5. Image processing

What is an image?

We can think of an image as a function, $f$, from $\mathbb{R}^2$ to $\mathbb{R}$:

- $f(x, y)$ gives the intensity of a channel at position $(x, y)$
- Realistically, we expect the image only to be defined over a rectangle, with a finite range:
  - $f : [a,b] \times [c,d] \rightarrow [0,1]$

A color image is just three functions pasted together. We can write this as a “vector-valued” function:

$$f(x, y) = \begin{bmatrix} r(x, y) \\ g(x, y) \\ b(x, y) \end{bmatrix}$$

Images as functions
What is a digital image?

In computer graphics, we usually operate on digital (discrete) images:

- **Sample** the space on a regular grid
- **Quantize** each sample (round to nearest integer)

If our samples are $\Delta$ apart, we can write this as:

$$f[i, j] = \text{Quantize}(f(i \Delta, j \Delta))$$

Image processing

An image processing operation typically defines a new image $g$ in terms of an existing image $f$.

The simplest operations are those that transform each pixel in isolation. These pixel-to-pixel operations can be written:

$$g(x, y) = t(f(x, y))$$

Examples: threshold, RGB $\rightarrow$ grayscale

Note: a typical choice for mapping to grayscale is to apply the YIQ television matrix and keep the $Y$.

$$
\begin{bmatrix}
Y \\
I \\
Q
\end{bmatrix} =
\begin{bmatrix}
0.299 & 0.587 & 0.144 \\
0.596 & 0.275 & -0.321 \\
0.212 & -0.528 & 0.311
\end{bmatrix}
\begin{bmatrix}
R \\
G \\
B
\end{bmatrix}
$$

Pixel movement

Some operations preserve intensities, but move pixels around in the image

$$g(x, y) = f(\tilde{x}(x, y), \tilde{y}(x, y))$$

Examples: many amusing warps of images

Noise

Image processing is also useful for noise reduction and edge enhancement. We will focus on these applications for the remainder of the lecture…

Common types of noise:

- **Salt and pepper noise**: contains random occurrences of black and white pixels
- **Impulse noise**: contains random occurrences of white pixels
- **Gaussian noise**: variations in intensity drawn from a Gaussian normal distribution
Practical noise reduction

How can we “smooth” away noise in a single image?

Is there a more abstract way to represent this sort of operation? Of course there is!

Convolution

One of the most common methods for filtering an image is called convolution.

In 1D, convolution is defined as:

\[ g(x) = f(x) * h(x) \]

\[ = \int_{-\infty}^{\infty} f(x') h(x - x') dx' \]

\[ = \int_{-\infty}^{\infty} f(x') \tilde{h}(x' - x) dx' \]

where \( \tilde{h}(x) = h(-x) \).

Example:
**Discrete convolution**

For a digital signal, we define **discrete convolution** as:

\[
g[i] = f[i] \ast h[i] = \sum_{j} f[j] h[j-i] = \sum_{j} f[j] \tilde{h}[i-j]
\]

where \( \tilde{h}[i] = h[-i] \).

Example

**Convolution in 2D**

In two dimensions, convolution becomes:

\[
g(x, y) = f(x, y) \ast h(x, y) = \int \int f(x', y') h(x-x', y-y') dx'dy'
\]

where \( h(x, y) = h(-x, -y) \).

Similarly, discrete convolution in 2D becomes:

\[
g[i, j] = f[i, j] \ast h[i, j] = \sum_{k} \sum_{l} f[k, l] h[k-i, l-j] = \sum_{k} \sum_{l} f[k, l] \tilde{h}[i-k, j-l]
\]

where \( \tilde{h}[i, j] = h[-i, -j] \).

**Convolution representation**

Since \( f \) and \( g \) are defined over finite regions, we can write them out in two-dimensional arrays:

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**Mean filters**

How can we represent our noise-reducing averaging filter as a convolution diagram (known as a **mean filter**)?

