
sep Documentation

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Kyle Barbary

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Python library for Source Extraction and Photometry

ABOUT

`Source Extractor` (Bertin & Arnouts 1996) is a widely used command-line program for segmentation and analysis of astronomical images. It reads in FITS format files, performs a configurable series of tasks, including background estimation, source detection, deblending and a wide array of source measurements, and finally outputs a FITS format catalog file.

While `Source Extractor` is highly useful, the fact that it can only be used as an executable can limit its applicability or lead to awkward workflows. There is often a desire to have programmatic access to perform one or more of the above tasks on in-memory images as part of a larger custom analysis.

SEP makes the core algorithms of `Source Extractor` available as a library of stand-alone functions and classes. These operate directly on in-memory arrays (no FITS files or configuration files). The code is derived from the `Source Extractor` code base (written in C) and aims to produce results compatible with `Source Extractor` whenever possible. SEP consists of a C library with no dependencies outside the standard library, and a Python module that wraps the C library in a Pythonic API. The Python wrapper operates on NumPy arrays with NumPy as its only dependency. See below for language-specific build and usage instructions.

Some features:

- spatially variable background and noise estimation
- source extraction, with on-the-fly convolution and source deblending
- circular and elliptical aperture photometry
- fast: implemented in C with Python bindings via Cython

Additional features not in `Source Extractor`:

- Optimized matched filter for variable noise in source extraction.
- Circular annulus and elliptical annulus aperture photometry functions.
- Local background subtraction in shape consistent with aperture in aperture photometry functions.
- Exact pixel overlap mode in all aperture photometry functions.
- Masking of elliptical regions on images.

INSTALLATION

2.1 with conda

SEP can be installed with conda from the conda-forge channel:

```
conda install -c conda-forge sep
```

2.2 with pip

SEP can also be installed with `pip`. After ensuring that numpy is installed, run

```
pip install sep
```

If you get an error about permissions, you are probably using your system Python. In this case, I recommend using `pip`'s “user install” option to install sep into your user directory

```
pip install --user sep
```

Do **not** install sep or other third-party Python packages using `sudo` unless you are fully aware of the risks.

USAGE GUIDE

3.1 Tutorial

This tutorial shows the basic steps of using SEP to detect objects in an image and perform some basic aperture photometry.

Here, we use the `fitsio` package, just to read the test image, but you can also use `astropy.io.fits` for this purpose (or any other FITS reader).

```
[1]: import numpy as np
import sep
```

```
[2]: # additional setup for reading the test image and displaying plots
import fitsio
import matplotlib.pyplot as plt
from matplotlib import rcParams

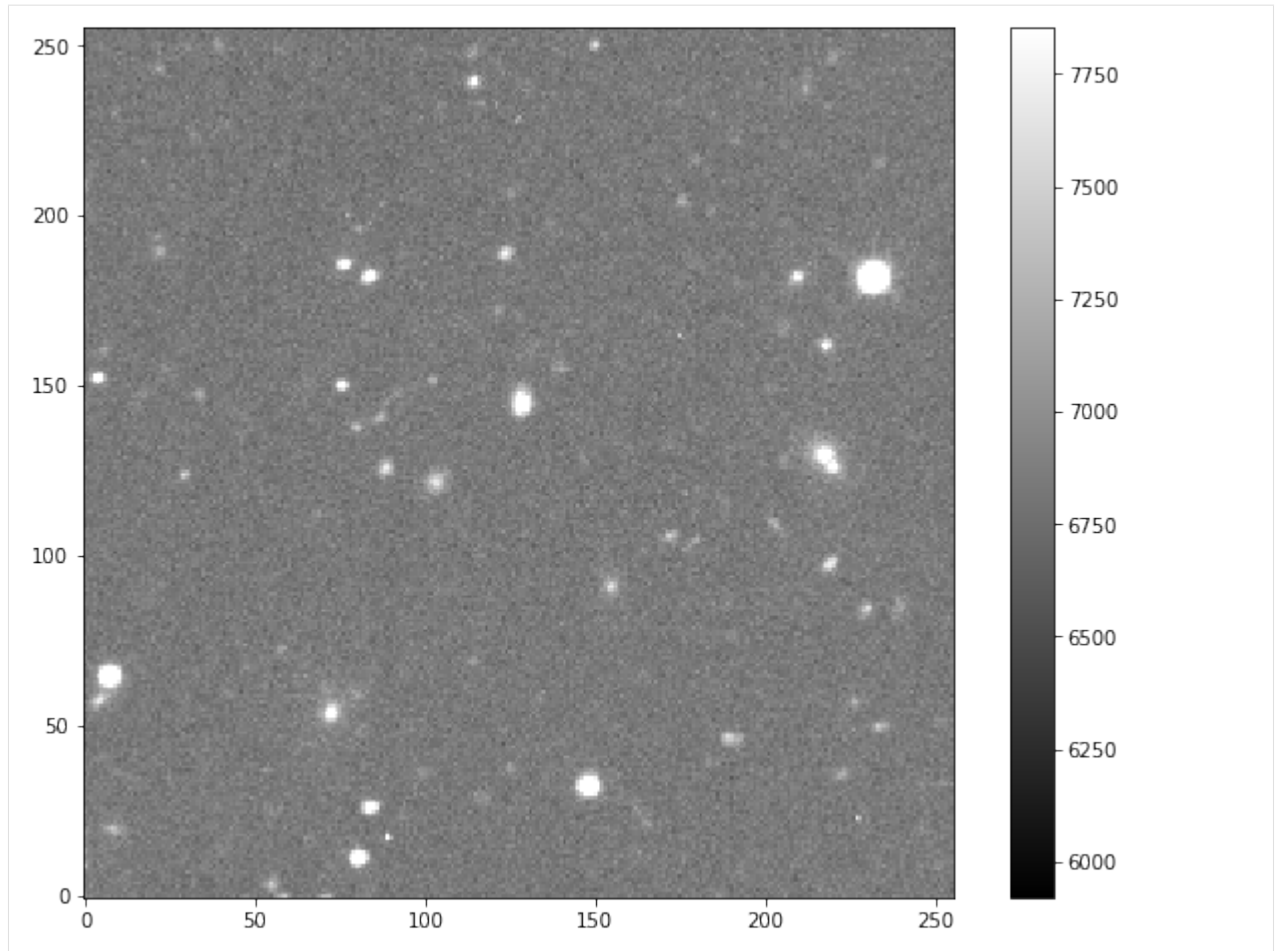
%matplotlib inline

rcParams['figure.figsize'] = [10., 8.]
```

First, we'll read an example image from a FITS file and display it, just to show what we're dealing with. The example image is just 256 x 256 pixels.

```
[3]: # read image into standard 2-d numpy array
data = fitsio.read("../data/image.fits")
```

```
[4]: # show the image
m, s = np.mean(data), np.std(data)
plt.imshow(data, interpolation='nearest', cmap='gray', vmin=m-s, vmax=m+s, origin='lower
→')
plt.colorbar();
```



3.1.1 Background subtraction

Most optical/IR data must be background subtracted before sources can be detected. In SEP, background estimation and source detection are two separate steps.

```
[5]: # measure a spatially varying background on the image
bkg = sep.Background(data)
```

There are various options for controlling the box size used in estimating the background. It is also possible to mask pixels. For example:

```
bkg = sep.Background(data, mask=mask, bw=64, bh=64, fw=3, fh=3)
```

See the reference section for descriptions of these parameters.

