composes_inplace_with*) – Transform to be applied **after** `self`

Raises`ValueError` – If `transform` isn't an instance of *composes_inplace_with*

copy()

Generate an efficient copy of this object.

Note that Numpy arrays and other *Copyable* objects on `self` will be deeply copied. Dictionaries and sets will be shallow copied, and everything else will be assigned (no copy will be made).

Classes that store state other than numpy arrays and immutable types should overwrite this method to ensure all state is copied.

Returns`type(self)` – A copy of this object

decompose()

A `DiscreteAffine` is already maximally decomposed - return a copy of self in a *list*.

Returnstransform (`DiscreteAffine`) – Deep copy of *self*.

from_vector(*vector*)

Build a new instance of the object from its vectorized state.

`self` is used to fill out the missing state required to rebuild a full object from it's standardized flattened state. This is the default implementation, which is a `deepcopy` of the object followed by a call to *from_vector_inplace()*. This method can be overridden for a performance benefit if desired.

Parametersvector (`(n_parameters,)` *ndarray*) – Flattened representation of the object.

Returnstransform (*Homogeneous*) – An new instance of this class.

from_vector_inplace(*vector*)

Deprecated. Use the non-mutating API, *from_vector*.

For internal usage in performance-sensitive spots, see *_from_vector_inplace()*

Parametersvector (`(n_parameters,)` *ndarray*) – Flattened representation of this object

has_nan_values()

Tests if the vectorized form of the object contains `nan` values or not. This is particularly useful for objects with unknown values that have been mapped to `nan` values.

Returnshas_nan_values (*bool*) – If the vectorized object contains `nan` values.

init_from_2d_shear(*phi*, *psi*, *degrees=True*)

Convenience constructor for 2D shear transformations about the origin.

Parameters

- **phi** (*float*) – The angle of shearing in the X direction.
- **psi** (*float*) – The angle of shearing in the Y direction.

- **degrees** (*bool*, optional) – If `True` phi and psi are interpreted as degrees. If `False`, phi and psi are interpreted as radians.

Returnsshear_transform (*Affine*) – A 2D shear transform.

classmethod init_identity(*n_dims*)

Creates an identity transform.

Parametersn_dims (*int*) – The number of dimensions.

Returnsidentity (*NonUniformScale*) – The identity matrix transform.

pseudoinverse()

The inverse scale matrix.

Type*NonUniformScale*

pseudoinverse_vector(*vector*)

The vectorized pseudoinverse of a provided vector instance. Syntactic sugar for:

```
self.from_vector(vector).pseudoinverse().as_vector()
```

Can be much faster than the explict call as object creation can be entirely avoided in some cases.

Parametersvector ((n_parameters,) *ndarray*) – A vectorized version of `self`

Returnspseudoinverse_vector ((n_parameters,) *ndarray*) – The pseudoinverse of the vector provided

set_h_matrix(*value*, *copy=True*, *skip_checks=False*)

Deprecated Deprecated - do not use this method - you are better off just creating a new transform!

Updates `h_matrix`, optionally performing sanity checks.

Note that it won't always be possible to manually specify the `h_matrix` through this method, specifically if changing the `h_matrix` could change the nature of the transform. See *h_matrix_is_mutable* for how you can discover if the `h_matrix` is allowed to be set for a given class.

Parameters

- **value** (*ndarray*) – The new homogeneous matrix to set.
- **copy** (*bool*, optional) – If `False`, do not copy the h_matrix. Useful for performance.
- **skip_checks** (*bool*, optional) – If `True`, skip checking. Useful for performance.

Raises`NotImplementedError` – If *h_matrix_is_mutable* returns `False`.

composes_inplace_with

NonUniformScale can swallow composition with any other *NonUniformScale* and *UniformScale*.

composes_with

Any Homogeneous can compose with any other Homogeneous.

h_matrix

The homogeneous matrix defining this transform.

Type (`n_dims + 1, n_dims + 1`) *ndarray*

h_matrix_is_mutable

Deprecated `True` iff *set_h_matrix()* is permitted on this type of transform.

If this returns `False` calls to *set_h_matrix()* will raise a `NotImplementedError`.

Type*bool*

has_true_inverse
The pseudoinverse is an exact inverse.

Type `True`

linear_component
The linear component of this affine transform.

Type `(n_dims, n_dims)` *ndarray*

n_dims
The dimensionality of the data the transform operates on.

Type *int*

n_dims_output
The output of the data from the transform.

Type *int*

n_parameters
The number of parameters – `n_dims`. They have the form `[scale_x, scale_y, ....]` representing the scale across each axis.

Type *list* of *int*

scale
The scale vector.

Type `(n_dims,)` *ndarray*

translation_component
The translation component of this affine transform.

Type `(n_dims,)` *ndarray*

Alignments

ThinPlateSplines

class `menpo.transform.`**`ThinPlateSplines`**(*source*, *target*, *kernel=None*, *min_singular_val=0.0001*)

Bases: `Alignment`, `Transform`, `Invertible`

The thin plate splines (TPS) alignment between 2D *source* and *target* landmarks.

`kernel` can be used to specify an alternative kernel function. If `None` is supplied, the `R2LogR2RBF` kernel will be used.

Parameters

- **source** (`(N, 2)` *ndarray*) – The source points to apply the tps from
- **target** (`(N, 2)` *ndarray*) – The target points to apply the tps to
- **kernel** (`RadialBasisFunction`, optional) – The kernel to apply.
- **min_singular_val** (*float*, optional) – If the target has points that are nearly coincident, the coefficients matrix is rank deficient, and therefore not invertible. Therefore, we only take the inverse on the full-rank matrix and drop any singular values that are less than this value (close to zero).

Raises `ValueError` – TPS is only with on 2-dimensional data

aligned_source()

The result of applying `self` to *source*

Type*PointCloud*

alignment_error()

The Frobenius Norm of the difference between the target and the aligned source.

Type*float*

apply(*x*, *batch_size=None*, ***kwargs*)

Applies this transform to `x`.

If `x` is *Transformable*, `x` will be handed this transform object to transform itself non-destructively (a transformed copy of the object will be returned).

If not, `x` is assumed to be an *ndarray*. The transformation will be non-destructive, returning the transformed version.

Any `kwargs` will be passed to the specific transform `_apply()` method.

Parameters

- **x** (*Transformable* or `(n_points, n_dims)` *ndarray*) – The array or object to be transformed.
- **batch_size** (*int*, optional) – If not `None`, this determines how many items from the numpy array will be passed through the transform at a time. This is useful for operations that require large intermediate matrices to be computed.
- **kwargs** (*dict*) – Passed through to `_apply()`.

Returnstransformed (`type(x)`) – The transformed object or array

apply_inplace(**args*, ***kwargs*)

Deprecated as public supported API, use the non-mutating *apply()* instead.

For internal performance-specific uses, see *_apply_inplace()*.

compose_after(*transform*)

Returns a *TransformChain* that represents **this** transform composed **after** the given transform:

```
c = a.compose_after(b)
c.apply(p) == a.apply(b.apply(p))
```

`a` and `b` are left unchanged.

This corresponds to the usual mathematical formalism for the compose operator, *o*.

Parameterstransform (*Transform*) – Transform to be applied **before** self

Returnstransform (*TransformChain*) – The resulting transform chain.

compose_before(*transform*)

Returns a *TransformChain* that represents **this** transform composed **before** the given transform:

```
c = a.compose_before(b)
c.apply(p) == b.apply(a.apply(p))
```

`a` and `b` are left unchanged.

Parameterstransform (*Transform*) – Transform to be applied **after** self

Returnstransform (*TransformChain*) – The resulting transform chain.

copy()
Generate an efficient copy of this object.

Note that Numpy arrays and other *Copyable* objects on `self` will be deeply copied. Dictionaries and sets will be shallow copied, and everything else will be assigned (no copy will be made).

Classes that store state other than numpy arrays and immutable types should overwrite this method to ensure all state is copied.

Returns `type(self)` – A copy of this object

pseudoinverse()
The pseudoinverse of the transform - that is, the transform that results from swapping *source* and *target*, or more formally, negating the transforms parameters. If the transform has a true inverse this is returned instead.

Type `type(self)`

set_target(*new_target*)
Update this object so that it attempts to recreate the `new_target`.

Parameters **new_target** (*PointCloud*) – The new target that this object should try and regenerate.

has_true_inverse
type – `False`

n_dims
The number of dimensions of the *target*.

Type *int*

n_dims_output
The output of the data from the transform.

`None` if the output of the transform is not dimension specific.

Type *int* or `None`

n_points
The number of points on the *target*.

Type *int*

source
The source *PointCloud* that is used in the alignment.

The source is not mutable.

Type *PointCloud*

target
The current *PointCloud* that this object produces.

To change the target, use *set_target()*.

Type *PointCloud*

PiecewiseAffine

menpo.transform.**PiecewiseAffine**
alias of `CachedPWA`

AlignmentAffine

class menpo.transform.**AlignmentAffine**(*source*, *target*)

Bases: HomogFamilyAlignment, Affine

Constructs an *Affine* by finding the optimal affine transform to align *source* to *target*.

Parameters

- **source** (*PointCloud*) – The source pointcloud instance used in the alignment
- **target** (*PointCloud*) – The target pointcloud instance used in the alignment

---

Notes

We want to find the optimal transform M which satisfies $Ma = b$ where a and b are the *source* and *target* homogeneous vectors respectively.

```
(M a)' = b'
a' M' = b'
a a' M' = a b'
```

a a' is of shape *(n_dim + 1, n_dim + 1)* and so can be inverted to solve for *M*.

This approach is the analytical linear least squares solution to the problem at hand. It will have a solution as long as *(a a')* is non-singular, which generally means at least 2 corresponding points are required.

---

aligned_source()

The result of applying self to *source*

Type*PointCloud*

alignment_error()

The Frobenius Norm of the difference between the target and the aligned source.

Type*float*

apply(*x*, *batch_size=None*, ***kwargs*)

Applies this transform to x.

If x is *Transformable*, x will be handed this transform object to transform itself non-destructively (a transformed copy of the object will be returned).

If not, x is assumed to be an *ndarray*. The transformation will be non-destructive, returning the transformed version.

Any kwargs will be passed to the specific transform _apply() method.

Parameters

- **x** (*Transformable* or (n_points, n_dims) *ndarray*) – The array or object to be transformed.
- **batch_size** (*int*, optional) – If not None, this determines how many items from the numpy array will be passed through the transform at a time. This is useful for operations that require large intermediate matrices to be computed.
- **kwargs** (*dict*) – Passed through to _apply().

Returnstransformed (type(x)) – The transformed object or array

apply_inplace(**args*, ***kwargs*)

Deprecated as public supported API, use the non-mutating *apply()* instead.

For internal performance-specific uses, see *_apply_inplace()*.

as_non_alignment()

Returns a copy of this `Affine` without its alignment nature.

Returnstransform (`Affine`) – A version of this affine with the same transform behavior but without the alignment logic.

as_vector(***kwargs*)

Returns a flattened representation of the object as a single vector.

Returnsvector (*(N,) ndarray*) – The core representation of the object, flattened into a single vector. Note that this is always a view back on to the original object, but is not writable.

compose_after(*transform*)

A `Transform` that represents **this** transform composed **after** the given transform:

```
c = a.compose_after(b)
c.apply(p) == a.apply(b.apply(p))
```

`a` and `b` are left unchanged.

This corresponds to the usual mathematical formalism for the compose operator, `o`.

An attempt is made to perform native composition, but will fall back to a `TransformChain` as a last resort. See `composes_with` for a description of how the mode of composition is decided.

Parameterstransform (`Transform`) – Transform to be applied **before** `self`

Returnstransform (`Transform` or `TransformChain`) – If the composition was native, a single new `Transform` will be returned. If not, a `TransformChain` is returned instead.

compose_after_inplace(*transform*)

Update `self` so that it represents **this** transform composed **after** the given transform:

```
a_orig = a.copy()
a.compose_after_inplace(b)
a.apply(p) == a_orig.apply(b.apply(p))
```

`a` is permanently altered to be the result of the composition. `b` is left unchanged.

Parameterstransform (`composes_inplace_with`) – Transform to be applied **before** `self`

Raises`ValueError` – If `transform` isn't an instance of `composes_inplace_with`

compose_before(*transform*)

A `Transform` that represents **this** transform composed **before** the given transform:

```
c = a.compose_before(b)
c.apply(p) == b.apply(a.apply(p))
```

`a` and `b` are left unchanged.

An attempt is made to perform native composition, but will fall back to a `TransformChain` as a last resort. See `composes_with` for a description of how the mode of composition is decided.

Parameterstransform (`Transform`) – Transform to be applied **after** `self`

Returnstransform (`Transform` or `TransformChain`) – If the composition was native, a single new `Transform` will be returned. If not, a `TransformChain` is returned instead.

compose_before_inplace(*transform*)

Update `self` so that it represents **this** transform composed **before** the given transform:

```
a_orig = a.copy()
a.compose_before_inplace(b)
a.apply(p) == b.apply(a_orig.apply(p))
```

`a` is permanently altered to be the result of the composition. `b` is left unchanged.

Parameters`transform` (*composes_inplace_with*) – Transform to be applied **after** `self`

Raises`ValueError` – If `transform` isn't an instance of *composes_inplace_with*

copy()

Generate an efficient copy of this `HomogFamilyAlignment`.

Returnsnew_transform (`type(self)`) – A copy of this object

decompose()

Decompose this transform into discrete Affine Transforms.

Useful for understanding the effect of a complex composite transform.

Returns

transforms (*list* of `DiscreteAffine`) – Equivalent to this affine transform, such that

```
reduce(lambda x, y: x.chain(y), self.decompose()) == self
```

from_vector(*vector*)

Build a new instance of the object from its vectorized state.

`self` is used to fill out the missing state required to rebuild a full object from it's standardized flattened state. This is the default implementation, which is a `deepcopy` of the object followed by a call to *from_vector_inplace()*. This method can be overridden for a performance benefit if desired.

Parameters`vector` (`(n_parameters,)` *ndarray*) – Flattened representation of the object.

Returnstransform (*Homogeneous*) – An new instance of this class.

from_vector_inplace(*vector*)

Deprecated. Use the non-mutating API, *from_vector*.

For internal usage in performance-sensitive spots, see *_from_vector_inplace()*

Parameters`vector` (`(n_parameters,)` *ndarray*) – Flattened representation of this object

has_nan_values()

Tests if the vectorized form of the object contains `nan` values or not. This is particularly useful for objects with unknown values that have been mapped to `nan` values.

Returnshas_nan_values (*bool*) – If the vectorized object contains `nan` values.

init_from_2d_shear(*phi*, *psi*, *degrees=True*)

Convenience constructor for 2D shear transformations about the origin.

Parameters

- **phi** (*float*) – The angle of shearing in the X direction.
- **psi** (*float*) – The angle of shearing in the Y direction.
- **degrees** (*bool*, optional) – If `True` phi and psi are interpreted as degrees. If `False`, phi and psi are interpreted as radians.

Returnsshear_transform (*Affine*) – A 2D shear transform.

init_identity(*n_dims*)

Creates an identity matrix Affine transform.

Parametersn_dims (*int*) – The number of dimensions.

Returnsidentity (*Affine*) – The identity matrix transform.

pseudoinverse()

The pseudoinverse of the transform - that is, the transform that results from swapping source and target, or more formally, negating the transforms parameters. If the transform has a true inverse this is returned instead.

Returnstransform (`type(self)`) – The inverse of this transform.

pseudoinverse_vector(*vector*)

The vectorized pseudoinverse of a provided vector instance. Syntactic sugar for:

```
self.from_vector(vector).pseudoinverse().as_vector()
```

Can be much faster than the explict call as object creation can be entirely avoided in some cases.

Parametersvector (`(n_parameters,)` *ndarray*) – A vectorized version of `self`

Returnspseudoinverse_vector (`(n_parameters,)` *ndarray*) – The pseudoinverse of the vector provided

set_h_matrix(*value*, *copy=True*, *skip_checks=False*)

Deprecated Deprecated - do not use this method - you are better off just creating a new transform!

Updates `h_matrix`, optionally performing sanity checks.

Note that it won't always be possible to manually specify the `h_matrix` through this method, specifically if changing the `h_matrix` could change the nature of the transform. See *h_matrix_is_mutable* for how you can discover if the `h_matrix` is allowed to be set for a given class.

Parameters

- **value** (*ndarray*) – The new homogeneous matrix to set.
- **copy** (*bool*, optional) – If `False`, do not copy the h_matrix. Useful for performance.
- **skip_checks** (*bool*, optional) – If `True`, skip checking. Useful for performance.

Raises`NotImplementedError` – If *h_matrix_is_mutable* returns `False`.

set_target(*new_target*)

Update this object so that it attempts to recreate the `new_target`.

Parametersnew_target (*PointCloud*) – The new target that this object should try and regenerate.

composes_inplace_with

Affine can swallow composition with any other *Affine*.

composes_with

Any Homogeneous can compose with any other Homogeneous.

h_matrix

The homogeneous matrix defining this transform.

Type `(n_dims + 1, n_dims + 1)` *ndarray*

h_matrix_is_mutable

Deprecated `True` iff *set_h_matrix()* is permitted on this type of transform.

If this returns `False` calls to *set_h_matrix()* will raise a `NotImplementedError`.

Type *bool*

has_true_inverse

The pseudoinverse is an exact inverse.

Type `True`

linear_component

The linear component of this affine transform.

Type `(n_dims, n_dims)` *ndarray*

n_dims

The number of dimensions of the *target*.

Type *int*

n_dims_output

The output of the data from the transform.

Type *int*

n_parameters

`n_dims * (n_dims + 1)` parameters - every element of the matrix but the homogeneous part.

Type int

Examples

2D Affine: 6 parameters:

```
[p1, p3, p5]
[p2, p4, p6]
```

3D Affine: 12 parameters:

```
[p1, p4, p7, p10]
[p2, p5, p8, p11]
[p3, p6, p9, p12]
```

n_points

The number of points on the *target*.

Type *int*

source

The source *PointCloud* that is used in the alignment.

The source is not mutable.

Type *PointCloud*

target

The current *PointCloud* that this object produces.

To change the target, use *set_target()*.

Type *PointCloud*

translation_component
The translation component of this affine transform.

Type (n_dims,) *ndarray*

AlignmentSimilarity

class menpo.transform.**AlignmentSimilarity**(*source*, *target*, *rotation=True*, *allow_mirror=False*)

Bases: HomogFamilyAlignment, Similarity

Infers the similarity transform relating two vectors with the same dimensionality. This is simply the procrustes alignment of the *source* to the *target*.

Parameters

- **source** (*PointCloud*) – The source pointcloud instance used in the alignment
- **target** (*PointCloud*) – The target pointcloud instance used in the alignment
- **rotation** (*bool*, optional) – If False, the rotation component of the similarity transform is not inferred.
- **allow_mirror** (*bool*, optional) – If True, the Kabsch algorithm check is not performed, and mirroring of the Rotation matrix is permitted.

aligned_source()
The result of applying self to *source*

Type*PointCloud*

alignment_error()
The Frobenius Norm of the difference between the target and the aligned source.

Type*float*

apply(*x*, *batch_size=None*, ***kwargs*)
Applies this transform to x.

If x is *Transformable*, x will be handed this transform object to transform itself non-destructively (a transformed copy of the object will be returned).

If not, x is assumed to be an *ndarray*. The transformation will be non-destructive, returning the transformed version.

Any kwargs will be passed to the specific transform _apply() method.

Parameters

- **x** (*Transformable* or (n_points, n_dims) *ndarray*) – The array or object to be transformed.
- **batch_size** (*int*, optional) – If not None, this determines how many items from the numpy array will be passed through the transform at a time. This is useful for operations that require large intermediate matrices to be computed.
- **kwargs** (*dict*) – Passed through to _apply().

Returnstransformed (type(x)) – The transformed object or array

apply_inplace(**args*, ***kwargs*)
Deprecated as public supported API, use the non-mutating *apply()* instead.

For internal performance-specific uses, see *_apply_inplace()*.

as_non_alignment()

Returns a copy of this similarity without it's alignment nature.

Returnstransform (*Similarity*) – A version of this similarity with the same transform behavior but without the alignment logic.

as_vector(***kwargs*)

Returns a flattened representation of the object as a single vector.

Returnsvector (*(N,) ndarray*) – The core representation of the object, flattened into a single vector. Note that this is always a view back on to the original object, but is not writable.

compose_after(*transform*)

A *Transform* that represents **this** transform composed **after** the given transform:

```
c = a.compose_after(b)
c.apply(p) == a.apply(b.apply(p))
```

a and b are left unchanged.

This corresponds to the usual mathematical formalism for the compose operator, o.

An attempt is made to perform native composition, but will fall back to a *TransformChain* as a last resort. See *composes_with* for a description of how the mode of composition is decided.

Parameterstransform (*Transform*) – Transform to be applied **before** self

Returnstransform (*Transform* or *TransformChain*) – If the composition was native, a single new *Transform* will be returned. If not, a *TransformChain* is returned instead.

compose_after_inplace(*transform*)

Update self so that it represents **this** transform composed **after** the given transform:

```
a_orig = a.copy()
a.compose_after_inplace(b)
a.apply(p) == a_orig.apply(b.apply(p))
```

a is permanently altered to be the result of the composition. b is left unchanged.

Parameterstransform (*composes_inplace_with*) – Transform to be applied **before** self

RaisesValueError – If transform isn't an instance of *composes_inplace_with*

compose_before(*transform*)

A *Transform* that represents **this** transform composed **before** the given transform:

```
c = a.compose_before(b)
c.apply(p) == b.apply(a.apply(p))
```

a and b are left unchanged.

An attempt is made to perform native composition, but will fall back to a *TransformChain* as a last resort. See *composes_with* for a description of how the mode of composition is decided.

Parameterstransform (*Transform*) – Transform to be applied **after** self

Returnstransform (*Transform* or *TransformChain*) – If the composition was native, a single new *Transform* will be returned. If not, a *TransformChain* is returned instead.

compose_before_inplace(*transform*)

Update self so that it represents **this** transform composed **before** the given transform:

```
a_orig = a.copy()
a.compose_before_inplace(b)
a.apply(p) == b.apply(a_orig.apply(p))
```

`a` is permanently altered to be the result of the composition. `b` is left unchanged.

Parameters`transform` (*composes_inplace_with*) – Transform to be applied **after** `self`

Raises`ValueError` – If `transform` isn't an instance of *composes_inplace_with*

copy()

Generate an efficient copy of this `HomogFamilyAlignment`.

Returnsnew_transform (`type(self)`) – A copy of this object

decompose()

Decompose this transform into discrete Affine Transforms.

Useful for understanding the effect of a complex composite transform.

Returns

transforms (*list* of `DiscreteAffine`) – Equivalent to this affine transform, such that

```
reduce(lambda x, y: x.chain(y), self.decompose()) == self
```

from_vector(*vector*)

Build a new instance of the object from its vectorized state.

`self` is used to fill out the missing state required to rebuild a full object from it's standardized flattened state. This is the default implementation, which is a `deepcopy` of the object followed by a call to *from_vector_inplace()*. This method can be overridden for a performance benefit if desired.

Parameters`vector` (`(n_parameters,)` *ndarray*) – Flattened representation of the object.

Returnstransform (*Homogeneous*) – An new instance of this class.

from_vector_inplace(*vector*)

Deprecated. Use the non-mutating API, *from_vector*.

For internal usage in performance-sensitive spots, see *_from_vector_inplace()*

Parameters`vector` (`(n_parameters,)` *ndarray*) – Flattened representation of this object

has_nan_values()

Tests if the vectorized form of the object contains `nan` values or not. This is particularly useful for objects with unknown values that have been mapped to `nan` values.

Returnshas_nan_values (*bool*) – If the vectorized object contains `nan` values.

init_from_2d_shear(*phi*, *psi*, *degrees=True*)

Convenience constructor for 2D shear transformations about the origin.

Parameters

- **phi** (*float*) – The angle of shearing in the X direction.
- **psi** (*float*) – The angle of shearing in the Y direction.
- **degrees** (*bool*, optional) – If `True` phi and psi are interpreted as degrees. If `False`, phi and psi are interpreted as radians.

Returnsshear_transform (*Affine*) – A 2D shear transform.

init_identity(*n_dims*)

Creates an identity transform.

Parametersn_dims (*int*) – The number of dimensions.

Returnsidentity (*Similarity*) – The identity matrix transform.

pseudoinverse()

The pseudoinverse of the transform - that is, the transform that results from swapping source and target, or more formally, negating the transforms parameters. If the transform has a true inverse this is returned instead.

Returnstransform (type(self)) – The inverse of this transform.

pseudoinverse_vector(*vector*)

The vectorized pseudoinverse of a provided vector instance. Syntactic sugar for:

```
self.from_vector(vector).pseudoinverse().as_vector()
```

Can be much faster than the explict call as object creation can be entirely avoided in some cases.

Parametersvector ((n_parameters,) *ndarray*) – A vectorized version of self

Returnspseudoinverse_vector ((n_parameters,) *ndarray*) – The pseudoinverse of the vector provided

set_h_matrix(*value*, *copy=True*, *skip_checks=False*)

Deprecated Deprecated - do not use this method - you are better off just creating a new transform!

Updates h_matrix, optionally performing sanity checks.

Note that it won't always be possible to manually specify the h_matrix through this method, specifically if changing the h_matrix could change the nature of the transform. See *h_matrix_is_mutable* for how you can discover if the h_matrix is allowed to be set for a given class.

Parameters

- **value** (*ndarray*) – The new homogeneous matrix to set.
- **copy** (*bool*, optional) – If False, do not copy the h_matrix. Useful for performance.
- **skip_checks** (*bool*, optional) – If True, skip checking. Useful for performance.

RaisesNotImplementedError – If *h_matrix_is_mutable* returns False.

set_target(*new_target*)

Update this object so that it attempts to recreate the new_target.

Parametersnew_target (*PointCloud*) – The new target that this object should try and regenerate.

composes_inplace_with

Affine can swallow composition with any other *Affine*.

composes_with

Any Homogeneous can compose with any other Homogeneous.

h_matrix

The homogeneous matrix defining this transform.

Type(n_dims + 1, n_dims + 1) *ndarray*

h_matrix_is_mutable

Deprecated True iff *set_h_matrix()* is permitted on this type of transform.

If this returns False calls to *set_h_matrix()* will raise a NotImplementedError.

Type *bool*

has_true_inverse
The pseudoinverse is an exact inverse.

Type `True`

linear_component
The linear component of this affine transform.

Type `(n_dims, n_dims)` *ndarray*

n_dims
The number of dimensions of the `target`.

Type *int*

n_dims_output
The output of the data from the transform.

Type *int*

n_parameters
Number of parameters of Similarity

2D Similarity - 4 parameters

```
[(1 + a), -b,       tx]
[b,       (1 + a), ty]
```

3D Similarity: Currently not supported

Returns **n_parameters** (*int*) – The transform parameters

Raises *DimensionalityError, NotImplementedError* – Only 2D transforms are supported.

n_points
The number of points on the `target`.

Type *int*

source
The source `PointCloud` that is used in the alignment.

The source is not mutable.

Type `PointCloud`

target
The current `PointCloud` that this object produces.

To change the target, use `set_target()`.

Type `PointCloud`

translation_component
The translation component of this affine transform.

Type `(n_dims,)` *ndarray*

AlignmentRotation

class `menpo.transform.`**`AlignmentRotation`**(*source*, *target*, *allow_mirror=False*)
Bases: `HomogFamilyAlignment`, `Rotation`

Constructs an `Rotation` by finding the optimal rotation transform to align *source* to *target*.

Parameters

- **source** (`PointCloud`) – The source pointcloud instance used in the alignment
- **target** (`PointCloud`) – The target pointcloud instance used in the alignment
- **allow_mirror** (*bool*, optional) – If `True`, the Kabsch algorithm check is not performed, and mirroring of the Rotation matrix is permitted.

aligned_source()

The result of applying `self` to `source`

Type `PointCloud`

alignment_error()

The Frobenius Norm of the difference between the target and the aligned source.

Type *float*

apply(*x*, *batch_size=None*, ***kwargs*)

Applies this transform to `x`.

If `x` is `Transformable`, `x` will be handed this transform object to transform itself non-destructively (a transformed copy of the object will be returned).

If not, `x` is assumed to be an *ndarray*. The transformation will be non-destructive, returning the transformed version.

Any `kwargs` will be passed to the specific transform `_apply()` method.

Parameters

- **x** (`Transformable` or `(n_points, n_dims)` *ndarray*) – The array or object to be transformed.
- **batch_size** (*int*, optional) – If not `None`, this determines how many items from the numpy array will be passed through the transform at a time. This is useful for operations that require large intermediate matrices to be computed.
- **kwargs** (*dict*) – Passed through to `_apply()`.

Returns **transformed** (`type(x)`) – The transformed object or array

apply_inplace(**args*, ***kwargs*)

Deprecated as public supported API, use the non-mutating *apply()* instead.

For internal performance-specific uses, see *_apply_inplace()*.

as_non_alignment()

Returns a copy of this rotation without its alignment nature.

Returns **transform** (`Rotation`) – A version of this rotation with the same transform behavior but without the alignment logic.

as_vector(***kwargs*)

Returns a flattened representation of the object as a single vector.

Returns **vector** (*(N,) ndarray*) – The core representation of the object, flattened into a single vector. Note that this is always a view back on to the original object, but is not writable.

axis_and_angle_of_rotation()

Abstract method for computing the axis and angle of rotation.

