Image filtering

Images by Pawan Sinha

What is an image?

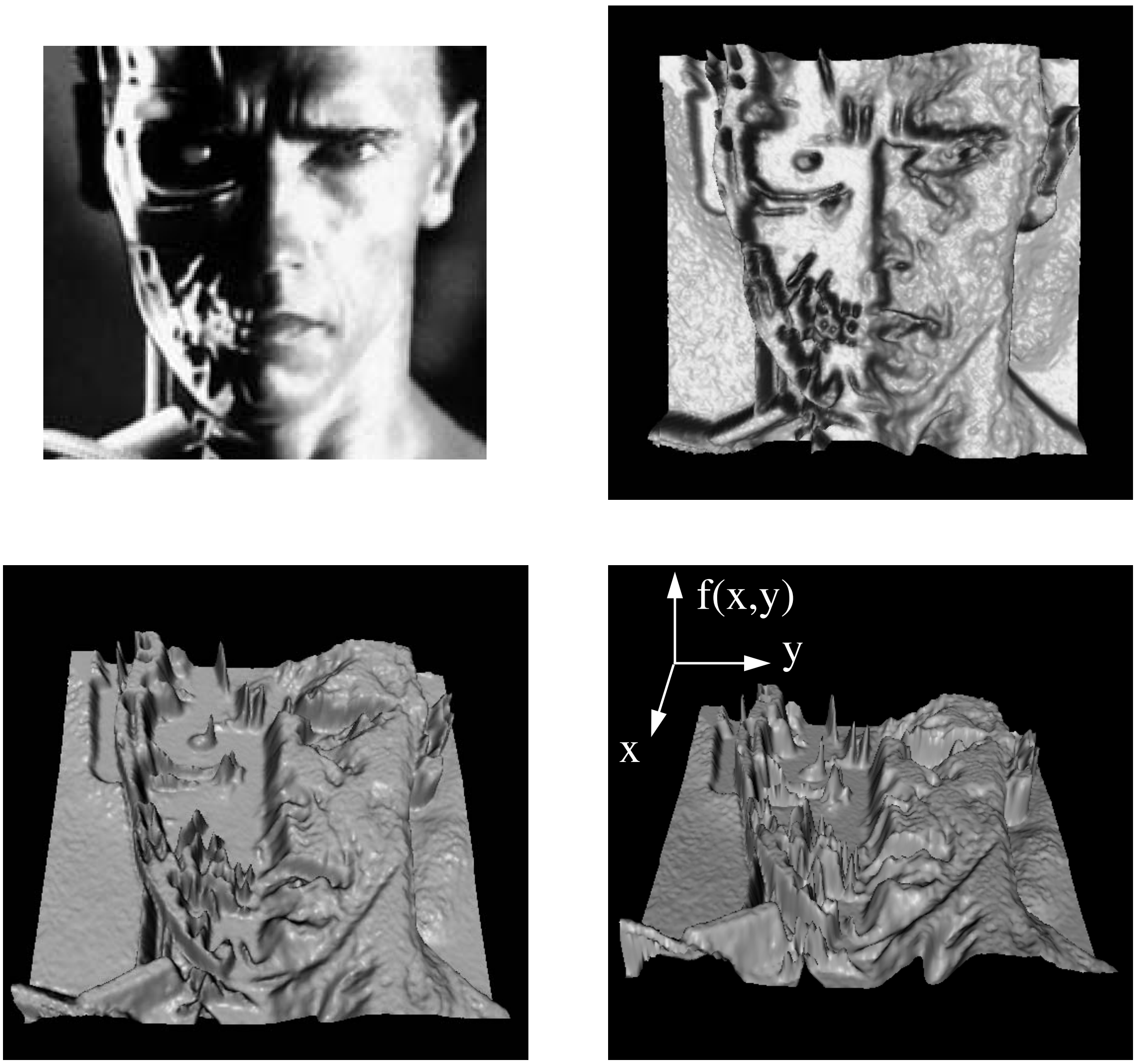
We can think of an **image** as a function, *f*, from R^2 to R:

- $f(x, y)$ gives the **intensity** 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 vision we usually operate on **digital** (**discrete**) images:

- **Sample** the 2D space on a regular grid
- **Quantize** each sample (round to nearest integer)

If our samples are Δ apart, we can write this as:

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

The image can now be represented as a matrix of integer values

j →

i ↓

62	79	23	119	120	105	4	0
10	10	9	62	12	78	34	0
10	58	197	46	46	0	0	48
176	135	5	188	191	68	0	49
2	1	1	29	26	37	0	77
0	89	144	147	187	102	62	208
255	252	0	166	123	62	0	31
166	63	127	17	1	0	99	30

Filtering Operations Use Masks

- **Masks operate on a neighborhood of pixels.**
- **A mask of coefficients is centered on a pixel.**
- **The mask coefficients are multiplied by the pixel values in its neighborhood and the products are summed.**
- **The result goes into the corresponding pixel position in the output image.**