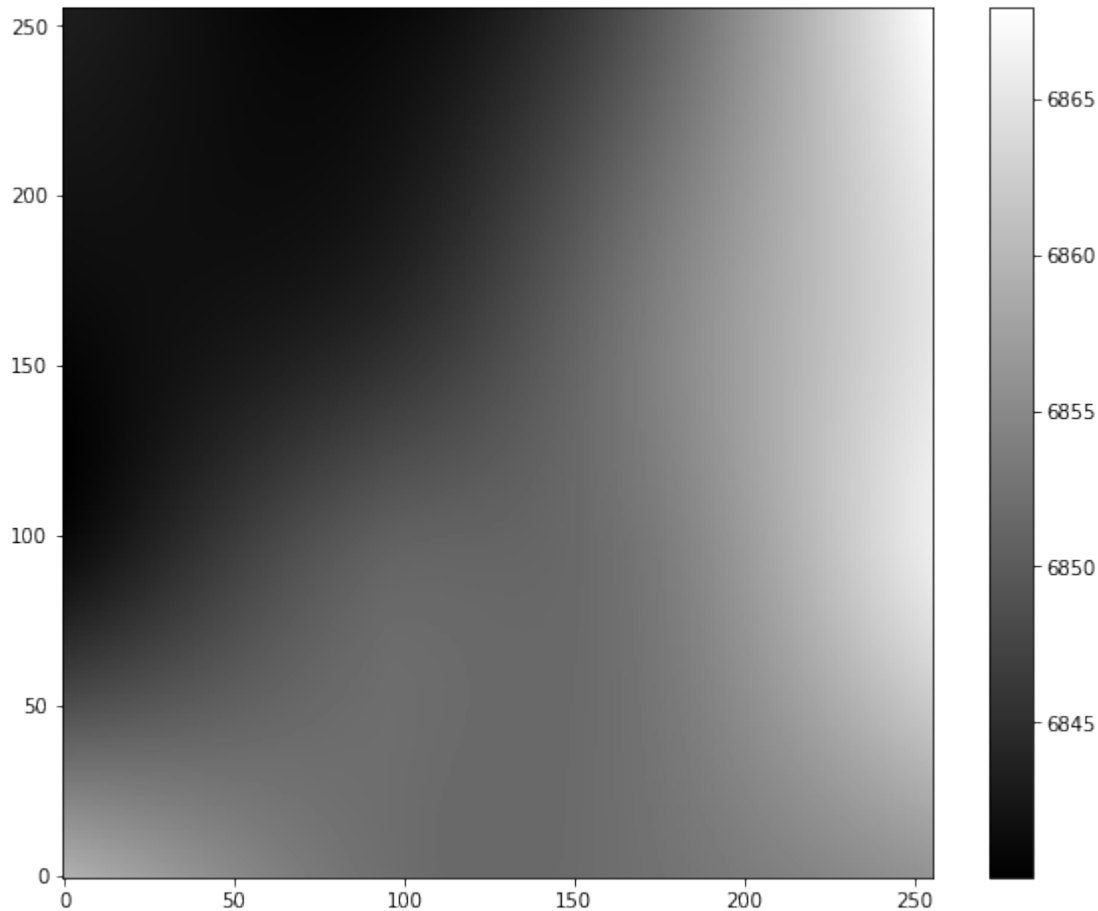
This returns an `Background` object that holds information on the spatially varying background and spatially varying background noise level. We can now do various things with this `Background` object:

```
[6]: # get a "global" mean and noise of the image background:
print(bkg.globalback)
print(bkg.globalrms)
```

```
6852.04931640625
65.46165466308594
```

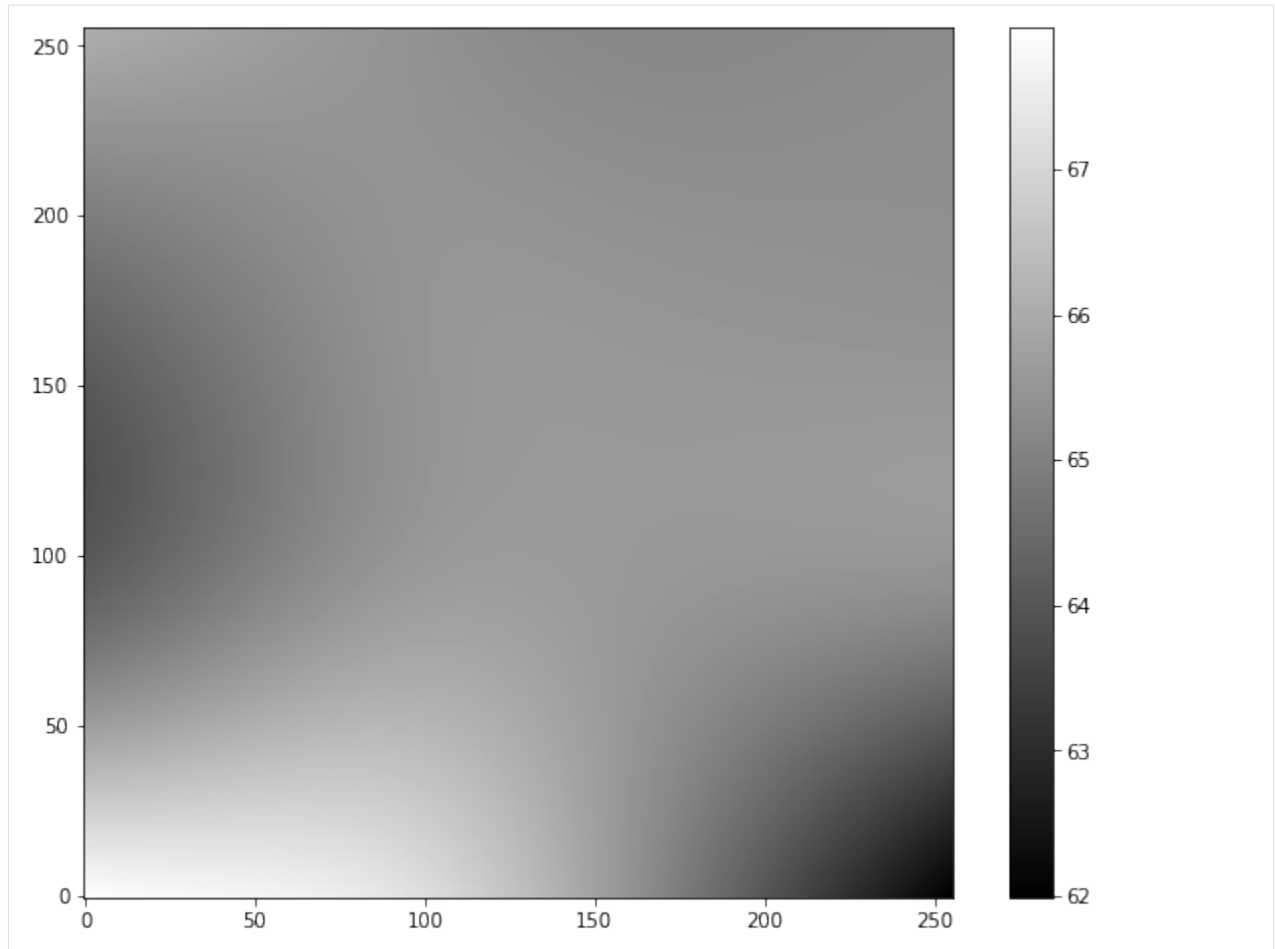
```
[7]: # evaluate background as 2-d array, same size as original image
bkg_image = bkg.back()
# bkg_image = np.array(bkg) # equivalent to above
```

```
[8]: # show the background
plt.imshow(bkg_image, interpolation='nearest', cmap='gray', origin='lower')
plt.colorbar();
```



```
[9]: # evaluate the background noise as 2-d array, same size as original image
bkg_rms = bkg.rms()
```

```
[10]: # show the background noise
plt.imshow(bkg_rms, interpolation='nearest', cmap='gray', origin='lower')
plt.colorbar();
```



```
[11]: # subtract the background  
data_sub = data - bkg
```

One can also subtract the background from the data array in-place by doing `bkg.subfrom(data)`.

Warning:

If the data array is not background-subtracted or the threshold is too low, you will tend to get one giant object when you run object detection using `sep.extract`. Or, more likely, an exception will be raised due to exceeding the internal memory constraints of the `sep.extract` function.

3.1.2 Object detection

Now that we've subtracted the background, we can run object detection on the background-subtracted data. You can see the background noise level is pretty flat. So here we're setting the detection threshold to be a constant value of 1.5σ where σ is the global background RMS.

```
[12]: objects = sep.extract(data_sub, 1.5, err=bkg.globalrms)
```

`sep.extract` has many options for controlling detection threshold, pixel masking, filtering, and object deblending. See the reference documentation for details.

