CS5670: Intro to Computer Vision

Noah Snavely

Lecture 1: Images and image filtering

Hybrid Images, Oliva et al., http://cvcl.mit.edu/hybridimage.htm

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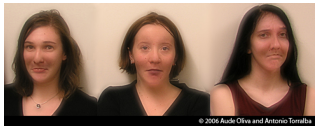

Hybrid Images, Oliva et al., http://cvcl.mit.edu/hybridimage.htm

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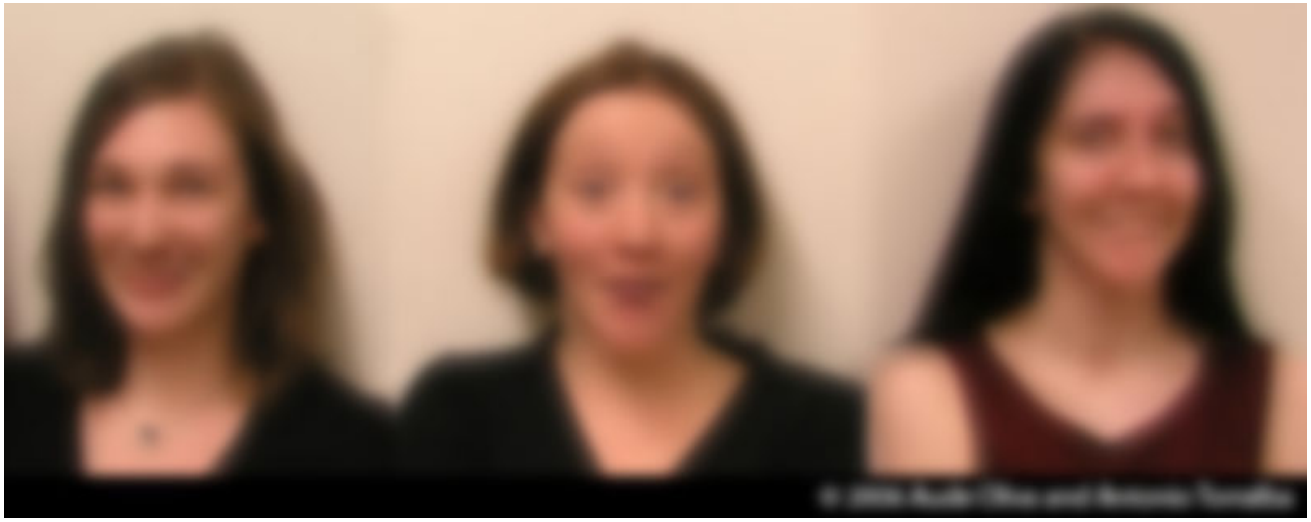


Hybrid Images, Oliva et al., http://cvcl.mit.edu/hybridimage.htm

Reading

- Szeliski, Chapter 3.1-3.2

Announcements

- You should have been invited to Piazza
- We will add students to CMS this week

Announcements

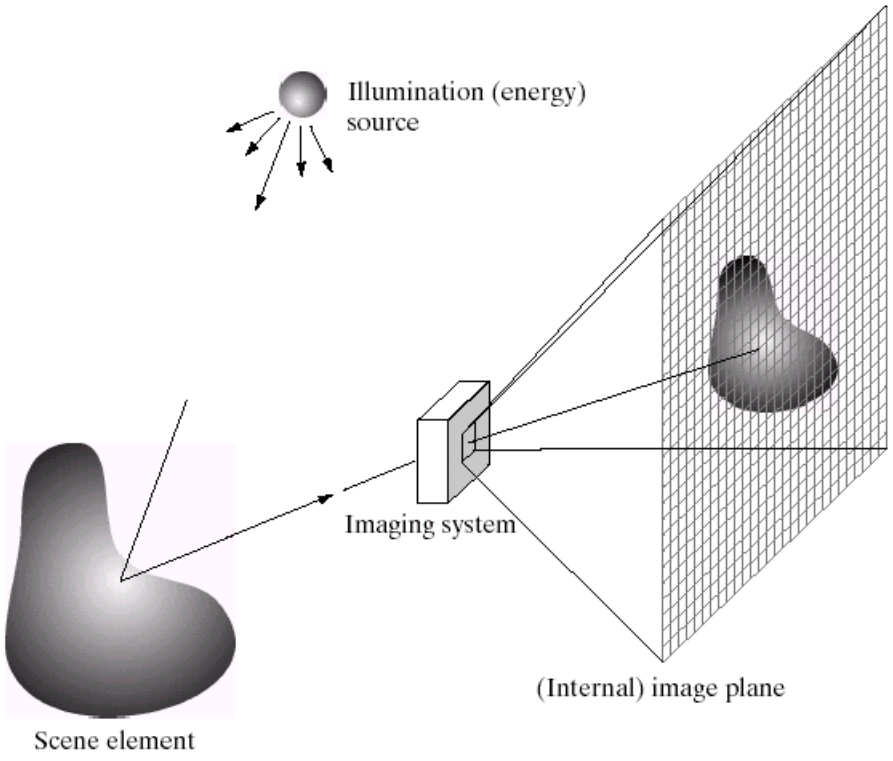
- Project 1 (Hybrid Images) will be released tomorrow or Wednesday
  - This project will be done solo
  - Other projects planned to be done in groups of 2