36	36	36	36	36
36	36	45	45	45
36	45	45	45	54
36	45	54	54	54
45	45	54	54	54

Input Image

1/9	1/9	1/9
1/9	1/9	1/9
1/9	1/9	1/9

3x3 Mask

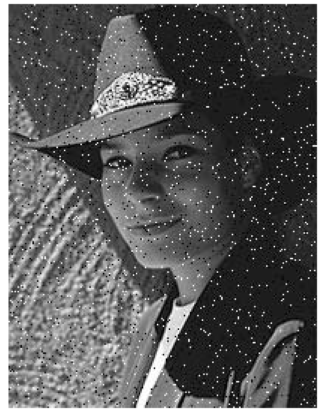
**	**	**	**	**
**	39	**	**	**
**	**	**	**	**
**	**	**	**	**
**	**	**	**	**

Output Image

Noise

Image processing is useful for noise reduction...

Original



Salt and pepper noise

Impulse noise

Gaussian noise

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?

0	0	0	0	0	0	0	0	0	0
0	0	0	0	0	0	0	0	0	0
0	0	0	100	130	110	120	110	0	0
0	0	0	110	90	100	90	100	0	0
0	0	0	130	100	90	130	110	0	0
0	0	0	120	100	130	110	120	0	0
0	0	0	90	110	80	120	100	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	0	0	0	0	0

Mean filtering

$F[x, y]$

0	0	0	0	0	0	0	0	0	0
0	0	0	0	0	0	0	0	0	0
0	0	0	90	90	90	90	90	0	0
0	0	0	90	90	90	90	90	0	0
0	0	0	90	90	90	90	90	0	0
0	0	0	90	0	90	90	90	0	0
0	0	0	90	90	90	90	90	0	0
0	0	0	0	0	0	0	0	0	0
0	0	90	0	0	0	0	0	0	0
0	0	0	0	0	0	0	0	0	0

$G[x, y]$

Mean filtering

$F[x, y]$

0	0	0	0	0	0	0	0	0	0
0	0	0	0	0	0	0	0	0	0
0	0	0	90	90	90	90	90	0	0
0	0	0	90	90	90	90	90	0	0
0	0	0	90	90	90	90	90	0	0
0	0	0	90	0	90	90	90	0	0
0	0	0	90	90	90	90	90	0	0
0	0	0	0	0	0	0	0	0	0
0	0	90	0	0	0	0	0	0	0
0	0	0	0	0	0	0	0	0	0

$G[x, y]$

	0	10	20	30	30	30	20	10	
	0	20	40	60	60	60	40	20	
	0	30	60	90	90	90	60	30	
	0	30	50	80	80	90	60	30	
	0	30	50	80	80	90	60	30	
	0	20	30	50	50	60	40	20	
	10	20	30	30	30	30	20	10	
	10	10	10	0	0	0	0	0	

Effect of mean filters

Gaussian noise | Salt and pepper noise

3x3

5x5

7x7

Cross-correlation filtering

Let's write this down as an equation. Assume the averaging window is (2k+1)x(2k+1):

$$G[i,j] = \frac{1}{(2k+1)^2} \sum_{u=-k}^{k} \sum_{v=-k}^{k} F[i+u, j+v]$$

We can generalize this idea by allowing different weights for different neighboring pixels:

$$G[i,j] = \sum_{u=-k}^{k} \sum_{v=-k}^{k} H[u,v] F[i+u, j+v]$$

This is called a **cross-correlation** operation and written:

$$G = H \otimes F$$

H is called the "filter," "kernel," or "mask."

The above allows negative filter indices. When you implement need to use: H[u+k,v+k] instead of H[u,v]

Mean kernel

What's the kernel for a 3x3 mean filter?

0	0	0	0	0	0	0	0	0	0
0	0	0	0	0	0	0	0	0	0
0	0	0	90	90	90	90	90	0	0
0	0	0	90	90	90	90	90	0	0
0	0	0	90	90	90	90	90	0	0
0	0	0	90	0	90	90	90	0	0
0	0	0	90	90	90	90	90	0	0
0	0	0	0	0	0	0	0	0	0
0	0	90	0	0	0	0	0	0	0
0	0	0	0	0	0	0	0	0	0

$F[x, y]$

$H[u, v]$

Gaussian Filtering

A Gaussian kernel gives less weight to pixels further from the center of the window

0	0	0	0	0	0	0	0	0	0
0	0	0	0	0	0	0	0	0	0
0	0	0	90	90	90	90	90	0	0
0	0	0	90	90	90	90	90	0	0
0	0	0	90	90	90	90	90	0	0
0	0	0	90	0	90	90	90	0	0
0	0	0	90	90	90	90	90	0	0
0	0	0	0	0	0	0	0	0	0
0	0	90	0	0	0	0	0	0	0
0	0	0	0	0	0	0	0	0	0