Note: *This is not matrix multiplication!*
**Effect of mean filters**

Gaussian noise

Salt and pepper noise

3x3

5x5

7x7

**Gaussian filters**

Gaussian filters weigh pixels based on their distance from the center of the convolution filter. In particular:

$$h[i, j] = \frac{e^{-(i^2+j^2)/(2\sigma^2)}}{C}$$

This does a decent job of blurring noise while preserving features of the image.

What parameter controls the width of the Gaussian?

What happens to the image as the Gaussian filter kernel gets wider?

What is the constant $C$? What should we set it to?

**Effect of Gaussian filters**

Gaussian noise

Salt and pepper noise

3x3

5x5

7x7

**Median filters**

A median filter operates over an $m \times m$ region by selecting the median intensity in the region.

What advantage does a median filter have over a mean filter?

Is a median filter a kind of convolution?
Effect of median filters

Comparison: Gaussian noise

Comparison: salt and pepper noise

Edge detection

One of the most important uses of image processing is edge detection:

- Really easy for humans
- Really difficult for computers

- Fundamental in computer vision
- Important in many graphics applications
What is an edge?

Step
Ramp
Line
Roof

Q: How might you detect an edge in 1D?

Gradients

The gradient is the 2D equivalent of the derivative:

\[ \nabla f(x, y) = \left( \frac{\partial f}{\partial x}, \frac{\partial f}{\partial y} \right) \]

Properties of the gradient

- It’s a vector
- Points in the direction of maximum increase of \( f \)
- Magnitude is rate of increase

How can we approximate the gradient in a discrete image?

Less than ideal edges

Steps in edge detection

Edge detection algorithms typically proceed in three or four steps:

- Filtering: cut down on noise
- Enhancement: amplify the difference between edges and non-edges
- Detection: use a threshold operation
- Localization (optional): estimate geometry of edges beyond pixels
**Edge enhancement**

A popular gradient magnitude computation is the **Sobel operator**:

\[
\begin{bmatrix}
-1 & 0 & 1 \\
-2 & 0 & 2 \\
-1 & 0 & 1
\end{bmatrix}
\]

We can then compute the magnitude of the vector \( (s_x, s_y) \).

**Results of Sobel edge detection**

![Original](image1.png) ![Smoothed](image2.png) ![Sx + 128](image3.png) ![Sy + 128](image4.png) ![Magnitude](image5.png) ![Threshold = 64](image6.png) ![Threshold = 128](image7.png)

**Second derivative operators**

The Sobel operator can produce thick edges. Ideally, we’re looking for infinitely thin boundaries.

An alternative approach is to look for local extrema in the first derivative: places where the change in the gradient is highest.

Q: A peak in the first derivative corresponds to what in the second derivative?

**Localization with the Laplacian**

An equivalent measure of the second derivative in 2D is the **Laplacian**:

\[
\nabla^2 f(x, y) = \frac{\partial^2 f}{\partial x^2} + \frac{\partial^2 f}{\partial y^2}
\]

Using the same arguments we used to compute the gradient filters, we can derive a Laplacian filter to be:

\[
\Delta^2 = \begin{bmatrix}
0 & 1 & 0 \\
1 & -4 & 1 \\
0 & 1 & 0
\end{bmatrix}
\]

Zero crossings of this filter correspond to positions of maximum gradient. These zero crossings can be used to localize edges.
Localization with the Laplacian

Original Smoothed

Original + Laplacian

Laplacian (+128)

Sharpening with the Laplacian

Original

Laplacian (+128)

Original + Laplacian

Original - Laplacian

Why does the sign make a difference?

How can you write each filter that makes each bottom image?

Summary

What you should take away from this lecture:

- The meanings of all the boldfaced terms.
- A richer understanding of the terms “image” and “image processing”
- How noise reduction is done
- How convolution filtering works
- The effect of mean, Gaussian, and median filters
- What an image gradient is and how it can be computed
- How edge detection is done
- What the Laplacian image is and how it is used in either edge detection or image sharpening