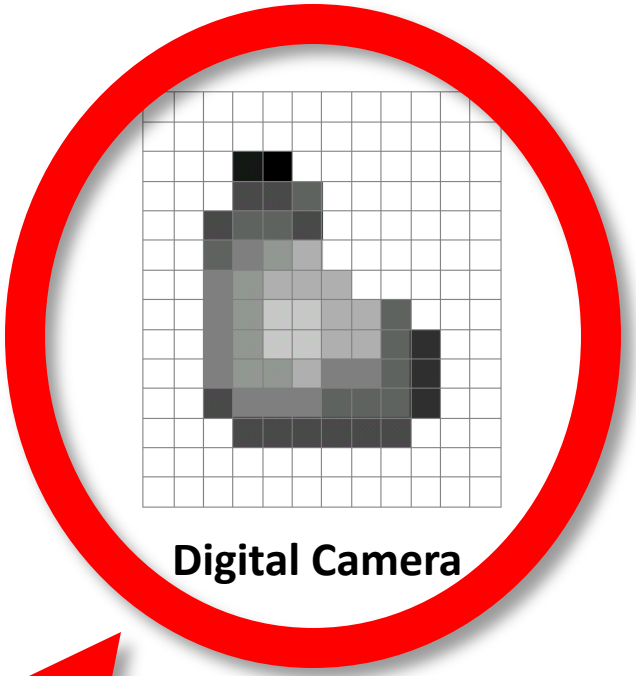
Announcements

- We provide a walkthrough for setting up a python environment for the project
- As a backup, we also have a course virtual machine (VM) for you to run the assignments
- The assignment also works on lab machines

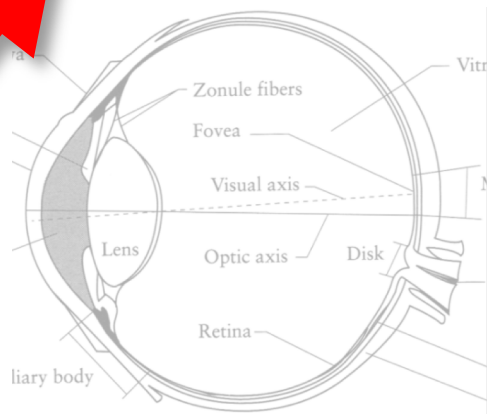
What is an image?

What is an image?





We'll focus on these in this class

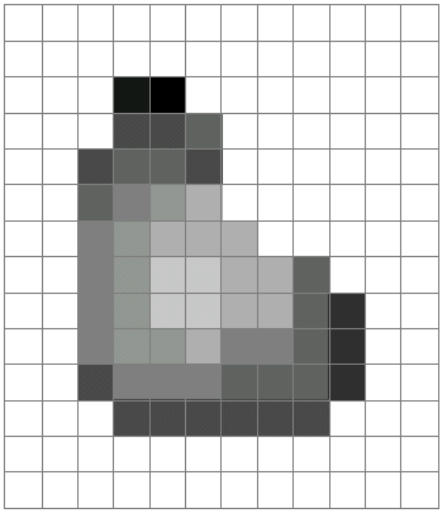


(More on this process later)

Source: A. Efros

What is an image?