Returns

- **axis** ((n_dims,) *ndarray*) – The unit vector representing the axis of rotation
- **angle_of_rotation** (*float*) – The angle in radians of the rotation about the axis. The angle is signed in a right handed sense.

compose_after(*transform*)

A *Transform* that represents **this** transform composed **after** the given transform:

```
c = a.compose_after(b)
c.apply(p) == a.apply(b.apply(p))
```

a and b are left unchanged.

This corresponds to the usual mathematical formalism for the compose operator, o.

An attempt is made to perform native composition, but will fall back to a *TransformChain* as a last resort. See *composes_with* for a description of how the mode of composition is decided.

Parameters **transform** (*Transform*) – Transform to be applied **before** self

Returns **transform** (*Transform* or *TransformChain*) – If the composition was native, a single new *Transform* will be returned. If not, a *TransformChain* is returned instead.

compose_after_inplace(*transform*)

Update self so that it represents **this** transform composed **after** the given transform:

```
a_orig = a.copy()
a.compose_after_inplace(b)
a.apply(p) == a_orig.apply(b.apply(p))
```

a is permanently altered to be the result of the composition. b is left unchanged.

Parameters **transform** (*composes_inplace_with*) – Transform to be applied **before** self

Raises ValueError – If transform isn't an instance of *composes_inplace_with*

compose_before(*transform*)

A *Transform* that represents **this** transform composed **before** the given transform:

```
c = a.compose_before(b)
c.apply(p) == b.apply(a.apply(p))
```

a and b are left unchanged.

An attempt is made to perform native composition, but will fall back to a *TransformChain* as a last resort. See *composes_with* for a description of how the mode of composition is decided.

Parameters **transform** (*Transform*) – Transform to be applied **after** self

Returns **transform** (*Transform* or *TransformChain*) – If the composition was native, a single new *Transform* will be returned. If not, a *TransformChain* is returned instead.

compose_before_inplace(*transform*)

Update self so that it represents **this** transform composed **before** the given transform:

```
a_orig = a.copy()
a.compose_before_inplace(b)
a.apply(p) == b.apply(a_orig.apply(p))
```

a is permanently altered to be the result of the composition. b is left unchanged.

Parameters **transform** (*composes_inplace_with*) – Transform to be applied **after** `self`

Raises `ValueError` – If `transform` isn't an instance of *composes_inplace_with*

copy()

Generate an efficient copy of this `HomogFamilyAlignment`.

Returns **new_transform** (`type(self)`) – A copy of this object

decompose()

A `DiscreteAffine` is already maximally decomposed - return a copy of self in a *list*.

Returns **transform** (`DiscreteAffine`) – Deep copy of *self*.

from_vector(*vector*)

Build a new instance of the object from its vectorized state.

`self` is used to fill out the missing state required to rebuild a full object from it's standardized flattened state. This is the default implementation, which is a `deepcopy` of the object followed by a call to *from_vector_inplace()*. This method can be overridden for a performance benefit if desired.

Parameters **vector** (`(n_parameters,)` *ndarray*) – Flattened representation of the object.

Returns **transform** (*Homogeneous*) – An new instance of this class.

from_vector_inplace(*vector*)

Deprecated. Use the non-mutating API, *from_vector*.

For internal usage in performance-sensitive spots, see *_from_vector_inplace()*

Parameters **vector** (`(n_parameters,)` *ndarray*) – Flattened representation of this object

has_nan_values()

Tests if the vectorized form of the object contains `nan` values or not. This is particularly useful for objects with unknown values that have been mapped to `nan` values.

Returns **has_nan_values** (*bool*) – If the vectorized object contains `nan` values.

init_3d_from_quaternion(*q*)

Convenience constructor for 3D rotations based on quaternion parameters.

Parameters **q** (`(4,)` *ndarray*) – The quaternion parameters.

Returns **rotation** (`Rotation`) – A 3D rotation transform.

init_from_2d_ccw_angle(*theta*, *degrees=True*)

Convenience constructor for 2D CCW rotations about the origin.

Parameters

- **theta** (*float*) – The angle of rotation about the origin
- **degrees** (*bool*, optional) – If `True` theta is interpreted as a degree. If `False`, theta is interpreted as radians.

Returns **rotation** (`Rotation`) – A 2D rotation transform.

init_from_2d_shear(*phi*, *psi*, *degrees=True*)

Convenience constructor for 2D shear transformations about the origin.

Parameters

- **phi** (*float*) – The angle of shearing in the X direction.
- **psi** (*float*) – The angle of shearing in the Y direction.

- **degrees** (*bool*, optional) – If `True` phi and psi are interpreted as degrees. If `False`, phi and psi are interpreted as radians.

Returnsshear_transform (*Affine*) – A 2D shear transform.

init_identity(*n_dims*)

Creates an identity transform.

Parametersn_dims (*int*) – The number of dimensions.

Returnsidentity (*Rotation*) – The identity matrix transform.

pseudoinverse()

The pseudoinverse of the transform - that is, the transform that results from swapping source and target, or more formally, negating the transforms parameters. If the transform has a true inverse this is returned instead.

Returnstransform (`type(self)`) – The inverse of this transform.

pseudoinverse_vector(*vector*)

The vectorized pseudoinverse of a provided vector instance. Syntactic sugar for:

```
self.from_vector(vector).pseudoinverse().as_vector()
```

Can be much faster than the explict call as object creation can be entirely avoided in some cases.

Parametersvector (`(n_parameters,)` *ndarray*) – A vectorized version of `self`

Returnspseudoinverse_vector (`(n_parameters,)` *ndarray*) – The pseudoinverse of the vector provided

set_h_matrix(*value*, *copy=True*, *skip_checks=False*)

Deprecated Deprecated - do not use this method - you are better off just creating a new transform!

Updates `h_matrix`, optionally performing sanity checks.

Note that it won't always be possible to manually specify the `h_matrix` through this method, specifically if changing the `h_matrix` could change the nature of the transform. See *h_matrix_is_mutable* for how you can discover if the `h_matrix` is allowed to be set for a given class.

Parameters

- **value** (*ndarray*) – The new homogeneous matrix to set.
- **copy** (*bool*, optional) – If `False`, do not copy the h_matrix. Useful for performance.
- **skip_checks** (*bool*, optional) – If `True`, skip checking. Useful for performance.

Raises`NotImplementedError` – If *h_matrix_is_mutable* returns `False`.

set_rotation_matrix(*value*, *skip_checks=False*)

Sets the rotation matrix.

Parameters

- **value** (`(n_dims, n_dims)` *ndarray*) – The new rotation matrix.
- **skip_checks** (*bool*, optional) – If `True` avoid sanity checks on `value` for performance.

set_target(*new_target*)

Update this object so that it attempts to recreate the `new_target`.

Parametersnew_target (*PointCloud*) – The new target that this object should try and regenerate.

composes_inplace_with
`Rotation` can swallow composition with any other `Rotation`.

composes_with
Any Homogeneous can compose with any other Homogeneous.

h_matrix
The homogeneous matrix defining this transform.

Type `(n_dims + 1, n_dims + 1)` *ndarray*

h_matrix_is_mutable
Deprecated `True` iff `set_h_matrix()` is permitted on this type of transform.

If this returns `False` calls to `set_h_matrix()` will raise a `NotImplementedError`.

Type*bool*

has_true_inverse
The pseudoinverse is an exact inverse.

Type`True`

linear_component
The linear component of this affine transform.

Type `(n_dims, n_dims)` *ndarray*

n_dims
The number of dimensions of the `target`.

Type*int*

n_dims_output
The output of the data from the transform.

Type*int*

n_parameters
Number of parameters of Rotation. Only 3D rotations are currently supported.

Returnsn_parameters (*int*) – The transform parameters. Only 3D rotations are currently supported which are parametrized with quaternions.

Raises*DimensionalityError, NotImplementedError* – Non-3D Rotations are not yet vectorizable

n_points
The number of points on the `target`.

Type*int*

rotation_matrix
The rotation matrix.

Type `(n_dims, n_dims)` *ndarray*

source
The source `PointCloud` that is used in the alignment.

The source is not mutable.

Type`PointCloud`

target
The current `PointCloud` that this object produces.

To change the target, use `set_target()`.

Type *PointCloud*

translation_component
The translation component of this affine transform.

Type (n_dims,) *ndarray*

AlignmentTranslation

class menpo.transform.**AlignmentTranslation**(*source*, *target*)
Bases: HomogFamilyAlignment, Translation

Constructs a *Translation* by finding the optimal translation transform to align *source* to *target*.

Parameters

- **source** (*PointCloud*) – The source pointcloud instance used in the alignment
- **target** (*PointCloud*) – The target pointcloud instance used in the alignment

aligned_source()
The result of applying self to *source*

Type *PointCloud*

alignment_error()
The Frobenius Norm of the difference between the target and the aligned source.

Type *float*

apply(*x*, *batch_size=None*, ***kwargs*)
Applies this transform to x.

If x is *Transformable*, x will be handed this transform object to transform itself non-destructively (a transformed copy of the object will be returned).

If not, x is assumed to be an *ndarray*. The transformation will be non-destructive, returning the transformed version.

Any kwargs will be passed to the specific transform _apply() method.

Parameters

- **x** (*Transformable* or (n_points, n_dims) *ndarray*) – The array or object to be transformed.
- **batch_size** (*int*, optional) – If not None, this determines how many items from the numpy array will be passed through the transform at a time. This is useful for operations that require large intermediate matrices to be computed.
- **kwargs** (*dict*) – Passed through to _apply().

Returns **transformed** (type(x)) – The transformed object or array

apply_inplace(**args*, ***kwargs*)
Deprecated as public supported API, use the non-mutating *apply()* instead.

For internal performance-specific uses, see *_apply_inplace()*.

as_non_alignment()
Returns a copy of this translation without its alignment nature.

Returns **transform** (*Translation*) – A version of this transform with the same transform behavior but without the alignment logic.

as_vector(***kwargs*)

Returns a flattened representation of the object as a single vector.

Returns **vector** (*(N,) ndarray*) – The core representation of the object, flattened into a single vector. Note that this is always a view back on to the original object, but is not writable.

compose_after(*transform*)

A `Transform` that represents **this** transform composed **after** the given transform:

```
c = a.compose_after(b)
c.apply(p) == a.apply(b.apply(p))
```

`a` and `b` are left unchanged.

This corresponds to the usual mathematical formalism for the compose operator, `o`.

An attempt is made to perform native composition, but will fall back to a `TransformChain` as a last resort. See `composes_with` for a description of how the mode of composition is decided.

Parameters **transform** (`Transform`) – Transform to be applied **before** `self`

Returns **transform** (`Transform` or `TransformChain`) – If the composition was native, a single new `Transform` will be returned. If not, a `TransformChain` is returned instead.

compose_after_inplace(*transform*)

Update `self` so that it represents **this** transform composed **after** the given transform:

```
a_orig = a.copy()
a.compose_after_inplace(b)
a.apply(p) == a_orig.apply(b.apply(p))
```

`a` is permanently altered to be the result of the composition. `b` is left unchanged.

Parameters **transform** (`composes_inplace_with`) – Transform to be applied **before** `self`

Raises `ValueError` – If `transform` isn't an instance of `composes_inplace_with`

compose_before(*transform*)

A `Transform` that represents **this** transform composed **before** the given transform:

```
c = a.compose_before(b)
c.apply(p) == b.apply(a.apply(p))
```

`a` and `b` are left unchanged.

An attempt is made to perform native composition, but will fall back to a `TransformChain` as a last resort. See `composes_with` for a description of how the mode of composition is decided.

Parameters **transform** (`Transform`) – Transform to be applied **after** `self`

Returns **transform** (`Transform` or `TransformChain`) – If the composition was native, a single new `Transform` will be returned. If not, a `TransformChain` is returned instead.

compose_before_inplace(*transform*)

Update `self` so that it represents **this** transform composed **before** the given transform:

```
a_orig = a.copy()
a.compose_before_inplace(b)
a.apply(p) == b.apply(a_orig.apply(p))
```

`a` is permanently altered to be the result of the composition. `b` is left unchanged.

Parameters **transform** (*composes_inplace_with*) – Transform to be applied **after** `self`

Raises `ValueError` – If `transform` isn't an instance of *composes_inplace_with*

copy()

Generate an efficient copy of this `HomogFamilyAlignment`.

Returns **new_transform** (`type(self)`) – A copy of this object

decompose()

A `DiscreteAffine` is already maximally decomposed - return a copy of self in a *list*.

Returns **transform** (`DiscreteAffine`) – Deep copy of *self*.

from_vector(*vector*)

Build a new instance of the object from its vectorized state.

`self` is used to fill out the missing state required to rebuild a full object from it's standardized flattened state. This is the default implementation, which is a `deepcopy` of the object followed by a call to *from_vector_inplace()*. This method can be overridden for a performance benefit if desired.

Parameters **vector** (`(n_parameters,)` *ndarray*) – Flattened representation of the object.

Returns **transform** (*Homogeneous*) – An new instance of this class.

from_vector_inplace(*vector*)

Deprecated. Use the non-mutating API, *from_vector*.

For internal usage in performance-sensitive spots, see *_from_vector_inplace()*

Parameters **vector** (`(n_parameters,)` *ndarray*) – Flattened representation of this object

has_nan_values()

Tests if the vectorized form of the object contains `nan` values or not. This is particularly useful for objects with unknown values that have been mapped to `nan` values.

Returns **has_nan_values** (*bool*) – If the vectorized object contains `nan` values.

init_from_2d_shear(*phi*, *psi*, *degrees=True*)

Convenience constructor for 2D shear transformations about the origin.

Parameters

- **phi** (*float*) – The angle of shearing in the X direction.
- **psi** (*float*) – The angle of shearing in the Y direction.
- **degrees** (*bool*, optional) – If `True` phi and psi are interpreted as degrees. If `False`, phi and psi are interpreted as radians.

Returns **shear_transform** (*Affine*) – A 2D shear transform.

init_identity(*n_dims*)

Creates an identity transform.

Parameters **n_dims** (*int*) – The number of dimensions.

Returns **identity** (*Translation*) – The identity matrix transform.

pseudoinverse()

The pseudoinverse of the transform - that is, the transform that results from swapping source and target, or more formally, negating the transforms parameters. If the transform has a true inverse this is returned instead.

Returns **transform** (`type(self)`) – The inverse of this transform.

pseudoinverse_vector(*vector*)

The vectorized pseudoinverse of a provided vector instance. Syntactic sugar for:

```
self.from_vector(vector).pseudoinverse().as_vector()
```

Can be much faster than the explict call as object creation can be entirely avoided in some cases.

Parametersvector ((n_parameters,) *ndarray*) – A vectorized version of `self`

Returnspseudoinverse_vector ((n_parameters,) *ndarray*) – The pseudoinverse of the vector provided

set_h_matrix(*value*, *copy=True*, *skip_checks=False*)

Deprecated Deprecated - do not use this method - you are better off just creating a new transform!

Updates `h_matrix`, optionally performing sanity checks.

Note that it won't always be possible to manually specify the `h_matrix` through this method, specifically if changing the `h_matrix` could change the nature of the transform. See *h_matrix_is_mutable* for how you can discover if the `h_matrix` is allowed to be set for a given class.

Parameters

- **value** (*ndarray*) – The new homogeneous matrix to set.
- **copy** (*bool*, optional) – If `False`, do not copy the h_matrix. Useful for performance.
- **skip_checks** (*bool*, optional) – If `True`, skip checking. Useful for performance.

Raises`NotImplementedError` – If *h_matrix_is_mutable* returns `False`.

set_target(*new_target*)

Update this object so that it attempts to recreate the `new_target`.

Parametersnew_target (*PointCloud*) – The new target that this object should try and regenerate.

composes_inplace_with

Affine can swallow composition with any other *Affine*.

composes_with

Any Homogeneous can compose with any other Homogeneous.

h_matrix

The homogeneous matrix defining this transform.

Type (n_dims + 1, n_dims + 1) *ndarray*

h_matrix_is_mutable

Deprecated `True` iff *set_h_matrix()* is permitted on this type of transform.

If this returns `False` calls to *set_h_matrix()* will raise a `NotImplementedError`.

Type*bool*

has_true_inverse

The pseudoinverse is an exact inverse.

Type`True`

linear_component

The linear component of this affine transform.

Type (n_dims, n_dims) *ndarray*

n_dims
The number of dimensions of the `target`.

Type *int*

n_dims_output
The output of the data from the transform.

Type *int*

n_parameters
The number of parameters – `n_dims`

Type *int*

n_points
The number of points on the `target`.

Type *int*

source
The source `PointCloud` that is used in the alignment.

The source is not mutable.

Type `PointCloud`

target
The current `PointCloud` that this object produces.

To change the target, use `set_target()`.

Type `PointCloud`

translation_component
The translation component of this affine transform.

Type `(n_dims,)` *ndarray*

AlignmentUniformScale

class `menpo.transform.`**`AlignmentUniformScale`**(*source*, *target*)
Bases: `HomogFamilyAlignment`, `UniformScale`

Constructs a `UniformScale` by finding the optimal scale transform to align *source* to *target*.

Parameters

- **source** (`PointCloud`) – The source pointcloud instance used in the alignment
- **target** (`PointCloud`) – The target pointcloud instance used in the alignment

aligned_source()
The result of applying `self` to `source`

Type `PointCloud`

alignment_error()
The Frobenius Norm of the difference between the target and the aligned source.

Type *float*

apply(*x*, *batch_size=None*, ***kwargs*)
Applies this transform to `x`.

If `x` is `Transformable`, `x` will be handed this transform object to transform itself non-destructively (a transformed copy of the object will be returned).

If not, `x` is assumed to be an *ndarray*. The transformation will be non-destructive, returning the transformed version.

Any `kwargs` will be passed to the specific transform `_apply()` method.

Parameters

- **x** (`Transformable` or `(n_points, n_dims)` *ndarray*) – The array or object to be transformed.
- **batch_size** (*int*, optional) – If not `None`, this determines how many items from the numpy array will be passed through the transform at a time. This is useful for operations that require large intermediate matrices to be computed.
- **kwargs** (*dict*) – Passed through to `_apply()`.

Returnstransformed (`type(x)`) – The transformed object or array

apply_inplace(**args*, ***kwargs*)

Deprecated as public supported API, use the non-mutating *apply()* instead.

For internal performance-specific uses, see *_apply_inplace()*.

as_non_alignment()

Returns a copy of this uniform scale without it's alignment nature.

Returnstransform (`UniformScale`) – A version of this scale with the same transform behavior but without the alignment logic.

as_vector(***kwargs*)

Returns a flattened representation of the object as a single vector.

Returnsvector (*(N,) ndarray*) – The core representation of the object, flattened into a single vector. Note that this is always a view back on to the original object, but is not writable.

compose_after(*transform*)

A `Transform` that represents **this** transform composed **after** the given transform:

```
c = a.compose_after(b)
c.apply(p) == a.apply(b.apply(p))
```

`a` and `b` are left unchanged.

This corresponds to the usual mathematical formalism for the compose operator, `o`.

An attempt is made to perform native composition, but will fall back to a `TransformChain` as a last resort. See `composes_with` for a description of how the mode of composition is decided.

Parameterstransform (`Transform`) – Transform to be applied **before** `self`

Returnstransform (`Transform` or `TransformChain`) – If the composition was native, a single new `Transform` will be returned. If not, a `TransformChain` is returned instead.

compose_after_inplace(*transform*)

Update `self` so that it represents **this** transform composed **after** the given transform:

```
a_orig = a.copy()
a.compose_after_inplace(b)
a.apply(p) == a_orig.apply(b.apply(p))
```

`a` is permanently altered to be the result of the composition. `b` is left unchanged.

Parameters **transform** (*composes_inplace_with*) – Transform to be applied **before** `self`

Raises `ValueError` – If `transform` isn't an instance of *composes_inplace_with*

compose_before(*transform*)

A *Transform* that represents **this** transform composed **before** the given transform:

```
c = a.compose_before(b)
c.apply(p) == b.apply(a.apply(p))
```

`a` and `b` are left unchanged.

An attempt is made to perform native composition, but will fall back to a *TransformChain* as a last resort. See *composes_with* for a description of how the mode of composition is decided.

Parameters **transform** (*Transform*) – Transform to be applied **after** `self`

Returns **transform** (*Transform* or *TransformChain*) – If the composition was native, a single new *Transform* will be returned. If not, a *TransformChain* is returned instead.

compose_before_inplace(*transform*)

Update `self` so that it represents **this** transform composed **before** the given transform:

```
a_orig = a.copy()
a.compose_before_inplace(b)
a.apply(p) == b.apply(a_orig.apply(p))
```

`a` is permanently altered to be the result of the composition. `b` is left unchanged.

Parameters **transform** (*composes_inplace_with*) – Transform to be applied **after** `self`

Raises `ValueError` – If `transform` isn't an instance of *composes_inplace_with*

copy()

Generate an efficient copy of this `HomogFamilyAlignment`.

Returns **new_transform** (`type(self)`) – A copy of this object

decompose()

A `DiscreteAffine` is already maximally decomposed - return a copy of self in a *list*.

Returns **transform** (`DiscreteAffine`) – Deep copy of *self*.

from_vector(*vector*)

Build a new instance of the object from its vectorized state.

`self` is used to fill out the missing state required to rebuild a full object from it's standardized flattened state. This is the default implementation, which is a `deepcopy` of the object followed by a call to *from_vector_inplace()*. This method can be overridden for a performance benefit if desired.

Parameters **vector** (`(n_parameters,)` *ndarray*) – Flattened representation of the object.

Returns **transform** (*Homogeneous*) – An new instance of this class.

from_vector_inplace(*vector*)

Deprecated. Use the non-mutating API, *from_vector*.

For internal usage in performance-sensitive spots, see *_from_vector_inplace()*

Parameters **vector** (`(n_parameters,)` *ndarray*) – Flattened representation of this object

has_nan_values()

Tests if the vectorized form of the object contains `nan` values or not. This is particularly useful for objects with unknown values that have been mapped to `nan` values.

Returnshas_nan_values (*bool*) – If the vectorized object contains `nan` values.

init_from_2d_shear(*phi*, *psi*, *degrees=True*)

Convenience constructor for 2D shear transformations about the origin.

Parameters

- **phi** (*float*) – The angle of shearing in the X direction.
- **psi** (*float*) – The angle of shearing in the Y direction.
- **degrees** (*bool*, optional) – If `True` phi and psi are interpreted as degrees. If `False`, phi and psi are interpreted as radians.

Returnsshear_transform (*Affine*) – A 2D shear transform.

init_identity(*n_dims*)

Creates an identity transform.

Parametersn_dims (*int*) – The number of dimensions.

Returnsidentity (*UniformScale*) – The identity matrix transform.

pseudoinverse()

The pseudoinverse of the transform - that is, the transform that results from swapping source and target, or more formally, negating the transforms parameters. If the transform has a true inverse this is returned instead.

Returnstransform (`type(self)`) – The inverse of this transform.

pseudoinverse_vector(*vector*)

The vectorized pseudoinverse of a provided vector instance. Syntactic sugar for:

```
self.from_vector(vector).pseudoinverse().as_vector()
```

Can be much faster than the explict call as object creation can be entirely avoided in some cases.

Parametersvector (`(n_parameters,)` *ndarray*) – A vectorized version of `self`

Returnspseudoinverse_vector (`(n_parameters,)` *ndarray*) – The pseudoinverse of the vector provided

set_h_matrix(*value*, *copy=True*, *skip_checks=False*)

Deprecated Deprecated - do not use this method - you are better off just creating a new transform!

Updates `h_matrix`, optionally performing sanity checks.

Note that it won't always be possible to manually specify the `h_matrix` through this method, specifically if changing the `h_matrix` could change the nature of the transform. See *h_matrix_is_mutable* for how you can discover if the `h_matrix` is allowed to be set for a given class.

Parameters

- **value** (*ndarray*) – The new homogeneous matrix to set.
- **copy** (*bool*, optional) – If `False`, do not copy the h_matrix. Useful for performance.
- **skip_checks** (*bool*, optional) – If `True`, skip checking. Useful for performance.

Raises`NotImplementedError` – If *h_matrix_is_mutable* returns `False`.

set_target(*new_target*)

Update this object so that it attempts to recreate the `new_target`.

Parameters **new_target** (*PointCloud*) – The new target that this object should try and regenerate.

composes_inplace_with

UniformScale can swallow composition with any other *UniformScale*.

composes_with

Any Homogeneous can compose with any other Homogeneous.

h_matrix

The homogeneous matrix defining this transform.

Type `(n_dims + 1, n_dims + 1)` *ndarray*

h_matrix_is_mutable

Deprecated `True` iff *set_h_matrix()* is permitted on this type of transform.

If this returns `False` calls to *set_h_matrix()* will raise a `NotImplementedError`.

Type *bool*

has_true_inverse

The pseudoinverse is an exact inverse.

Type `True`

linear_component

The linear component of this affine transform.

Type `(n_dims, n_dims)` *ndarray*

n_dims

The number of dimensions of the *target*.

Type *int*

n_dims_output

The output of the data from the transform.

Type *int*

n_parameters

The number of parameters – 1

Type *int*

n_points

The number of points on the *target*.

Type *int*

scale

The single scale value.

Type *float*

source

The source *PointCloud* that is used in the alignment.

The source is not mutable.

Type *PointCloud*

target
The current `PointCloud` that this object produces.

To change the target, use `set_target()`.

Type `PointCloud`

translation_component
The translation component of this affine transform.

Type `(n_dims,)` *ndarray*

Group Alignments

GeneralizedProcrustesAnalysis

class `menpo.transform.`**`GeneralizedProcrustesAnalysis`**(*sources*, *target=None*, *allow_mirror=False*)

Bases: `MultipleAlignment`

Class for aligning multiple source shapes between them.

After construction, the `AlignmentSimilarity` transforms used to map each *source* optimally to the *target* can be found at *transforms*.

Parameters

- **sources** (*list* of `PointCloud`) – List of pointclouds to be aligned.
- **target** (`PointCloud`, optional) – The target `PointCloud` to align each source to. If `None`, then the mean of the sources is used.
- **allow_mirror** (*bool*, optional) – If `True`, the Kabsch algorithm check is not performed, and mirroring of the Rotation matrix is permitted.

Raises `ValueError` – Need at least two sources to align

mean_aligned_shape()
Returns the mean of the aligned shapes.

Type `PointCloud`

mean_alignment_error()
Returns the average error of the recursive procrustes alignment.

Type *float*

Composite Transforms

TransformChain

class `menpo.transform.`**`TransformChain`**(*transforms*)

Bases: `ComposableTransform`

A chain of transforms that can be efficiently applied one after the other.

This class is the natural product of composition. Note that objects may know how to compose themselves more efficiently - such objects implement the `ComposableTransform` or `VComposable` interfaces.

Parameters`transforms` (*list* of `Transform`) – The *list* of transforms to be applied. Note that the first transform will be applied first - the result of which is fed into the second transform and so on until the chain is exhausted.

apply(*x*, *batch_size=None*, ***kwargs*)

Applies this transform to `x`.

If `x` is `Transformable`, `x` will be handed this transform object to transform itself non-destructively (a transformed copy of the object will be returned).

If not, `x` is assumed to be an *ndarray*. The transformation will be non-destructive, returning the transformed version.

Any `kwargs` will be passed to the specific transform `_apply()` method.

Parameters

- **x** (`Transformable` or `(n_points, n_dims)` *ndarray*) – The array or object to be transformed.
- **batch_size** (*int*, optional) – If not `None`, this determines how many items from the numpy array will be passed through the transform at a time. This is useful for operations that require large intermediate matrices to be computed.
- **kwargs** (*dict*) – Passed through to `_apply()`.

Returns`transformed` (`type(x)`) – The transformed object or array

apply_inplace(**args*, ***kwargs*)

Deprecated as public supported API, use the non-mutating *apply()* instead.

For internal performance-specific uses, see *_apply_inplace()*.

compose_after(*transform*)

A `Transform` that represents **this** transform composed **after** the given transform:

```
c = a.compose_after(b)
c.apply(p) == a.apply(b.apply(p))
```

`a` and `b` are left unchanged.

This corresponds to the usual mathematical formalism for the compose operator, `o`.

An attempt is made to perform native composition, but will fall back to a `TransformChain` as a last resort. See `composes_with` for a description of how the mode of composition is decided.

Parameters`transform` (`Transform`) – Transform to be applied **before** `self`

Returns`transform` (`Transform` or `TransformChain`) – If the composition was native, a single new `Transform` will be returned. If not, a `TransformChain` is returned instead.

compose_after_inplace(*transform*)

Update `self` so that it represents **this** transform composed **after** the given transform:

```
a_orig = a.copy()
a.compose_after_inplace(b)
a.apply(p) == a_orig.apply(b.apply(p))
```

`a` is permanently altered to be the result of the composition. `b` is left unchanged.

Parameters`transform` (`composes_inplace_with`) – Transform to be applied **before** `self`

Raises`ValueError` – If `transform` isn't an instance of `composes_inplace_with`

compose_before(*transform*)

A *Transform* that represents **this** transform composed **before** the given transform:

```
c = a.compose_before(b)
c.apply(p) == b.apply(a.apply(p))
```

a and b are left unchanged.

An attempt is made to perform native composition, but will fall back to a *TransformChain* as a last resort. See *composes_with* for a description of how the mode of composition is decided.

Parameters **transform** (*Transform*) – Transform to be applied **after** self

Returns **transform** (*Transform* or *TransformChain*) – If the composition was native, a single new *Transform* will be returned. If not, a *TransformChain* is returned instead.

compose_before_inplace(*transform*)

Update self so that it represents **this** transform composed **before** the given transform:

```
a_orig = a.copy()
a.compose_before_inplace(b)
a.apply(p) == b.apply(a_orig.apply(p))
```

a is permanently altered to be the result of the composition. b is left unchanged.