`objects` is a NumPy structured array with many fields.

```
[13]: # how many objects were detected
len(objects)
```

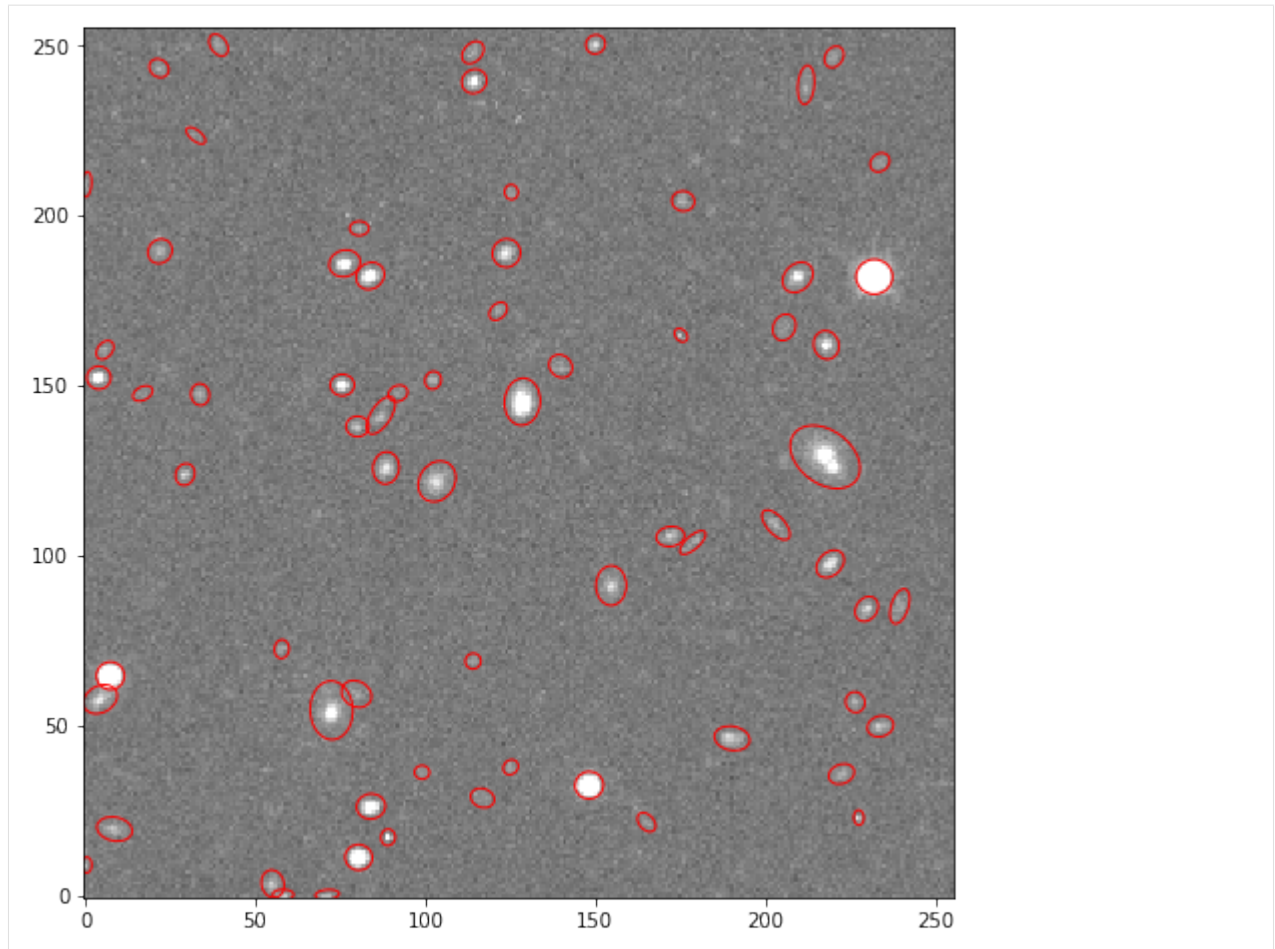
```
[13]: 69
```

`objects['x']` and `objects['y']` will give the centroid coordinates of the objects. Just to check where the detected objects are, we'll over-plot the object coordinates with some basic shape parameters on the image:

```
[14]: from matplotlib.patches import Ellipse

# plot background-subtracted image
fig, ax = plt.subplots()
m, s = np.mean(data_sub), np.std(data_sub)
im = ax.imshow(data_sub, interpolation='nearest', cmap='gray',
               vmin=m-s, vmax=m+s, origin='lower')

# plot an ellipse for each object
for i in range(len(objects)):
    e = Ellipse(xy=(objects['x'][i], objects['y'][i]),
               width=6*objects['a'][i],
               height=6*objects['b'][i],
               angle=objects['theta'][i] * 180. / np.pi)
    e.set_facecolor('none')
    e.set_edgecolor('red')
    ax.add_artist(e)
```



objects has many other fields, giving information such as second moments, and peak pixel positions and values. See the reference documentation for `sep.extract` for descriptions of these fields. You can see the available fields:

```
[15]: # available fields
objects.dtype.names
```

```
[15]: ('thresh',
      'npix',
      'tnpix',
      'xmin',
      'xmax',
      'ymin',
      'ymax',
      'x',
      'y',
      'x2',
      'y2',
      'xy',
      'errx2',
      'erry2',
      'errxy',
      'a',
      'b',
```

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```
'theta',
'cxx',
'cyy',
'cxy',
'cflux',
'flux',
'cpeak',
'peak',
'xcpeak',
'ycpeak',
'xpeak',
'ypeak',
'flag')
```

3.1.3 Aperture photometry

Finally, we'll perform simple circular aperture photometry with a 3 pixel radius at the locations of the objects:

```
[16]: flux, fluxerr, flag = sep.sum_circle(data_sub, objects['x'], objects['y'],
                                         3.0, err=bkg.globalrms, gain=1.0)
```

flux, fluxerr and flag are all 1-d arrays with one entry per object.

```
[17]: # show the first 10 objects results:
for i in range(10):
    print("object {:d}: flux = {:f} +/- {:f}".format(i, flux[i], fluxerr[i]))
```

```
object 0: flux = 2249.173164 +/- 291.027422
object 1: flux = 3092.230000 +/- 291.591821
object 2: flux = 5949.882168 +/- 356.561539
object 3: flux = 1851.435000 +/- 295.028419
object 4: flux = 72736.400605 +/- 440.171830
object 5: flux = 3860.762324 +/- 352.162684
object 6: flux = 6418.924336 +/- 357.458504
object 7: flux = 2210.745605 +/- 350.790787
object 8: flux = 2741.598848 +/- 352.277244
object 9: flux = 20916.877324 +/- 376.965683
```

3.1.4 Finally a brief word on byte order

Note:

If you are using SEP to analyze data read from FITS files with `astropy.io.fits` you may see an error message such as:

```
ValueError: Input array with dtype '>f4' has non-native byte order.
Only native byte order arrays are supported. To change the byte
order of the array 'data', do 'data = data.byteswap().newbyteorder()'
```

It is usually easiest to do this byte-swap operation directly after reading the array from the FITS file. You can even perform the byte swap in-place by doing

```
>>> data = data.byteswap(inplace=True).newbyteorder()
```

If you do this in-place operation, ensure that there are no other references to `data`, as they will be rendered nonsensical.

For the interested reader, this byteswap operation is necessary because `astropy.io.fits` always returns big-endian byte order arrays, even on little-endian machines. For more on this, see

3.2 Matched Filter (Convolution)

For source detection, SEP supports using a matched filter, which can give the optimal detection signal-to-noise for objects with some known shape. This is controlled using the `filter_kernel` keyword in `sep.extract`. For example:

```
kernel = np.array([[1., 2., 3., 2., 1.],
                  [2., 3., 5., 3., 2.],
                  [3., 5., 8., 5., 3.],
                  [2., 3., 5., 3., 2.],
                  [1., 2., 3., 2., 1.]])
objects = sep.extract(data, thresh, filter_kernel=kernel)
```

If `filter_kernel` is not specified, a default 3-by-3 kernel is used. To disable filtering entirely, specify `filter_kernel=None`.

What array should be used for `filter_kernel`? It should be approximately the shape of the objects you are trying to detect. For example, to optimize for the detection of point sources, `filter_kernel` should be set to shape of the point spread function (PSF) in the data. For galaxy detection, a larger kernel could be used. In practice, anything that is roughly the shape of the desired object works well since the main goal is to negate the effects of background noise, and a reasonable estimate is good enough.

3.2.1 Correct treatment in the presence of variable noise

In Source Extractor, the matched filter is implemented assuming there is equal noise across all pixels in the kernel. The matched filter then simplifies to a convolution of the data with the kernel. In `sep.extract`, this is also the behavior when there is constant noise (when `err` is not specified).

In the presence of independent noise on each pixel, SEP uses a full matched filter implementation that correctly accounts for the noise in each pixel. This is not available in Source Extractor. Some benefits of this method are that detector sensitivity can be taken into account and edge effects are handled gracefully. For example, suppose we have an image with noise that is higher in one region than another. This can often occur when coadding images:

```
# create a small image with higher noise in the upper left
n = 16
X, Y = np.meshgrid(np.arange(n), np.arange(n))
mask = Y > X
error = np.ones((n, n))
error[mask] = 4.0
data = error * np.random.normal(size=(n, n))

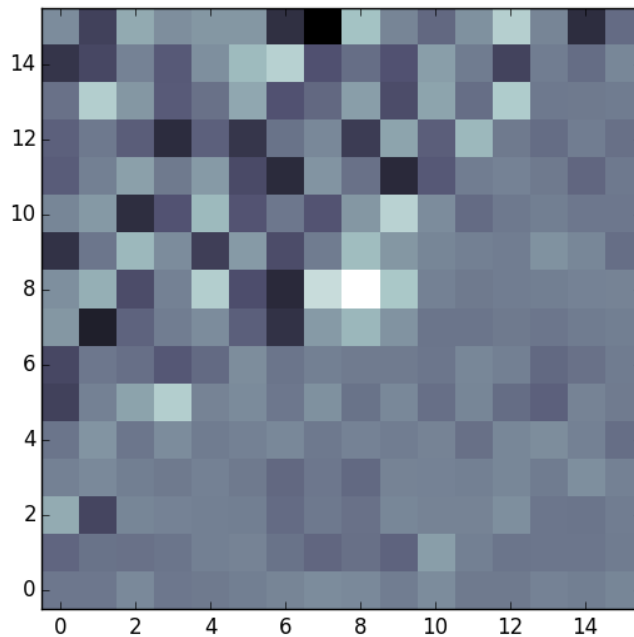
# add source to middle of data
source = 3.0 * np.array([[1., 2., 1.],
                        [2., 4., 2.],
                        [1., 2., 1.]])
```

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```
m = n // 2 - 1
data[m:m+3, m:m+3] += source

plt.imshow(data, interpolation='nearest', origin='lower', cmap='bone')
```



Specifying `filter_type='conv'` will use simple convolution, matching the behavior of Source Extractor. The object is not detected:

```
>>> objects = sep.extract(data, 3.0, err=error, filter_type='conv')
>>> len(objects)
0
```

Setting `filter_type='matched'` (the default) correctly deweights the noisier pixels around the source and detects the object:

```
>>> objects = sep.extract(data, 3.0, err=error, filter_type='matched')
>>> len(objects)
1
```

3.2.2 Derivation of the matched filter formula

Assume that we have an image containing a single point source. This produces a signal with PSF S_i and noise N_i at each pixel indexed by i . Then the measured image data D_i (i.e. our pixel values) is given by:

$$D_i = S_i + N_i$$

Then we want to apply a linear transformation T_i which gives an output Y :

$$Y = \sum_i T_i D_i = T^T D$$

We use matrix notation from here on and drop the explicit sums. Our objective is to find the transformation T_i which maximizes the signal-to-noise ratio SNR .

$$SNR^2 = \frac{(T^T S)^2}{E[(T^T N)^2]}$$

We can expand the denominator as:

$$E[(T^T N)^2] = E[(T^T N)(N^T T)] = T^T \cdot E[NN^T] \cdot T = T^T C T$$

Where C_{ik} is the covariance of the noise between pixels i and k . Now using the Cauchy-Schwarz inequality on the numerator:

$$(T^T S)^2 = (T^T C^{1/2} C^{-1/2} S)^2 \leq (T^T C^{1/2})^2 (C^{-1/2} S)^2 = (T^T C T)(S^T C^{-1} S)$$

since $C^T = C$. The signal-to-noise ratio is therefore bounded by:

$$\begin{aligned} SNR^2 &\leq \frac{(T^T C T)(S^T C^{-1} S)}{(T^T C T)} \\ SNR^2 &\leq S^T C^{-1} S \end{aligned}$$

Choosing $T = \alpha C^{-1} S$ where α is an arbitrary normalization constant, we get equality. Hence this choice of T is the optimal linear transformation. We normalize this linear transformation so that if there is no signal and only noise, we get an expected signal-to-noise ratio of 1. With this definition, the output SNR represents the number of standard deviations above the background. This gives:

$$\begin{aligned} E[(T^T N)^2] &= T^T C T = \alpha^2 S^T C^{-1} C C^{-1} S = \alpha^2 S^T C^{-1} S = 1 \\ \alpha &= \frac{1}{\sqrt{S^T C^{-1} S}} \end{aligned}$$

Putting everything together, our normalized linear transformation is:

$$T = \frac{C^{-1} S}{\sqrt{S^T C^{-1} S}}$$

And the optimal signal-to-noise is given in terms of the known variables as:

$$SNR = \frac{S^T C^{-1} D}{\sqrt{S^T C^{-1} S}}$$

3.3 Aperture photometry

There are four aperture functions available:

Function	Sums data within...
<code>sep.sum_circle</code>	circle(s)
<code>sep.sum_circann</code>	circular annulus/annuli
<code>sep.sum_ellipse</code>	ellipse(s)
<code>sep.sum_ellipann</code>	elliptical annulus/annuli

The follow examples demonstrate options for circular aperture photometry. The other functions behave similarly.

```
# sum flux in circles of radius=3.0
flux, fluxerr, flag = sep.sum_circle(data, objs['x'], objs['y'], 3.0)

# x, y and r can be arrays and obey numpy broadcasting rules.
# Here, r is an array instead of a single number:
flux, fluxerr, flag = sep.sum_circle(data, objs['x'], objs['y'],
                                     3.0 * np.ones(len(objs)))

# use a different subpixel sampling (default is 5; 0 means "exact")
flux, fluxerr, flag = sep.sum_circle(data, objs['x'], objs['y'], 3.0,
                                     subpix=0)
```

Error calculation

In the default modes illustrated above, the uncertainty `fluxerr` is not calculated and values of 0 are simply returned. The uncertainty can be flexibly and efficiently calculated, depending on the characteristics of your data. The presence of an `err` or `var` keyword indicates a per-pixel noise, while the presence of a `gain` keyword indicates that the Poisson uncertainty on the total sum should be included. Some illustrative examples:

```
# Specify a per-pixel "background" error and a gain. This is suitable
# when the data have been background subtracted.
flux, fluxerr, flag = sep.sum_circle(data, objs['x'], objs['y'], 3.0,
                                     err=bkg.globalrms, gain=1.0)

# Variance can be passed instead of error, with identical results.
flux, fluxerr, flag = sep.sum_circle(data, objs['x'], objs['y'], 3.0,
                                     var=bkg.globalrms**2, gain=1.0)

# Error or variance can be arrays, indicating that the background error
# is variable.
bkgrms = bkg.rms() # array, same shape as data
flux, fluxerr, flag = sep.sum_circle(data, objs['x'], objs['y'], 3.0,
                                     err=bkgrms, gain=1.0)

# If your uncertainty array already includes Poisson noise from the object,
# leave gain as None (default):
flux, fluxerr, flag = sep.sum_circle(data, objs['x'], objs['y'], 3.0,
                                     err=error_array)

# If your data represent raw counts (it is not background-subtracted),
# set only gain to get the poisson error:
```

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```
flux, fluxerr, flag = sep.sum_circle(data, objs['x'], objs['y'], 3.0,
                                   gain=1.0)
```

The error is calculated as

$$\sigma_F^2 = \sum_i \sigma_i^2 + F/g$$

where the sum is over pixels in the aperture, σ_i is the noise in each pixel, F is the sum in the aperture and g is the gain. The last term is not added if `gain` is `None`.

Masking

Apply a mask (same shape as data). Pixels where the mask is True are “corrected” to the average value within the aperture.