- A grid (matrix) of intensity values



=

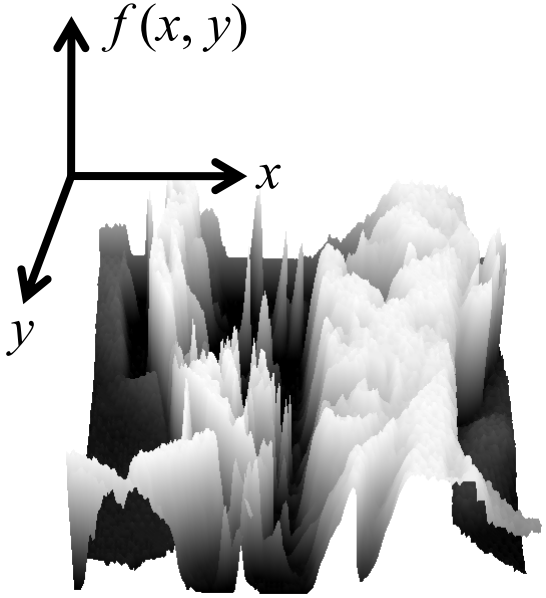
255	255	255	255	255	255	255	255	255	255	255	255
255	255	255	255	255	255	255	255	255	255	255	255
255	255	255	20	0	255	255	255	255	255	255	255
255	255	255	75	75	75	255	255	255	255	255	255
255	255	75	95	95	75	255	255	255	255	255	255
255	255	96	127	145	175	255	255	255	255	255	255
255	255	127	145	175	175	175	255	255	255	255	255
255	255	127	145	200	200	175	175	95	255	255	255
255	255	127	145	200	200	175	175	95	47	255	255
255	255	127	145	145	175	127	127	95	47	255	255
255	255	74	127	127	127	95	95	95	47	255	255
255	255	255	74	74	74	74	74	74	255	255	255
255	255	255	255	255	255	255	255	255	255	255	255
255	255	255	255	255	255	255	255	255	255	255	255

(common to use one byte per value: 0 = black, 255 = white)

What is an image?

- We can think of a (grayscale) image as a **function**, f, from R^2 to R:
  - $f(x,y)$ gives the **intensity** at position (x,y)

snoop

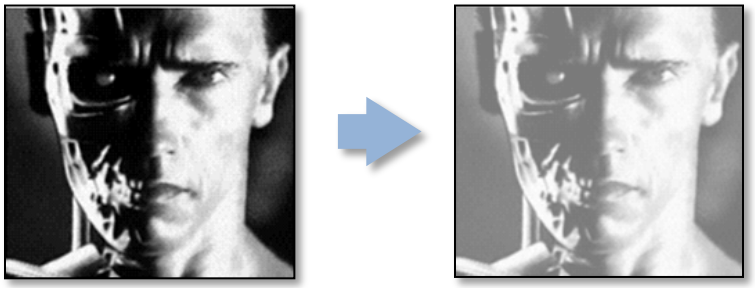


3D view

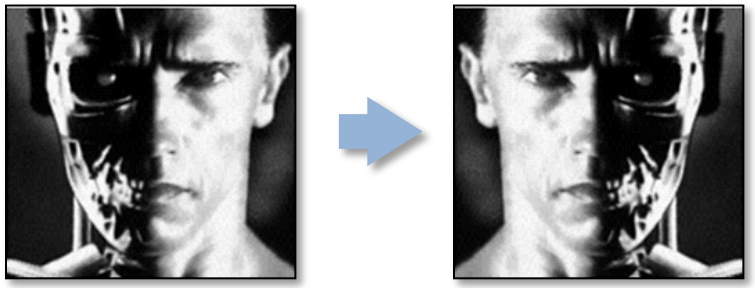
  - A **digital** image is a discrete (**sampled**, **quantized**) version of this function

Image transformations

- As with any function, we can apply operators to an image



$g(x,y) = f(x,y) + 20$



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

- Today we'll talk about a special kind of operator, *convolution* (linear filtering)

Filters

- Filtering
  - Form a new image whose pixels are a combination of the original pixels
- Why?
  - To get useful information from images
    - E.g., extract edges or contours (to understand shape)
  - To enhance the image
    - E.g., to remove noise
    - E.g., to sharpen and “enhance image” a la CSI
  - A key operator in Convolutional Neural Networks

Canonical Image Processing problems

- Image Restoration
  - denoising
  - deblurring
- Image Compression
  - JPEG, JPEG2000, MPEG..
- Computing Field Properties
  - optical flow
  - disparity
- Locating Structural Features
  - corners
  - edges

Question: Noise reduction

- Given a camera and a still scene, how can you reduce noise?