Parameters **transform** (*composes_inplace_with*) – Transform to be applied **after** self

Raises ValueError – If transform isn't an instance of *composes_inplace_with*

copy()

Generate an efficient copy of this object.

Note that Numpy arrays and other *Copyable* objects on self will be deeply copied. Dictionaries and sets will be shallow copied, and everything else will be assigned (no copy will be made).

Classes that store state other than numpy arrays and immutable types should overwrite this method to ensure all state is copied.

Returns type(self) – A copy of this object

composes_inplace_with

The *Transform* s that this transform composes inplace with **natively** (i.e. no *TransformChain* will be produced).

An attempt to compose inplace against any type that is not an instance of this property on this class will result in an *Exception*.

Type *Transform* or *tuple* of *Transform* s

composes_with

The *Transform* s that this transform composes with **natively** (i.e. no *TransformChain* will be produced).

If native composition is not possible, falls back to producing a *TransformChain*.

By default, this is the same list as *composes_inplace_with*.

Type *Transform* or *tuple* of *Transform* s

n_dims

The dimensionality of the data the transform operates on.

None if the transform is not dimension specific.

Type*int* or `None`

n_dims_output
The output of the data from the transform.

`None` if the output of the transform is not dimension specific.

Type*int* or `None`

Radial Basis Functions

R2LogR2RBF

class `menpo.transform.`**`R2LogR2RBF`**(*c*)
Bases: `RadialBasisFunction`

The $r^2 \log r^2$ basis function.

The derivative of this function is $2r(\log r^2 + 1)$.

Note: $r = \|x - c\|$

Parametersc (`(n_centres, n_dims)` *ndarray*) – The set of centers that make the basis. Usually represents a set of source landmarks.

apply(*x*, *batch_size=None*, ***kwargs*)
Applies this transform to `x`.

If `x` is `Transformable`, `x` will be handed this transform object to transform itself non-destructively (a transformed copy of the object will be returned).

If not, `x` is assumed to be an *ndarray*. The transformation will be non-destructive, returning the transformed version.

Any `kwargs` will be passed to the specific transform `_apply()` method.

Parameters

- **x** (`Transformable` or `(n_points, n_dims)` *ndarray*) – The array or object to be transformed.
- **batch_size** (*int*, optional) – If not `None`, this determines how many items from the numpy array will be passed through the transform at a time. This is useful for operations that require large intermediate matrices to be computed.
- **kwargs** (*dict*) – Passed through to `_apply()`.

Returnstransformed (`type(x)`) – The transformed object or array

apply_inplace(**args*, ***kwargs*)
Deprecated as public supported API, use the non-mutating *apply()* instead.

For internal performance-specific uses, see *_apply_inplace()*.

compose_after(*transform*)
Returns a `TransformChain` that represents **this** transform composed **after** the given transform:

```
c = a.compose_after(b)
c.apply(p) == a.apply(b.apply(p))
```

`a` and `b` are left unchanged.

This corresponds to the usual mathematical formalism for the compose operator, o.

Parameters`transform` (*Transform*) – Transform to be applied **before** self

Returns`transform` (*TransformChain*) – The resulting transform chain.

compose_before(*transform*)

Returns a *TransformChain* that represents **this** transform composed **before** the given transform:

```
c = a.compose_before(b)
c.apply(p) == b.apply(a.apply(p))
```

`a` and `b` are left unchanged.

Parameters`transform` (*Transform*) – Transform to be applied **after** self

Returns`transform` (*TransformChain*) – The resulting transform chain.

copy()

Generate an efficient copy of this object.

Note that Numpy arrays and other *Copyable* objects on `self` will be deeply copied. Dictionaries and sets will be shallow copied, and everything else will be assigned (no copy will be made).

Classes that store state other than numpy arrays and immutable types should overwrite this method to ensure all state is copied.

Returns`type(self)` – A copy of this object

n_centres

The number of centres.

Type*int*

n_dims

The RBF can only be applied on points with the same dimensionality as the centres.

Type*int*

n_dims_output

The result of the transform has a dimension (weight) for every centre.

Type*int*

R2LogRRBF

class menpo.transform.**R2LogRRBF**(c)

Bases: `RadialBasisFunction`

Calculates the $r^2 \log r$ basis function.

The derivative of this function is $r(1 + 2 \log r)$.

Note: $r = \|x - c\|$

Parameters`c` (`(n_centres, n_dims)` *ndarray*) – The set of centers that make the basis. Usually represents a set of source landmarks.

apply(*x*, *batch_size=None*, ***kwargs*)

Applies this transform to `x`.

If `x` is `Transformable`, `x` will be handed this transform object to transform itself non-destructively (a transformed copy of the object will be returned).

If not, `x` is assumed to be an *ndarray*. The transformation will be non-destructive, returning the transformed version.

Any `kwargs` will be passed to the specific transform `_apply()` method.

Parameters

- **x** (`Transformable` or `(n_points, n_dims)` *ndarray*) – The array or object to be transformed.
- **batch_size** (*int*, optional) – If not `None`, this determines how many items from the numpy array will be passed through the transform at a time. This is useful for operations that require large intermediate matrices to be computed.
- **kwargs** (*dict*) – Passed through to `_apply()`.

Returnstransformed (`type(x)`) – The transformed object or array

apply_inplace(**args*, ***kwargs*)

Deprecated as public supported API, use the non-mutating *apply()* instead.

For internal performance-specific uses, see *_apply_inplace()*.

compose_after(*transform*)

Returns a `TransformChain` that represents **this** transform composed **after** the given transform:

```
c = a.compose_after(b)
c.apply(p) == a.apply(b.apply(p))
```

`a` and `b` are left unchanged.

This corresponds to the usual mathematical formalism for the compose operator, *o*.

Parameterstransform (`Transform`) – Transform to be applied **before** self

Returnstransform (`TransformChain`) – The resulting transform chain.

compose_before(*transform*)

Returns a `TransformChain` that represents **this** transform composed **before** the given transform:

```
c = a.compose_before(b)
c.apply(p) == b.apply(a.apply(p))
```

`a` and `b` are left unchanged.

Parameterstransform (`Transform`) – Transform to be applied **after** self

Returnstransform (`TransformChain`) – The resulting transform chain.

copy()

Generate an efficient copy of this object.

Note that Numpy arrays and other `Copyable` objects on `self` will be deeply copied. Dictionaries and sets will be shallow copied, and everything else will be assigned (no copy will be made).

Classes that store state other than numpy arrays and immutable types should overwrite this method to ensure all state is copied.

Returns`type(self)` – A copy of this object

n_centres
The number of centres.

Type *int*

n_dims
The RBF can only be applied on points with the same dimensionality as the centres.

Type *int*

n_dims_output
The result of the transform has a dimension (weight) for every centre.

Type *int*

Abstract Bases

Transform

class menpo.transform.**Transform**
Bases: *Copyable*

Abstract representation of any spatial transform.

Provides a unified interface to apply the transform with *apply_inplace()* and *apply()*.

All Transforms support basic composition to form a *TransformChain*.

There are two useful forms of composition. Firstly, the mathematical composition symbol *o* has the following definition:

```
Let a(x) and b(x) be two transforms on x.
(a o b)(x) == a(b(x))
```

This functionality is provided by the *compose_after()* family of methods:

```
(a.compose_after(b)).apply(x) == a.apply(b.apply(x))
```

Equally useful is an inversion the order of composition - so that over time a large chain of transforms can be built to do a useful job, and composing on this chain adds another transform to the end (after all other preceding transforms have been performed).

For instance, let's say we want to rescale a *PointCloud* p around its mean, and then translate it some place else. It would be nice to be able to do something like:

```
t = Translation(-p.centre)  # translate to centre
s = Scale(2.0)  # rescale
move = Translate([10, 0 ,0])  # budge along the x axis
t.compose(s).compose(-t).compose(move)
```

In Menpo, this functionality is provided by the *compose_before()* family of methods:

```
(a.compose_before(b)).apply(x) == b.apply(a.apply(x))
```

For native composition, see the *ComposableTransform* subclass and the VComposable mix-in.

For inversion, see the *Invertible* and *VInvertible* mix-ins.

For alignment, see the Alignment mix-in.

apply(*x*, *batch_size=None*, ***kwargs*)

Applies this transform to `x`.

If `x` is `Transformable`, `x` will be handed this transform object to transform itself non-destructively (a transformed copy of the object will be returned).

If not, `x` is assumed to be an *ndarray*. The transformation will be non-destructive, returning the transformed version.

Any `kwargs` will be passed to the specific transform `_apply()` method.

Parameters

- **x** (`Transformable` or `(n_points, n_dims)` *ndarray*) – The array or object to be transformed.
- **batch_size** (*int*, optional) – If not `None`, this determines how many items from the numpy array will be passed through the transform at a time. This is useful for operations that require large intermediate matrices to be computed.
- **kwargs** (*dict*) – Passed through to `_apply()`.

Returnstransformed (`type(x)`) – The transformed object or array

apply_inplace(**args*, ***kwargs*)

Deprecated as public supported API, use the non-mutating *apply()* instead.

For internal performance-specific uses, see *_apply_inplace()*.

compose_after(*transform*)

Returns a `TransformChain` that represents **this** transform composed **after** the given transform:

```
c = a.compose_after(b)
c.apply(p) == a.apply(b.apply(p))
```

`a` and `b` are left unchanged.

This corresponds to the usual mathematical formalism for the compose operator, *o*.

Parameterstransform (`Transform`) – Transform to be applied **before** self

Returnstransform (`TransformChain`) – The resulting transform chain.

compose_before(*transform*)

Returns a `TransformChain` that represents **this** transform composed **before** the given transform:

```
c = a.compose_before(b)
c.apply(p) == b.apply(a.apply(p))
```

`a` and `b` are left unchanged.

Parameterstransform (`Transform`) – Transform to be applied **after** self

Returnstransform (`TransformChain`) – The resulting transform chain.

copy()

Generate an efficient copy of this object.

Note that Numpy arrays and other `Copyable` objects on `self` will be deeply copied. Dictionaries and sets will be shallow copied, and everything else will be assigned (no copy will be made).

Classes that store state other than numpy arrays and immutable types should overwrite this method to ensure all state is copied.

Returns`type(self)` – A copy of this object

n_dims
The dimensionality of the data the transform operates on.

`None` if the transform is not dimension specific.

Type*int* or `None`

n_dims_output
The output of the data from the transform.

`None` if the output of the transform is not dimension specific.

Type*int* or `None`

Transformable

class `menpo.transform.base.`**`Transformable`**
Bases: *`Copyable`*

Interface for objects that know how to be transformed by the *`Transform`* interface.

When `Transform.apply_inplace` is called on an object, the *`_transform_inplace()`* method is called, passing in the transforms' `_apply()` function.

This allows for the object to define how it should transform itself.

`_transform_inplace`(*transform*)
Apply the given transform function to `self` inplace.

Parameters`transform` (*function*) – Function that applies a transformation to the transformable object.

Returns`transformed` (`type(self)`) – The transformed object, having been transformed in place.

`copy`()
Generate an efficient copy of this object.

Note that Numpy arrays and other *`Copyable`* objects on `self` will be deeply copied. Dictionaries and sets will be shallow copied, and everything else will be assigned (no copy will be made).

Classes that store state other than numpy arrays and immutable types should overwrite this method to ensure all state is copied.

Returns`type(self)` – A copy of this object

ComposableTransform

class `menpo.transform.base.composable.`**`ComposableTransform`**
Bases: `Transform`

`Transform` subclass that enables native composition, such that the behavior of multiple *`Transform`* s is composed together in a natural way.

`_compose_after_inplace`(*transform*)
Specialised inplace composition. This should be overridden to provide specific cases of composition as defined in *`composes_inplace_with`*.

Parameters`transform` (*`composes_inplace_with`*) – Transform to be applied **before** `self`

_compose_before_inplace(*transform*)

Specialised inplace composition. This should be overridden to provide specific cases of composition as defined in `composes_inplace_with`.

Parameters **transform** (`composes_inplace_with`) – Transform to be applied **after** `self`

apply(*x*, *batch_size=None*, ***kwargs*)

Applies this transform to `x`.

If `x` is `Transformable`, `x` will be handed this transform object to transform itself non-destructively (a transformed copy of the object will be returned).

If not, `x` is assumed to be an *ndarray*. The transformation will be non-destructive, returning the transformed version.

Any `kwargs` will be passed to the specific transform `_apply()` method.

Parameters

- **x** (`Transformable` or `(n_points, n_dims)` *ndarray*) – The array or object to be transformed.
- **batch_size** (*int*, optional) – If not `None`, this determines how many items from the numpy array will be passed through the transform at a time. This is useful for operations that require large intermediate matrices to be computed.
- **kwargs** (*dict*) – Passed through to `_apply()`.

Returns **transformed** (`type(x)`) – The transformed object or array

apply_inplace(**args*, ***kwargs*)

Deprecated as public supported API, use the non-mutating *apply()* instead.

For internal performance-specific uses, see *_apply_inplace()*.

compose_after(*transform*)

A `Transform` that represents **this** transform composed **after** the given transform:

```
c = a.compose_after(b)
c.apply(p) == a.apply(b.apply(p))
```

`a` and `b` are left unchanged.

This corresponds to the usual mathematical formalism for the compose operator, `o`.

An attempt is made to perform native composition, but will fall back to a `TransformChain` as a last resort. See `composes_with` for a description of how the mode of composition is decided.

Parameters **transform** (`Transform`) – Transform to be applied **before** `self`

Returns **transform** (`Transform` or `TransformChain`) – If the composition was native, a single new `Transform` will be returned. If not, a `TransformChain` is returned instead.

compose_after_inplace(*transform*)

Update `self` so that it represents **this** transform composed **after** the given transform:

```
a_orig = a.copy()
a.compose_after_inplace(b)
a.apply(p) == a_orig.apply(b.apply(p))
```

`a` is permanently altered to be the result of the composition. `b` is left unchanged.

Parameters **transform** (*composes_inplace_with*) – Transform to be applied **before** `self`

Raises `ValueError` – If `transform` isn't an instance of *composes_inplace_with*

compose_before(*transform*)

A *Transform* that represents **this** transform composed **before** the given transform:

```
c = a.compose_before(b)
c.apply(p) == b.apply(a.apply(p))
```

`a` and `b` are left unchanged.

An attempt is made to perform native composition, but will fall back to a *TransformChain* as a last resort. See *composes_with* for a description of how the mode of composition is decided.

Parameters **transform** (*Transform*) – Transform to be applied **after** `self`

Returns **transform** (*Transform* or *TransformChain*) – If the composition was native, a single new *Transform* will be returned. If not, a *TransformChain* is returned instead.

compose_before_inplace(*transform*)

Update `self` so that it represents **this** transform composed **before** the given transform:

```
a_orig = a.copy()
a.compose_before_inplace(b)
a.apply(p) == b.apply(a_orig.apply(p))
```

`a` is permanently altered to be the result of the composition. `b` is left unchanged.

Parameters **transform** (*composes_inplace_with*) – Transform to be applied **after** `self`

Raises `ValueError` – If `transform` isn't an instance of *composes_inplace_with*

copy()

Generate an efficient copy of this object.

Note that Numpy arrays and other *Copyable* objects on `self` will be deeply copied. Dictionaries and sets will be shallow copied, and everything else will be assigned (no copy will be made).

Classes that store state other than numpy arrays and immutable types should overwrite this method to ensure all state is copied.

Returns `type(self)` – A copy of this object

composes_inplace_with

The *Transform* s that this transform composes inplace with **natively** (i.e. no *TransformChain* will be produced).

An attempt to compose inplace against any type that is not an instance of this property on this class will result in an *Exception*.

Type *Transform* or *tuple* of *Transform* s

composes_with

The *Transform* s that this transform composes with **natively** (i.e. no *TransformChain* will be produced).

If native composition is not possible, falls back to producing a *TransformChain*.

By default, this is the same list as *composes_inplace_with*.

Type *Transform* or *tuple* of *Transform* s

n_dims
The dimensionality of the data the transform operates on.

`None` if the transform is not dimension specific.

Type*int* or `None`

n_dims_output
The output of the data from the transform.

`None` if the output of the transform is not dimension specific.

Type*int* or `None`

Invertible

class `menpo.transform.base.invertible.`**`Invertible`**
Bases: `object`

Mix-in for invertible transforms. Provides an interface for taking the *pseudo* or true inverse of a transform.

Has to be implemented in conjunction with `Transform`.

pseudoinverse()
The pseudoinverse of the transform - that is, the transform that results from swapping *source* and *target*, or more formally, negating the transforms parameters. If the transform has a true inverse this is returned instead.

Type`type(self)`

has_true_inverse
`True` if the pseudoinverse is an exact inverse.

Type*bool*

Alignment

class `menpo.transform.base.alignment.`**`Alignment`**(*source*, *target*)
Bases: `Targetable`, `Viewable`

Mix-in for `Transform` that have been constructed from an optimisation aligning a source `PointCloud` to a target `PointCloud`.

This is naturally an extension of the `Targetable` interface - we just augment `Targetable` with the concept of a source, and related methods to construct alignments between a source and a target.

Note that to inherit from `Alignment`, you have to be a `Transform` subclass first.

Parameters

- **source** (`PointCloud`) – A PointCloud that the alignment will be based from
- **target** (`PointCloud`) – A PointCloud that the alignment is targeted towards

aligned_source()
The result of applying `self` to `source`

Type`PointCloud`

alignment_error()
The Frobenius Norm of the difference between the target and the aligned source.

Type*float*

copy()
Generate an efficient copy of this object.

Note that Numpy arrays and other *Copyable* objects on `self` will be deeply copied. Dictionaries and sets will be shallow copied, and everything else will be assigned (no copy will be made).

Classes that store state other than numpy arrays and immutable types should overwrite this method to ensure all state is copied.

Returns `type(self)` – A copy of this object

set_target(*new_target*)
Update this object so that it attempts to recreate the `new_target`.

Parameters **new_target** (*PointCloud*) – The new target that this object should try and regenerate.

n_dims
The number of dimensions of the *target*.

Type *int*

n_points
The number of points on the *target*.

Type *int*

source
The source *PointCloud* that is used in the alignment.

The source is not mutable.

Type *PointCloud*

target
The current *PointCloud* that this object produces.

To change the target, use *set_target()*.

Type *PointCloud*

MultipleAlignment

class menpo.transform.groupalign.base.**MultipleAlignment**(*sources*, *target=None*)
Bases: `object`

Abstract base class for aligning multiple *source* shapes to a *target* shape.

Parameters

- **sources** (*list* of *PointCloud*) – List of pointclouds to be aligned.
- **target** (*PointCloud*, optional) – The target *PointCloud* to align each source to. If `None`, then the mean of the sources is used.

Raises `ValueError` – Need at least two sources to align

DiscreteAffine

class menpo.transform.homogeneous.affine.**DiscreteAffine**
Bases: `object`

A discrete Affine transform operation (such as a `Scale()`, `Translation` or `Rotation()`). Has to be invertable. Make sure you inherit from `DiscreteAffine` first, for optimal *decompose()* behavior.

decompose()

A `DiscreteAffine` is already maximally decomposed - return a copy of self in a *list*.

Returnstransform (`DiscreteAffine`) – Deep copy of *self*.

Performance Specializations

Mix-ins that provide fast vectorized variants of methods.

VComposable

class menpo.transform.base.composable.**VComposable**

Bases: `object`

Mix-in for `Vectorizable` `ComposableTransform` s.

Use this mix-in with `ComposableTransform` if the `ComposableTransform` in question is `Vectorizable` as this adds `from_vector()` variants to the `ComposableTransform` interface.

These can be tuned for performance.

compose_after_from_vector_inplace(*vector*)

Specialised inplace composition with a vector. This should be overridden to provide specific cases of composition whereby the current state of the transform can be derived purely from the provided vector.

Parametersvector ((`n_parameters,`) *ndarray*) – Vector to update the transform state with.

VInvertible

class menpo.transform.base.invertible.**VInvertible**

Bases: `Invertible`

Mix-in for `Vectorizable` `Invertible` `Transform` s.

Prefer this mix-in over `Invertible` if the `Transform` in question is `Vectorizable` as this adds `from_vector()` variants to the `Invertible` interface. These can be tuned for performance, and are, for instance, needed by some of the machinery of fit.

pseudoinverse()

The pseudoinverse of the transform - that is, the transform that results from swapping *source* and *target*, or more formally, negating the transforms parameters. If the transform has a true inverse this is returned instead.

Type`type(self)`

pseudoinverse_vector(*vector*)

The vectorized pseudoinverse of a provided vector instance. Syntactic sugar for:

```
self.from_vector(vector).pseudoinverse().as_vector()
```

Can be much faster than the explict call as object creation can be entirely avoided in some cases.

Parametersvector ((`n_parameters,`) *ndarray*) – A vectorized version of `self`

Returnspseudoinverse_vector ((n_parameters,) *ndarray*) – The pseudoinverse of the vector provided

has_true_inverse
`True` if the pseudoinverse is an exact inverse.

Type*bool*

menpo.visualize

Abstract Classes

Renderer

class menpo.visualize.**Renderer** (*figure_id*, *new_figure*)
Bases: `object`

Abstract class for rendering visualizations. Framework specific implementations of these classes are made in order to separate implementation cleanly from the rest of the code.

It is assumed that the renderers follow some form of stateful pattern for rendering to Figures. Therefore, the major interface for rendering involves providing a *figure_id* or a *bool* about whether a new figure should be used. If neither are provided then the default state of the rendering engine is assumed to be maintained.

Providing both a `figure_id` and `new_figure == True` is not a valid state.

Parameters

- **figure_id** (*object*) – A figure id. Could be any valid object that identifies a figure in a given framework (*str*, *int*, *float*, etc.).
- **new_figure** (*bool*) – Whether the rendering engine should create a new figure.

Raises`ValueError` – It is not valid to provide a figure id AND request a new figure to be rendered on.

clear_figure()
Abstract method for clearing the current figure.

force_draw()
Abstract method for forcing the current figure to render.

get_figure()
Abstract method for getting the correct figure to render on. Should also set the correct *figure_id* for the figure.

Returnsfigure (*object*) – The figure object that the renderer will render on.

render (***kwargs*)
Abstract method to be overridden by the renderer. This will implement the actual rendering code for a given object class.

Parameterskwargs (*dict*) – Passed through to specific rendering engine.

Returnsviewer (`Renderer`) – Pointer to *self*.

save_figure (***kwargs*)
Abstract method for saving the figure of the current *figure_id* to file. It will implement the actual saving code for a given object class.

Parameterskwargs (*dict*) – Options to be set when saving the figure to file.

Viewable

class menpo.visualize.**Viewable**

Bases: object

Abstract interface for objects that can visualize themselves. This assumes that the class has dimensionality as the view method checks the n_dims property to wire up the correct view method.

LandmarkableViewable

class menpo.visualize.**LandmarkableViewable**

Bases: object

Mixin for Landmarkable and Viewable objects. Provides a single helper method for viewing Landmarks and *self* on the same figure.

MatplotlibRenderer

class menpo.visualize.**MatplotlibRenderer**(*figure_id*, *new_figure*)

Bases: Renderer

Abstract class for rendering visualizations using Matplotlib.

Parameters

- **figure_id** (*int* or None) – A figure id or None. None assumes we maintain the Matplotlib state machine and use *plt.gcf()*.
- **new_figure** (*bool*) – If True, it creates a new figure to render on.

clear_figure()

Method for clearing the current figure.

force_draw()

Method for forcing the current figure to render. This is useful for the widgets animation.

get_figure()

Gets the figure specified by the combination of self.figure_id and self.new_figure. If self.figure_id == None then plt.gcf() is used. self.figure_id is also set to the correct id of the figure if a new figure is created.

Returns figure (*Matplotlib figure object*) – The figure we will be rendering on.

render(***kwargs*)

Abstract method to be overridden by the renderer. This will implement the actual rendering code for a given object class.

Parameters kwargs (*dict*) – Passed through to specific rendering engine.

Returns viewer (Renderer) – Pointer to *self*.

save_figure(*filename*, *format='png'*, *dpi=None*, *face_colour='w'*, *edge_colour='w'*, *orientation='portrait'*, *paper_type='letter'*, *transparent=False*, *pad_inches=0.1*, *overwrite=False*)

Method for saving the figure of the current *figure_id* to file.

Parameters

- **filename** (*str* or *file*-like object) – The string path or file-like object to save the figure at/into.

- **format** (*str*) – The format to use. This must match the file path if the file path is a *str*.
- **dpi** (*int* > 0 or `None`, optional) – The resolution in dots per inch.
- **face_colour** (*See Below, optional*) – The face colour of the figure rectangle. Example options

```
{``r``, ``g``, ``b``, ``c``, ``m``, ``k``, ``w``}
or
``(3, )`` `ndarray`
or
`list` of len 3
```

- **edge_colour** (*See Below, optional*) – The edge colour of the figure rectangle. Example options

```
{``r``, ``g``, ``b``, ``c``, ``m``, ``k``, ``w``}
or
``(3, )`` `ndarray`
or
`list` of len 3
```

- **orientation** ({`portrait`, `landscape`}, optional) – The page orientation.
- **paper_type** (*See Below, optional*) – The type of the paper. Example options

```
{``letter``, ``legal``, ``executive``, ``ledger``,
 ``a0`` through ``a10``, ``b0` through ``b10``}
```

- **transparent** (*bool*, optional) – If `True`, the axes patches will all be transparent; the figure patch will also be transparent unless *face_colour* and/or *edge_colour* are specified. This is useful, for example, for displaying a plot on top of a coloured background on a web page. The transparency of these patches will be restored to their original values upon exit of this function.
- **pad_inches** (*float*, optional) – Amount of padding around the figure.
- **overwrite** (*bool*, optional) – If `True`, the file will be overwritten if it already exists.

save_figure_widget()

Method for saving the figure of the current `figure_id` to file using *menpowidgets.base.save_matplotlib_figure* widget.

Patches

view_patches

menpo.visualize.**view_patches**(*patches*, *patch_centers*, *patches_indices=None*, *offset_index=None*, *figure_id=None*, *new_figure=False*, *background='white'*, *render_patches=True*, *channels=None*, *interpolation='none'*, *cmap_name=None*, *alpha=1.0*, *render_patches_bboxes=True*, *bboxes_line_colour='r'*, *bboxes_line_style='-'*, *bboxes_line_width=1*, *render_centers=True*, *render_lines=True*, *line_colour=None*, *line_style='-'*, *line_width=1*, *render_markers=True*, *marker_style='o'*, *marker_size=5*, *marker_face_colour=None*, *marker_edge_colour=None*, *marker_edge_width=1.0*, *render_numbering=False*, *numbers_horizontal_align='center'*, *numbers_vertical_align='bottom'*, *numbers_font_name='sans-serif'*, *numbers_font_size=10*, *numbers_font_style='normal'*, *numbers_font_weight='normal'*, *numbers_font_colour='k'*, *render_axes=False*, *axes_font_name='sans-serif'*, *axes_font_size=10*, *axes_font_style='normal'*, *axes_font_weight='normal'*, *axes_x_limits=None*, *axes_y_limits=None*, *axes_x_ticks=None*, *axes_y_ticks=None*, *figure_size=(7, 7)*)

Method that renders the provided *patches* on a canvas. The user can choose whether to render the patch centers (*render_centers*) as well as rectangle boundaries around the patches (*render_patches_bboxes*).

The patches argument can have any of the two formats that are returned from the *extract_patches()* and *extract_patches_around_landmarks()* methods of the `Image` class. Specifically it can be:

1. `(n_center, n_offset, self.n_channels, patch_shape)` *ndarray*
2. *list* of `n_center * n_offset` `Image` objects

Parameters

- **patches** (*ndarray* or *list*) – The values of the patches. It can have any of the two formats that are returned from the *extract_patches()* and *extract_patches_around_landmarks()* methods. Specifically, it can either be an `(n_center, n_offset, self.n_channels, patch_shape)` *ndarray* or a *list* of `n_center * n_offset` `Image` objects.
- **patch_centers** (`PointCloud`) – The centers around which to visualize the patches.
- **patches_indices** (*int* or *list* of *int* or `None`, optional) – Defines the patches that will be visualized. If `None`, then all the patches are selected.
- **offset_index** (*int* or `None`, optional) – The offset index within the provided *patches* argument, thus the index of the second dimension from which to sample. If `None`, then `0` is used.
- **figure_id** (*object*, optional) – The id of the figure to be used.
- **new_figure** (*bool*, optional) – If `True`, a new figure is created.
- **background** (`{'black', 'white'}`, optional) – If `'black'`, then the background is set equal to the minimum value of *patches*. If `'white'`, then the background is set equal to the maximum value of *patches*.
- **render_patches** (*bool*, optional) – Flag that determines whether to render the patch values.
- **channels** (*int* or *list* of *int* or `all` or `None`, optional) – If *int* or *list* of *int*, the specified channel(s) will be rendered. If `all`, all the channels will be rendered in subplots. If `None`

and the image is RGB, it will be rendered in RGB mode. If `None` and the image is not RGB, it is equivalent to `all`.

