4. Image processing

Reading

Required:

- Jain, Kasturi, Schunck, *Machine Vision.* McGraw-Hill, 1995. Chapter 4 and Sections 5.1-5.4.

Image processing

Defintion: *Image processing* is an operation that takes an image into an image.

Useful for:

- Enhancing contrast
- Removing noise
- Enhancing edges
- Warping (rotating, scaling, shearing, ...)

Image analysis

Defintion: *Image analysis* is an operation that takes an image into anything else.

Examples:

- Extracting measurements
- Recovering edges or geometry
- Image segmentation

(The term "image processing" is sometimes loosely used to cover both processing and analysis.)

What is an image?

We can think of an *image* as a continuous function over two dimensions:

$$f(x, y)$$

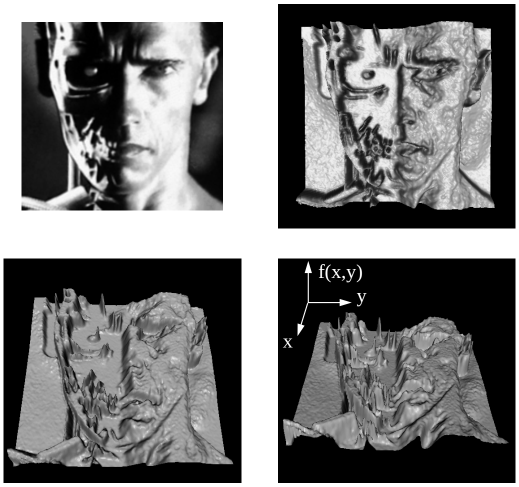
The image may represent light captured by a real or synthetic camera. It could also represent a drawing or painting or visualization of data.

A color image is a "vector-valued" function:

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

For now, we will concentrate on grayscale images, $f(x, y)$.

Images as functions

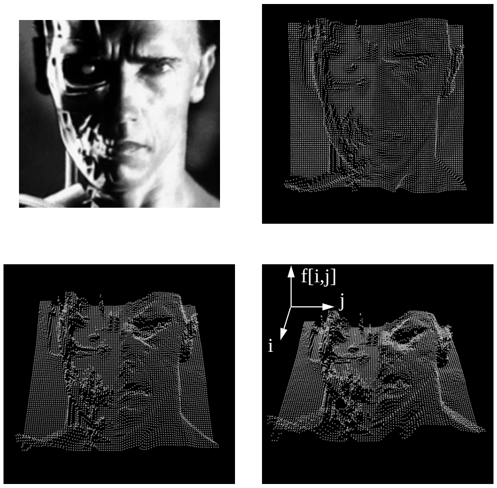


What is a digital image?

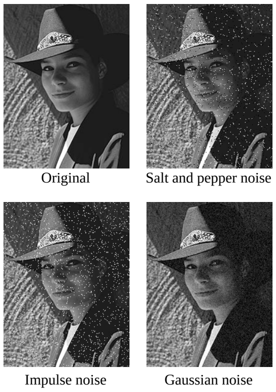
A *digital image* results from sampling and quantizing an image.

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

We will use the term "image" to refer to either continuous or digital images.



Noise



Some common types of noise include:

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

Mean filters

One of the simplest filters we can design is the *mean filter*. It takes the form:

$$\frac{1}{m^2}\begin{bmatrix} 1 & 1 & 1 & \cdots & 1 \\ 1 & 1 & 1 & \cdots & 1 \\ 1 & 1 & 1 & \cdots & 1 \\ & & & \ddots & \\ 1 & 1 & 1 & \cdots & 1 \end{bmatrix}$$

Q: To which continuous domain filter does this correspond?

Q: What are mean filters good for?

Q: What is the effect of varying m?

Effect of mean filters

Mean filtering of various filter sizes applied to two types of noisy images

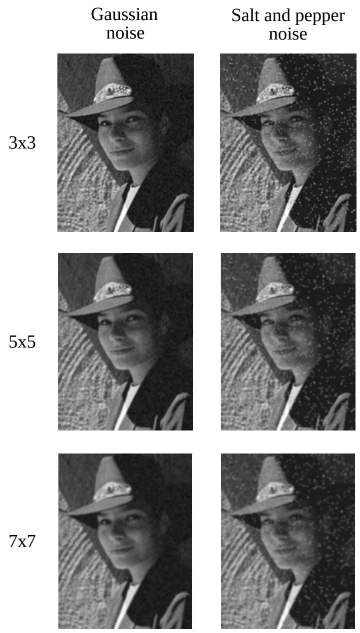
Gaussian filters

Choosing weights according to a Gaussian often does a nicer job than mean filters:

$$g[i,k] = e^{-(i^2+k^2)/(2\sigma^2)}$$

Gaussians provide a nice trade-off between blurring and preserving features in the image.