Take lots of images and average them!

What's the next best thing?

Source: S. Seitz

Image filtering

- Modify the pixels in an image based on some function of a local neighborhood of each pixel

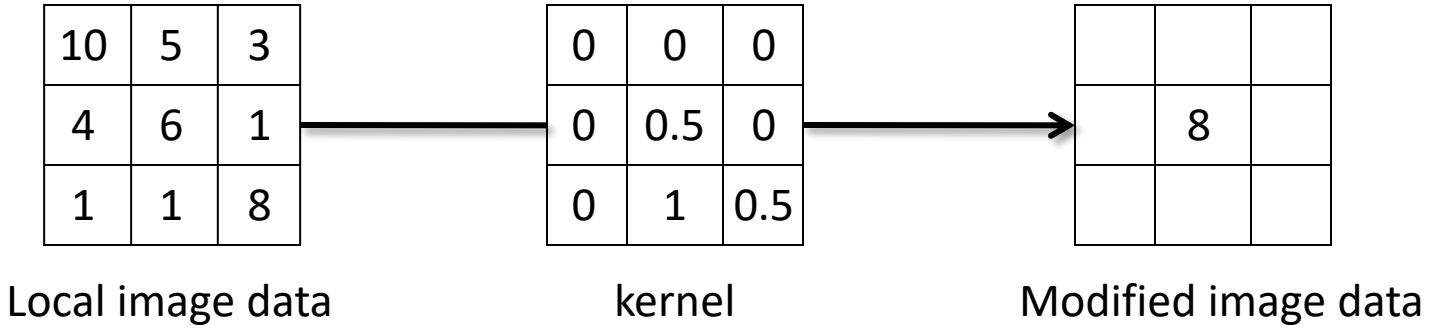
Local image data

Modified image data

Source: L. Zhang

Linear filtering

- One simple version of filtering: linear filtering (cross-correlation, convolution)
  - Replace each pixel by a linear combination (a weighted sum) of its neighbors
- The prescription for the linear combination is called the "kernel" (or "mask", "filter")



Source: L. Zhang

Cross-correlation

Let F be the image, H be the kernel (of size 2*k*+1 x 2*k*+1), and G be the output image

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

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

$$G = H \otimes F$$

- Can think of as a "dot product" between local neighborhood and kernel for each pixel

Convolution

- Same as cross-correlation, except that the kernel is “flipped” (horizontally and vertically)

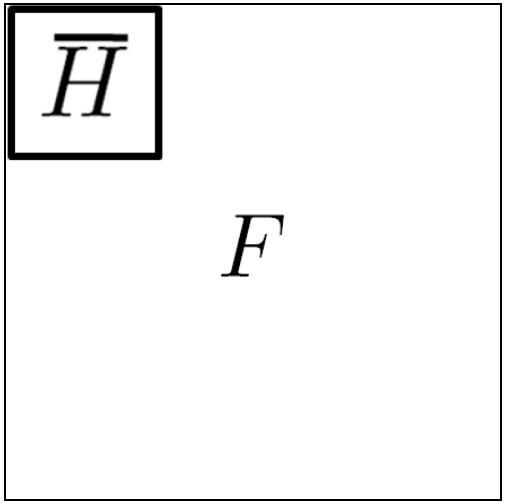
$$G[i,j] = \sum_{u=-k}^{k} \sum_{v=-k}^{k} H[u,v]F[i-u,j-v]$$