- **interpolation** (*See Below, optional*) – The interpolation used to render the image. For example, if `bilinear`, the image will be smooth and if `nearest`, the image will be pixelated. Example options

```
{none, nearest, bilinear, bicubic, spline16, spline36, hanning,
hamming, hermite, kaiser, quadric, catrom, gaussian, bessel,
mitchell, sinc, lanczos}
```

- **cmap_name** (*str*, optional,) – If `None`, single channel and three channel images default to greyscale and rgb colormaps respectively.
- **alpha** (*float*, optional) – The alpha blending value, between 0 (transparent) and 1 (opaque).
- **render_patches_bboxes** (*bool*, optional) – Flag that determines whether to render the bounding box lines around the patches.
- **bboxes_line_colour** (*See Below, optional*) – The colour of the lines. Example options:

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **bboxes_line_style** (`{-, --, -., :}`, optional) – The style of the lines.
- **bboxes_line_width** (*float*, optional) – The width of the lines.
- **render_centers** (*bool*, optional) – Flag that determines whether to render the patch centers.
- **render_lines** (*bool*, optional) – If `True`, the edges will be rendered.
- **line_colour** (*See Below, optional*) – The colour of the lines. Example options:

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **line_style** (`{-, --, -., :}`, optional) – The style of the lines.
- **line_width** (*float*, optional) – The width of the lines.
- **render_markers** (*bool*, optional) – If `True`, the markers will be rendered.
- **marker_style** (*See Below, optional*) – The style of the markers. Example options

```
{., ,, o, v, ^, <, >, +, x, D, d, s, p, *, h, H, 1, 2, 3, 4, 8}
```

- **marker_size** (*int*, optional) – The size of the markers in points.
- **marker_face_colour** (*See Below, optional*) – The face (filling) colour of the markers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **marker_edge_colour** (*See Below, optional*) – The edge colour of the markers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **marker_edge_width** (*float*, optional) – The width of the markers' edge.
- **render_numbering** (*bool*, optional) – If `True`, the landmarks will be numbered.
- **numbers_horizontal_align** (`{center, right, left}`, optional) – The horizontal alignment of the numbers' texts.
- **numbers_vertical_align** (`{center, top, bottom, baseline}`, optional) – The vertical alignment of the numbers' texts.
- **numbers_font_name** (*See Below, optional*) – The font of the numbers. Example options

```
{serif, sans-serif, cursive, fantasy, monospace}
```

- **numbers_font_size** (*int*, optional) – The font size of the numbers.
- **numbers_font_style** (`{normal, italic, oblique}`, optional) – The font style of the numbers.
- **numbers_font_weight** (*See Below, optional*) – The font weight of the numbers. Example options

```
{ultralight, light, normal, regular, book, medium, roman,
semibold, demibold, demi, bold, heavy, extra bold, black}
```

- **numbers_font_colour** (*See Below, optional*) – The font colour of the numbers. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **render_axes** (*bool*, optional) – If `True`, the axes will be rendered.
- **axes_font_name** (*See Below, optional*) – The font of the axes. Example options

```
{serif, sans-serif, cursive, fantasy, monospace}
```

- **axes_font_size** (*int*, optional) – The font size of the axes.
- **axes_font_style** (`{normal, italic, oblique}`, optional) – The font style of the axes.
- **axes_font_weight** (*See Below, optional*) – The font weight of the axes. Example options

```
{ultralight, light, normal, regular, book, medium, roman,
semibold,demibold, demi, bold, heavy, extra bold, black}
```

- **axes_x_limits** (*float* or (*float*, *float*) or `None`, optional) – The limits of the x axis. If *float*, then it sets padding on the right and left of the shape as a percentage of the shape's

width. If *tuple* or *list*, then it defines the axis limits. If `None`, then the limits are set automatically.

- **axes_y_limits** (*float* or (*float*, *float*) or `None`, optional) – The limits of the y axis. If *float*, then it sets padding on the top and bottom of the shape as a percentage of the shape's height. If *tuple* or *list*, then it defines the axis limits. If `None`, then the limits are set automatically.
- **axes_x_ticks** (*list* or *tuple* or `None`, optional) – The ticks of the x axis.
- **axes_y_ticks** (*list* or *tuple* or `None`, optional) – The ticks of the y axis.
- **figure_size** ((*float*, *float*) *tuple* or `None` optional) – The size of the figure in inches.

Returns **viewer** (*ImageViewer*) – The image viewing object.

Print Utilities

print_progress

`menpo.visualize.`**`print_progress`**(*iterable*, *prefix=''*, *n_items=None*, *offset=0*, *show_bar=True*, *show_count=True*, *show_eta=True*, *end_with_newline=True*, *min_seconds_between_updates=0.1*)

Print the remaining time needed to compute over an iterable.

To use, wrap an existing iterable with this function before processing in a for loop (see example).

The estimate of the remaining time is based on a moving average of the last 100 items completed in the loop.

Parameters

- **iterable** (*iterable*) – An iterable that will be processed. The iterable is passed through by this function, with the time taken for each complete iteration logged.
- **prefix** (*str*, optional) – If provided a string that will be prepended to the progress report at each level.
- **n_items** (*int*, optional) – Allows for `iterator` to be a generator whose length will be assumed to be *n_items*. If not provided, then `iterator` needs to be *Sizable*.
- **offset** (*int*, optional) – Useful in combination with `n_items` - report back the progress as if *offset* items have already been handled. `n_items` will be left unchanged.
- **show_bar** (*bool*, optional) – If False, The progress bar (e.g. [=========]) will be hidden.
- **show_count** (*bool*, optional) – If False, The item count (e.g. (4/25)) will be hidden.
- **show_eta** (*bool*, optional) – If False, The estimated time to finish (e.g. - 00:00:03 remaining) will be hidden.
- **end_with_newline** (*bool*, optional) – If False, there will be no new line added at the end of the dynamic printing. This means the next print statement will overwrite the dynamic report presented here. Useful if you want to follow up a print_progress with a second print_progress, where the second overwrites the first on the same line.
- **min_seconds_between_updates** (*float*, optional) – The number of seconds that have to pass between two print updates. This allows `print_progress` to be used on fast iterations without incurring a significant overhead. Set to `0` to disable this throttling.

Raises `ValueError` – `offset` provided without `n_items`

Examples

This for loop:

```
from time import sleep
for i in print_progress(range(100)):
    sleep(1)
```

prints a progress report of the form:

```
[=============       ] 70% (7/10) - 00:00:03 remaining
```

print_dynamic

`menpo.visualize.print_dynamic(str_to_print)`

Prints dynamically the provided *str*, i.e. the *str* is printed and then the buffer gets flushed.

Parameters **str_to_print** (*str*) – The string to print.

progress_bar_str

`menpo.visualize.progress_bar_str(percentage, bar_length=20, bar_marker='=', show_bar=True)`

Returns an *str* of the specified progress percentage. The percentage is represented either in the form of a progress bar or in the form of a percentage number. It can be combined with the `print_dynamic()` function.

Parameters

- **percentage** (*float*) – The progress percentage to be printed. It must be in the range `[0, 1]`.
- **bar_length** (*int*, optional) – Defines the length of the bar in characters.
- **bar_marker** (*str*, optional) – Defines the marker character that will be used to fill the bar.
- **show_bar** (*bool*, optional) – If `True`, the *str* includes the bar followed by the percentage, e.g. `'[===== ] 50%'`

  If `False`, the *str* includes only the percentage, e.g. `'50%'`

Returns **progress_str** (*str*) – The progress percentage string that can be printed.

Raises

- `ValueError` – `percentage` is not in the range `[0, 1]`
- `ValueError` – `bar_length` must be an integer >= `1`
- `ValueError` – `bar_marker` must be a string of length 1

Examples

This for loop:

```
n_iters = 2000
for k in range(n_iters):
    print_dynamic(progress_bar_str(float(k) / (n_iters-1)))
```

prints a progress bar of the form:

```
[=============        ] 68%
```

---

bytes_str

`menpo.visualize.bytes_str(num)`

Converts bytes to a human readable format. For example:

```
print_bytes(12345) returns '12.06 KB'
print_bytes(123456789) returns '117.74 MB'
```

Parameters **num** (*int*) – The size in bytes.

Raises `ValueError` – num must be int >= 0

Various

plot_curve

`menpo.visualize.plot_curve(x_axis, y_axis, figure_id=None, new_figure=True, legend_entries=None, title='', x_label='', y_label='', axes_x_limits=0.0, axes_y_limits=None, axes_x_ticks=None, axes_y_ticks=None, render_lines=True, line_colour=None, line_style='-', line_width=1, render_markers=True, marker_style='o', marker_size=5, marker_face_colour=None, marker_edge_colour='k', marker_edge_width=1.0, render_legend=True, legend_title='', legend_font_name='sans-serif', legend_font_style='normal', legend_font_size=10, legend_font_weight='normal', legend_marker_scale=None, legend_location=2, legend_bbox_to_anchor=(1.05, 1.0), legend_border_axes_pad=None, legend_n_columns=1, legend_horizontal_spacing=None, legend_vertical_spacing=None, legend_border=True, legend_border_padding=None, legend_shadow=False, legend_rounded_corners=False, render_axes=True, axes_font_name='sans-serif', axes_font_size=10, axes_font_style='normal', axes_font_weight='normal', figure_size=(7, 7), render_grid=True, grid_line_style='–', grid_line_width=1)`

Plot a single or multiple curves on the same figure.

Parameters

- **x_axis** (*list* or *array*) – The values of the horizontal axis. They are common for all curves.
- **y_axis** (*list* of *lists* or *arrays*) – A *list* with *lists* or *arrays* with the values of the vertical axis for each curve.
- **figure_id** (*object*, optional) – The id of the figure to be used.
- **new_figure** (*bool*, optional) – If `True`, a new figure is created.
- **legend_entries** (*list of 'str* or `None`, optional) – If *list* of *str*, it must have the same length as *errors list* and each *str* will be used to name each curve. If `None`, the CED curves will be named as *'Curve %d'*.

- **title** (*str*, optional) – The figure's title.
- **x_label** (*str*, optional) – The label of the horizontal axis.
- **y_label** (*str*, optional) – The label of the vertical axis.
- **axes_x_limits** (*float* or (*float*, *float*) or `None`, optional) – The limits of the x axis. If *float*, then it sets padding on the right and left of the graph as a percentage of the curves' width. If *tuple* or *list*, then it defines the axis limits. If `None`, then the limits are set automatically.
- **axes_y_limits** (*float* or (*float*, *float*) or `None`, optional) – The limits of the y axis. If *float*, then it sets padding on the top and bottom of the graph as a percentage of the curves' height. If *tuple* or *list*, then it defines the axis limits. If `None`, then the limits are set automatically.
- **axes_x_ticks** (*list* or *tuple* or `None`, optional) – The ticks of the x axis.
- **axes_y_ticks** (*list* or *tuple* or `None`, optional) – The ticks of the y axis.
- **render_lines** (*bool* or *list* of *bool*, optional) – If `True`, the line will be rendered. If *bool*, this value will be used for all curves. If *list*, a value must be specified for each curve, thus it must have the same length as *y_axis*.
- **line_colour** (*colour* or *list* of *colour* or `None`, optional) – The colour of the lines. If not a *list*, this value will be used for all curves. If *list*, a value must be specified for each curve, thus it must have the same length as *y_axis*. If `None`, the colours will be linearly sampled from jet colormap. Example *colour* options are

```
{'r', 'g', 'b', 'c', 'm', 'k', 'w'}
or
(3, ) ndarray
```

- **line_style** (`{'-', '--', '-.', ':'}` or *list* of those, optional) – The style of the lines. If not a *list*, this value will be used for all curves. If *list*, a value must be specified for each curve, thus it must have the same length as *y_axis*.
- **line_width** (*float* or *list* of *float*, optional) – The width of the lines. If *float*, this value will be used for all curves. If *list*, a value must be specified for each curve, thus it must have the same length as *y_axis*.
- **render_markers** (*bool* or *list* of *bool*, optional) – If `True`, the markers will be rendered. If *bool*, this value will be used for all curves. If *list*, a value must be specified for each curve, thus it must have the same length as *y_axis*.
- **marker_style** (*marker* or *list* of *markers*, optional) – The style of the markers. If not a *list*, this value will be used for all curves. If *list*, a value must be specified for each curve, thus it must have the same length as *y_axis*. Example *marker* options

```
{'.', ',', 'o', 'v', '^', '<', '>', '+', 'x', 'D', 'd', 's',
 'p', '*', 'h', 'H', '1', '2', '3', '4', '8'}
```

- **marker_size** (*int* or *list* of *int*, optional) – The size of the markers in points. If *int*, this value will be used for all curves. If *list*, a value must be specified for each curve, thus it must have the same length as *y_axis*.
- **marker_face_colour** (*colour* or *list* of *colour* or `None`, optional) – The face (filling) colour of the markers. If not a *list*, this value will be used for all curves. If *list*, a value must be specified for each curve, thus it must have the same length as *y_axis*. If `None`, the colours will be linearly sampled from jet colormap. Example *colour* options are

```
{'r', 'g', 'b', 'c', 'm', 'k', 'w'}
or
(3, ) ndarray
```

- **marker_edge_colour** (*colour* or *list* of *colour* or `None`, optional) – The edge colour of the markers. If not a *list*, this value will be used for all curves. If *list*, a value must be specified for each curve, thus it must have the same length as *y_axis*. If `None`, the colours will be linearly sampled from jet colormap. Example *colour* options are

```
{'r', 'g', 'b', 'c', 'm', 'k', 'w'}
or
(3, ) ndarray
```

- **marker_edge_width** (*float* or *list* of *float*, optional) – The width of the markers' edge. If *float*, this value will be used for all curves. If *list*, a value must be specified for each curve, thus it must have the same length as *y_axis*.
- **render_legend** (*bool*, optional) – If `True`, the legend will be rendered.
- **legend_title** (*str*, optional) – The title of the legend.
- **legend_font_name** (*See below, optional*) – The font of the legend. Example options

```
{'serif', 'sans-serif', 'cursive', 'fantasy', 'monospace'}
```

- **legend_font_style** (`{'normal', 'italic', 'oblique'}`, optional) – The font style of the legend.
- **legend_font_size** (*int*, optional) – The font size of the legend.
- **legend_font_weight** (*See below, optional*) – The font weight of the legend. Example options

```
{'ultralight', 'light', 'normal', 'regular', 'book', 'medium',
 'roman', 'semibold', 'demibold', 'demi', 'bold', 'heavy',
 'extra bold', 'black'}
```

- **legend_marker_scale** (*float*, optional) – The relative size of the legend markers with respect to the original
- **legend_location** (*int*, optional) – The location of the legend. The predefined values are:

'best'	0
'upper right'	1
'upper left'	2
'lower left'	3
'lower right'	4
'right'	5
'center left'	6
'center right'	7
'lower center'	8
'upper center'	9
'center'	10

- **legend_bbox_to_anchor** ((*float*, *float*), optional) – The bbox that the legend will be anchored.

- **legend_border_axes_pad** (*float*, optional) – The pad between the axes and legend border.
- **legend_n_columns** (*int*, optional) – The number of the legend's columns.
- **legend_horizontal_spacing** (*float*, optional) – The spacing between the columns.
- **legend_vertical_spacing** (*float*, optional) – The vertical space between the legend entries.
- **legend_border** (*bool*, optional) – If `True`, a frame will be drawn around the legend.
- **legend_border_padding** (*float*, optional) – The fractional whitespace inside the legend border.
- **legend_shadow** (*bool*, optional) – If `True`, a shadow will be drawn behind legend.
- **legend_rounded_corners** (*bool*, optional) – If `True`, the frame's corners will be rounded (fancybox).
- **render_axes** (*bool*, optional) – If `True`, the axes will be rendered.
- **axes_font_name** (*See below, optional*) – The font of the axes. Example options

```
{'serif', 'sans-serif', 'cursive', 'fantasy', 'monospace'}
```

- **axes_font_size** (*int*, optional) – The font size of the axes.
- **axes_font_style** (`{'normal', 'italic', 'oblique'}`, optional) – The font style of the axes.
- **axes_font_weight** (*See below, optional*) – The font weight of the axes. Example options

```
{'ultralight', 'light', 'normal', 'regular', 'book', 'medium',
 'roman', 'semibold', 'demibold', 'demi', 'bold', 'heavy',
 'extra bold', 'black'}
```

- **figure_size** ((*float*, *float*) or `None`, optional) – The size of the figure in inches.
- **render_grid** (*bool*, optional) – If `True`, the grid will be rendered.
- **grid_line_style** (`{'-', '--', '-.', ':'}`, optional) – The style of the grid lines.
- **grid_line_width** (*float*, optional) – The width of the grid lines.

Raises `ValueError` – legend_entries list has different length than y_axis list

Returns **viewer** (`GraphPlotter`) – The viewer object.

plot_gaussian_ellipses

`menpo.visualize.`**`plot_gaussian_ellipses`**(*covariances*, *means*, *n_std=2*, *render_colour_bar=True*, *colour_bar_label='Normalized Standard Deviation'*, *colour_map='jet'*, *figure_id=None*, *new_figure=False*, *image_view=True*, *line_colour='r'*, *line_style='-'*, *line_width=1.0*, *render_markers=True*, *marker_edge_colour='k'*, *marker_face_colour='k'*, *marker_edge_width=1.0*, *marker_size=5*, *marker_style='o'*, *render_axes=False*, *axes_font_name='sans-serif'*, *axes_font_size=10*, *axes_font_style='normal'*, *axes_font_weight='normal'*, *crop_proportion=0.1*, *figure_size=(7, 7)*)

Method that renders the Gaussian ellipses that correspond to a set of covariance matrices and mean vectors. Naturally, this only works for 2-dimensional random variables.

Parameters

- **`covariances`** (*list* of `(2, 2)` *ndarray*) – The covariance matrices that correspond to each ellipse.
- **`means`** (*list* of `(2, )` *ndarray*) – The mean vectors that correspond to each ellipse.
- **`n_std`** (*float*, optional) – This defines the size of the ellipses in terms of number of standard deviations.
- **`render_colour_bar`** (*bool*, optional) – If `True`, then the ellipses will be coloured based on their normalized standard deviations and a colour bar will also appear on the side. If `False`, then all the ellipses will have the same colour.
- **`colour_bar_label`** (*str*, optional) – The title of the colour bar. It only applies if *render_colour_bar* is `True`.
- **`colour_map`** (*str*, optional) – A valid Matplotlib colour map. For more info, please refer to *matplotlib.cm*.
- **`figure_id`** (*object*, optional) – The id of the figure to be used.
- **`new_figure`** (*bool*, optional) – If `True`, a new figure is created.
- **`image_view`** (*bool*, optional) – If `True` the ellipses will be rendered in the image coordinates system.
- **`line_colour`** (*`See Below, optional`*) – The colour of the lines of the ellipses. Example options:

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **`line_style`** (`{-, --, -., :}`, optional) – The style of the lines of the ellipses.
- **`line_width`** (*float*, optional) – The width of the lines of the ellipses.
- **`render_markers`** (*bool*, optional) – If `True`, the centers of the ellipses will be rendered.
- **`marker_style`** (*`See Below, optional`*) – The style of the centers of the ellipses. Example options

```
{., ,, o, v, ^, <, >, +, x, D, d, s, p, *, h, H, 1, 2, 3, 4, 8}
```

- **marker_size** (*int*, optional) – The size of the centers of the ellipses in points.
- **marker_face_colour** (*See Below, optional*) – The face (filling) colour of the centers of the ellipses. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **marker_edge_colour** (*See Below, optional*) – The edge colour of the centers of the ellipses. Example options

```
{r, g, b, c, m, k, w}
or
(3, ) ndarray
```

- **marker_edge_width** (*float*, optional) – The edge width of the centers of the ellipses.
- **render_axes** (*bool*, optional) – If `True`, the axes will be rendered.
- **axes_font_name** (*See Below, optional*) – The font of the axes. Example options

```
{serif, sans-serif, cursive, fantasy, monospace}
```

- **axes_font_size** (*int*, optional) – The font size of the axes.
- **axes_font_style** (`{normal, italic, oblique}`, optional) – The font style of the axes.
- **axes_font_weight** (*See Below, optional*) – The font weight of the axes. Example options

```
{ultralight, light, normal, regular, book, medium, roman,
semibold,demibold, demi, bold, heavy, extra bold, black}
```

- **crop_proportion** (*float*, optional) – The proportion to be left around the centers' point-cloud.
- **figure_size** ((*float*, *float*) *tuple* or `None` optional) – The size of the figure in inches.

Changelog

0.8.0 (2017/05/04)

Menpo 0.8.0 includes a variety of minor bug fixes and a few major features:

A large simplification is made to how Menpo handles landmarks. In the past, Landmarks were a special type in Menpo, they weren't shapes. That meant we frequently had to access the underlying shape information (at *.lms*), which was always a litle clunky and confusing, especailly to newcomers.

In this release, we instead change the dynamic so that any shape can be attached as a landmark directly. If you only need to store a list of points with no groups or labels, you can now just use a PointCloud, which is totally natural in Menpo. The traditional features of LandmarkGroup (handling groups etc) are now available in a speciailization Shape called *LabelledPointUndirectedGraph*.

The migration is simple - just remove *.lms* anywhere from your codebase (a warning will be raised when you do use *.lms* - this will be deprecated in the future).

A smaller set of additional features in 0.8:

1. Most menpo objects print a sensible string for their __repr__, which is helpful in the notebook.
2. you can now tab complete landmark keys in the notebook.

Github Pull Requests

- #766 upgrades for menpowidgets (ipywidgets 6) (@nontas)
- #798 move back to making macOS builds with travis (@patricksnape)
- #799 move back to making Win builds with appveyor (@patricksnape)
- #792 add throttling to print_progress for fast iterations (@jabooth)
- #790 fix __setstate__ for old landmarks (@jabooth)
- #787 add a default __str__ implementation to avoid inf recursion on __repr__ (@jabooth)
- #782 __repr__ return __str__ for all Copyable objects (@jabooth)
- #780 add support for ipython tab complete landmarks (@jabooth)
- #675 LandmarkGroups are now Shapes (@patricksnape, @jabooth, @nontas)
- #778 Minor documentation clarification in image rasterize utility (@grigorisg9gr)
- #761 Add clip_pixels to Image and automatically clip RGB visualisations (@grigorisg9gr)

0.7.7 (2017/01/05)

Minor bug fixes

Github Pull Requests

- #767 Minor fixes (@patricksnape)
- #774 Fix pip install by properly including source files (@patricksnape)
- #775 Allow Pillow 4.x (@patricksnape)
- #776 Manifest includes should be recursive (@jabooth)

0.7.6 (2016/12/10)

Minor bug fixes and three new pieces of functionality:

- 3D visualization improvements (@nontas)
- Bounding cubiod method for 3D shapes (@nontas)
- New transforms to change dimensionality of shapes (@jabooth)

Github Pull Requests

- #745 Documentation change in image gradient for int pixels dtype. (@grigorisg9gr)
- #750 Copy landmarks and path (@jabooth)
- #751 WithDims transform and with_dims method (@jabooth)
- #754 Restrict the video channels in exports(@grigorisg9gr)
- #755 fix ndarray slicing of lazylist, cleaner __add__ implementation (@jabooth)
- #756 remove duplicate import_pickles def (!) (@jabooth)
- #757 don't print_dynamic size report in as_matrix (@jabooth)
- #759 Bounding cuboid (@nontas)
- #760 Quaternions for 3D Rotations (@nontas)
- #762 3D Visualization Upgrade (@nontas)
- #764 Fix NUMPY_INC_PATH detection for multiple dirs found (@jabooth)

0.7.5 (2016/11/17)

Minor bug fixes and three new pieces of functionality:

- Fix bug in video importing when importing long videos (closed pipe) (@patricksnape)
- Update *MANIFEST.in* to include the *LICENSE.txt* and *AUTHORS.txt*
- Add new *transform_about_centre* method on images. Allow easily performing operations such as rotating an image about it's centre or shearing an image about it's centre.
- Allow path only exporters (rather than hard requiring a buffer). The exporting logic was also updated to support multiple kwargs to be passed through to the exporters easily.
- New transforms to move between image and texture coordinates. (@jabooth).

Github Pull Requests

- #724 add transforms for tcoords -> image coords (@jabooth)
- #733 Remove user guide as it now lives at www.menpo.org (@nontas)
- #729 Fix PCA docs w.r.t *centre* parameter (@jabooth)
- #736 Fix bug importing boolean images with pillow (@grigorisg9gr)
- #739 Fix PointGraph printing to mention dimensionality (@nontas)
- #737 Allow path only exporters. Fix landmarking exporting on Python 3. (@patricksnape)
- #735 Fix *init_from_channels_at_back* to support 2D arrays. (@grigorisg9gr, @patricksnape)
- #738 Add *transform_about_centre* to images (@nontas, @patricksnape)
- #743 Set *nan* values to *None* in video importing (@JeanKossaifi)
- #744 Fix Regression: Allow *None* for *landmark_resolver* (@grigorisg9gr, @patricksnape)

0.7.4 (2016/08/18)

Minor fixes and additions including improved compatibility with loading older menpo PCAModel pickles and importing Python 2 pickles in Python 3.

Github Pull Requests

- #723 Add optional 'encoding' argument to import_pickle. (@patricksnape)
- #728 Allow for unpickling of the older PCAModel. (@patricksnape)
- #726 Improve pip install. (@patricksnape)
- #731 Pin setuptools to 23.x. (@jabooth)

0.7.3 (2016/08/05)

Minor fixes and additions including allowing more flexibility in FFMPEG exporting options, supporting more types with normal calculations, and tidying up the conda build recipe.

Github Pull Requests

- #716 allow for forced inexact frame count in FFMpegVideoReader. (@san-bil)
- #714 Utilise the kwargs in exporting video with ffmpeg. (@grigorisg9gr)
- #720 Simplify the conda build. (@patricksnape)
- #719 Support more types for normals. (@patricksnape)

0.7.2 (2016/06/22)

Minor fixes including allowing exporting grayscale videos and fixing a minor bug in `PointGraph` masking. The Menpo logo has also been updated.

Github Pull Requests

- #709 Minor change in documentation of pickle, contrain_landmarks in image. (@grigorisg9gr)
- #713 Remove zero edge adjacency check. (@patricksnape)
- #711 Enable greyscale video to be exported. (@grigorisg9gr,@patricksnape)

0.7.1 (2016/06/10)

We now ship our own FFMPEG video importer based on piping, thus removing the dependency on imageio. A couple of further minor improvements were also introduced:

- Added `register_*` methods to the importing packages to make it simpler to add custom importers. For example, use `menpo.io.register_image_importer('.extension', your_method)` to register a new importer.
- Fix rasterization bug for maplotlib on Python 3.x

- `normalise` keyword arguments are now deprecated in favour of `normalize` to make spelling consistent across project.
- LazyList is now copyable -> `LazyList.copy`
- LazyList `map` method now accepts a list of callables as well as a single callable.
- Add `LazyList.init_from_iterable` for easily creating lazy lists from existing iterables.
- Fix small visualisation bug for viewing of LandmarkGroup that contain PointClouds
- New `pixel_with_channels_at_back` method for images
- Deprecate `init_from_rolled_channels` in favour of new method `init_from_channels_at_back`
- Deprecate `as_imageio`

Finally, as of this release we no longer use Appveyor, in favour of our own Windows Jenkins build boxes.

Github Pull Requests

- #694 Functional IO Package. (@patricksnape)
- #703 Fix the bug with rasterize landmarks with matplotlib backend. (@grigorisg9gr)
- #700 Standardise the normalize spelling in importers. (@grigorisg9gr)
- #702 Now reading videos using subprocess and ffmpeg. Drop ImageIO. (@JeanKossaifi,@patricksnape)
- #706 Autoscale PointCloud if no limits set. (@patricksnape)
- #707 LazyList init methods and are now Copyable. (@patricksnape)
- #708 Remove appveyor in favour of Jenkins. (@patricksnape)

0.7.0 (2016/05/20)

New release that contains some minor breaking changes. In general, the biggest changes are:

- Use ImageIO rather than Pillow for basic importing of some image types. The most important aspect of this change is that we now support importing videos! Our GIF support also became much more robust. Note that importing videos is still considered to be relatively experimental due to the underlying implementation in imageio not being 100% accurate. Therefore, we warn our users that importing videos for important experiments is not advised.
- Change multi-asset importing to use a new type - the *`LazyList`*. Lazy lists are a generic concept for a container that holds onto a list of callables which are invoked on indexing. This means that image importing, for example, returns immediately but can be **randomly indexed**. This is in contrast to generators, which have to be sequentially accessed. This is particularly important for video support, as the frames can be accessed randomly or sliced from the end (rather than having to pay the penalty of importing the entirety of a long video just to access the last frame, for example). A simple example of using the *`LazyList`* to import images is as follows:

```
import menpo.io as mio
images = mio.import_images('/path/to/many/images')  # Returns immediately
image0 = images[0]  # Loading performed at access

# Example of much simpler preprocessing
preprocess_func = lambda x: x.as_greyscale()
greyscale_images = images.map(preprocess_func)  # Returns immediately
grey_image0 = greyscale_images[0]  # Loading and as_greyscale() performed␣
↪at access
```

```
# Visualizing randomly is now much simpler too!
% matplotlib inline
from menpowidgets import visualize_images
visualize_images(greyscale_images)  # Can now randomly access list
```

- Move one step closer to ensuring that all image operatons are copies rather than inplace. This means breaking some methods as there was no 'non' inplace method (the break was to change them to return a copy). Likely the most common anti-pattern was code such as:

  ```
  import menpo.io as mio
  image = mio.import_builtin_asset.takeo_ppm().as_masked()
  image.constrain_landmarks_to_bounds()
  ```

  Which now requires assigning the call to `constrain_landmarks_to_bounds` to a variable, as a copy is returned:

  ```
  import menpo.io as mio
  image = mio.import_builtin_asset.takeo_ppm().as_masked()
  image = image.constrain_landmarks_to_bounds()
  ```

Note that this release also officially supports **Python 3.5**!