```
flux, fluxerr, flag = sep.sum_circle(data, objs['x'], objs['y'], 3.0,
                                   mask=mask)
```

Local background subtraction

The `sum_circle` and `sum_ellipse` functions have options for performing local background subtraction. For example, to subtract the background calculated in an annulus between 6 and 8 pixel radius:

```
flux, fluxerr, flag = sep.sum_circle(data, objs['x'], objs['y'], 3.0,
                                   mask=mask, bkgann=(6., 8.))
```

Pixels in the background annulus are not subsampled and any masked pixels in the annulus are completely ignored rather than corrected. The inner and outer radii can also be arrays. The error in the background is included in the reported error.

3.3.1 Equivalent of FLUX_AUTO (e.g., MAG_AUTO) in Source Extractor

This is a two-step process. First we calculate the Kron radius for each object, then we perform elliptical aperture photometry within that radius:

```
kronrad, krflag = sep.kron_radius(data, x, y, a, b, theta, 6.0)
flux, fluxerr, flag = sep.sum_ellipse(data, x, y, a, b, theta, 2.5*kronrad,
                                   subpix=1)
flag |= krflag # combine flags into 'flag'
```

This specific example is the equivalent of setting `PHOT_AUTOPARAMS 2.5, 0.0` in Source Extractor (note the 2.5 in the argument to `sep.sum_ellipse`). The second Source Extractor parameter is a minimum diameter. To replicate Source Extractor behavior for non-zero values of the minimum diameter, one would put in logic to use circular aperture photometry if the Kron radius is too small. For example:

```
r_min = 1.75 # minimum diameter = 3.5
use_circle = kronrad * np.sqrt(a * b) < r_min
cflux, cfluxerr, cflag = sep.sum_circle(data, x[use_circle], y[use_circle],
                                       r_min, subpix=1)

flux[use_circle] = cflux
fluxerr[use_circle] = cfluxerr
flag[use_circle] = cflag
```

3.3.2 Equivalent of FLUX_RADIUS in Source Extractor

In Source Extractor, the FLUX_RADIUS parameter gives the radius of a circle enclosing a desired fraction of the total flux. For example, with the setting PHOT_FLUXFRAC 0.5, FLUX_RADIUS will give the radius of a circle containing half the “total flux” of the object. For the definition of “total flux”, Source Extractor uses its measurement of FLUX_AUTO, which is taken through an elliptical aperture (see above). Thus, with the setting PHOT_FLUXFRAC 1.0, you would find the circle containing the same flux as whatever ellipse Source Extractor used for FLUX_AUTO.

Given a previous calculation of flux as above, calculate the radius for a flux fraction of 0.5:

```
r, flag = sep.flux_radius(data, objs['x'], objs['y'], 6.*objs['a'], 0.5,
                        normflux=flux, subpix=5)
```

And for multiple flux fractions:

```
r, flag = sep.flux_radius(data, objs['x'], objs['y'], 6.*objs['a'],
                        [0.5, 0.6], normflux=flux, subpix=5)
```

3.3.3 Equivalent of XWIN_IMAGE, YWIN_IMAGE in Source Extractor

Source Extractor’s XWIN_IMAGE, YWIN_IMAGE parameters can be used for more accurate object centroids than the default X_IMAGE, Y_IMAGE. Here, the winpos function provides this behavior. To match Source Extractor exactly, the right sig parameter (giving a description of the effective width) must be used for each object. Source Extractor uses $2. / 2.35 * (\text{half-light radius})$ where the half-light radius is calculated using flux_radius with a fraction of 0.5 and a normalizing flux of FLUX_AUTO. The equivalent here is:

```
sig = 2. / 2.35 * r # r from sep.flux_radius() above, with fluxfrac = 0.5
xwin, ywin, flag = sep.winpos(data, objs['x'], objs['y'], sig)
```

3.3.4 Segmentation-masked image measurements

SourceExtractor provides a mechanism for measuring the “AUTO” and “FLUX_RADIUS” parameters for a given object including a mask for neighboring sources. In addition to the mask, setting the SourceExtractor parameter MASK_TYPE=CORRECT further fills the masked pixels of a given source with “good” pixel values reflected opposite of the masked pixels. The SEP photometry and measurement functions provide an option for simple masking without reflection or subtracting neighbor flux.

For example, using a segmentation array provided by sep.extract, we can compute the masked flux_radius that could otherwise be artificially large due to flux from nearby sources:

```
# list of object id numbers that correspond to the segments
seg_id = np.arange(1, len(objs)+1, dtype=np.int32)

r, flag = sep.flux_radius(data, objs['x'], objs['y'], 6.*objs['a'], 0.5,
                        seg_id=seg_id, seg=seg,
                        normflux=flux, subpix=5)
```

To enforce that a given measurement **only** includes pixels within a segment, provide negative values in the seg_id list. Otherwise the mask for a given object will be pixels with $(\text{seg} == 0) \mid (\text{seg_id} == \text{id_i})$.

The following functions include the segmentation masking: sum_circle, sum_circann, sum_ellipse, sum_ellipann, flux_radius, and kron_radius (winpos **currently does not**).

3.3.5 Masking image regions

Create a boolean array with elliptical regions set to True:

```
mask = np.zeros(data.shape, dtype=np.bool)
sep.mask_ellipse(mask, objs['x'], objs['y'], obs['a'], objs['b'],
                 objs['theta'], r=3.)
```

3.4 Reference/API

Background estimation & source detection

<code>sep.Background(data[, mask, maskthresh, bw, ...])</code>	Representation of spatially variable image background and noise.
<code>sep.extract(data, thresh[, err, mask, ...])</code>	Extract sources from an image.

3.4.1 sep.Background

class `sep.Background(data, mask=None, maskthresh=0.0, bw=64, bh=64, fw=3, fh=3, fthresh=0.0)`

Representation of spatially variable image background and noise.

Parameters

data

[2-d ndarray] Data array.

mask

[2-d ndarray, optional] Mask array, optional

maskthresh

[float, optional] Mask threshold. This is the inclusive upper limit on the mask value in order for the corresponding pixel to be unmasked. For boolean arrays, False and True are interpreted as 0 and 1, respectively. Thus, given a threshold of zero, True corresponds to masked and False corresponds to unmasked.

bw, bh

[int, optional] Size of background boxes in pixels. Default is 64.

fw, fh

[int, optional] Filter width and height in boxes. Default is 3.

fthresh

[float, optional] Filter threshold. Default is 0.0.

__init__(data, mask=None, maskthresh=0.0, bw=64, bh=64, fw=3, fh=3, fthresh=0.0)

Methods

<code>__init__(data[, mask, maskthresh, bw, bh, ...])</code>	
<code>back([dtype])</code>	Create an array of the background.
<code>rms([dtype])</code>	Create an array of the background rms.
<code>subfrom(data)</code>	Subtract the background from an existing array.

Attributes

<code>globalback</code>	Global background level.
<code>globalrms</code>	Global background RMS.

3.4.2 sep.extract

`sep.extract(data, thresh, err=None, mask=None, minarea=5, filter_kernel=default_kernel, filter_type='matched', deblend_nthresh=32, deblend_cont=0.005, clean=True, clean_param=1.0, segmentation_map=False)`

Extract sources from an image.

Parameters

data

[`ndarray`] Data array (2-d).

thresh

[float] Threshold pixel value for detection. If an `err` or `var` array is not given, this is interpreted as an absolute threshold. If `err` or `var` is given, this is interpreted as a relative threshold: the absolute threshold at pixel (j, i) will be `thresh * err[j, i]` or `thresh * sqrt(var[j, i])`.

err, var

[float or `ndarray`, optional] Error *or* variance (specify at most one). This can be used to specify a pixel-by-pixel detection threshold; see “thresh” argument.

gain

[float, optional] Conversion factor between data array units and poisson counts. This does not affect detection; it is used only in calculating Poisson noise contribution to uncertainty parameters such as `errx2`. If not given, no Poisson noise will be added.

mask

[`ndarray`, optional] Mask array. True values, or numeric values greater than `maskthresh`, are considered masked. Masking a pixel is equivalent to setting data to zero and noise (if present) to infinity.

maskthresh

[float, optional] Threshold for a pixel to be masked. Default is `0.0`.

minarea

[int, optional] Minimum number of pixels required for an object. Default is 5.

filter_kernel

[`ndarray` or None, optional] Filter kernel used for on-the-fly filtering (used to enhance detection). Default is a 3x3 array: `[[1,2,1], [2,4,2], [1,2,1]]`. Set to None to skip convolution.

filter_type

[{'matched', 'conv'}, optional] Filter treatment. This affects filtering behavior when a noise array is supplied. 'matched' (default) accounts for pixel-to-pixel noise in the filter kernel. 'conv' is simple convolution of the data array, ignoring pixel-to-pixel noise across the kernel. 'matched' should yield better detection of faint sources in areas of rapidly varying noise (such as found in coadded images made from semi-overlapping exposures). The two options are equivalent when noise is constant.

deblend_nthresh

[int, optional] Number of thresholds used for object deblending. Default is 32.

deblend_cont

[float, optional] Minimum contrast ratio used for object deblending. Default is 0.005. To entirely disable deblending, set to 1.0.

clean

[bool, optional] Perform cleaning? Default is True.

clean_param

[float, optional] Cleaning parameter (see SExtractor manual). Default is 1.0.

segmentation_map

[bool, optional] If True, also return a “segmentation map” giving the member pixels of each object. Default is False.

Returns**objects**

[[ndarray](#)] Extracted object parameters (structured array). Available fields are:

- **thresh** (float) Threshold at object location.
- **npix** (int) Number of pixels belonging to the object.
- **tnpix** (int) Number of pixels above threshold (unconvolved data).
- **xmin, xmax** (int) Minimum, maximum x coordinates of pixels.
- **ymin, ymax** (int) Minimum, maximum y coordinates of pixels.
- **x, y** (float) object barycenter (first moments).
- **x2, y2, xy** (float) Second moments.
- **errx2, erry2, errxy** (float) Second moment errors. Note that these will be zero if error is not given.
- **a, b, theta** (float) Ellipse parameters, scaled as described by Section 8.4.2 in “The Source Extractor Guide” or Section 10.1.5-6 of v2.13 of SExtractor’s User Manual.
- **cxx, cyy, cxy** (float) Alternative ellipse parameters.
- **cflux** (float) Sum of member pixels in convolved data.
- **flux** (float) Sum of member pixels in unconvolved data.
- **cpeak** (float) Peak value in convolved data.
- **peak** (float) Peak value in unconvolved data.
- **xcpeak, ycpeak** (int) Coordinate of convolved peak pixel.
- **xpeak, ypeak** (int) Coordinate of unconvolved peak pixel.
- **flag** (int) Extraction flags.

segmap

[[ndarray](#), optional] Array of integers with same shape as data. Pixels not belonging to any object have value 0. All pixels belonging to the *i*-th object (e.g., `objects[i]`) have value *i*+1. Only returned if `segmentation_map=True`.

Aperture photometry

<code>sep.sum_circle(data, x, y, r[, err, var, ...])</code>	Sum data in circular aperture(s).
<code>sep.sum_circann(data, x, y, rin, rout[, ...])</code>	Sum data in circular annular aperture(s).
<code>sep.sum_ellipse(data, x, y, a, b, theta, r)</code>	Sum data in elliptical aperture(s).
<code>sep.sum_ellipann(data, x, y, a, b, theta, ...)</code>	Sum data in elliptical annular aperture(s).

3.4.3 sep.sum_circle

`sep.sum_circle(data, x, y, r, err=None, var=None, mask=None, maskthresh=0.0, segmap=None, seg_id=None, bkgann=None, gain=None, subpix=5)`

Sum data in circular aperture(s).

Parameters**data**

[[ndarray](#)] 2-d array to be summed.

x, y, r

[[array_like](#)] Center coordinates and radius (radii) of aperture(s). *x* corresponds to the second (“fast”) axis of the input array and *y* corresponds to the first (“slow”) axis. *x*, *y* = (0.0, 0.0) corresponds to the center of the first element of the array. These inputs obey numpy broadcasting rules.

err, var

[float or [ndarray](#)] Error *or* variance (specify at most one).

mask

[[ndarray](#), optional] Mask array. If supplied, a given pixel is masked if its value is greater than `maskthresh`.

maskthresh

[float, optional] Threshold for a pixel to be masked. Default is 0.0.

segmap

[[ndarray](#), optional] Segmentation image with dimensions of data and dtype `np.int32`. This is an optional input and corresponds to the segmentation map output by `extract`.

seg_id

[[array_like](#), optional] Array of segmentation ids used to mask additional pixels in the image. Dimensions correspond to the dimensions of *x* and *y*. The behavior differs depending on whether `seg_id` is negative or positive. If `seg_id` is positive, all pixels belonging to other objects are masked. (Pixel *j*, *i* is masked if `seg[j, i] != seg_id` and `seg[j, i] != 0`). If `seg_id` is negative, all pixels other than those belonging to the object of interest are masked. (Pixel *j*, *i* is masked if `seg[j, i] != -seg_id`). NB: must be included if `segmap`` is provided.

bkgann

[[tuple](#), optional] Length 2 tuple giving the inner and outer radius of a “background annulus”. If supplied, the background is estimated by averaging unmasked pixels in this annulus. If supplied, the inner and outer radii obey numpy broadcasting rules along with *x*, *y* and *r*.

gain

[float, optional] Conversion factor between data array units and poisson counts, used in calculating poisson noise in aperture sum. If `None` (default), do not add poisson noise.

subpix

[int, optional] Subpixel sampling factor. If 0, exact overlap is calculated. Default is 5.

Returns**sum**

[`ndarray`] The sum of the data array within the aperture.

sumerr

[`ndarray`] Error on the sum.

flags

[`ndarray`] Integer giving flags. (0 if no flags set.)

3.4.4 `sep.sum_circann`

`sep.sum_circann(data, x, y, rin, rout, err=None, var=None, mask=None, maskthresh=0.0, seg_id=None, segmap=None, gain=None, subpix=5)`

Sum data in circular annular aperture(s).

Parameters**data**

[`ndarray`] 2-d array to be summed.

x, y, rin, rout

[array_like] Center coordinates and inner and outer radii of aperture(s). `x` corresponds to the second (“fast”) axis of the input array and `y` corresponds to the first (“slow”) axis. `x, y = (0.0, 0.0)` corresponds to the center of the first element of the array. These inputs obey numpy broadcasting rules. It is required that `rout >= rin >= 0.0`.

err, var

[float or `ndarray`] Error *or* variance (specify at most one).

mask