This is called a **convolution** operation:

$$G = H * F$$

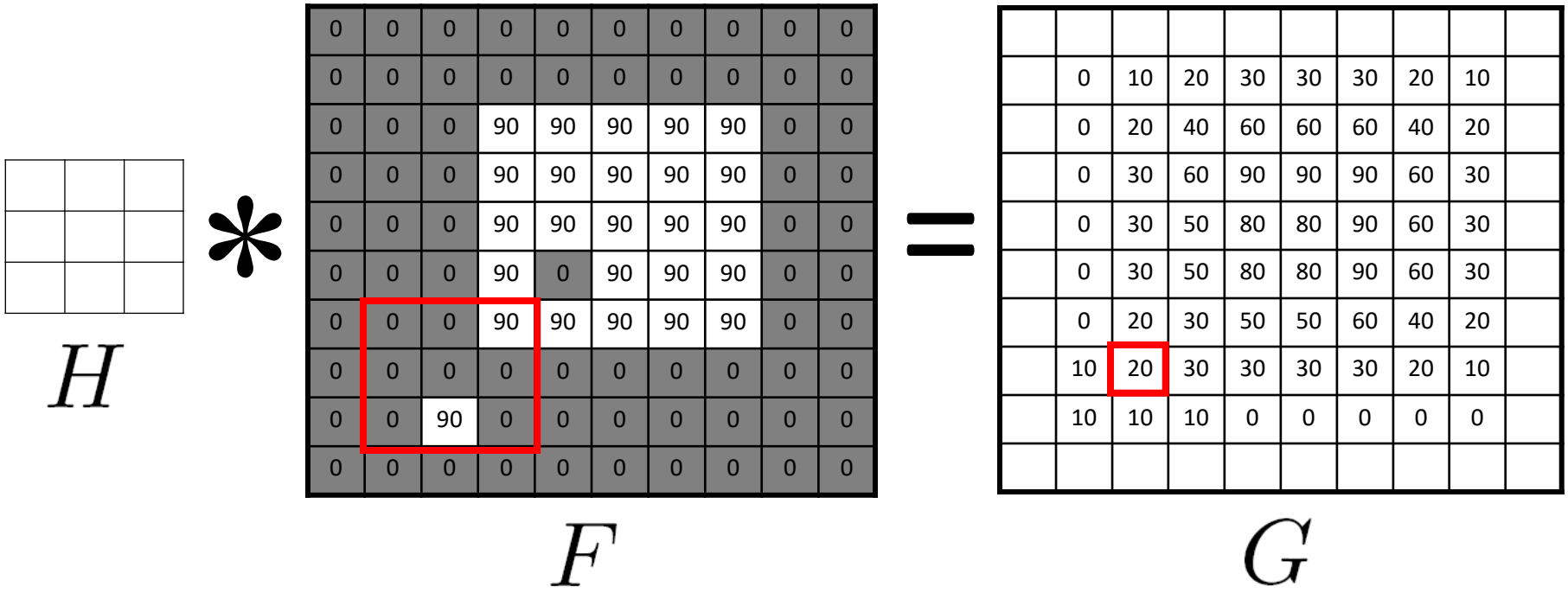
- Convolution is **commutative** and **associative**