Breaking Changes

- ImageIO is used for importing. Therefore, the pixel values of some images have changed due to the difference in underlying importing code.
- Multi-asset importers are now of type `LazyList`.
- HOG previously returned negative values due to rounding errors on binning. This has been rectified, so the output values of HOG are now slightly different.
- `set_boundary_pixels` is no longer in place.
- `normalize_inplace` has been deprecated and removed. `normalize` is now a feature that abstracts out the normalisation logic.
- `gaussian_pyramid` and `pyramid` always return copies (before the first image was the original image, not copied).
- `constrain_to_landmarks`/`constrain_to_pointcloud`/`constrain_mask_to_landmarks` are no longer in place.
- `set_patches` is no longer in place.
- `has_landmarks_outside_bounds` is now a method.

New Features

- `from_tri_mask` method added to `TriMesh`
- `LazyList` type that holds a list of callables that are invoked on indexing.
- New rasterize methods. Given an image and a landmark group, return a new image with the landmarks rasterized onto the image. Useful for saving results to disk.
- Python 3.5 support!

- Better support for non `float64` image types. For example, `as_greyscale` can be called on a `uint8` image.
- New method `rasterize_landmarks` that allows easy image rasterization. By default, MaskedImages are masked with a black background. Use `as_unmasked` to change the colour/not returned masked image.
- Add `bounds` method to images. This is defined as `((0, 0), (height - 1, width - 1))` - the set of indices that are indexable into the image for sampling.
- Add `constrain_to_bounds` to `PointCloud`. Snaps the pointcloud exactly to the bounds given.
- `init_from_pointcloud` method add to `Image`. Allows the creation of an image that completely bounds a given pointcloud. This is useful for both viewing images of pointclouds and for creating 'reference frames' for algorithms like Active Appearance Models.
- `init_from_depth_image` method on `PointCloud` and subclasses. Allows the creation of a mesh from an image that contains pixel values that represent depth/height values. Very useful for visualising RGB-D data.
- `pickle_paths` method.
- Overwriting images now throws `OverwriteError` rather than just `ValueError` (`OverwriteError` is a subclass of `ValueError`) so this is not a breaking change.

Deprecated

- The previously deprecated `inplace` image methods **were not removed in this release**.
- `set_h_matrix` is deprecated for `Homogeneous` transforms.
- `set_masked_pixels` is deprecated in favor of from_vector.
- Deprecate `constrain_landmarks_to_bounds` on images.

Github Pull Requests

- #698 Video importing warnings. (@patricksnape)
- #697 Relex version constraints on dependencies. (@jabooth)
- #695 condaci fixes. (@patricksnape)
- #692 new OverwriteError raised specifically for overwrite errors in io.export. (@jabooth)
- #691 Add mio.pickle_paths(glob). (@jabooth)
- #690 Fix init_2d_grid for TriMesh subclasses + add init_from_depth_image. (@patricksnape)
- #687 WIP: BREAKING: Various release fixes. (@patricksnape)
- #685 GMRF mahalanobis computation with sparse precision. (@nontas)
- #684 Video importer docs and negative max_images. (@grigorisg9gr)
- #683 Bugfix: Widget imports. (@nontas)
- #682 Update the view_patches to show only the selected landmarks. (@grigorisg9gr)
- #680 Expose file extension to exporters (Fix PIL exporter bug). (@patricksnape)
- #678 Deprecate set_h_matrix and fix #677. (@patricksnape)
- #676 Implement LazyList __add__. (@patricksnape)
- #673 Fix the widgets in PCA. (@grigorisg9gr)
- #672 Use Conda environment.yml on RTD. (@patricksnape)

- #670 Rasterize 2D Landmarks Method. (@patricksnape)
- #669 BREAKING: Add LazyList - default importing is now Lazy. (@patricksnape)
- #668 Speedup as_greyscale. (@patricksnape)
- #666 Add the protocol option in exporting pickle. (@grigorisg9gr)
- #665 Fix bug with patches of different type than float64. (@patricksnape)
- #664 Python 3.5 builds. (@patricksnape)
- #661 Return labels - which maps to a KeysView as a list. (@patricksnape)
- #648 Turn coverage checking back on. (@patricksnape)
- #644 Remove label kwarg. (@patricksnape)
- #639 add from_tri_mask method to TriMesh instances. (@jabooth)
- #633 BREAKING: Imageio. (@patricksnape)
- #606 Fix negative values in HOG calculation. (@patricksnape)

0.6.2 (2015/12/13)

Add axes ticks option to `view_patches`.

Github Pull Requests

- #659 Add axes ticks options to view_patches (@nontas)

0.6.1 (2015/12/09)

Fix a nasty bug pertaining to a Diamond inheritance problem in PCA. Add the Gaussion Markov Random Field (GRMF) model. Also a couple of other bugfixes for visualization.

Github Pull Requests

- #658 PCA Diamond problem fix (@patricksnape)
- #655 Bugfix and improvements in visualize package (@nontas)
- #656 print_dynamic bugfix (@nontas)
- #635 Gaussian Markov Random Field (@nontas, @patricksnape)

0.6.0 (2015/11/26)

This release is another set of breaking changes for Menpo. All `in_place` methods have been deprecated to make the API clearer (always copy). The largest change is the removal of all widgets into a subpackage called menpowidgets. To continue using widgets within the Jupyter notebook, you should install menpowidgets.

Breaking Changes

- Procrustes analysis now checks for mirroring and disables it by default. This is a change in behaviour.
- The `sample_offsets` argument of `menpo.image.Image.extract_patches()` now expects a numpy array rather than a `PointCloud`.
- All widgets are removed and now exist as part of the menpowidgets project. The widgets are now only compatible with Jupyter 4.0 and above.
- Landmark labellers have been totally refactored and renamed. They have not been deprecated due to the changes. However, the new changes mean that the naming scheme of labels is now much more intuitive. Practically, the usage of labelling has only changed in that now it is possible to label not only *LandmarkGroup* but also `PointCloud` and numpy arrays directly.
- Landmarks are now warped by default, where previously they were not.
- All vlfeat features have now become optional and will not appear if cyvlfeat is not installed.
- All `label` keyword arguments have been removed. They were not found to be useful. For the same effect, you can always create a new landmark group that only contains that label and use that as the `group` key.

New Features

- New SIFT type features that return vectors rather than dense features. (`menpo.feature.vector_128_dsift()`, `menpo.feature.hellinger_vector_128_dsift()`)
- `menpo.shape.PointCloud.init_2d_grid()` static constructor for `PointCloud` and subclasses.
- Add `PCAVectorModel` class that allows performing PCA directly on arrays.
- New static constructors on PCA models for building PCA directly from covariance matrices or components (`menpo.model.PCAVectorModel.init_from_components()` and `menpo.model.PCAVectorModel.init_from_covariance_matrix()`).
- New `menpo.image.Image.mirror()` method on images.
- New `menpo.image.Image.set_patches()` methods on images.
- New `menpo.image.Image.rotate_ccw_about_centre()` method on images.
- When performing operations on images, you can now add the `return_transform` kwarg that will return both the new image **and** the transform that created the image. This can be very useful for processing landmarks after images have been cropped and rescaled for example.

Github Pull Requests

- #652 Deprecate a number of inplace methods (@jabooth)
- #653 New features (vector dsift) (@patricksnape)
- #651 remove deprecations from 0.5.0 (@jabooth)
- #650 PointCloud init_2d_grid (@patricksnape)
- #646 Add ibug_49 -> ibug_49 labelling (@patricksnape)
- #645 Add new PCAVectorModel class, refactor model package (@patricksnape, @nontas)
- #644 Remove label kwarg (@patricksnape)
- #643 Build fixes (@patricksnape)

- #638 bugfix 2D triangle areas sign was ambiguous (@jabooth)
- #634 Fixing @patricksnape and @nontas foolish errors (@yuxiang-zhou)
- #542 Add mirroring check to procrustes (@nontas, @patricksnape)
- #632 Widgets Migration (@patricksnape, @nontas)
- #631 Optional transform return on Image methods (@nontas)
- #628 Patches Visualization (@nontas)
- #629 Image counter-clockwise rotation (@nontas)
- #630 Mirror image (@nontas)
- #625 Labellers Refactoring (@patricksnape)
- #623 Fix widgets for new Jupyter/IPython 4 release (@patricksnape)
- #620 Define patches offsets as ndarray (@nontas)

0.5.3 (2015/08/12)

Tiny point release just fixing a typo in the `unique_edge_indices` method.

0.5.2 (2015/08/04)

Minor bug fixes and impovements including:

- Menpo is now better at preserving dtypes other than np.float through common operations
- Image has a new convenience constructor `init_from_rolled_channels()` to handle building images that have the channels at the back of the array.
- There are also new `crop_to_pointcloud()` and `crop_to_pointcloud_proportion()` methods to round out the Image API, and a deprecation of `rescale_to_reference_shape()` in favour of `rescale_to_pointcloud()` to make things more consistent.
- The `gradient()` method is deprecated (use `menpo.feature.gradient` instead)
- Propagation of the `.path` property when using `as_masked()` was fixed
- Fix for exporting 3D LJSON landmark files
- A new `shuffle` kwarg (default `False`) is present on all multi importers.

Github Pull Requests

- #617 add shuffle kwarg to multi import generators (@jabooth)
- #619 Ensure that LJSON landmarks are read in as floats (@jabooth)
- #618 Small image fix (@patricksnape)
- #613 Balance out rescale/crop methods (@patricksnape)
- #615 Allow exporting of 3D landmarks. (@mmcauliffe)
- #612 Type maintain (@patricksnape)
- #602 Extract patches types (@patricksnape)

- #608 Slider for selecting landmark group on widgets (@nontas)
- #605 tmp move to master condaci (@jabooth)

0.5.1 (2015/07/16)

A small point release that improves the Cython code (particularly extracting patches) compatibility with different data types. In particular, more floating point data types are now supported. `print_progress` was added and widgets were fixed after the Jupyter 4.0 release. Also, upgrade cyvlfeat requirement to 0.4.0.

Github Pull Requests

- #604 print_progress enhancements (@jabooth)
- #603 Fixes for new cyvlfeat (@patricksnape)
- #599 Add erode and dilate methods to MaskedImage (@jalabort)
- #601 Add sudo: false to turn on container builds (@patricksnape)
- #600 Human3.6M labels (@nontas)

0.5.0 (2015/06/25)

This release of Menpo makes a number of very important **BREAKING** changes to the format of Menpo's core data types. Most importantly is #524 which swaps the position of the channels on an image from the last axis to the first. This is to maintain row-major ordering and make iterating over the pixels of a channel efficient. This made a huge improvement in speed in other packages such as MenpoFit. It also makes common operations such as iterating over the pixels in an image much simpler:

```
for channels in image.pixels:
    print(channels.shape)  # This will be a (height x width) ndarray
```

Other important changes include:

- Updating all widgets to work with IPython 3
- Incremental PCA was added.
- non-inplace cropping methods
- Dense SIFT features provided by vlfeat
- The implementation of graphs was changed to use sparse matrices by default. **This may cause breaking changes.**
- Many other improvements detailed in the pull requests below!

If you have serialized data using Menpo, you will likely find you have trouble reimporting it. If this is the case, please visit the user group for advice.

Github Pull Requests

- #598 Visualize sum of channels in widgets (@nontas, @patricksnape)
- #597 test new dev tag behavior on condaci (@jabooth)
- #591 Scale around centre (@patricksnape)

- #596 Update to versioneer v0.15 (@jabooth, @patricksnape)
- #495 SIFT features (@nontas, @patricksnape, @jabooth, @jalabort)
- #595 Update mean_pointcloud (@patricksnape, @jalabort)
- #541 Add triangulation labels for ibug_face_(66/51/49) (@jalabort)
- #590 Fix centre and diagonal being properties on Images (@patricksnape)
- #592 Refactor out bounding_box method (@patricksnape)
- #566 TriMesh utilities (@jabooth)
- #593 Minor bugfix on AnimationOptionsWidget (@nontas)
- #587 promote non-inplace crop methods, crop performance improvements (@jabooth, @patricksnape)
- #586 fix as_matrix where the iterator finished early (@jabooth)
- #574 Widgets for IPython3 (@nontas, @patricksnape, @jabooth)
- #588 test condaci 0.2.1, less noisy slack notifications (@jabooth)
- #568 rescale_pixels() for rescaling the range of pixels (@jabooth)
- #585 Hotfix: suffix change led to double path resolution. (@patricksnape)
- #581 Fix the landmark importer in case the landmark file has a '.' in its filename. (@grigorisg9gr)
- #584 new print_progress visualization function (@jabooth)
- #580 export_pickle now ensures pathlib.Path save as PurePath (@jabooth)
- #582 New readers for Middlebury FLO and FRGC ABS files (@patricksnape)
- #579 Fix the image importer in case of upper case letters in the suffix (@grigorisg9gr)
- #575 Allowing expanding user paths in exporting pickle (@patricksnape)
- #577 Change to using run_test.py (@patricksnape)
- #570 Zoom (@jabooth, @patricksnape)
- #569 Add new point_in_pointcloud kwarg to constrain (@patricksnape)
- #563 TPS Updates (@patricksnape)
- #567 Optional cmaps (@jalabort)
- #559 Graphs with isolated vertices (@nontas)
- #564 Bugfix: PCAModel print (@nontas)
- #565 fixed minor typo in introduction.rst (@evanjbowling)
- #562 IPython3 widgets (@patricksnape, @jalabort)
- #558 Channel roll (@patricksnape)
- #524 BREAKING CHANGE: Channels flip (@patricksnape, @jabooth, @jalabort)
- #512 WIP: remove_all_landmarks convienience method, quick lm filter (@jabooth)
- #554 Bugfix:visualize_images (@nontas)
- #553 Transform docs fixes (@nontas)
- #533 LandmarkGroup.init_with_all_label, init_* convenience constructors (@jabooth, @patricksnape)
- #552 Many fixes for Python 3 support (@patricksnape)

- #532 Incremental PCA (@patricksnape, @jabooth, @jalabort)
- #528 New as_matrix and from_matrix methods (@patricksnape)

0.4.4 (2015/03/05)

A hotfix release for properly handling nan values in the landmark formats. Also, a few other bug fixes crept in:

- Fix 3D Ljson importing
- Fix trim_components on PCA
- Fix setting None key on the landmark manager
- Making mean_pointcloud faster

Also makes an important change to the build configuration that syncs this version of Menpo to IPython 2.x.

Github Pull Requests

- #560 Assorted fixes (@patricksnape)
- #557 Ljson nan fix (@patricksnape)

0.4.3 (2015/02/19)

Adds the concept of nan values to the landmarker format for labelling missing landmarks.

Github Pull Requests

- #556 [0.4.x] Ljson nan/null fixes (@patricksnape)

0.4.2 (2015/02/19)

A hotfix release for landmark groups that have no connectivity.

Github Pull Requests

- #555 don't try and build a Graph with no connectivity (@jabooth)

0.4.1 (2015/02/07)

A hotfix release to enable compatibility with landmarker.io.

Github Pull Requests

- #551 HOTFIX: remove incorrect tojson() methods (@jabooth)

0.4.0 (2015/02/04)

The 0.4.0 release (pending any currently unknown bugs), represents a very significant overhaul of Menpo from v0.3.0. In particular, Menpo has been broken into four distinct packages: Menpo, MenpoFit, Menpo3D and MenpoDetect.

Visualization has had major improvements for 2D viewing, in particular through the use of IPython widgets and explicit options on the viewing methods for common tasks (like changing the landmark marker color). This final release is a much smaller set of changes over the alpha releases, so please check the full changelog for the alphas to see all changes from v0.3.0 to v0.4.0.

Summary of changes since v0.4.0a2:

- Lots of documentation rendering fixes and style fixes including this changelog.
- Move the LJSON format to V2. V1 is now being deprecated over the next version.
- More visualization customization fixes including multiple marker colors for landmark groups.

Github Pull Requests

- #546 IO doc fixes (@jabooth)
- #545 Different marker colour per label (@nontas)
- #543 Bug fix for importing an image, case of a dot in image name. (@grigorisg9gr)
- #544 Move docs to Sphinx 1.3b2 (@patricksnape)
- #536 Docs fixes (@patricksnape)
- #530 Visualization and Widgets upgrade (@patricksnape, @nontas)
- #540 LJSON v2 (@jabooth)
- #537 fix BU3DFE connectivity, pretty JSON files (@jabooth)
- #529 BU3D-FE labeller added (@jabooth)
- #527 fixes paths for pickle importing (@jabooth)
- #525 Fix .rst doc files, auto-generation script (@jabooth)

v0.4.0a2 (2014/12/03)

Alpha 2 moves towards extending the graphing API so that visualization is more dependable.

Summary:

- Add graph classes, `PointUndirectedGraph`, `PointDirectedGraph`, `PointTree`. This makes visualization of landmarks much nicer looking.
- Better support of pickling menpo objects
- Add a bounding box method to `PointCloud` for calculating the correctly oriented bounding box of point clouds.
- Allow PCA to operate in place for large data matrices.

Github Pull Requests

- #522 Add bounding box method to pointclouds (@patricksnape)
- #523 HOTFIX: fix export_pickle bug, add path support (@jabooth)
- #521 menpo.io add pickle support, move to pathlib (@jabooth)
- #520 Documentation fixes (@patricksnape, @jabooth)
- #518 PCA memory improvements, inplace dot product (@jabooth)
- #519 replace wrapt with functools.wraps - we can pickle (@jabooth)
- #517 (@jabooth)
- #514 Remove the use of triplot (@patricksnape)
- #516 Fix how images are converted to PIL (@patricksnape)
- #515 Show the path in the image widgets (@patricksnape)
- #511 2D Rotation convenience constructor, Image.rotate_ccw_about_centre (@jabooth)
- #510 all menpo io glob operations are now always sorted (@jabooth)
- #508 visualize image on MaskedImage reports Mask proportion (@jabooth)
- #509 path is now preserved on image warping (@jabooth)
- #507 fix rounding issue in n_components (@jabooth)
- #506 is_tree update in Graph (@nontas)
- #505 (@nontas)
- #504 explicitly have kwarg in IO for landmark extensions (@jabooth)
- #503 Update the README (@patricksnape)

v0.4.0a1 (2014/10/31)

This first alpha release makes a number of large, breaking changes to Menpo from v0.3.0. The biggest change is that Menpo3D and MenpoFit were created and thus all AAM and 3D visualization/rasterization code has been moved out of the main Menpo repository. This is working towards Menpo being pip installable.

Summary:

- Fixes memory leak whereby weak references were being kept between landmarks and their host objects. The Landmark manager now no longer keeps references to its host object. This also helps with serialization.
- Use pathlib instead of strings for paths in the `io` module.
- Importing of builtin assets from a simple function
- Improve support for image importing (including ability to import without normalising)
- Add fast methods for image warping, `warp_to_mask` and `warp_to_shape` instead of `warp_to`
- Allow masking of triangle meshes
- Add IPython visualization widgets for our core types
- All expensive properties (properties that would be worth caching in a variable and are not merely a lookup) are changed to methods.

Github Pull Requests

- #502 Fixes pseudoinverse for Alignment Transforms (@jalabort, @patricksnape)
- #501 Remove menpofit widgets (@nontas)
- #500 Shapes widget (@nontas)
- #499 spin out AAM, CLM, SDM, ATM and related code to menpofit (@jabooth)
- #498 Minimum spanning tree bug fix (@nontas)
- #492 Some fixes for PIL image importing (@patricksnape)
- #494 Widgets bug fix and Active Template Model widget (@nontas)
- #491 Widgets fixes (@nontas)
- #489 remove _view, fix up color_list -> colour_list (@jabooth)
- #486 Image visualisation improvements (@patricksnape)
- #488 Move expensive image properties to methods (@jabooth)
- #487 Change expensive PCA properties to methods (@jabooth)
- #485 MeanInstanceLinearModel.mean is now a method (@jabooth)
- #452 Advanced widgets (@patricksnape, @nontas)
- #481 Remove 3D (@patricksnape)
- #480 Graphs functionality (@nontas)
- #479 Extract patches on image (@patricksnape)
- #469 Active Template Models (@nontas)
- #478 Fix residuals for AAMs (@patricksnape, @jabooth)
- #474 remove HDF5able making room for h5it (@jabooth)
- #475 Normalize norm and std of Image object (@nontas)
- #472 Daisy features (@nontas)
- #473 Fix from_mask for Trimesh subclasses (@patricksnape)
- #470 expensive properties should really be methods (@jabooth)
- #467 get a progress bar on top level feature computation (@jabooth)
- #466 Spin out rasterization and related methods to menpo3d (@jabooth)
- #465 'me_norm' error type in tests (@nontas)
- #463 goodbye ioinfo, hello path (@jabooth)
- #464 make mayavi an optional dependency (@jabooth)
- #447 Displacements in fitting result (@nontas)
- #451 AppVeyor Windows continuous builds from condaci (@jabooth)
- #445 Serialize fit results (@patricksnape)
- #444 remove pyramid_on_features from Menpo (@jabooth)
- #443 create_pyramid now applies features even if pyramid_on_features=False, SDM uses it too (@jabooth)
- #369 warp_to_mask, warp_to_shape, fast resizing of images (@nontas, @patricksnape, @jabooth)

- #442 add rescale_to_diagonal, diagonal property to Image (@jabooth)
- #441 adds constrain_to_landmarks on BooleanImage (@jabooth)
- #440 pathlib.Path can no be used in menpo.io (@jabooth)
- #439 Labelling fixes (@jabooth, @patricksnape)
- #438 extract_channels (@jabooth)
- #437 GLRasterizer becomes HDF5able (@jabooth)
- #435 import_builtin_asset.ASSET_NAME (@jabooth)
- #434 check_regression_features unified with check_features, classmethods removed from SDM (@jabooth)
- #433 tidy classifiers (@jabooth)
- #432 aam.fitter, clm.fitter, sdm.trainer packages (@jabooth)
- #431 More fitmultilevel tidying (@jabooth)
- #430 Remove classmethods from DeformableModelBuilder (@jabooth)
- #412 First visualization widgets (@jalabort, @nontas)
- #429 Masked image fixes (@patricksnape)
- #426 rename 'feature_type' to 'features throughout Menpo (@jabooth)
- #427 Adds HDF5able serialization support to Menpo (@jabooth)
- #425 Faster cached piecewise affine, Cython varient demoted (@jabooth)
- #424 (@nontas)
- #378 Fitting result fixes (@jabooth, @nontas, @jalabort)
- #423 name now displays on constrained features (@jabooth)
- #421 Travis CI now makes builds, Linux/OS X Python 2.7/3.4 (@jabooth, @patricksnape)
- #400 Features as functions (@nontas, @patricksnape, @jabooth)
- #420 move IOInfo to use pathlib (@jabooth)
- #405 import menpo is now twice as fast (@jabooth)
- #416 waffle.io Badge (@waffle-iron)
- #415 export_mesh with .OBJ exporter (@jabooth, @patricksnape)
- #410 Fix the render_labels logic (@patricksnape)
- #407 Exporters (@patricksnape)
- #406 Fix greyscale PIL images (@patricksnape)
- #404 LandmarkGroup tojson method and PointGraph (@patricksnape)
- #403 Fixes a couple of viewing problems in fitting results (@patricksnape)
- #402 Landmarks fixes (@jabooth, @patricksnape)
- #401 Dogfood landmark_resolver in menpo.io (@jabooth)
- #399 bunch of Python 3 compatibility fixes (@jabooth)
- #398 throughout Menpo. (@jabooth)
- #397 Performance improvements for Similarity family (@jabooth)

- #396 More efficient initialisations of Menpo types (@jabooth)
- #395 remove cyclic target reference from landmarks (@jabooth)
- #393 Groundwork for dense correspondence pipeline (@jabooth)
- #394 weakref to break cyclic references (@jabooth)
- #389 assorted fixes (@jabooth)
- #390 (@jabooth)
- #387 Adds landmark label for tongues (@nontas)
- #386 Adds labels for the ibug eye annotation scheme (@jalabort)
- #382 BUG fixed: block element not reset if norm=0 (@dubzzz)
- #381 Recursive globbing (@jabooth)
- #384 Adds support for odd patch shapes in function extract_local_patches_fast (@jalabort)
- #379 imported textures have ioinfo, docs improvements (@jabooth)

v0.3.0 (2014/05/27)

First public release of Menpo, this release coincided with submission to the ACM Multimedia Open Source Software Competition 2014. This provides the basic scaffolding for Menpo, but it is not advised to use this version over the improvements in 0.4.0.

Github Pull Requests

- #377 Simple fixes (@patricksnape)
- #375 improvements to importing multiple assets (@jabooth)
- #374 Menpo's User guide (@jabooth)

Index

Symbols

_compose_after_inplace() (menpo.transform.base.composable.ComposableTransform method), 384
_compose_before_inplace() (menpo.transform.base.composable.ComposableTransform method), 384
_transform_inplace() (menpo.transform.base.Transformable method), 384
_view_2d() (menpo.image.Image method), 18
_view_2d() (menpo.image.MaskedImage method), 67
_view_2d() (menpo.shape.ColouredTriMesh method), 292
_view_2d() (menpo.shape.LabelledPointUndirectedGraph method), 259
_view_2d() (menpo.shape.PointCloud method), 180
_view_2d() (menpo.shape.PointDirectedGraph method), 226
_view_2d() (menpo.shape.PointTree method), 242
_view_2d() (menpo.shape.PointUndirectedGraph method), 209
_view_2d() (menpo.shape.TexturedTriMesh method), 304
_view_2d() (menpo.shape.TriMesh method), 279
_view_landmarks_2d() (menpo.image.Image method), 19
_view_landmarks_2d() (menpo.image.MaskedImage method), 68
_view_landmarks_2d() (menpo.shape.ColouredTriMesh method), 294
_view_landmarks_2d() (menpo.shape.LabelledPointUndirectedGraph method), 262
_view_landmarks_2d() (menpo.shape.PointCloud method), 182
_view_landmarks_2d() (menpo.shape.PointDirectedGraph method), 228
_view_landmarks_2d() (menpo.shape.PointTree method), 245
_view_landmarks_2d() (menpo.shape.PointUndirectedGraph method), 211
_view_landmarks_2d() (menpo.shape.TexturedTriMesh method), 307
_view_landmarks_2d() (menpo.shape.TriMesh method), 282

A

add_label() (menpo.shape.LabelledPointUndirectedGraph method), 267
Affine (class in menpo.transform), 324
aligned_source() (menpo.transform.AlignmentAffine method), 352
aligned_source() (menpo.transform.AlignmentRotation method), 362
aligned_source() (menpo.transform.AlignmentSimilarity method), 357
aligned_source() (menpo.transform.AlignmentTranslation method), 367
aligned_source() (menpo.transform.AlignmentUniformScale method), 371
aligned_source() (menpo.transform.base.alignment.Alignment method), 387
aligned_source() (menpo.transform.ThinPlateSplines method), 349
Alignment (class in menpo.transform.base.alignment), 387
alignment_error() (menpo.transform.AlignmentAffine method), 352
alignment_error() (menpo.transform.AlignmentRotation method), 362
alignment_error() (menpo.transform.AlignmentSimilarity method), 357
alignment_error() (menpo.transform.AlignmentTranslation method), 367
alignment_error() (menpo.transform.AlignmentUniformScale method), 371
alignment_error() (menpo.transform.base.alignment.Alignment method), 387
alignment_error() (menpo.transform.ThinPlateSplines method), 350
AlignmentAffine (class in menpo.transform), 352