[`ndarray`, optional] Mask array. If supplied, a given pixel is masked if its value is greater than `maskthresh`.

maskthresh

[float, optional] Threshold for a pixel to be masked. Default is `0.0`.

segmap

[`ndarray`, optional] Segmentation image with dimensions of `data` and dtype `np.int32`. This is an optional input and corresponds to the segmentation map output by `extract`.

seg_id

[array_like, optional] Array of segmentation ids used to mask additional pixels in the image. Dimensions correspond to the dimensions of `x` and `y`. The behavior differs depending on whether `seg_id` is negative or positive. If `seg_id` is positive, all pixels belonging to other objects are masked. (Pixel `j, i` is masked if `seg[j, i] != seg_id` and `seg[j, i] != 0`). If `seg_id` is negative, all pixels other than those belonging to the object of interest are masked. (Pixel `j, i` is masked if `seg[j, i] != -seg_id`). NB: must be included if `segmap`` is provided.

gain

[float, optional] Conversion factor between data array units and poisson counts, used in calculating poisson noise in aperture sum. If `None` (default), do not add poisson noise.

subpix

[int, optional] Subpixel sampling factor. Default is 5.

Returns**sum**

[`ndarray`] The sum of the data array within the aperture.

sumerr

[`ndarray`] Error on the sum.

flags

[`ndarray`] Integer giving flags. (0 if no flags set.)

3.4.5 sep.sum_ellipse

`sep.sum_ellipse(data, x, y, a, b, theta, r, err=None, var=None, mask=None, maskthresh=0.0, seg_id=None, segmap=None, bkgann=None, gain=None, subpix=5)`

Sum data in elliptical aperture(s).

Parameters**data**

[`ndarray`] 2-d array to be summed.

x, y

[array_like] Center coordinates and radius (radii) of aperture(s). `x` corresponds to the second (“fast”) axis of the input array and `y` corresponds to the first (“slow”) axis. `x, y = (0.0, 0.0)` corresponds to the center of the first element of the array. These inputs obey numpy broadcasting rules.

a, b, theta

[array_like] Ellipse parameters. These inputs, along with `x, y,` and `r,` obey numpy broadcasting rules. `a` is the semi-major axis, `b` is the semi-minor axis and `theta` is angle in radians between the positive `x` axis and the major axis. It must be in the range $[-\pi/2, \pi/2]$. It is also required that `a >= b >= 0.0`.

r

[array_like, optional] Scaling factor for the semi-minor and semi-major axes. The actual ellipse used will have semi-major axis `a * r` and semi-minor axis `b * r`. Setting this parameter to a value other than 1.0 is exactly equivalent to scaling both `a` and `b` by the same value. Default is 1.0.

err, var

[float or `ndarray`] Error *or* variance (specify at most one).

mask

[`ndarray`, optional] Mask array. If supplied, a given pixel is masked if its value is greater than `maskthresh`.

maskthresh

[float, optional] Threshold for a pixel to be masked. Default is `0.0`.

segmap

[`ndarray`, optional] Segmentation image with dimensions of `data` and dtype `np.int32`. This is an optional input and corresponds to the segmentation map output by `extract`.

seg_id

[array_like, optional] Array of segmentation ids used to mask additional pixels in the image. Dimensions correspond to the dimensions of `x` and `y`. The behavior differs depending on whether `seg_id` is negative or positive. If `seg_id` is positive, all pixels belonging to other objects are masked. (Pixel `j`, `i` is masked if `seg[j, i] != seg_id` and `seg[j, i] != 0`). If `seg_id` is negative, all pixels other than those belonging to the object of interest are masked. (Pixel `j`, `i` is masked if `seg[j, i] != -seg_id`). NB: must be included if `segmap`` is provided.

bkgann

[tuple, optional] Length 2 tuple giving the inner and outer radius of a “background annulus”. If supplied, the background is estimated by averaging unmasked pixels in this annulus. If supplied, the inner and outer radii obey numpy broadcasting rules, along with `x`, `y`, and ellipse parameters.

gain

[float, optional] Conversion factor between data array units and poisson counts, used in calculating poisson noise in aperture sum. If `None` (default), do not add poisson noise.

subpix

[int, optional] Subpixel sampling factor. Default is 5.

Returns**sum**

[ndarray] The sum of the data array within the aperture.

sumerr

[ndarray] Error on the sum.

flags

[ndarray] Integer giving flags. (0 if no flags set.)

3.4.6 sep.sum_ellipann

`sep.sum_ellipann(data, x, y, a, b, theta, rin, rout, err=None, var=None, mask=None, maskthresh=0.0, gain=None, subpix=5)`

Sum data in elliptical annular aperture(s).

Parameters**data**

[ndarray] 2-d array to be summed.

x, y

[array_like] Center coordinates and radius (radii) of aperture(s). `x` corresponds to the second (“fast”) axis of the input array and `y` corresponds to the first (“slow”) axis. `x, y = (0.0, 0.0)` corresponds to the center of the first element of the array. These inputs obey numpy broadcasting rules.

a, b, theta, rin, rout

[array_like] Elliptical annulus parameters. These inputs, along with `x` and `y`, obey numpy broadcasting rules. `a` is the semi-major axis, `b` is the semi-minor axis and `theta` is angle in radians between the positive `x` axis and the major axis. It must be in the range $[-\pi/2, \pi/2]$. It is also required that `a >= b >= 0.0` and `rout >= rin >= 0.0`

err, var

[float or ndarray] Error *or* variance (specify at most one).

mask

[[ndarray](#), optional] Mask array. If supplied, a given pixel is masked if its value is greater than `maskthresh`.

maskthresh

[float, optional] Threshold for a pixel to be masked. Default is `0.0`.

gain

[float, optional] Conversion factor between data array units and poisson counts, used in calculating poisson noise in aperture sum. If `None` (default), do not add poisson noise.

segmap

[[ndarray](#), optional] Segmentation image with dimensions of `data` and dtype `np.int32`. This is an optional input and corresponds to the segmentation map output by [extract](#).

seg_id

[array_like, optional] Array of segmentation ids used to mask additional pixels in the image. Dimensions correspond to the dimensions of `x` and `y`. The behavior differs depending on whether `seg_id` is negative or positive. If `seg_id` is positive, all pixels belonging to other objects are masked. (Pixel `j, i` is masked if `seg[j, i] != seg_id` and `seg[j, i] != 0`). If `seg_id` is negative, all pixels other than those belonging to the object of interest are masked. (Pixel `j, i` is masked if `seg[j, i] != -seg_id`). NB: must be included if `segmap`` is provided.

subpix

[int, optional] Subpixel sampling factor. Default is 5.

Returns**sum**

[[ndarray](#)] The sum of the data array within the aperture(s).

sumerr

[[ndarray](#)] Error on the sum.

flags

[[ndarray](#)] Integer giving flags. (0 if no flags set.)

Aperture utilities

sep.kron_radius (data, x, y, a, b, theta, r)	Calculate Kron "radius" within an ellipse.
sep.flux_radius (data, x, y, rmax, frac[, ...])	Return radius of a circle enclosing requested fraction of total flux.
sep.winpos (data, xinit, yinit, sig[, mask, ...])	Calculate more accurate object centroids using 'windowed' algorithm.
sep.mask_ellipse (arr, x, y, a, b, theta[, r])	Mask ellipse(s) in an array.
sep.ellipse_axes (cxx, cyy, cxy)	Convert from coefficient ellipse representation to ellipse axes and angle.
sep.ellipse_coeffs (a, b, theta)	Convert from ellipse axes and angle to coefficient representation.

3.4.7 sep.kron_radius

sep.kron_radius(*data*, *x*, *y*, *a*, *b*, *theta*, *r*, *mask=None*, *maskthresh=0.0*, *seg_id=None*, *segmap=None*)

Calculate Kron “radius” within an ellipse.

The Kron radius is given by

$$\sum_i r_i I(r_i) / \sum_i I(r_i)$$

where the sum is over all pixels in the aperture and the radius is given in units of **a** and **b**: **r_i** is the distance to the pixel relative to the distance to the ellipse specified by **a**, **b**, **theta**. Equivalently, after converting the ellipse parameters to their coefficient representation, **r_i** is given by

$$r_i^2 = cxx(x_i - x)^2 + cyy(y_i - y)^2 + cxy(x_i - x)(y_i - y)$$

Parameters

data

[[ndarray](#)] Data array.

x, y

[[array_like](#)] Ellipse center(s).

a, b, theta

[[array_like](#)] Ellipse parameters.

r

[[array_like](#)] “Radius” of ellipse over which to integrate. If the ellipse extent corresponds to second moments of an object, this is the number of “isophotal radii” in Source Extractor parlance. A Fixed value of 6 is used in Source Extractor.

mask

[[numpy.ndarray](#), optional] An optional mask.

maskthresh

[[float](#), optional] Pixels with mask > maskthresh will be ignored.

segmap

[[ndarray](#), optional] Segmentation image with dimensions of **data** and dtype `np.int32`. This is an optional input and corresponds to the segmentation map output by [extract](#).

seg_id

[[array_like](#), optional] Array of segmentation ids used to mask additional pixels in the image. Dimensions correspond to the dimensions of **x** and **y**. The behavior differs depending on whether **seg_id** is negative or positive. If **seg_id** is positive, all pixels belonging to other objects are masked. (Pixel *j*, *i* is masked if `seg[j, i] != seg_id` and `seg[j, i] != 0`). If **seg_id** is negative, all pixels other than those belonging to the object of interest are masked. (Pixel *j*, *i* is masked if `seg[j, i] != -seg_id`). NB: must be included if `segmap` is provided.`

Returns

kronrad

[[array_like](#)] The Kron radius.

flag