Convolution

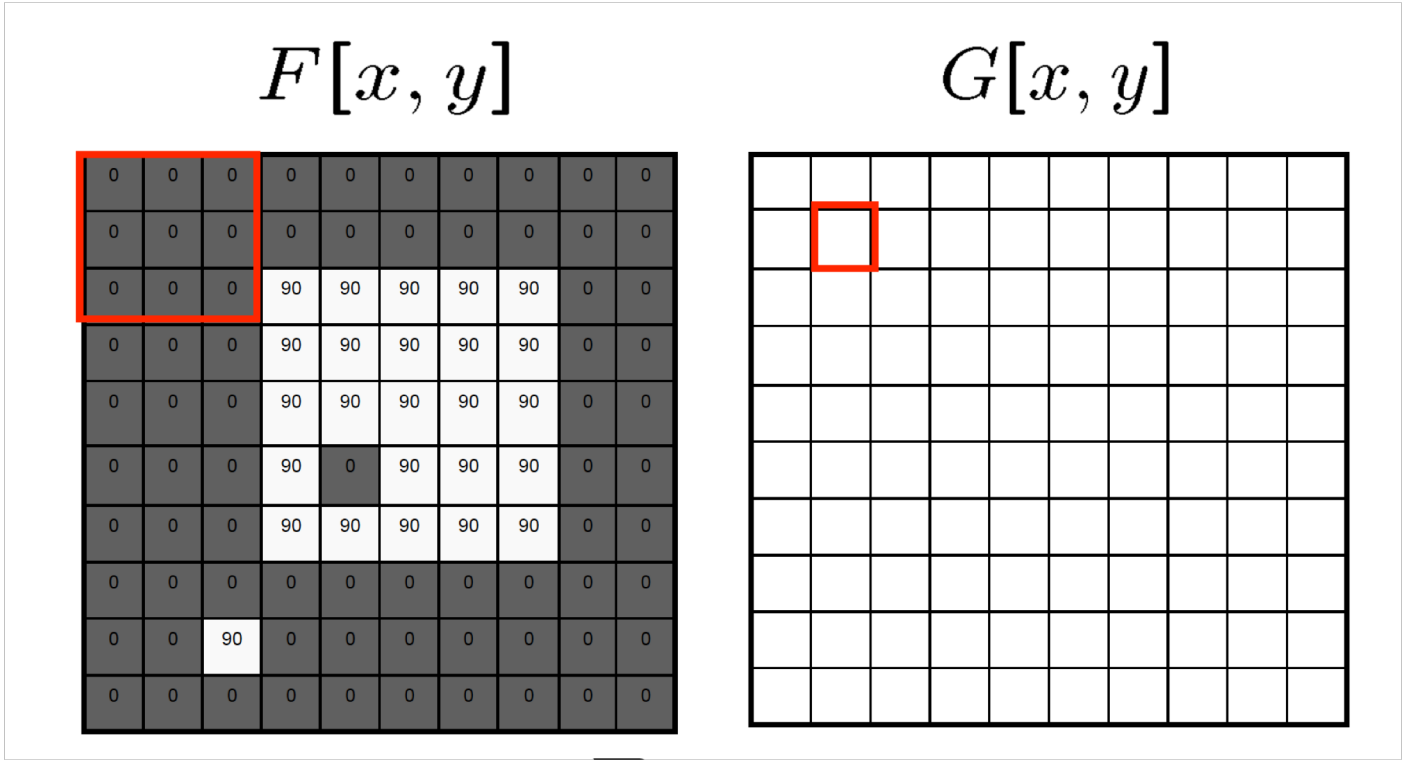


Adapted from F. Durand

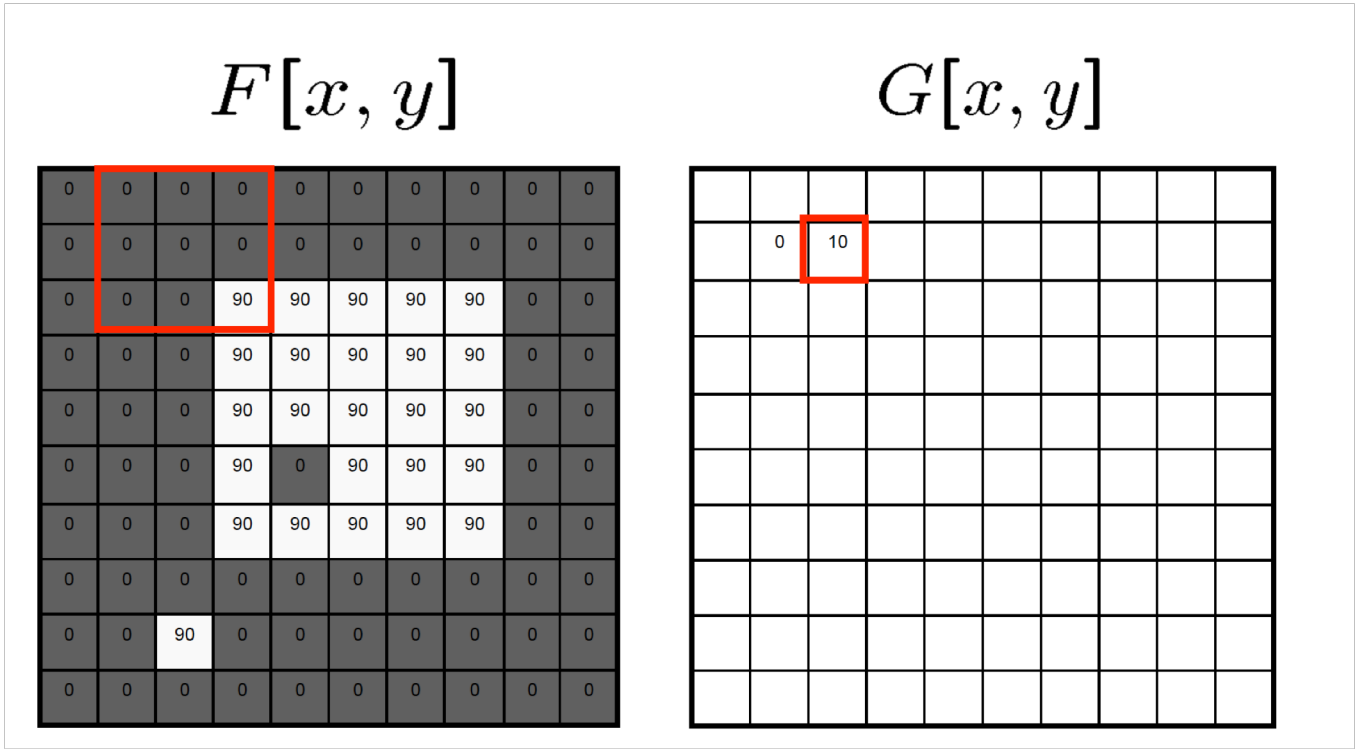