AlignmentRotation (class in menpo.transform), 361
AlignmentSimilarity (class in menpo.transform), 357
AlignmentTranslation (class in menpo.transform), 367
AlignmentUniformScale (class in menpo.transform), 371
all_true() (menpo.image.BooleanImage method), 44
apply() (menpo.transform.Affine method), 324
apply() (menpo.transform.AlignmentAffine method), 352
apply() (menpo.transform.AlignmentRotation method), 362
apply() (menpo.transform.AlignmentSimilarity method), 357
apply() (menpo.transform.AlignmentTranslation method), 367
apply() (menpo.transform.AlignmentUniformScale method), 371
apply() (menpo.transform.base.composable.ComposableTransform method), 385
apply() (menpo.transform.Homogeneous method), 320
apply() (menpo.transform.NonUniformScale method), 345
apply() (menpo.transform.R2LogR2RBF method), 379
apply() (menpo.transform.R2LogRRBF method), 380
apply() (menpo.transform.Rotation method), 332
apply() (menpo.transform.Similarity method), 328
apply() (menpo.transform.ThinPlateSplines method), 350
apply() (menpo.transform.Transform method), 382
apply() (menpo.transform.TransformChain method), 377
apply() (menpo.transform.Translation method), 337
apply() (menpo.transform.UniformScale method), 341
apply_inplace() (menpo.transform.Affine method), 324
apply_inplace() (menpo.transform.AlignmentAffine method), 352
apply_inplace() (menpo.transform.AlignmentRotation method), 362
apply_inplace() (menpo.transform.AlignmentSimilarity method), 357
apply_inplace() (menpo.transform.AlignmentTranslation method), 367
apply_inplace() (menpo.transform.AlignmentUniformScale method), 372
apply_inplace() (menpo.transform.base.composable.ComposableTransform method), 385
apply_inplace() (menpo.transform.Homogeneous method), 320
apply_inplace() (menpo.transform.NonUniformScale method), 346
apply_inplace() (menpo.transform.R2LogR2RBF method), 379
apply_inplace() (menpo.transform.R2LogRRBF method), 381
apply_inplace() (menpo.transform.Rotation method), 333
apply_inplace() (menpo.transform.Similarity method), 329
apply_inplace() (menpo.transform.ThinPlateSplines method), 350
apply_inplace() (menpo.transform.Transform method), 383
apply_inplace() (menpo.transform.TransformChain method), 377
apply_inplace() (menpo.transform.Translation method), 337
apply_inplace() (menpo.transform.UniformScale method), 342
as_greyscale() (menpo.image.BooleanImage method), 44
as_greyscale() (menpo.image.Image method), 24
as_greyscale() (menpo.image.MaskedImage method), 72
as_histogram() (menpo.image.BooleanImage method), 45
as_histogram() (menpo.image.Image method), 24
as_histogram() (menpo.image.MaskedImage method), 72
as_imageio() (menpo.image.BooleanImage method), 45
as_imageio() (menpo.image.Image method), 24
as_imageio() (menpo.image.MaskedImage method), 73
as_masked() (menpo.image.BooleanImage method), 46
as_masked() (menpo.image.Image method), 25
as_masked() (menpo.image.MaskedImage method), 73
as_matrix() (in module menpo.math), 145
as_non_alignment() (menpo.transform.AlignmentAffine method), 353
as_non_alignment() (menpo.transform.AlignmentRotation method), 362
as_non_alignment() (menpo.transform.AlignmentSimilarity method), 357
as_non_alignment() (menpo.transform.AlignmentTranslation method), 367
as_non_alignment() (menpo.transform.AlignmentUniformScale method), 372
as_PILImage() (menpo.image.BooleanImage method), 44
as_PILImage() (menpo.image.Image method), 23
as_PILImage() (menpo.image.MaskedImage method), 71
as_pointgraph() (menpo.shape.ColouredTriMesh method), 298
as_pointgraph() (menpo.shape.TexturedTriMesh method), 311
as_pointgraph() (menpo.shape.TriMesh method), 286
as_unmasked() (menpo.image.MaskedImage method), 73
as_vector() (menpo.base.Vectorizable method), 4
as_vector() (menpo.image.BooleanImage method), 46
as_vector() (menpo.image.Image method), 25
as_vector() (menpo.image.MaskedImage method), 74
as_vector() (menpo.shape.base.Shape method), 178
as_vector() (menpo.shape.ColouredTriMesh method), 298
as_vector() (menpo.shape.LabelledPointUndirectedGraph method), 267
as_vector() (menpo.shape.PointCloud method), 186
as_vector() (menpo.shape.PointDirectedGraph method),

232
as_vector() (menpo.shape.PointTree method), 249
as_vector() (menpo.shape.PointUndirectedGraph method), 216
as_vector() (menpo.shape.TexturedTriMesh method), 311
as_vector() (menpo.shape.TriMesh method), 286
as_vector() (menpo.transform.Affine method), 324
as_vector() (menpo.transform.AlignmentAffine method), 353
as_vector() (menpo.transform.AlignmentRotation method), 362
as_vector() (menpo.transform.AlignmentSimilarity method), 358
as_vector() (menpo.transform.AlignmentTranslation method), 367
as_vector() (menpo.transform.AlignmentUniformScale method), 372
as_vector() (menpo.transform.Homogeneous method), 321
as_vector() (menpo.transform.NonUniformScale method), 346
as_vector() (menpo.transform.Rotation method), 333
as_vector() (menpo.transform.Similarity method), 329
as_vector() (menpo.transform.Translation method), 337
as_vector() (menpo.transform.UniformScale method), 342
axis_and_angle_of_rotation() (menpo.transform.AlignmentRotation method), 362
axis_and_angle_of_rotation() (menpo.transform.Rotation method), 333

B

BooleanImage (class in menpo.image), 44
boundary_tri_index() (menpo.shape.ColouredTriMesh method), 298
boundary_tri_index() (menpo.shape.TexturedTriMesh method), 311
boundary_tri_index() (menpo.shape.TriMesh method), 286
bounding_box() (in module menpo.shape), 318
bounding_box() (menpo.shape.ColouredTriMesh method), 298
bounding_box() (menpo.shape.LabelledPointUndirectedGraph method), 267
bounding_box() (menpo.shape.PointCloud method), 186
bounding_box() (menpo.shape.PointDirectedGraph method), 232
bounding_box() (menpo.shape.PointTree method), 249
bounding_box() (menpo.shape.PointUndirectedGraph method), 216
bounding_box() (menpo.shape.TexturedTriMesh method), 311
bounding_box() (menpo.shape.TriMesh method), 286
bounding_box_mirrored_to_bounding_box() (in module menpo.landmark), 113
bounding_box_to_bounding_box() (in module menpo.landmark), 113
bounding_cuboid() (in module menpo.shape), 318
bounds() (menpo.image.BooleanImage method), 46
bounds() (menpo.image.Image method), 25
bounds() (menpo.image.MaskedImage method), 74
bounds() (menpo.shape.ColouredTriMesh method), 299
bounds() (menpo.shape.LabelledPointUndirectedGraph method), 267
bounds() (menpo.shape.PointCloud method), 186
bounds() (menpo.shape.PointDirectedGraph method), 232
bounds() (menpo.shape.PointTree method), 249
bounds() (menpo.shape.PointUndirectedGraph method), 216
bounds() (menpo.shape.TexturedTriMesh method), 311
bounds() (menpo.shape.TriMesh method), 286
bounds_false() (menpo.image.BooleanImage method), 46
bounds_true() (menpo.image.BooleanImage method), 46
build_mask_around_landmarks() (menpo.image.MaskedImage method), 74
bytes_str() (in module menpo.visualize), 398

C

car_streetscene_20_to_car_streetscene_view_0_8() (in module menpo.landmark), 135
car_streetscene_20_to_car_streetscene_view_1_14() (in module menpo.landmark), 136
car_streetscene_20_to_car_streetscene_view_2_10() (in module menpo.landmark), 137
car_streetscene_20_to_car_streetscene_view_3_14() (in module menpo.landmark), 137
car_streetscene_20_to_car_streetscene_view_4_14() (in module menpo.landmark), 138
car_streetscene_20_to_car_streetscene_view_5_10() (in module menpo.landmark), 139
car_streetscene_20_to_car_streetscene_view_6_14() (in module menpo.landmark), 140
car_streetscene_20_to_car_streetscene_view_7_8() (in module menpo.landmark), 141
centre() (menpo.image.BooleanImage method), 47
centre() (menpo.image.Image method), 25
centre() (menpo.image.MaskedImage method), 74
centre() (menpo.shape.ColouredTriMesh method), 299
centre() (menpo.shape.LabelledPointUndirectedGraph method), 268
centre() (menpo.shape.PointCloud method), 186
centre() (menpo.shape.PointDirectedGraph method), 233
centre() (menpo.shape.PointTree method), 249
centre() (menpo.shape.PointUndirectedGraph method), 216
centre() (menpo.shape.TexturedTriMesh method), 312

centre() (menpo.shape.TriMesh method), 287
centre_of_bounds() (menpo.shape.ColouredTriMesh method), 299
centre_of_bounds() (menpo.shape.LabelledPointUndirectedGraph method), 268
centre_of_bounds() (menpo.shape.PointCloud method), 187
centre_of_bounds() (menpo.shape.PointDirectedGraph method), 233
centre_of_bounds() (menpo.shape.PointTree method), 250
centre_of_bounds() (menpo.shape.PointUndirectedGraph method), 217
centre_of_bounds() (menpo.shape.TexturedTriMesh method), 312
centre_of_bounds() (menpo.shape.TriMesh method), 287
chain_graph() (in module menpo.shape), 277
children() (menpo.shape.DirectedGraph method), 196
children() (menpo.shape.PointDirectedGraph method), 233
children() (menpo.shape.PointTree method), 250
children() (menpo.shape.Tree method), 202
clear() (menpo.landmark.LandmarkManager method), 111
clear_figure() (menpo.visualize.MatplotlibRenderer method), 391
clear_figure() (menpo.visualize.Renderer method), 390
clip_pixels() (menpo.image.BooleanImage method), 47
clip_pixels() (menpo.image.Image method), 25
clip_pixels() (menpo.image.MaskedImage method), 74
clip_texture() (menpo.shape.ColouredTriMesh method), 299
clip_texture() (menpo.shape.TexturedTriMesh method), 312
ColouredTriMesh (class in menpo.shape), 291
complete_graph() (in module menpo.shape), 276
component() (menpo.model.LinearVectorModel method), 148
component() (menpo.model.MeanLinearVectorModel method), 150
component() (menpo.model.PCAModel method), 153
component() (menpo.model.PCAVectorModel method), 164
component_vector() (menpo.model.PCAModel method), 153
components (menpo.model.LinearVectorModel attribute), 149
components (menpo.model.MeanLinearVectorModel attribute), 152
components (menpo.model.PCAModel attribute), 163
components (menpo.model.PCAVectorModel attribute), 174
ComposableTransform (class in menpo.transform.base.composable), 384
compose_after() (menpo.transform.Affine method), 324
compose_after() (menpo.transform.AlignmentAffine method), 353
compose_after() (menpo.transform.AlignmentRotation method), 363
compose_after() (menpo.transform.AlignmentSimilarity method), 358
compose_after() (menpo.transform.AlignmentTranslation method), 368
compose_after() (menpo.transform.AlignmentUniformScale method), 372
compose_after() (menpo.transform.base.composable.ComposableTransform method), 385
compose_after() (menpo.transform.Homogeneous method), 321
compose_after() (menpo.transform.NonUniformScale method), 346
compose_after() (menpo.transform.R2LogR2RBF method), 379
compose_after() (menpo.transform.R2LogRRBF method), 381
compose_after() (menpo.transform.Rotation method), 333
compose_after() (menpo.transform.Similarity method), 329
compose_after() (menpo.transform.ThinPlateSplines method), 350
compose_after() (menpo.transform.Transform method), 383
compose_after() (menpo.transform.TransformChain method), 377
compose_after() (menpo.transform.Translation method), 337
compose_after() (menpo.transform.UniformScale method), 342
compose_after_from_vector_inplace() (menpo.transform.base.composable.VComposable method), 389
compose_after_inplace() (menpo.transform.Affine method), 325
compose_after_inplace() (menpo.transform.AlignmentAffine method), 353
compose_after_inplace() (menpo.transform.AlignmentRotation method), 363
compose_after_inplace() (menpo.transform.AlignmentSimilarity method), 358
compose_after_inplace() (menpo.transform.AlignmentTranslation method), 368
compose_after_inplace() (menpo.transform.AlignmentUniformScale method), 372
compose_after_inplace() (menpo.transform.base.composable.ComposableT method), 385
compose_after_inplace() (menpo.transform.Homogeneous method), 321

compose_after_inplace() (menpo.transform.NonUniformScale method), 346
compose_after_inplace() (menpo.transform.Rotation method), 333
compose_after_inplace() (menpo.transform.Similarity method), 329
compose_after_inplace() (menpo.transform.TransformChain method), 377
compose_after_inplace() (menpo.transform.Translation method), 338
compose_after_inplace() (menpo.transform.UniformScale method), 342
compose_before() (menpo.transform.Affine method), 325
compose_before() (menpo.transform.AlignmentAffine method), 353
compose_before() (menpo.transform.AlignmentRotation method), 363
compose_before() (menpo.transform.AlignmentSimilarity method), 358
compose_before() (menpo.transform.AlignmentTranslation method), 368
compose_before() (menpo.transform.AlignmentUniformScale method), 373
compose_before() (menpo.transform.base.composable.ComposableTransform method), 386
compose_before() (menpo.transform.Homogeneous method), 321
compose_before() (menpo.transform.NonUniformScale method), 346
compose_before() (menpo.transform.R2LogR2RBF method), 380
compose_before() (menpo.transform.R2LogRRBF method), 381
compose_before() (menpo.transform.Rotation method), 333
compose_before() (menpo.transform.Similarity method), 329
compose_before() (menpo.transform.ThinPlateSplines method), 350
compose_before() (menpo.transform.Transform method), 383
compose_before() (menpo.transform.TransformChain method), 377
compose_before() (menpo.transform.Translation method), 338
compose_before() (menpo.transform.UniformScale method), 342
compose_before_inplace() (menpo.transform.Affine method), 325
compose_before_inplace() (menpo.transform.AlignmentAffine method), 354
compose_before_inplace() (menpo.transform.AlignmentRotation method), 363
compose_before_inplace() (menpo.transform.AlignmentSimilarity method), 358
compose_before_inplace() (menpo.transform.AlignmentTranslation method), 368
compose_before_inplace() (menpo.transform.AlignmentUniformScale method), 373
compose_before_inplace() (menpo.transform.base.composable.ComposableTransform method), 386
compose_before_inplace() (menpo.transform.Homogeneous method), 321
compose_before_inplace() (menpo.transform.NonUniformScale method), 347
compose_before_inplace() (menpo.transform.Rotation method), 334
compose_before_inplace() (menpo.transform.Similarity method), 329
compose_before_inplace() (menpo.transform.TransformChain method), 378
compose_before_inplace() (menpo.transform.Translation method), 338
compose_before_inplace() (menpo.transform.UniformScale method), 343
composes_inplace_with (menpo.transform.Affine attribute), 327
composes_inplace_with (menpo.transform.AlignmentAffine attribute), 355
composes_inplace_with (menpo.transform.AlignmentRotation attribute), 365
composes_inplace_with (menpo.transform.AlignmentSimilarity attribute), 360
composes_inplace_with (menpo.transform.AlignmentTranslation attribute), 370
composes_inplace_with (menpo.transform.AlignmentUniformScale attribute), 375
composes_inplace_with (menpo.transform.base.composable.ComposableTr attribute), 386
composes_inplace_with (menpo.transform.Homogeneous attribute), 323
composes_inplace_with (menpo.transform.NonUniformScale attribute), 348
composes_inplace_with (menpo.transform.Rotation attribute), 336
composes_inplace_with (menpo.transform.Similarity attribute), 331
composes_inplace_with (menpo.transform.TransformChain

attribute), 378
composes_inplace_with (menpo.transform.Translation attribute), 340
composes_inplace_with (menpo.transform.UniformScale attribute), 344
composes_with (menpo.transform.Affine attribute), 327
composes_with (menpo.transform.AlignmentAffine attribute), 355
composes_with (menpo.transform.AlignmentRotation attribute), 366
composes_with (menpo.transform.AlignmentSimilarity attribute), 360
composes_with (menpo.transform.AlignmentTranslation attribute), 370
composes_with (menpo.transform.AlignmentUniformScale attribute), 375
composes_with (menpo.transform.base.composable.ComposableTransform attribute), 386
composes_with (menpo.transform.Homogeneous attribute), 323
composes_with (menpo.transform.NonUniformScale attribute), 348
composes_with (menpo.transform.Rotation attribute), 336
composes_with (menpo.transform.Similarity attribute), 331
composes_with (menpo.transform.TransformChain attribute), 378
composes_with (menpo.transform.Translation attribute), 340
composes_with (menpo.transform.UniformScale attribute), 344
constrain_landmarks_to_bounds() (menpo.image.BooleanImage method), 47
constrain_landmarks_to_bounds() (menpo.image.Image method), 26
constrain_landmarks_to_bounds() (menpo.image.MaskedImage method), 74
constrain_mask_to_landmarks() (menpo.image.MaskedImage method), 74
constrain_mask_to_patches_around_landmarks() (menpo.image.MaskedImage method), 75
constrain_points_to_bounds() (menpo.image.BooleanImage method), 47
constrain_points_to_bounds() (menpo.image.Image method), 26
constrain_points_to_bounds() (menpo.image.MaskedImage method), 75
constrain_to_bounds() (menpo.shape.ColouredTriMesh method), 299
constrain_to_bounds() (menpo.shape.LabelledPointUndirectedGraph method), 268
constrain_to_bounds() (menpo.shape.PointCloud method), 187
constrain_to_bounds() (menpo.shape.PointDirectedGraph method), 233
constrain_to_bounds() (menpo.shape.PointTree method), 250
constrain_to_bounds() (menpo.shape.PointUndirectedGraph method), 217
constrain_to_bounds() (menpo.shape.TexturedTriMesh method), 312
constrain_to_bounds() (menpo.shape.TriMesh method), 287
constrain_to_landmarks() (menpo.image.BooleanImage method), 47
constrain_to_pointcloud() (menpo.image.BooleanImage method), 48
copy() (menpo.base.Copyable method), 3
copy() (menpo.base.LazyList method), 5
copy() (menpo.base.Targetable method), 5
copy() (menpo.base.Vectorizable method), 4
copy() (menpo.image.BooleanImage method), 48
copy() (menpo.image.Image method), 26
copy() (menpo.image.MaskedImage method), 75
copy() (menpo.landmark.Landmarkable method), 110
copy() (menpo.landmark.LandmarkManager method), 111
copy() (menpo.model.LinearVectorModel method), 148
copy() (menpo.model.MeanLinearVectorModel method), 150
copy() (menpo.model.PCAModel method), 153
copy() (menpo.model.PCAVectorModel method), 164
copy() (menpo.shape.base.Shape method), 179
copy() (menpo.shape.ColouredTriMesh method), 299
copy() (menpo.shape.LabelledPointUndirectedGraph method), 268
copy() (menpo.shape.PointCloud method), 187
copy() (menpo.shape.PointDirectedGraph method), 233
copy() (menpo.shape.PointTree method), 250
copy() (menpo.shape.PointUndirectedGraph method), 217
copy() (menpo.shape.TexturedTriMesh method), 312
copy() (menpo.shape.TriMesh method), 287
copy() (menpo.transform.Affine method), 325
copy() (menpo.transform.AlignmentAffine method), 354
copy() (menpo.transform.AlignmentRotation method), 364
copy() (menpo.transform.AlignmentSimilarity method), 359
copy() (menpo.transform.AlignmentTranslation method), 369
copy() (menpo.transform.AlignmentUniformScale method), 373
copy() (menpo.transform.base.alignment.Alignment method), 387
copy() (menpo.transform.base.composable.ComposableTransform method), 386

copy() (menpo.transform.base.Transformable method), 384
copy() (menpo.transform.Homogeneous method), 322
copy() (menpo.transform.NonUniformScale method), 347
copy() (menpo.transform.R2LogR2RBF method), 380
copy() (menpo.transform.R2LogRRBF method), 381
copy() (menpo.transform.Rotation method), 334
copy() (menpo.transform.Similarity method), 330
copy() (menpo.transform.ThinPlateSplines method), 350
copy() (menpo.transform.Transform method), 383
copy() (menpo.transform.TransformChain method), 378
copy() (menpo.transform.Translation method), 338
copy() (menpo.transform.UniformScale method), 343
Copyable (class in menpo.base), 3
count() (menpo.base.LazyList method), 6
crop() (menpo.image.BooleanImage method), 48
crop() (menpo.image.Image method), 26
crop() (menpo.image.MaskedImage method), 75
crop_to_landmarks() (menpo.image.BooleanImage method), 49
crop_to_landmarks() (menpo.image.Image method), 27
crop_to_landmarks() (menpo.image.MaskedImage method), 76
crop_to_landmarks_proportion() (menpo.image.BooleanImage method), 49
crop_to_landmarks_proportion() (menpo.image.Image method), 27
crop_to_landmarks_proportion() (menpo.image.MaskedImage method), 76
crop_to_pointcloud() (menpo.image.BooleanImage method), 50
crop_to_pointcloud() (menpo.image.Image method), 28
crop_to_pointcloud() (menpo.image.MaskedImage method), 77
crop_to_pointcloud_proportion() (menpo.image.BooleanImage method), 50
crop_to_pointcloud_proportion() (menpo.image.Image method), 28
crop_to_pointcloud_proportion() (menpo.image.MaskedImage method), 77
crop_to_true_mask() (menpo.image.MaskedImage method), 78

D

daisy() (in module menpo.feature), 101
data_dir_path() (in module menpo.io), 18
data_path_to() (in module menpo.io), 17
decompose() (menpo.transform.Affine method), 325
decompose() (menpo.transform.AlignmentAffine method), 354
decompose() (menpo.transform.AlignmentRotation method), 364
decompose() (menpo.transform.AlignmentSimilarity method), 359
decompose() (menpo.transform.AlignmentTranslation method), 369
decompose() (menpo.transform.AlignmentUniformScale method), 373
decompose() (menpo.transform.homogeneous.affine.DiscreteAffine method), 389
decompose() (menpo.transform.NonUniformScale method), 347
decompose() (menpo.transform.Rotation method), 334
decompose() (menpo.transform.Similarity method), 330
decompose() (menpo.transform.Translation method), 339
decompose() (menpo.transform.UniformScale method), 343
delaunay_graph() (in module menpo.shape), 277
depth_of_vertex() (menpo.shape.PointTree method), 250
depth_of_vertex() (menpo.shape.Tree method), 202
diagonal() (menpo.image.BooleanImage method), 51
diagonal() (menpo.image.Image method), 29
diagonal() (menpo.image.MaskedImage method), 78
dilate() (menpo.image.MaskedImage method), 78
DirectedGraph (class in menpo.shape), 195
DiscreteAffine (class in menpo.transform.homogeneous.affine), 388
distance_to() (menpo.shape.ColouredTriMesh method), 299
distance_to() (menpo.shape.LabelledPointUndirectedGraph method), 268
distance_to() (menpo.shape.PointCloud method), 187
distance_to() (menpo.shape.PointDirectedGraph method), 233
distance_to() (menpo.shape.PointTree method), 250
distance_to() (menpo.shape.PointUndirectedGraph method), 217
distance_to() (menpo.shape.TexturedTriMesh method), 312
distance_to() (menpo.shape.TriMesh method), 287
dot_inplace_left() (in module menpo.math), 145
dot_inplace_right() (in module menpo.math), 145
double_igo() (in module menpo.feature), 104
dsift() (in module menpo.feature), 102

E

edge_indices() (menpo.shape.ColouredTriMesh method), 300
edge_indices() (menpo.shape.TexturedTriMesh method), 312
edge_indices() (menpo.shape.TriMesh method), 287
edge_lengths() (menpo.shape.ColouredTriMesh method), 300
edge_lengths() (menpo.shape.TexturedTriMesh method), 313
edge_lengths() (menpo.shape.TriMesh method), 288

edge_vectors() (menpo.shape.ColouredTriMesh method), 300
edge_vectors() (menpo.shape.TexturedTriMesh method), 313
edge_vectors() (menpo.shape.TriMesh method), 288
eigenvalue_decomposition() (in module menpo.math), 142
eigenvalues (menpo.model.PCAModel attribute), 163
eigenvalues (menpo.model.PCAVectorModel attribute), 174
eigenvalues_cumulative_ratio() (menpo.model.PCAModel method), 153
eigenvalues_cumulative_ratio() (menpo.model.PCAVectorModel method), 165
eigenvalues_ratio() (menpo.model.PCAModel method), 153
eigenvalues_ratio() (menpo.model.PCAVectorModel method), 165
empty_graph() (in module menpo.shape), 276
erode() (menpo.image.MaskedImage method), 79
es() (in module menpo.feature), 97
export_image() (in module menpo.io), 15
export_landmark_file() (in module menpo.io), 16
export_pickle() (in module menpo.io), 16
export_video() (in module menpo.io), 15
extract_channels() (menpo.image.BooleanImage method), 51
extract_channels() (menpo.image.Image method), 29
extract_channels() (menpo.image.MaskedImage method), 79
extract_patches() (menpo.image.BooleanImage method), 51
extract_patches() (menpo.image.Image method), 29
extract_patches() (menpo.image.MaskedImage method), 79
extract_patches_around_landmarks() (menpo.image.BooleanImage method), 52
extract_patches_around_landmarks() (menpo.image.Image method), 29
extract_patches_around_landmarks() (menpo.image.MaskedImage method), 79
eye_ibug_close_17_to_eye_ibug_close_17() (in module menpo.landmark), 126
eye_ibug_close_17_to_eye_ibug_close_17_trimesh() (in module menpo.landmark), 127
eye_ibug_open_38_to_eye_ibug_open_38() (in module menpo.landmark), 128
eye_ibug_open_38_to_eye_ibug_open_38_trimesh() (in module menpo.landmark), 129

F

face_bu3dfe_83_to_face_bu3dfe_83() (in module menpo.landmark), 125
face_ibug_49_to_face_ibug_49() (in module menpo.landmark), 123
face_ibug_68_mirrored_to_face_ibug_68() (in module menpo.landmark), 122
face_ibug_68_to_face_ibug_49() (in module menpo.landmark), 114
face_ibug_68_to_face_ibug_49_trimesh() (in module menpo.landmark), 115
face_ibug_68_to_face_ibug_51() (in module menpo.landmark), 116
face_ibug_68_to_face_ibug_51_trimesh() (in module menpo.landmark), 117
face_ibug_68_to_face_ibug_65() (in module menpo.landmark), 117
face_ibug_68_to_face_ibug_66() (in module menpo.landmark), 118
face_ibug_68_to_face_ibug_66_trimesh() (in module menpo.landmark), 119
face_ibug_68_to_face_ibug_68() (in module menpo.landmark), 120
face_ibug_68_to_face_ibug_68_trimesh() (in module menpo.landmark), 121
face_imm_58_to_face_imm_58() (in module menpo.landmark), 123
face_lfpw_29_to_face_lfpw_29() (in module menpo.landmark), 124
false_indices() (menpo.image.BooleanImage method), 52
fast_dsift() (in module menpo.feature), 103
features_selection_widget() (in module menpo.feature), 109
find_all_paths() (menpo.shape.DirectedGraph method), 197
find_all_paths() (menpo.shape.LabelledPointUndirectedGraph method), 268
find_all_paths() (menpo.shape.PointDirectedGraph method), 233
find_all_paths() (menpo.shape.PointTree method), 250
find_all_paths() (menpo.shape.PointUndirectedGraph method), 217
find_all_paths() (menpo.shape.Tree method), 203
find_all_paths() (menpo.shape.UndirectedGraph method), 191
find_all_shortest_paths() (menpo.shape.DirectedGraph method), 197
find_all_shortest_paths() (menpo.shape.LabelledPointUndirectedGraph method), 268
find_all_shortest_paths() (menpo.shape.PointDirectedGraph method), 234
find_all_shortest_paths() (menpo.shape.PointTree method), 251
find_all_shortest_paths() (menpo.shape.PointUndirectedGraph method), 217
find_all_shortest_paths() (menpo.shape.Tree method), 203

find_all_shortest_paths() (menpo.shape.UndirectedGraph method), 191
find_path() (menpo.shape.DirectedGraph method), 197
find_path() (menpo.shape.LabelledPointUndirectedGraph method), 269
find_path() (menpo.shape.PointDirectedGraph method), 234
find_path() (menpo.shape.PointTree method), 251
find_path() (menpo.shape.PointUndirectedGraph method), 218
find_path() (menpo.shape.Tree method), 203
find_path() (menpo.shape.UndirectedGraph method), 192
find_shortest_path() (menpo.shape.DirectedGraph method), 198
find_shortest_path() (menpo.shape.LabelledPointUndirectedGraph method), 269
find_shortest_path() (menpo.shape.PointDirectedGraph method), 234
find_shortest_path() (menpo.shape.PointTree method), 251
find_shortest_path() (menpo.shape.PointUndirectedGraph method), 218
find_shortest_path() (menpo.shape.Tree method), 203
find_shortest_path() (menpo.shape.UndirectedGraph method), 192
force_draw() (menpo.visualize.MatplotlibRenderer method), 391
force_draw() (menpo.visualize.Renderer method), 390
from_mask() (menpo.shape.ColouredTriMesh method), 300
from_mask() (menpo.shape.LabelledPointUndirectedGraph method), 270
from_mask() (menpo.shape.PointCloud method), 187
from_mask() (menpo.shape.PointDirectedGraph method), 235
from_mask() (menpo.shape.PointTree method), 252
from_mask() (menpo.shape.PointUndirectedGraph method), 218
from_mask() (menpo.shape.TexturedTriMesh method), 313
from_mask() (menpo.shape.TriMesh method), 288
from_matrix() (in module menpo.math), 146
from_tri_mask() (menpo.shape.ColouredTriMesh method), 300
from_tri_mask() (menpo.shape.TexturedTriMesh method), 313
from_tri_mask() (menpo.shape.TriMesh method), 288
from_vector() (menpo.base.Vectorizable method), 4
from_vector() (menpo.image.BooleanImage method), 52
from_vector() (menpo.image.Image method), 30
from_vector() (menpo.image.MaskedImage method), 80
from_vector() (menpo.shape.base.Shape method), 179
from_vector() (menpo.shape.ColouredTriMesh method), 300
from_vector() (menpo.shape.LabelledPointUndirectedGraph method), 270
from_vector() (menpo.shape.PointCloud method), 187
from_vector() (menpo.shape.PointDirectedGraph method), 235
from_vector() (menpo.shape.PointTree method), 252
from_vector() (menpo.shape.PointUndirectedGraph method), 219
from_vector() (menpo.shape.TexturedTriMesh method), 313
from_vector() (menpo.shape.TriMesh method), 288
from_vector() (menpo.transform.Affine method), 326
from_vector() (menpo.transform.AlignmentAffine method), 354
from_vector() (menpo.transform.AlignmentRotation method), 364
from_vector() (menpo.transform.AlignmentSimilarity method), 359
from_vector() (menpo.transform.AlignmentTranslation method), 369
from_vector() (menpo.transform.AlignmentUniformScale method), 373
from_vector() (menpo.transform.Homogeneous method), 322
from_vector() (menpo.transform.NonUniformScale method), 347
from_vector() (menpo.transform.Rotation method), 334
from_vector() (menpo.transform.Similarity method), 330
from_vector() (menpo.transform.Translation method), 339
from_vector() (menpo.transform.UniformScale method), 343
from_vector_inplace() (menpo.base.Vectorizable method), 4
from_vector_inplace() (menpo.image.BooleanImage method), 53
from_vector_inplace() (menpo.image.Image method), 30
from_vector_inplace() (menpo.image.MaskedImage method), 80
from_vector_inplace() (menpo.shape.base.Shape method), 179
from_vector_inplace() (menpo.shape.ColouredTriMesh method), 301
from_vector_inplace() (menpo.shape.LabelledPointUndirectedGraph method), 270
from_vector_inplace() (menpo.shape.PointCloud method), 187
from_vector_inplace() (menpo.shape.PointDirectedGraph method), 235
from_vector_inplace() (menpo.shape.PointTree method), 252
from_vector_inplace() (menpo.shape.PointUndirectedGraph method), 219
from_vector_inplace() (menpo.shape.TexturedTriMesh

method), 313
from_vector_inplace() (menpo.shape.TriMesh method), 288
from_vector_inplace() (menpo.transform.Affine method), 326
from_vector_inplace() (menpo.transform.AlignmentAffine method), 354
from_vector_inplace() (menpo.transform.AlignmentRotation method), 364
from_vector_inplace() (menpo.transform.AlignmentSimilarity method), 359
from_vector_inplace() (menpo.transform.AlignmentTranslation method), 369
from_vector_inplace() (menpo.transform.AlignmentUniformScale method), 373
from_vector_inplace() (menpo.transform.Homogeneous method), 322
from_vector_inplace() (menpo.transform.NonUniformScale method), 347
from_vector_inplace() (menpo.transform.Rotation method), 334
from_vector_inplace() (menpo.transform.Similarity method), 330
from_vector_inplace() (menpo.transform.Translation method), 339
from_vector_inplace() (menpo.transform.UniformScale method), 343