Effect of Gaussian filters



Gaussian filtering of various filter sizes applied to two types of noisy images

Median filters

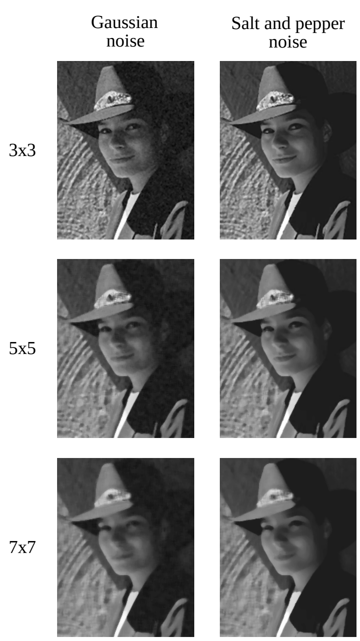
A *median filter* operates over an $m \times m$ window by selecting the median pixel in the window.

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

Q: Is a median filter an LSI filter?

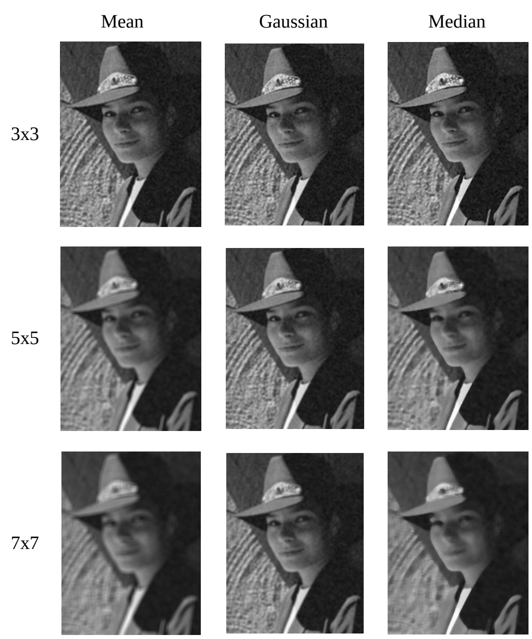
Q: Can we write a median filter as a convolution filter?

Effect of median filters

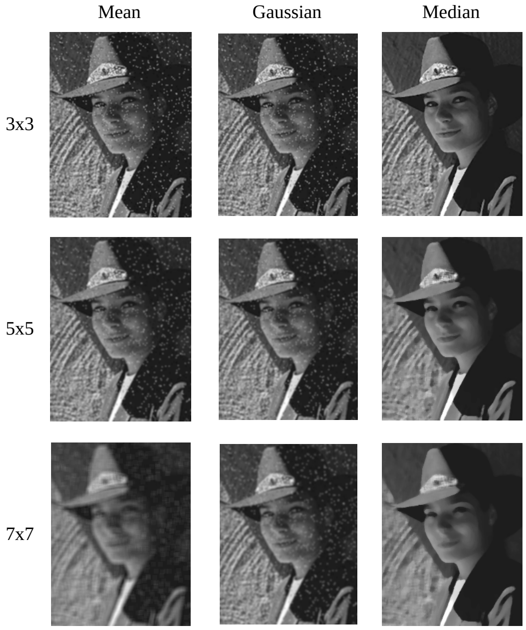


Median filtering of various filter sizes applied to two types of noisy images

Comparison of filters: Gaussian noise



Comparison of filters: Salt and pepper noise



Edge detection

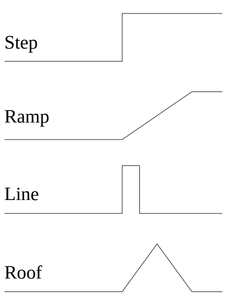
Edge detection is

- Easy for humans
- Not so easy for computers

It's also

- Fundamental in computer vision
- Pretty useful in graphics too

What is an edge?