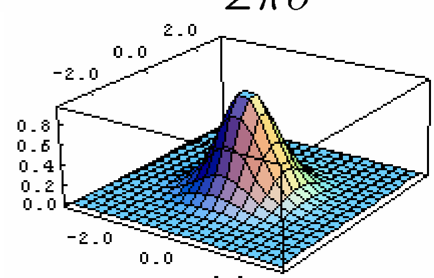
$$F[x,y]$$

$$\frac{1}{16}\begin{bmatrix} 1 & 2 & 1 \\ 2 & 4 & 2 \\ 1 & 2 & 1 \end{bmatrix}$$

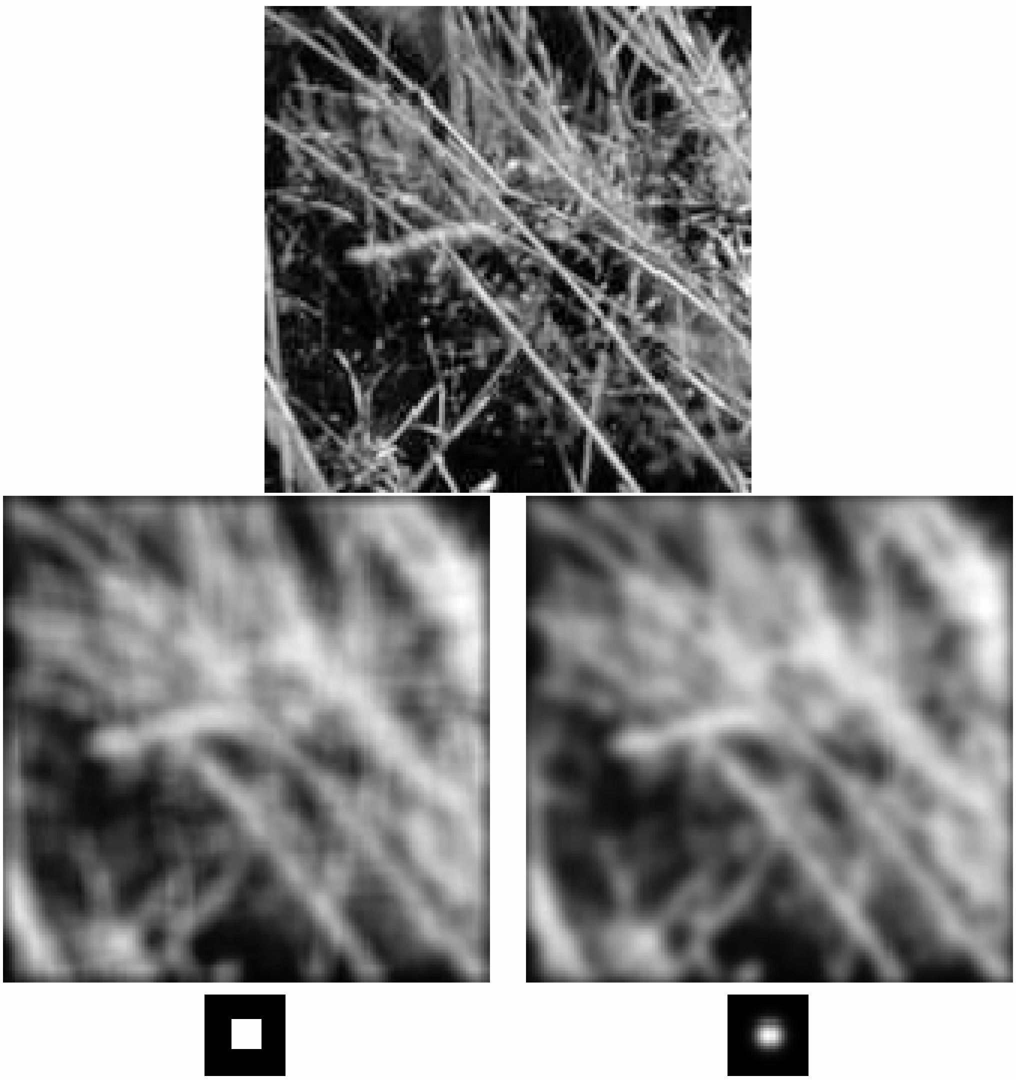
$$H[u,v]$$

This kernel is an approximation of a Gaussian function:

$$h(u,v) = \frac{1}{2\pi\sigma^2} e^{-\frac{u^2+v^2}{\sigma^2}}$$



Mean vs. Gaussian filtering



Convolution

A **convolution** operation is a cross-correlation where the filter is flipped both horizontally and vertically before being applied to the image:

$$G[i,j] = \sum_{u=-k}^{k} \sum_{v=-k}^{k} H[u,v] F[i-u, j-v]$$

It is written: $G = H \star F$

Suppose H is a Gaussian or mean kernel. How does convolution differ from cross-correlation?

Median filters

A **Median Filter** operates over a window by selecting the median intensity in the window.

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

Is a median filter a kind of convolution?

Comparison: salt and pepper noise

Mean Gaussian Median

3x3

5x5

7x7

Comparison: Gaussian noise

Mean Gaussian Median

3x3

5x5

7x7