G

gaussian_filter() (in module menpo.feature), 97
gaussian_pyramid() (menpo.image.BooleanImage method), 53
gaussian_pyramid() (menpo.image.Image method), 30
gaussian_pyramid() (menpo.image.MaskedImage method), 80
GeneralizedProcrustesAnalysis (class in menpo.transform), 376
get() (menpo.landmark.LandmarkManager method), 111
get_adjacency_list() (menpo.shape.DirectedGraph method), 198
get_adjacency_list() (menpo.shape.LabelledPointUndirectedGraph method), 270
get_adjacency_list() (menpo.shape.PointDirectedGraph method), 235
get_adjacency_list() (menpo.shape.PointTree method), 252
get_adjacency_list() (menpo.shape.PointUndirectedGraph method), 219
get_adjacency_list() (menpo.shape.Tree method), 204
get_adjacency_list() (menpo.shape.UndirectedGraph method), 192
get_figure() (menpo.visualize.MatplotlibRenderer method), 391
get_figure() (menpo.visualize.Renderer method), 390
get_label() (menpo.shape.LabelledPointUndirectedGraph method), 270
glyph() (in module menpo.feature), 109
GMRFModel (class in menpo.model), 174
GMRFVectorModel (class in menpo.model), 176
gradient() (in module menpo.feature), 96
group_labels (menpo.landmark.LandmarkManager attribute), 112

H

h_matrix (menpo.transform.Affine attribute), 327
h_matrix (menpo.transform.AlignmentAffine attribute), 355
h_matrix (menpo.transform.AlignmentRotation attribute), 366
h_matrix (menpo.transform.AlignmentSimilarity attribute), 360
h_matrix (menpo.transform.AlignmentTranslation attribute), 370
h_matrix (menpo.transform.AlignmentUniformScale attribute), 375
h_matrix (menpo.transform.Homogeneous attribute), 323
h_matrix (menpo.transform.NonUniformScale attribute), 348
h_matrix (menpo.transform.Rotation attribute), 336
h_matrix (menpo.transform.Similarity attribute), 331
h_matrix (menpo.transform.Translation attribute), 340
h_matrix (menpo.transform.UniformScale attribute), 344
h_matrix_is_mutable (menpo.transform.Affine attribute), 327
h_matrix_is_mutable (menpo.transform.AlignmentAffine attribute), 355
h_matrix_is_mutable (menpo.transform.AlignmentRotation attribute), 366
h_matrix_is_mutable (menpo.transform.AlignmentSimilarity attribute), 360
h_matrix_is_mutable (menpo.transform.AlignmentTranslation attribute), 370
h_matrix_is_mutable (menpo.transform.AlignmentUniformScale attribute), 375
h_matrix_is_mutable (menpo.transform.Homogeneous attribute), 323
h_matrix_is_mutable (menpo.transform.NonUniformScale attribute), 348
h_matrix_is_mutable (menpo.transform.Rotation attribute), 336
h_matrix_is_mutable (menpo.transform.Similarity attribute), 331
h_matrix_is_mutable (menpo.transform.Translation attribute), 340
h_matrix_is_mutable (menpo.transform.UniformScale attribute), 344
h_points() (menpo.shape.ColouredTriMesh method), 301

h_points() (menpo.shape.LabelledPointUndirectedGraph method), 270
h_points() (menpo.shape.PointCloud method), 187
h_points() (menpo.shape.PointDirectedGraph method), 235
h_points() (menpo.shape.PointTree method), 252
h_points() (menpo.shape.PointUndirectedGraph method), 219
h_points() (menpo.shape.TexturedTriMesh method), 313
h_points() (menpo.shape.TriMesh method), 288
hand_ibug_39_to_hand_ibug_39() (in module menpo.landmark), 129
has_cycles() (menpo.shape.DirectedGraph method), 198
has_cycles() (menpo.shape.LabelledPointUndirectedGraph method), 270
has_cycles() (menpo.shape.PointDirectedGraph method), 235
has_cycles() (menpo.shape.PointTree method), 253
has_cycles() (menpo.shape.PointUndirectedGraph method), 219
has_cycles() (menpo.shape.Tree method), 204
has_cycles() (menpo.shape.UndirectedGraph method), 192
has_isolated_vertices() (menpo.shape.DirectedGraph method), 198
has_isolated_vertices() (menpo.shape.LabelledPointUndirectedGraph method), 270
has_isolated_vertices() (menpo.shape.PointDirectedGraph method), 235
has_isolated_vertices() (menpo.shape.PointTree method), 253
has_isolated_vertices() (menpo.shape.PointUndirectedGraph method), 219
has_isolated_vertices() (menpo.shape.Tree method), 204
has_isolated_vertices() (menpo.shape.UndirectedGraph method), 193
has_landmarks (menpo.image.BooleanImage attribute), 65
has_landmarks (menpo.image.Image attribute), 43
has_landmarks (menpo.image.MaskedImage attribute), 94
has_landmarks (menpo.landmark.Landmarkable attribute), 110
has_landmarks (menpo.landmark.LandmarkManager attribute), 112
has_landmarks (menpo.shape.base.Shape attribute), 179
has_landmarks (menpo.shape.ColouredTriMesh attribute), 303
has_landmarks (menpo.shape.LabelledPointUndirectedGraph attribute), 275
has_landmarks (menpo.shape.PointCloud attribute), 189
has_landmarks (menpo.shape.PointDirectedGraph attribute), 240
has_landmarks (menpo.shape.PointTree attribute), 257
has_landmarks (menpo.shape.PointUndirectedGraph attribute), 223
has_landmarks (menpo.shape.TexturedTriMesh attribute), 317
has_landmarks (menpo.shape.TriMesh attribute), 291
has_landmarks_outside_bounds() (menpo.image.BooleanImage method), 53
has_landmarks_outside_bounds() (menpo.image.Image method), 30
has_landmarks_outside_bounds() (menpo.image.MaskedImage method), 81
has_nan_values() (menpo.base.Vectorizable method), 4
has_nan_values() (menpo.image.BooleanImage method), 53
has_nan_values() (menpo.image.Image method), 31
has_nan_values() (menpo.image.MaskedImage method), 81
has_nan_values() (menpo.shape.base.Shape method), 179
has_nan_values() (menpo.shape.ColouredTriMesh method), 301
has_nan_values() (menpo.shape.LabelledPointUndirectedGraph method), 271
has_nan_values() (menpo.shape.PointCloud method), 188
has_nan_values() (menpo.shape.PointDirectedGraph method), 236
has_nan_values() (menpo.shape.PointTree method), 253
has_nan_values() (menpo.shape.PointUndirectedGraph method), 219
has_nan_values() (menpo.shape.TexturedTriMesh method), 314
has_nan_values() (menpo.shape.TriMesh method), 289
has_nan_values() (menpo.transform.Affine method), 326
has_nan_values() (menpo.transform.AlignmentAffine method), 354
has_nan_values() (menpo.transform.AlignmentRotation method), 364
has_nan_values() (menpo.transform.AlignmentSimilarity method), 359
has_nan_values() (menpo.transform.AlignmentTranslation method), 369
has_nan_values() (menpo.transform.AlignmentUniformScale method), 373
has_nan_values() (menpo.transform.Homogeneous method), 322
has_nan_values() (menpo.transform.NonUniformScale method), 347
has_nan_values() (menpo.transform.Rotation method), 334
has_nan_values() (menpo.transform.Similarity method), 330
has_nan_values() (menpo.transform.Translation method), 339
has_nan_values() (menpo.transform.UniformScale

method), 343
has_true_inverse (menpo.transform.Affine attribute), 327
has_true_inverse (menpo.transform.AlignmentAffine attribute), 356
has_true_inverse (menpo.transform.AlignmentRotation attribute), 366
has_true_inverse (menpo.transform.AlignmentSimilarity attribute), 361
has_true_inverse (menpo.transform.AlignmentTranslation attribute), 370
has_true_inverse (menpo.transform.AlignmentUniformScale attribute), 375
has_true_inverse (menpo.transform.base.invertible.Invertible attribute), 387
has_true_inverse (menpo.transform.base.invertible.VInvertible attribute), 390
has_true_inverse (menpo.transform.Homogeneous attribute), 323
has_true_inverse (menpo.transform.NonUniformScale attribute), 348
has_true_inverse (menpo.transform.Rotation attribute), 336
has_true_inverse (menpo.transform.Similarity attribute), 332
has_true_inverse (menpo.transform.ThinPlateSplines attribute), 351
has_true_inverse (menpo.transform.Translation attribute), 340
has_true_inverse (menpo.transform.UniformScale attribute), 345
height (menpo.image.BooleanImage attribute), 65
height (menpo.image.Image attribute), 43
height (menpo.image.MaskedImage attribute), 94
hellinger_vector_128_dsift() (in module menpo.feature), 104
hog() (in module menpo.feature), 99
Homogeneous (class in menpo.transform), 320

I

igo() (in module menpo.feature), 97
Image (class in menpo.image), 18
image_paths() (in module menpo.io), 17
ImageBoundaryError (class in menpo.image), 95
import_builtin_asset() (in module menpo.io), 13
import_image() (in module menpo.io), 8
import_images() (in module menpo.io), 8
import_landmark_file() (in module menpo.io), 12
import_landmark_files() (in module menpo.io), 12
import_pickle() (in module menpo.io), 12
import_pickles() (in module menpo.io), 13
import_video() (in module menpo.io), 9
import_videos() (in module menpo.io), 10
increment() (menpo.model.GMRFModel method), 175
increment() (menpo.model.GMRFVectorModel method), 177
increment() (menpo.model.PCAModel method), 153
increment() (menpo.model.PCAVectorModel method), 165
index() (menpo.base.LazyList method), 6
indices() (menpo.image.BooleanImage method), 53
indices() (menpo.image.Image method), 31
indices() (menpo.image.MaskedImage method), 81
init_2d_grid() (menpo.shape.ColouredTriMesh class method), 301
init_2d_grid() (menpo.shape.LabelledPointUndirectedGraph method), 271
init_2d_grid() (menpo.shape.PointCloud class method), 188
init_2d_grid() (menpo.shape.PointDirectedGraph method), 236
init_2d_grid() (menpo.shape.PointTree class method), 253
init_2d_grid() (menpo.shape.PointUndirectedGraph method), 219
init_2d_grid() (menpo.shape.TexturedTriMesh class method), 314
init_2d_grid() (menpo.shape.TriMesh class method), 289
init_3d_from_quaternion() (menpo.transform.AlignmentRotation method), 364
init_3d_from_quaternion() (menpo.transform.Rotation class method), 335
init_blank() (menpo.image.BooleanImage class method), 53
init_blank() (menpo.image.Image class method), 31
init_blank() (menpo.image.MaskedImage class method), 81
init_from_2d_ccw_angle() (menpo.transform.AlignmentRotation method), 364
init_from_2d_ccw_angle() (menpo.transform.Rotation class method), 335
init_from_2d_shear() (menpo.transform.Affine class method), 326
init_from_2d_shear() (menpo.transform.AlignmentAffine method), 354
init_from_2d_shear() (menpo.transform.AlignmentRotation method), 364
init_from_2d_shear() (menpo.transform.AlignmentSimilarity method), 359
init_from_2d_shear() (menpo.transform.AlignmentTranslation method), 369
init_from_2d_shear() (menpo.transform.AlignmentUniformScale method), 374
init_from_2d_shear() (menpo.transform.NonUniformScale method), 347
init_from_2d_shear() (menpo.transform.Rotation

method), 335
init_from_2d_shear() (menpo.transform.Similarity method), 330
init_from_2d_shear() (menpo.transform.Translation method), 339
init_from_2d_shear() (menpo.transform.UniformScale method), 343
init_from_channels_at_back() (menpo.image.BooleanImage class method), 53
init_from_channels_at_back() (menpo.image.Image class method), 31
init_from_channels_at_back() (menpo.image.MaskedImage class method), 81
init_from_components() (menpo.model.PCAModel class method), 154
init_from_components() (menpo.model.PCAVectorModel class method), 165
init_from_covariance_matrix() (menpo.model.PCAModel class method), 154
init_from_covariance_matrix() (menpo.model.PCAVectorModel class method), 166
init_from_depth_image() (menpo.shape.ColouredTriMesh class method), 301
init_from_depth_image() (menpo.shape.LabelledPointUndirectedGraph method), 271
init_from_depth_image() (menpo.shape.PointCloud class method), 188
init_from_depth_image() (menpo.shape.PointDirectedGraph method), 236
init_from_depth_image() (menpo.shape.PointTree class method), 253
init_from_depth_image() (menpo.shape.PointUndirectedGraph method), 220
init_from_depth_image() (menpo.shape.TexturedTriMesh class method), 314
init_from_depth_image() (menpo.shape.TriMesh class method), 289
init_from_edges() (menpo.shape.DirectedGraph method), 198
init_from_edges() (menpo.shape.LabelledPointUndirectedGraph class method), 272
init_from_edges() (menpo.shape.PointDirectedGraph method), 237
init_from_edges() (menpo.shape.PointTree class method), 254
init_from_edges() (menpo.shape.PointUndirectedGraph class method), 220
init_from_edges() (menpo.shape.Tree class method), 204
init_from_edges() (menpo.shape.UndirectedGraph class method), 193
init_from_index_callable() (menpo.base.LazyList class method), 6
init_from_indices_mapping() (menpo.shape.LabelledPointUndirectedGraph class method), 272
init_from_iterable() (menpo.base.LazyList class method), 6
init_from_pointcloud() (menpo.image.BooleanImage class method), 53
init_from_pointcloud() (menpo.image.Image class method), 31
init_from_pointcloud() (menpo.image.MaskedImage class method), 82
init_from_rolled_channels() (menpo.image.BooleanImage method), 54
init_from_rolled_channels() (menpo.image.Image class method), 32
init_from_rolled_channels() (menpo.image.MaskedImage method), 82
init_identity() (menpo.transform.Affine class method), 326
init_identity() (menpo.transform.AlignmentAffine method), 355
init_identity() (menpo.transform.AlignmentRotation method), 365
init_identity() (menpo.transform.AlignmentSimilarity method), 359
init_identity() (menpo.transform.AlignmentTranslation method), 369
init_identity() (menpo.transform.AlignmentUniformScale method), 374
init_identity() (menpo.transform.Homogeneous class method), 322
init_identity() (menpo.transform.NonUniformScale class method), 348
init_identity() (menpo.transform.Rotation class method), 335
init_identity() (menpo.transform.Similarity class method), 331
init_identity() (menpo.transform.Translation class method), 339
init_identity() (menpo.transform.UniformScale class method), 344
init_with_all_label() (menpo.shape.LabelledPointUndirectedGraph class method), 272
instance() (menpo.model.LinearVectorModel method), 148
instance() (menpo.model.MeanLinearVectorModel method), 151
instance() (menpo.model.PCAModel method), 155

instance() (menpo.model.PCAVectorModel method), 166
instance_vector() (menpo.model.PCAModel method), 155
instance_vectors() (menpo.model.LinearVectorModel method), 148
instance_vectors() (menpo.model.MeanLinearVectorModel method), 151
instance_vectors() (menpo.model.PCAModel method), 155
instance_vectors() (menpo.model.PCAVectorModel method), 166
inverse_noise_variance() (menpo.model.PCAModel method), 155
inverse_noise_variance() (menpo.model.PCAVectorModel method), 167
invert() (menpo.image.BooleanImage method), 54
Invertible (class in menpo.transform.base.invertible), 387
ipca() (in module menpo.math), 144
is_edge() (menpo.shape.DirectedGraph method), 200
is_edge() (menpo.shape.LabelledPointUndirectedGraph method), 273
is_edge() (menpo.shape.PointDirectedGraph method), 238
is_edge() (menpo.shape.PointTree method), 255
is_edge() (menpo.shape.PointUndirectedGraph method), 221
is_edge() (menpo.shape.Tree method), 205
is_edge() (menpo.shape.UndirectedGraph method), 194
is_leaf() (menpo.shape.PointTree method), 255
is_leaf() (menpo.shape.Tree method), 205
is_tree() (menpo.shape.DirectedGraph method), 200
is_tree() (menpo.shape.LabelledPointUndirectedGraph method), 273
is_tree() (menpo.shape.PointDirectedGraph method), 238
is_tree() (menpo.shape.PointTree method), 255
is_tree() (menpo.shape.PointUndirectedGraph method), 222
is_tree() (menpo.shape.Tree method), 205
is_tree() (menpo.shape.UndirectedGraph method), 194
isolated_vertices() (menpo.shape.DirectedGraph method), 200
isolated_vertices() (menpo.shape.LabelledPointUndirectedGraph method), 273
isolated_vertices() (menpo.shape.PointDirectedGraph method), 238
isolated_vertices() (menpo.shape.PointTree method), 255
isolated_vertices() (menpo.shape.PointUndirectedGraph method), 222
isolated_vertices() (menpo.shape.Tree method), 205
isolated_vertices() (menpo.shape.UndirectedGraph method), 194
items() (menpo.landmark.LandmarkManager method), 111
items_matching() (menpo.landmark.LandmarkManager method), 111
iteritems() (menpo.landmark.LandmarkManager method), 111
iterkeys() (menpo.landmark.LandmarkManager method), 111
itervalues() (menpo.landmark.LandmarkManager method), 111

K

keys() (menpo.landmark.LandmarkManager method), 111
keys_matching() (menpo.landmark.LandmarkManager method), 111

L

LabelledPointUndirectedGraph (class in menpo.shape), 258
labeller() (in module menpo.landmark), 112
LabellingError (class in menpo.landmark), 111
labels (menpo.shape.LabelledPointUndirectedGraph attribute), 275
landmark_file_paths() (in module menpo.io), 17
Landmarkable (class in menpo.landmark), 110
LandmarkableViewable (class in menpo.visualize), 391
LandmarkManager (class in menpo.landmark), 111
landmarks (menpo.image.BooleanImage attribute), 66
landmarks (menpo.image.Image attribute), 43
landmarks (menpo.image.MaskedImage attribute), 94
landmarks (menpo.landmark.Landmarkable attribute), 110
landmarks (menpo.shape.base.Shape attribute), 179
landmarks (menpo.shape.ColouredTriMesh attribute), 303
landmarks (menpo.shape.LabelledPointUndirectedGraph attribute), 275
landmarks (menpo.shape.PointCloud attribute), 189
landmarks (menpo.shape.PointDirectedGraph attribute), 240
landmarks (menpo.shape.PointTree attribute), 257
landmarks (menpo.shape.PointUndirectedGraph attribute), 223
landmarks (menpo.shape.TexturedTriMesh attribute), 317
landmarks (menpo.shape.TriMesh attribute), 291
LazyList (class in menpo.base), 5
lbp() (in module menpo.feature), 98
leaves (menpo.shape.PointTree attribute), 257
leaves (menpo.shape.Tree attribute), 207
linear_component (menpo.transform.Affine attribute), 327
linear_component (menpo.transform.AlignmentAffine attribute), 356
linear_component (menpo.transform.AlignmentRotation attribute), 366

linear_component (menpo.transform.AlignmentSimilarity attribute), 361
linear_component (menpo.transform.AlignmentTranslation attribute), 370
linear_component (menpo.transform.AlignmentUniformScale attribute), 375
linear_component (menpo.transform.NonUniformScale attribute), 349
linear_component (menpo.transform.Rotation attribute), 336
linear_component (menpo.transform.Similarity attribute), 332
linear_component (menpo.transform.Translation attribute), 340
linear_component (menpo.transform.UniformScale attribute), 345
LinearModel (in module menpo.model), 148
LinearVectorModel (class in menpo.model), 148
lms (menpo.shape.ColouredTriMesh attribute), 303
lms (menpo.shape.LabelledPointUndirectedGraph attribute), 275
lms (menpo.shape.PointCloud attribute), 189
lms (menpo.shape.PointDirectedGraph attribute), 240
lms (menpo.shape.PointTree attribute), 257
lms (menpo.shape.PointUndirectedGraph attribute), 223
lms (menpo.shape.TexturedTriMesh attribute), 317
lms (menpo.shape.TriMesh attribute), 291
log_gabor() (in module menpo.math), 146
ls_builtin_assets() (in module menpo.io), 18

M

mahalanobis_distance() (menpo.model.GMRFModel method), 176
mahalanobis_distance() (menpo.model.GMRFVectorModel method), 178
map() (menpo.base.LazyList method), 6
mask (menpo.image.BooleanImage attribute), 66
masked_pixels() (menpo.image.MaskedImage method), 82
MaskedImage (class in menpo.image), 66
MatplotlibRenderer (class in menpo.visualize), 391
maximum_depth (menpo.shape.PointTree attribute), 258
maximum_depth (menpo.shape.Tree attribute), 207
mean() (menpo.model.GMRFModel method), 176
mean() (menpo.model.GMRFVectorModel method), 178
mean() (menpo.model.MeanLinearVectorModel method), 151
mean() (menpo.model.PCAModel method), 155
mean() (menpo.model.PCAVectorModel method), 167
mean_aligned_shape() (menpo.transform.GeneralizedProcrustesAnalysis method), 376
mean_alignment_error() (menpo.transform.GeneralizedProcrustesAnalysis method), 376
mean_edge_length() (menpo.shape.ColouredTriMesh method), 301
mean_edge_length() (menpo.shape.TexturedTriMesh method), 314
mean_edge_length() (menpo.shape.TriMesh method), 289
mean_pointcloud() (in module menpo.shape), 317
mean_tri_area() (menpo.shape.ColouredTriMesh method), 302
mean_tri_area() (menpo.shape.TexturedTriMesh method), 315
mean_tri_area() (menpo.shape.TriMesh method), 289
mean_vector (menpo.model.PCAModel attribute), 163
MeanLinearModel (in module menpo.model), 150
MeanLinearVectorModel (class in menpo.model), 150
menpo_src_dir_path() (in module menpo.base), 7
MenpoDeprecationWarning (class in menpo.base), 7
MenpoMissingDependencyError (class in menpo.base), 7
minimum_spanning_tree() (menpo.shape.LabelledPointUndirectedGraph method), 273
minimum_spanning_tree() (menpo.shape.PointUndirectedGraph method), 222
minimum_spanning_tree() (menpo.shape.UndirectedGraph method), 194
mirror() (menpo.image.BooleanImage method), 54
mirror() (menpo.image.Image method), 32
mirror() (menpo.image.MaskedImage method), 82
MultipleAlignment (class in menpo.transform.groupalign.base), 388

N

n_active_components (menpo.model.PCAModel attribute), 164
n_active_components (menpo.model.PCAVectorModel attribute), 174
n_centres (menpo.transform.R2LogR2RBF attribute), 380
n_centres (menpo.transform.R2LogRRBF attribute), 381
n_channels (menpo.image.BooleanImage attribute), 66
n_channels (menpo.image.Image attribute), 43
n_channels (menpo.image.MaskedImage attribute), 95
n_channels (menpo.shape.ColouredTriMesh attribute), 304
n_channels (menpo.shape.TexturedTriMesh attribute), 317
n_children() (menpo.shape.DirectedGraph method), 200
n_children() (menpo.shape.PointDirectedGraph method), 239
n_children() (menpo.shape.PointTree method), 255
n_children() (menpo.shape.Tree method), 206

n_components (menpo.model.LinearVectorModel attribute), 150
n_components (menpo.model.MeanLinearVectorModel attribute), 152
n_components (menpo.model.PCAModel attribute), 164
n_components (menpo.model.PCAVectorModel attribute), 174
n_dims (menpo.base.Targetable attribute), 5
n_dims (menpo.image.BooleanImage attribute), 66
n_dims (menpo.image.Image attribute), 43
n_dims (menpo.image.MaskedImage attribute), 95
n_dims (menpo.landmark.LandmarkManager attribute), 112
n_dims (menpo.shape.ColouredTriMesh attribute), 304
n_dims (menpo.shape.LabelledPointUndirectedGraph attribute), 275
n_dims (menpo.shape.PointCloud attribute), 189
n_dims (menpo.shape.PointDirectedGraph attribute), 240
n_dims (menpo.shape.PointTree attribute), 258
n_dims (menpo.shape.PointUndirectedGraph attribute), 223
n_dims (menpo.shape.TexturedTriMesh attribute), 317
n_dims (menpo.shape.TriMesh attribute), 291
n_dims (menpo.transform.Affine attribute), 327
n_dims (menpo.transform.AlignmentAffine attribute), 356
n_dims (menpo.transform.AlignmentRotation attribute), 366
n_dims (menpo.transform.AlignmentSimilarity attribute), 361
n_dims (menpo.transform.AlignmentTranslation attribute), 370
n_dims (menpo.transform.AlignmentUniformScale attribute), 375
n_dims (menpo.transform.base.alignment.Alignment attribute), 388
n_dims (menpo.transform.base.composable.ComposableTransform attribute), 386
n_dims (menpo.transform.Homogeneous attribute), 323
n_dims (menpo.transform.NonUniformScale attribute), 349
n_dims (menpo.transform.R2LogR2RBF attribute), 380
n_dims (menpo.transform.R2LogRRBF attribute), 382
n_dims (menpo.transform.Rotation attribute), 336
n_dims (menpo.transform.Similarity attribute), 332
n_dims (menpo.transform.ThinPlateSplines attribute), 351
n_dims (menpo.transform.Transform attribute), 383
n_dims (menpo.transform.TransformChain attribute), 378
n_dims (menpo.transform.Translation attribute), 340
n_dims (menpo.transform.UniformScale attribute), 345
n_dims() (menpo.landmark.Landmarkable method), 110
n_dims() (menpo.shape.base.Shape method), 179
n_dims_output (menpo.transform.Affine attribute), 327
n_dims_output (menpo.transform.AlignmentAffine attribute), 356
n_dims_output (menpo.transform.AlignmentRotation attribute), 366
n_dims_output (menpo.transform.AlignmentSimilarity attribute), 361
n_dims_output (menpo.transform.AlignmentTranslation attribute), 371
n_dims_output (menpo.transform.AlignmentUniformScale attribute), 375
n_dims_output (menpo.transform.base.composable.ComposableTransform attribute), 387
n_dims_output (menpo.transform.Homogeneous attribute), 323
n_dims_output (menpo.transform.NonUniformScale attribute), 349
n_dims_output (menpo.transform.R2LogR2RBF attribute), 380
n_dims_output (menpo.transform.R2LogRRBF attribute), 382
n_dims_output (menpo.transform.Rotation attribute), 336
n_dims_output (menpo.transform.Similarity attribute), 332
n_dims_output (menpo.transform.ThinPlateSplines attribute), 351
n_dims_output (menpo.transform.Transform attribute), 384
n_dims_output (menpo.transform.TransformChain attribute), 379
n_dims_output (menpo.transform.Translation attribute), 340
n_dims_output (menpo.transform.UniformScale attribute), 345
n_edges (menpo.shape.DirectedGraph attribute), 201
n_edges (menpo.shape.LabelledPointUndirectedGraph attribute), 275
n_edges (menpo.shape.PointDirectedGraph attribute), 241
n_edges (menpo.shape.PointTree attribute), 258
n_edges (menpo.shape.PointUndirectedGraph attribute), 223
n_edges (menpo.shape.Tree attribute), 207
n_edges (menpo.shape.UndirectedGraph attribute), 195
n_elements (menpo.image.BooleanImage attribute), 66
n_elements (menpo.image.Image attribute), 43
n_elements (menpo.image.MaskedImage attribute), 95
n_false() (menpo.image.BooleanImage method), 54
n_false_elements() (menpo.image.MaskedImage method), 83
n_false_pixels() (menpo.image.MaskedImage method), 83
n_features (menpo.model.LinearVectorModel attribute), 150
n_features (menpo.model.MeanLinearVectorModel at-