[[array_like](#)] Integer value indicating conditions about the aperture or how many masked pixels it contains.

3.4.8 sep.flux_radius

sep.flux_radius(*data*, *x*, *y*, *rmax*, *frac*, *normflux=None*, *mask=None*, *maskthresh=0.0*, *subpix=5*)

Return radius of a circle enclosing requested fraction of total flux.

Parameters

data

[[ndarray](#)] 2-d array to be summed.

x, y

[[array_like](#)] Center coordinates and radius (radii) of aperture(s). *x* corresponds to the second (“fast”) axis of the input array and *y* corresponds to the first (“slow”) axis. *x*, *y* = (0.0, 0.0) corresponds to the center of the first element of the array. Shapes must match.

rmax

[[array_like](#)] Maximum radius to analyze. Used as normalizing flux if *normflux* is None. Shape must match *x* and *y*.

frac

[[array_like](#)] Requested fraction of light (in range 0 to 1). Can be scalar or array.

normflux

[[array_like](#), optional] Normalizing flux for each position. If not given, the sum within *rmax* is used as the normalizing flux. If given, shape must match *x*, *y* and *rmax*.

mask

[[ndarray](#), optional] Mask array. If supplied, a given pixel is masked if its value is greater than *maskthresh*.

maskthresh

[float, optional] Threshold for a pixel to be masked. Default is 0.0.

segmap

[[ndarray](#), optional] Segmentation image with dimensions of *data* and dtype `np.int32`. This is an optional input and corresponds to the segmentation map output by [extract](#).

seg_id

[[array_like](#), optional] Array of segmentation ids used to mask additional pixels in the image. Dimensions correspond to the dimensions of *x* and *y*. The behavior differs depending on whether *seg_id* is negative or positive. If *seg_id* is positive, all pixels belonging to other objects are masked. (Pixel *j*, *i* is masked if `seg[j, i] != seg_id` and `seg[j, i] != 0`). If *seg_id* is negative, all pixels other than those belonging to the object of interest are masked. (Pixel *j*, *i* is masked if `seg[j, i] != -seg_id`). NB: must be included if `segmap` is provided.`

subpix

[int, optional] Subpixel sampling factor. Default is 5.

Returns

radius

[[ndarray](#)] The sum of the data array within the aperture(s). Shape is same as *x*, except if *frac* is an array; then the dimension of *frac* will be appended. For example, if *x* and *frac* are both 1-d arrays, the result will be a 2-d array with the trailing dimension corresponding to *frac*.

flags

[[ndarray](#)] Integer giving flags. Same shape as *x*. (0 if no flags set.)

3.4.9 sep.winpos

`sep.winpos(data, xinit, yinit, sig, mask=None, maskthresh=0.0, subpix=11, minsig=2.0 / 2.35 * 0.5)`

Calculate more accurate object centroids using ‘windowed’ algorithm.

Starting from the supplied initial center position, an iterative algorithm is used to determine a better object centroid. On each iteration, the centroid is calculated using all pixels within a circular aperture of $4 * sig$ from the current position, weighting pixel positions by their flux and the amplitude of a 2-d Gaussian with sigma `sig`. Iteration stops when the change in position falls under some threshold or a maximum number of iterations is reached. This is equivalent to `XWIN_IMAGE` and `YWIN_IMAGE` parameters in Source Extractor (for the correct choice of sigma for each object).

Note: One should be cautious about using windowed positions in crowded fields or for sources with nearby neighbors, as the iterative algorithm can fail catastrophically.

Parameters

data

[`ndarray`] Data array.

xinit, yinit

[`array_like`] Initial center(s).

sig

[`array_like`] Gaussian sigma used for weighting pixels. Pixels within a circular aperture of radius $4 * sig$ are included.

mask

[`numpy.ndarray`, optional] An optional mask.

maskthresh

[`float`, optional] Pixels with `mask > maskthresh` will be ignored.

subpix

[`int`, optional] Subpixel sampling used to determine pixel overlap with aperture. 11 is used in Source Extractor. For exact overlap calculation, use 0.

minsig

[`float`, optional] Minimum bound on `sig` parameter. `sig` values smaller than this are increased to `minsig` to replicate Source Extractor behavior. Source Extractor uses a minimum half-light radius of 0.5 pixels, equivalent to a sigma of $0.5 * 2.0 / 2.35$.

Returns

x, y

[`np.ndarray`] New x and y position(s).

flag

[`np.ndarray`] Flags.

3.4.10 sep.mask_ellipse

`sep.mask_ellipse(arr, x, y, a, b, theta, r=1.0)`

Mask ellipse(s) in an array.

Set array elements to True (or 1) if they fall within the given ellipse. The `r` keyword can be used to scale the ellipse. Equivalently, after converting `a`, `b`, `theta` to a coefficient ellipse representation (`cxx`, `cyy`, `cxy`), pixels that fulfill the condition

$$cyy(y_i - y)^2 + cxx(x_i - x)^2 + 2cxy(x_i - x)(y_i - y) < r^2$$

will be masked.

Parameters

arr

[`ndarray`] Input array to be masked. Array is updated in-place.

x, y

[`array_like`] Center of ellipse(s).

a, b, theta

[`array_like`, optional] Parameters defining the extent of the ellipse(s).

cxx, cyy, cxy

[`array_like`, optional] Alternative ellipse representation. Can be used as `mask_ellipse(arr, x, y, cxx=..., cyy=..., cxy=...)`.

r

[`array_like`, optional] Scale factor of ellipse(s). Default is 1.

3.4.11 sep.ellipse_axes

`sep.ellipse_axes(cxx, cyy, cxy)`

Convert from coefficient ellipse representation to ellipse axes and angle.

Parameters

cxx, cyy, cxy

[`array_like`] Describes the ellipse(s) $cxx * x^2 + cyy * y^2 + cxy * x * y = 1$

Returns

a, b, theta

[`ndarray`] Ellipse(s) semi-major, semi-minor axes and position angle respectively. Position angle is radians counter clockwise from positive x axis to major axis, and lies in range $(-\pi/2, \pi/2)$

Raises

ValueError

If input parameters do not describe an ellipse.

3.4.12 sep.ellipse_coeffs

`sep.ellipse_coeffs(a, b, theta)`

Convert from ellipse axes and angle to coefficient representation.

Parameters

a, b, theta

[array_like] Ellipse(s) semi-major, semi-minor axes and position angle respectively. Position angle is radians counter clockwise from positive x axis to major axis, and lies in range $[-\pi/2, \pi/2]$

Returns

cxx, cyy, cxy

[ndarray] Describes the ellipse(s) $cxx * x^2 + cyy * y^2 + cxy * xy = 1$

Low-level utilities

<code>sep.get_extract_pixstack()</code>	Get the size in pixels of the internal pixel buffer used in <code>extract()</code> .
<code>sep.set_extract_pixstack(size)</code>	Set the size in pixels of the internal pixel buffer used in <code>extract()</code> .
<code>sep.get_sub_object_limit()</code>	Get the limit on the number of sub-objects when deblending in <code>extract()</code> .
<code>sep.set_sub_object_limit(limit)</code>	Set the limit on the number of sub-objects when deblending in <code>extract()</code> .

3.4.13 sep.get_extract_pixstack

`sep.get_extract_pixstack()`

Get the size in pixels of the internal pixel buffer used in `extract()`.

3.4.14 sep.set_extract_pixstack

`sep.set_extract_pixstack(size)`

Set the size in pixels of the internal pixel buffer used in `extract()`.

The current value can be retrieved with `get_extract_pixstack`. The initial default is 300000.

3.4.15 sep.get_sub_object_limit

`sep.get_sub_object_limit()`

Get the limit on the number of sub-objects when deblending in `extract()`.

3.4.16 sep.set_sub_object_limit

`sep.set_sub_object_limit(limit)`

Set the limit on the number of sub-objects when deblending in `extract()`.

The current value can be retrieved with `get_sub_object_limit`. The initial default is 1024.

Flags

Flag	Description
<code>sep.OBJ_MERGED</code>	object is result of deblending
<code>sep.OBJ_TRUNC</code>	object is truncated at image boundary
<code>sep.OBJ_SINGU</code>	x, y fully correlated in object
<code>sep.APER_TRUNC</code>	aperture truncated at image boundary
<code>sep.APER_HASMASKED</code>	aperture contains one or more masked pixels
<code>sep.APER_ALLMASKED</code>	aperture contains only masked pixels
<code>sep.APER_NONPOSITIVE</code>	aperture sum is negative in <code>kron_radius</code>

To see if a given flag is set in `flags`:

```
is_merged = (flags & sep.OBJ_MERGED) != 0
```

Note: The coordinate convention in SEP is that (0, 0) corresponds to the center of the first element of the data array. This agrees with the 0-based indexing in Python and C. However, note that this differs from the FITS convention where the center of the first element is at coordinates (1, 1). As Source Extractor deals with FITS files, its outputs follow the FITS convention. Thus, the coordinates from SEP will be offset from Source Extractor coordinates by -1 in x and y.

For complete API documentation, see [Reference/API](#).

CONTRIBUTING

Report a bug or documentation issue: <http://github.com/kbarbary/sep/issues>

Development of SEP takes place on GitHub at <http://github.com/kbarbary/sep>. Contributions of bug fixes, documentation improvements and minor feature additions are welcome via GitHub pull requests. For major features, it is best to open an issue discussing the change first.

LICENSE AND CITATION

The license for SEP is the Lesser GNU Public License (LGPL), granted with the permission from the original author of Source Extractor.

If you use SEP in a publication, please cite [Barbary \(2016\)](#) and the original Source Extractor paper: [Bertin & Arnouts 1996](#).

The DOI for the sep v1.0.0 code release is [10.5281/zenodo.159035](https://doi.org/10.5281/zenodo.159035).

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