Some ideal edge profiles

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

Gradients

The *gradient* is the equivalent of the first derivative:

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

Properties of the gradient:

- Points in the direction of maximum increase of f
- Magnitude gives the rate of increase along this direction

Derivatives of discrete signals

How can we take the derivative of a discrete function?
Consider the 1D case:

$$g(x) = \left[\frac{d}{dx}\left\{[f(x)\cdot \mathrm{III}(x)] * r(x)\right\}\right]\mathrm{III}(x)$$

Going through the steps:

$$\begin{aligned}
\frac{d}{dx}\left\{[f(x)\cdot \mathrm{III}(x)] * r(x)\right\} &= \frac{d}{dx}\sum_i f[i]r(x-i)\\
&= \sum_i f[i]\frac{d}{dx}r(x-i)\\
&= \sum_i f[i]r'(x-i)\\
\left[\frac{d}{dx}\left\{[f(x)\cdot \mathrm{III}(x)] * r(x)\right\}\right]\mathrm{III}(x) &= \sum_{k=-\infty}^{\infty}\left\{f[k]*r'[k]\right\}\delta(x-k)
\end{aligned}$$

we arrive at:

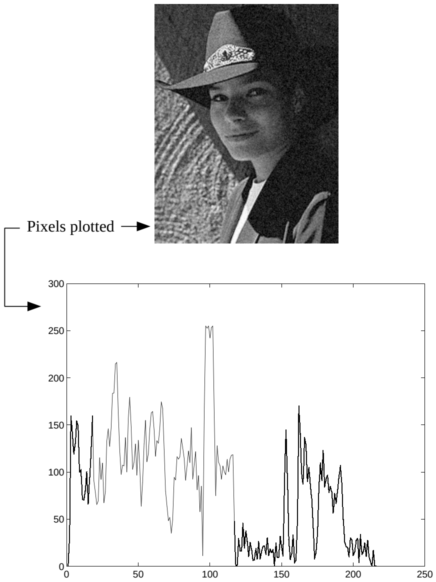
$$g[k] = f[i] * r'[i]$$

Image gradients

Q: What is the 1D derivative filter assuming piecewise linear reconstruction (interpolation)?

Q: What is the 2D gradient filter for images, assuming blinear reconstruction (interpolation)?

Less than ideal edges



Some real edge profiles

Steps in edge detection

Algorithms for edge detection contain 3 or 4 steps:

1. Filtering
   Q: Why?
2. Enhancement
   Usually through gradient magnitude
3. Detection
   Usually via thresholding
4. Localization (optional)
   Estimating subpixel resolution and orientation.

Enhancement step

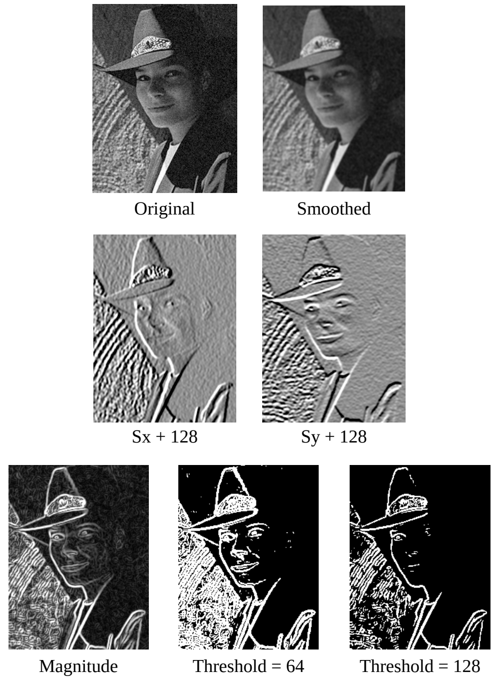
One of the most common measures of gradient magnitude is the *Sobel operator*. The partials s_x and s_y are computed by:

$$s_x = \begin{bmatrix} -1 & 0 & 1 \\ -2 & 0 & 2 \\ -1 & 0 & 1 \end{bmatrix}$$

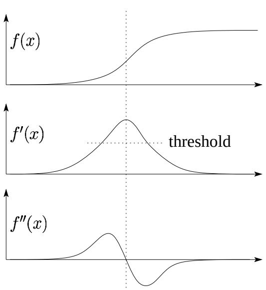
$$s_y = \begin{bmatrix} 1 & 2 & 1 \\ 0 & 0 & 0 \\ -1 & -2 & -1 \end{bmatrix}$$

(Gives more emphasis to pixels near the center of the mask.)

Results of Sobel edge detection



Second derivative operators



Comparison of first and second derivative approaches

Note that the Sobel operator gives thick edges anywhere the derivative is above threshold.

A better approach might be to look for peaks in the first derivative.

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*:

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

A common choice for the Laplacian is:

$$\nabla^2 = \begin{bmatrix} 0 & 1 & 0 \\ 1 & -4 & 1 \\ 0 & 1 & 0 \end{bmatrix}$$

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