tribute), 152
n_features (menpo.model.PCAModel attribute), 164
n_features (menpo.model.PCAVectorModel attribute), 174
n_groups (menpo.landmark.LandmarkManager attribute), 112
n_labels (menpo.shape.LabelledPointUndirectedGraph attribute), 275
n_landmark_groups (menpo.image.BooleanImage attribute), 66
n_landmark_groups (menpo.image.Image attribute), 43
n_landmark_groups (menpo.image.MaskedImage attribute), 95
n_landmark_groups (menpo.landmark.Landmarkable attribute), 110
n_landmark_groups (menpo.shape.base.Shape attribute), 179
n_landmark_groups (menpo.shape.ColouredTriMesh attribute), 304
n_landmark_groups (menpo.shape.LabelledPointUndirectedGraph attribute), 275
n_landmark_groups (menpo.shape.PointCloud attribute), 189
n_landmark_groups (menpo.shape.PointDirectedGraph attribute), 241
n_landmark_groups (menpo.shape.PointTree attribute), 258
n_landmark_groups (menpo.shape.PointUndirectedGraph attribute), 223
n_landmark_groups (menpo.shape.TexturedTriMesh attribute), 317
n_landmark_groups (menpo.shape.TriMesh attribute), 291
n_landmarks (menpo.shape.LabelledPointUndirectedGraph attribute), 275
n_leaves (menpo.shape.PointTree attribute), 258
n_leaves (menpo.shape.Tree attribute), 207
n_neighbours() (menpo.shape.LabelledPointUndirectedGraph method), 273
n_neighbours() (menpo.shape.PointUndirectedGraph method), 222
n_neighbours() (menpo.shape.UndirectedGraph method), 194
n_parameters (menpo.base.Vectorizable attribute), 4
n_parameters (menpo.image.BooleanImage attribute), 66
n_parameters (menpo.image.Image attribute), 43
n_parameters (menpo.image.MaskedImage attribute), 95
n_parameters (menpo.shape.base.Shape attribute), 179
n_parameters (menpo.shape.ColouredTriMesh attribute), 304
n_parameters (menpo.shape.LabelledPointUndirectedGraph attribute), 275
n_parameters (menpo.shape.PointCloud attribute), 189
n_parameters (menpo.shape.PointDirectedGraph attribute), 241
n_parameters (menpo.shape.PointTree attribute), 258
n_parameters (menpo.shape.PointUndirectedGraph attribute), 223
n_parameters (menpo.shape.TexturedTriMesh attribute), 317
n_parameters (menpo.shape.TriMesh attribute), 291
n_parameters (menpo.transform.Affine attribute), 327
n_parameters (menpo.transform.AlignmentAffine attribute), 356
n_parameters (menpo.transform.AlignmentRotation attribute), 366
n_parameters (menpo.transform.AlignmentSimilarity attribute), 361
n_parameters (menpo.transform.AlignmentTranslation attribute), 371
n_parameters (menpo.transform.AlignmentUniformScale attribute), 375
n_parameters (menpo.transform.Homogeneous attribute), 323
n_parameters (menpo.transform.NonUniformScale attribute), 349
n_parameters (menpo.transform.Rotation attribute), 336
n_parameters (menpo.transform.Similarity attribute), 332
n_parameters (menpo.transform.Translation attribute), 340
n_parameters (menpo.transform.UniformScale attribute), 345
n_parents() (menpo.shape.DirectedGraph method), 200
n_parents() (menpo.shape.PointDirectedGraph method), 239
n_parents() (menpo.shape.PointTree method), 255
n_parents() (menpo.shape.Tree method), 206
n_paths() (menpo.shape.DirectedGraph method), 200
n_paths() (menpo.shape.LabelledPointUndirectedGraph method), 273
n_paths() (menpo.shape.PointDirectedGraph method), 239
n_paths() (menpo.shape.PointTree method), 256
n_paths() (menpo.shape.PointUndirectedGraph method), 222
n_paths() (menpo.shape.Tree method), 206
n_paths() (menpo.shape.UndirectedGraph method), 194
n_pixels (menpo.image.BooleanImage attribute), 66
n_pixels (menpo.image.Image attribute), 43
n_pixels (menpo.image.MaskedImage attribute), 95
n_points (menpo.base.Targetable attribute), 5
n_points (menpo.shape.ColouredTriMesh attribute), 304
n_points (menpo.shape.LabelledPointUndirectedGraph attribute), 275
n_points (menpo.shape.PointCloud attribute), 189
n_points (menpo.shape.PointDirectedGraph attribute), 241
n_points (menpo.shape.PointTree attribute), 258

n_points (menpo.shape.PointUndirectedGraph attribute), 224
n_points (menpo.shape.TexturedTriMesh attribute), 317
n_points (menpo.shape.TriMesh attribute), 291
n_points (menpo.transform.AlignmentAffine attribute), 356
n_points (menpo.transform.AlignmentRotation attribute), 366
n_points (menpo.transform.AlignmentSimilarity attribute), 361
n_points (menpo.transform.AlignmentTranslation attribute), 371
n_points (menpo.transform.AlignmentUniformScale attribute), 375
n_points (menpo.transform.base.alignment.Alignment attribute), 388
n_points (menpo.transform.ThinPlateSplines attribute), 351
n_tris (menpo.shape.ColouredTriMesh attribute), 304
n_tris (menpo.shape.TexturedTriMesh attribute), 317
n_tris (menpo.shape.TriMesh attribute), 291
n_true() (menpo.image.BooleanImage method), 55
n_true_elements() (menpo.image.MaskedImage method), 83
n_true_pixels() (menpo.image.MaskedImage method), 83
n_vertices (menpo.shape.DirectedGraph attribute), 201
n_vertices (menpo.shape.LabelledPointUndirectedGraph attribute), 275
n_vertices (menpo.shape.PointDirectedGraph attribute), 241
n_vertices (menpo.shape.PointTree attribute), 258
n_vertices (menpo.shape.PointUndirectedGraph attribute), 224
n_vertices (menpo.shape.Tree attribute), 207
n_vertices (menpo.shape.UndirectedGraph attribute), 195
n_vertices_at_depth() (menpo.shape.PointTree method), 256
n_vertices_at_depth() (menpo.shape.Tree method), 206
name_of_callable() (in module menpo.base), 7
neighbours() (menpo.shape.LabelledPointUndirectedGraph method), 273
neighbours() (menpo.shape.PointUndirectedGraph method), 222
neighbours() (menpo.shape.UndirectedGraph method), 194
no_op() (in module menpo.feature), 96
noise_variance() (menpo.model.PCAModel method), 156
noise_variance() (menpo.model.PCAVectorModel method), 167
noise_variance_ratio() (menpo.model.PCAModel method), 156
noise_variance_ratio() (menpo.model.PCAVectorModel method), 167
NonUniformScale (class in menpo.transform), 345
norm() (menpo.shape.ColouredTriMesh method), 302
norm() (menpo.shape.LabelledPointUndirectedGraph method), 274
norm() (menpo.shape.PointCloud method), 188
norm() (menpo.shape.PointDirectedGraph method), 239
norm() (menpo.shape.PointTree method), 256
norm() (menpo.shape.PointUndirectedGraph method), 222
norm() (menpo.shape.TexturedTriMesh method), 315
norm() (menpo.shape.TriMesh method), 289
normalize() (in module menpo.feature), 107
normalize_norm() (in module menpo.feature), 107
normalize_norm() (menpo.image.BooleanImage method), 55
normalize_norm() (menpo.image.Image method), 32
normalize_norm() (menpo.image.MaskedImage method), 83
normalize_std() (in module menpo.feature), 108
normalize_std() (menpo.image.BooleanImage method), 55
normalize_std() (menpo.image.Image method), 32
normalize_std() (menpo.image.MaskedImage method), 83
normalize_var() (in module menpo.feature), 108

O

original_variance() (menpo.model.PCAModel method), 156
original_variance() (menpo.model.PCAVectorModel method), 167
orthonormalize_against_inplace() (menpo.model.LinearVectorModel method), 149
orthonormalize_against_inplace() (menpo.model.MeanLinearVectorModel method), 151
orthonormalize_against_inplace() (menpo.model.PCAModel method), 156
orthonormalize_against_inplace() (menpo.model.PCAVectorModel method), 167
orthonormalize_inplace() (menpo.model.LinearVectorModel method), 149
orthonormalize_inplace() (menpo.model.MeanLinearVectorModel method), 151
orthonormalize_inplace() (menpo.model.PCAModel method), 156
orthonormalize_inplace() (menpo.model.PCAVectorModel method), 167
OutOfMaskSampleError (class in menpo.image), 96

P

parent() (menpo.shape.PointTree method), 256
parent() (menpo.shape.Tree method), 206
parents() (menpo.shape.DirectedGraph method), 201
parents() (menpo.shape.PointDirectedGraph method), 239
parents() (menpo.shape.PointTree method), 256
parents() (menpo.shape.Tree method), 206
pca() (in module menpo.math), 143
pcacov() (in module menpo.math), 143
PCAModel (class in menpo.model), 152
PCAVectorModel (class in menpo.model), 164
pickle_paths() (in module menpo.io), 17
PiecewiseAffine (in module menpo.transform), 351
pixels_range() (menpo.image.BooleanImage method), 55
pixels_range() (menpo.image.Image method), 32
pixels_range() (menpo.image.MaskedImage method), 83
pixels_with_channels_at_back() (menpo.image.BooleanImage method), 55
pixels_with_channels_at_back() (menpo.image.Image method), 32
pixels_with_channels_at_back() (menpo.image.MaskedImage method), 83
plot_curve() (in module menpo.visualize), 398
plot_eigenvalues() (menpo.model.PCAModel method), 156
plot_eigenvalues() (menpo.model.PCAVectorModel method), 167
plot_eigenvalues_cumulative_ratio() (menpo.model.PCAModel method), 158
plot_eigenvalues_cumulative_ratio() (menpo.model.PCAVectorModel method), 169
plot_eigenvalues_cumulative_ratio_widget() (menpo.model.PCAModel method), 159
plot_eigenvalues_cumulative_ratio_widget() (menpo.model.PCAVectorModel method), 170
plot_eigenvalues_ratio() (menpo.model.PCAModel method), 159
plot_eigenvalues_ratio() (menpo.model.PCAVectorModel method), 170
plot_eigenvalues_ratio_widget() (menpo.model.PCAModel method), 161
plot_eigenvalues_ratio_widget() (menpo.model.PCAVectorModel method), 172
plot_eigenvalues_widget() (menpo.model.PCAModel method), 161
plot_eigenvalues_widget() (menpo.model.PCAVectorModel method), 172
plot_gaussian_ellipses() (in module menpo.visualize), 402
PointCloud (class in menpo.shape), 180
PointDirectedGraph (class in menpo.shape), 224
PointTree (class in menpo.shape), 241
PointUndirectedGraph (class in menpo.shape), 207
pop() (menpo.landmark.LandmarkManager method), 112
popitem() (menpo.landmark.LandmarkManager method), 112
pose_flic_11_to_pose_flic_11() (in module menpo.landmark), 130
pose_human36M_32_to_pose_human36M_17() (in module menpo.landmark), 131
pose_human36M_32_to_pose_human36M_32() (in module menpo.landmark), 132
pose_lsp_14_to_pose_lsp_14() (in module menpo.landmark), 133
pose_stickmen_12_to_pose_stickmen_12() (in module menpo.landmark), 134
principal_components_analysis() (menpo.model.GMRFModel method), 176
principal_components_analysis() (menpo.model.GMRFVectorModel method), 178
print_dynamic() (in module menpo.visualize), 397
print_progress() (in module menpo.visualize), 396
progress_bar_str() (in module menpo.visualize), 397
project() (menpo.model.LinearVectorModel method), 149
project() (menpo.model.MeanLinearVectorModel method), 151
project() (menpo.model.PCAModel method), 161
project() (menpo.model.PCAVectorModel method), 172
project_out() (menpo.model.LinearVectorModel method), 149
project_out() (menpo.model.MeanLinearVectorModel method), 151
project_out() (menpo.model.PCAModel method), 161
project_out() (menpo.model.PCAVectorModel method), 172
project_out_vector() (menpo.model.PCAModel method), 161
project_out_vectors() (menpo.model.LinearVectorModel method), 149
project_out_vectors() (menpo.model.MeanLinearVectorModel method), 151
project_out_vectors() (menpo.model.PCAModel method), 161
project_out_vectors() (menpo.model.PCAVectorModel method), 173
project_vector() (menpo.model.PCAModel method), 162
project_vectors() (menpo.model.LinearVectorModel method), 149
project_vectors() (menpo.model.MeanLinearVectorModel method), 152
project_vectors() (menpo.model.PCAModel method),

162
project_vectors() (menpo.model.PCAVectorModel method), 173
project_whitened() (menpo.model.PCAModel method), 162
project_whitened() (menpo.model.PCAVectorModel method), 173
project_whitened_vector() (menpo.model.PCAModel method), 162
proportion_false() (menpo.image.BooleanImage method), 55
proportion_true() (menpo.image.BooleanImage method), 55
pseudoinverse() (menpo.transform.Affine method), 326
pseudoinverse() (menpo.transform.AlignmentAffine method), 355
pseudoinverse() (menpo.transform.AlignmentRotation method), 365
pseudoinverse() (menpo.transform.AlignmentSimilarity method), 360
pseudoinverse() (menpo.transform.AlignmentTranslation method), 369
pseudoinverse() (menpo.transform.AlignmentUniformScale method), 374
pseudoinverse() (menpo.transform.base.invertible.Invertible method), 387
pseudoinverse() (menpo.transform.base.invertible.VInvertible method), 389
pseudoinverse() (menpo.transform.Homogeneous method), 322
pseudoinverse() (menpo.transform.NonUniformScale method), 348
pseudoinverse() (menpo.transform.Rotation method), 335
pseudoinverse() (menpo.transform.Similarity method), 331
pseudoinverse() (menpo.transform.ThinPlateSplines method), 351
pseudoinverse() (menpo.transform.Translation method), 339
pseudoinverse() (menpo.transform.UniformScale method), 344
pseudoinverse_vector() (menpo.transform.Affine method), 326
pseudoinverse_vector() (menpo.transform.AlignmentAffine method), 355
pseudoinverse_vector() (menpo.transform.AlignmentRotation method), 365
pseudoinverse_vector() (menpo.transform.AlignmentSimilarity method), 360
pseudoinverse_vector() (menpo.transform.AlignmentTranslation method), 369
pseudoinverse_vector() (menpo.transform.AlignmentUniformScale method), 374
pseudoinverse_vector() (menpo.transform.base.invertible.VInvertible method), 389
pseudoinverse_vector() (menpo.transform.Homogeneous method), 322
pseudoinverse_vector() (menpo.transform.NonUniformScale method), 348
pseudoinverse_vector() (menpo.transform.Rotation method), 335
pseudoinverse_vector() (menpo.transform.Similarity method), 331
pseudoinverse_vector() (menpo.transform.Translation method), 339
pseudoinverse_vector() (menpo.transform.UniformScale method), 344
pyramid() (menpo.image.BooleanImage method), 55
pyramid() (menpo.image.Image method), 33
pyramid() (menpo.image.MaskedImage method), 84

R

R2LogR2RBF (class in menpo.transform), 379
R2LogRRBF (class in menpo.transform), 380
range() (menpo.shape.ColouredTriMesh method), 302
range() (menpo.shape.LabelledPointUndirectedGraph method), 274
range() (menpo.shape.PointCloud method), 188
range() (menpo.shape.PointDirectedGraph method), 239
range() (menpo.shape.PointTree method), 256
range() (menpo.shape.PointUndirectedGraph method), 223
range() (menpo.shape.TexturedTriMesh method), 315
range() (menpo.shape.TriMesh method), 289
rasterize_landmarks() (menpo.image.BooleanImage method), 55
rasterize_landmarks() (menpo.image.Image method), 33
rasterize_landmarks() (menpo.image.MaskedImage method), 84
reconstruct() (menpo.model.LinearVectorModel method), 149
reconstruct() (menpo.model.MeanLinearVectorModel method), 152
reconstruct() (menpo.model.PCAModel method), 162
reconstruct() (menpo.model.PCAVectorModel method), 173
reconstruct_vector() (menpo.model.PCAModel method), 162
reconstruct_vectors() (menpo.model.LinearVectorModel method), 149
reconstruct_vectors() (menpo.model.MeanLinearVectorModel method), 152
reconstruct_vectors() (menpo.model.PCAModel method), 162
reconstruct_vectors() (menpo.model.PCAVectorModel method), 173
register_image_importer() (in module menpo.io), 14
register_landmark_importer() (in module menpo.io), 14

register_pickle_importer() (in module menpo.io), 14
register_video_importer() (in module menpo.io), 14
relative_location_edge() (menpo.shape.PointDirectedGraph method), 240
relative_location_edge() (menpo.shape.PointTree method), 256
relative_locations() (menpo.shape.PointDirectedGraph method), 240
relative_locations() (menpo.shape.PointTree method), 257
remove_label() (menpo.shape.LabelledPointUndirectedGraph method), 274
render() (menpo.visualize.MatplotlibRenderer method), 391
render() (menpo.visualize.Renderer method), 390
Renderer (class in menpo.visualize), 390
repeat() (menpo.base.LazyList method), 6
rescale() (menpo.image.BooleanImage method), 56
rescale() (menpo.image.Image method), 34
rescale() (menpo.image.MaskedImage method), 85
rescale_landmarks_to_diagonal_range() (menpo.image.BooleanImage method), 57
rescale_landmarks_to_diagonal_range() (menpo.image.Image method), 34
rescale_landmarks_to_diagonal_range() (menpo.image.MaskedImage method), 85
rescale_pixels() (menpo.image.BooleanImage method), 58
rescale_pixels() (menpo.image.Image method), 35
rescale_pixels() (menpo.image.MaskedImage method), 86
rescale_texture() (menpo.shape.ColouredTriMesh method), 302
rescale_texture() (menpo.shape.TexturedTriMesh method), 315
rescale_to_diagonal() (menpo.image.BooleanImage method), 58
rescale_to_diagonal() (menpo.image.Image method), 35
rescale_to_diagonal() (menpo.image.MaskedImage method), 86
rescale_to_pointcloud() (menpo.image.BooleanImage method), 58
rescale_to_pointcloud() (menpo.image.Image method), 35
rescale_to_pointcloud() (menpo.image.MaskedImage method), 86
resize() (menpo.image.BooleanImage method), 59
resize() (menpo.image.Image method), 36
resize() (menpo.image.MaskedImage method), 87
rolled_channels() (menpo.image.BooleanImage method), 59
rolled_channels() (menpo.image.Image method), 37
rolled_channels() (menpo.image.MaskedImage method), 88
rotate_ccw_about_centre() (in module menpo.transform), 319
rotate_ccw_about_centre() (menpo.image.BooleanImage method), 59
rotate_ccw_about_centre() (menpo.image.Image method), 37
rotate_ccw_about_centre() (menpo.image.MaskedImage method), 88
Rotation (class in menpo.transform), 332
rotation_matrix (menpo.transform.AlignmentRotation attribute), 366
rotation_matrix (menpo.transform.Rotation attribute), 337

S

sample() (menpo.image.BooleanImage method), 60
sample() (menpo.image.Image method), 37
sample() (menpo.image.MaskedImage method), 88
save_figure() (menpo.visualize.MatplotlibRenderer method), 391
save_figure() (menpo.visualize.Renderer method), 390
save_figure_widget() (menpo.visualize.MatplotlibRenderer method), 392
scale (menpo.transform.AlignmentUniformScale attribute), 375
scale (menpo.transform.NonUniformScale attribute), 349
scale (menpo.transform.UniformScale attribute), 345
Scale() (in module menpo.transform), 341
scale_about_centre() (in module menpo.transform), 319
set_boundary_pixels() (menpo.image.MaskedImage method), 89
set_h_matrix() (menpo.transform.Affine method), 327
set_h_matrix() (menpo.transform.AlignmentAffine method), 355
set_h_matrix() (menpo.transform.AlignmentRotation method), 365
set_h_matrix() (menpo.transform.AlignmentSimilarity method), 360
set_h_matrix() (menpo.transform.AlignmentTranslation method), 370
set_h_matrix() (menpo.transform.AlignmentUniformScale method), 374
set_h_matrix() (menpo.transform.Homogeneous method), 323
set_h_matrix() (menpo.transform.NonUniformScale method), 348
set_h_matrix() (menpo.transform.Rotation method), 335
set_h_matrix() (menpo.transform.Similarity method), 331
set_h_matrix() (menpo.transform.Translation method), 340
set_h_matrix() (menpo.transform.UniformScale method), 344

set_masked_pixels() (menpo.image.MaskedImage method), 89
set_patches() (menpo.image.BooleanImage method), 60
set_patches() (menpo.image.Image method), 38
set_patches() (menpo.image.MaskedImage method), 89
set_patches_around_landmarks() (menpo.image.BooleanImage method), 61
set_patches_around_landmarks() (menpo.image.Image method), 38
set_patches_around_landmarks() (menpo.image.MaskedImage method), 90
set_rotation_matrix() (menpo.transform.AlignmentRotation method), 365
set_rotation_matrix() (menpo.transform.Rotation method), 336
set_target() (menpo.base.Targetable method), 5
set_target() (menpo.transform.AlignmentAffine method), 355
set_target() (menpo.transform.AlignmentRotation method), 365
set_target() (menpo.transform.AlignmentSimilarity method), 360
set_target() (menpo.transform.AlignmentTranslation method), 370
set_target() (menpo.transform.AlignmentUniformScale method), 374
set_target() (menpo.transform.base.alignment.Alignment method), 388
set_target() (menpo.transform.ThinPlateSplines method), 351
setdefault() (menpo.landmark.LandmarkManager method), 112
Shape (class in menpo.shape.base), 178
shape (menpo.image.BooleanImage attribute), 66
shape (menpo.image.Image attribute), 44
shape (menpo.image.MaskedImage attribute), 95
shear_about_centre() (in module menpo.transform), 319
Similarity (class in menpo.transform), 328
source (menpo.transform.AlignmentAffine attribute), 356
source (menpo.transform.AlignmentRotation attribute), 366
source (menpo.transform.AlignmentSimilarity attribute), 361
source (menpo.transform.AlignmentTranslation attribute), 371
source (menpo.transform.AlignmentUniformScale attribute), 375
source (menpo.transform.base.alignment.Alignment attribute), 388
source (menpo.transform.ThinPlateSplines attribute), 351
sparse_hog() (in module menpo.feature), 105
star_graph() (in module menpo.shape), 276
stencil_grid() (in module menpo.shape), 278
sum_channels() (in module menpo.feature), 109

T

target (menpo.base.Targetable attribute), 5
target (menpo.transform.AlignmentAffine attribute), 356
target (menpo.transform.AlignmentRotation attribute), 366
target (menpo.transform.AlignmentSimilarity attribute), 361
target (menpo.transform.AlignmentTranslation attribute), 371
target (menpo.transform.AlignmentUniformScale attribute), 375
target (menpo.transform.base.alignment.Alignment attribute), 388
target (menpo.transform.ThinPlateSplines attribute), 351
Targetable (class in menpo.base), 4
tcoords_pixel_scaled() (menpo.shape.TexturedTriMesh method), 315
TexturedTriMesh (class in menpo.shape), 304
ThinPlateSplines (class in menpo.transform), 349
tojson() (menpo.shape.ColouredTriMesh method), 302
tojson() (menpo.shape.LabelledPointUndirectedGraph method), 274
tojson() (menpo.shape.PointCloud method), 188
tojson() (menpo.shape.PointDirectedGraph method), 240
tojson() (menpo.shape.PointTree method), 257
tojson() (menpo.shape.PointUndirectedGraph method), 223
tojson() (menpo.shape.TexturedTriMesh method), 316
tojson() (menpo.shape.TriMesh method), 290
tongue_ibug_19_to_tongue_ibug_19() (in module menpo.landmark), 142
Transform (class in menpo.transform), 382
transform_about_centre() (in module menpo.transform), 320
transform_about_centre() (menpo.image.BooleanImage method), 62
transform_about_centre() (menpo.image.Image method), 39
transform_about_centre() (menpo.image.MaskedImage method), 90
Transformable (class in menpo.transform.base), 384
TransformChain (class in menpo.transform), 376
Translation (class in menpo.transform), 337
translation_component (menpo.transform.Affine attribute), 328
translation_component (menpo.transform.AlignmentAffine attribute), 356
translation_component (menpo.transform.AlignmentRotation attribute), 367
translation_component (menpo.transform.AlignmentSimilarity attribute), 361
translation_component (menpo.transform.AlignmentTranslation attribute), 371

translation_component (menpo.transform.AlignmentUniformScale attribute), 376
translation_component (menpo.transform.NonUniformScale attribute), 349
translation_component (menpo.transform.Rotation attribute), 337
translation_component (menpo.transform.Similarity attribute), 332
translation_component (menpo.transform.Translation attribute), 341
translation_component (menpo.transform.UniformScale attribute), 345
Tree (class in menpo.shape), 201
tri_areas() (menpo.shape.ColouredTriMesh method), 302
tri_areas() (menpo.shape.TexturedTriMesh method), 316
tri_areas() (menpo.shape.TriMesh method), 290
tri_normals() (menpo.shape.ColouredTriMesh method), 302
tri_normals() (menpo.shape.TexturedTriMesh method), 316
tri_normals() (menpo.shape.TriMesh method), 290
trim_components() (menpo.model.PCAModel method), 163
trim_components() (menpo.model.PCAVectorModel method), 173
TriMesh (class in menpo.shape), 279
true_indices() (menpo.image.BooleanImage method), 64

U

UndirectedGraph (class in menpo.shape), 189
UniformScale (class in menpo.transform), 341
unique_edge_indices() (menpo.shape.ColouredTriMesh method), 303
unique_edge_indices() (menpo.shape.TexturedTriMesh method), 316
unique_edge_indices() (menpo.shape.TriMesh method), 290
unique_edge_lengths() (menpo.shape.ColouredTriMesh method), 303
unique_edge_lengths() (menpo.shape.TexturedTriMesh method), 316
unique_edge_lengths() (menpo.shape.TriMesh method), 290
unique_edge_vectors() (menpo.shape.ColouredTriMesh method), 303
unique_edge_vectors() (menpo.shape.TexturedTriMesh method), 316
unique_edge_vectors() (menpo.shape.TriMesh method), 290
update() (menpo.landmark.LandmarkManager method), 112

V

values() (menpo.landmark.LandmarkManager method), 112
variance() (menpo.model.PCAModel method), 163
variance() (menpo.model.PCAVectorModel method), 173
variance_ratio() (menpo.model.PCAModel method), 163
variance_ratio() (menpo.model.PCAVectorModel method), 174
VComposable (class in menpo.transform.base.composable), 389
vector_128_dsift() (in module menpo.feature), 104
Vectorizable (class in menpo.base), 4
vertex_normals() (menpo.shape.ColouredTriMesh method), 303
vertex_normals() (menpo.shape.TexturedTriMesh method), 316
vertex_normals() (menpo.shape.TriMesh method), 290
vertices (menpo.shape.DirectedGraph attribute), 201
vertices (menpo.shape.LabelledPointUndirectedGraph attribute), 276
vertices (menpo.shape.PointDirectedGraph attribute), 241
vertices (menpo.shape.PointTree attribute), 258
vertices (menpo.shape.PointUndirectedGraph attribute), 224
vertices (menpo.shape.Tree attribute), 207
vertices (menpo.shape.UndirectedGraph attribute), 195
vertices_at_depth() (menpo.shape.PointTree method), 257
vertices_at_depth() (menpo.shape.Tree method), 207
video_paths() (in module menpo.io), 17
view_patches() (in module menpo.visualize), 393
view_widget() (menpo.image.BooleanImage method), 64
view_widget() (menpo.image.Image method), 41
view_widget() (menpo.image.MaskedImage method), 92
view_widget() (menpo.model.PCAModel method), 163
Viewable (class in menpo.visualize), 391
VInvertible (class in menpo.transform.base.invertible), 389

W

warp_to_mask() (menpo.image.BooleanImage method), 64
warp_to_mask() (menpo.image.Image method), 41
warp_to_mask() (menpo.image.MaskedImage method), 92
warp_to_shape() (menpo.image.BooleanImage method), 64
warp_to_shape() (menpo.image.Image method), 42
warp_to_shape() (menpo.image.MaskedImage method), 93
whitened_components() (menpo.model.PCAModel method), 163
whitened_components() (menpo.model.PCAVectorModel method), 174
width (menpo.image.BooleanImage attribute), 66
width (menpo.image.Image attribute), 44

width (menpo.image.MaskedImage attribute), 95
with_dims() (menpo.shape.ColouredTriMesh method), 303
with_dims() (menpo.shape.LabelledPointUndirectedGraph method), 274
with_dims() (menpo.shape.PointCloud method), 189
with_dims() (menpo.shape.PointDirectedGraph method), 240
with_dims() (menpo.shape.PointTree method), 257
with_dims() (menpo.shape.PointUndirectedGraph method), 223
with_dims() (menpo.shape.TexturedTriMesh method), 316
with_dims() (menpo.shape.TriMesh method), 291
with_labels() (menpo.shape.LabelledPointUndirectedGraph method), 274
without_labels() (menpo.shape.LabelledPointUndirectedGraph method), 274

Z

zoom() (menpo.image.BooleanImage method), 65
zoom() (menpo.image.Image method), 42
zoom() (menpo.image.MaskedImage method), 94