Mean filtering



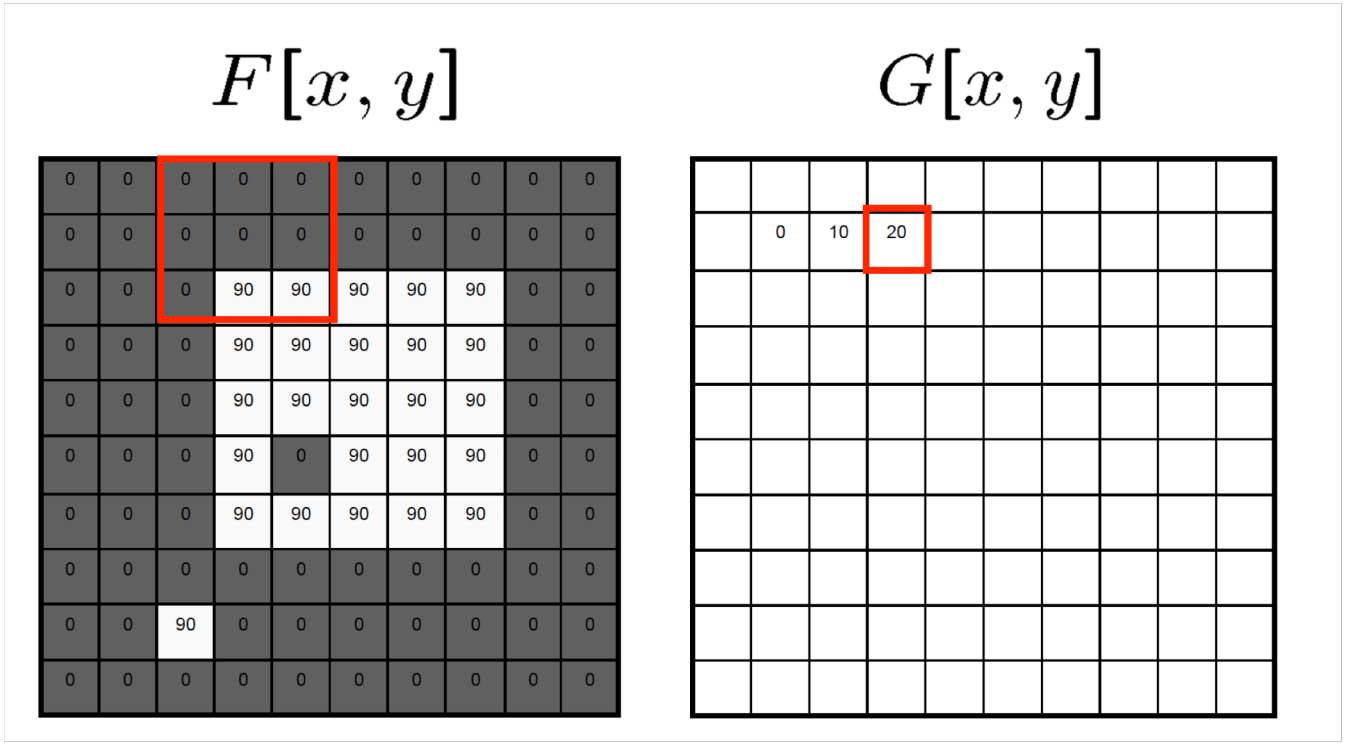
Mean filtering/Moving average



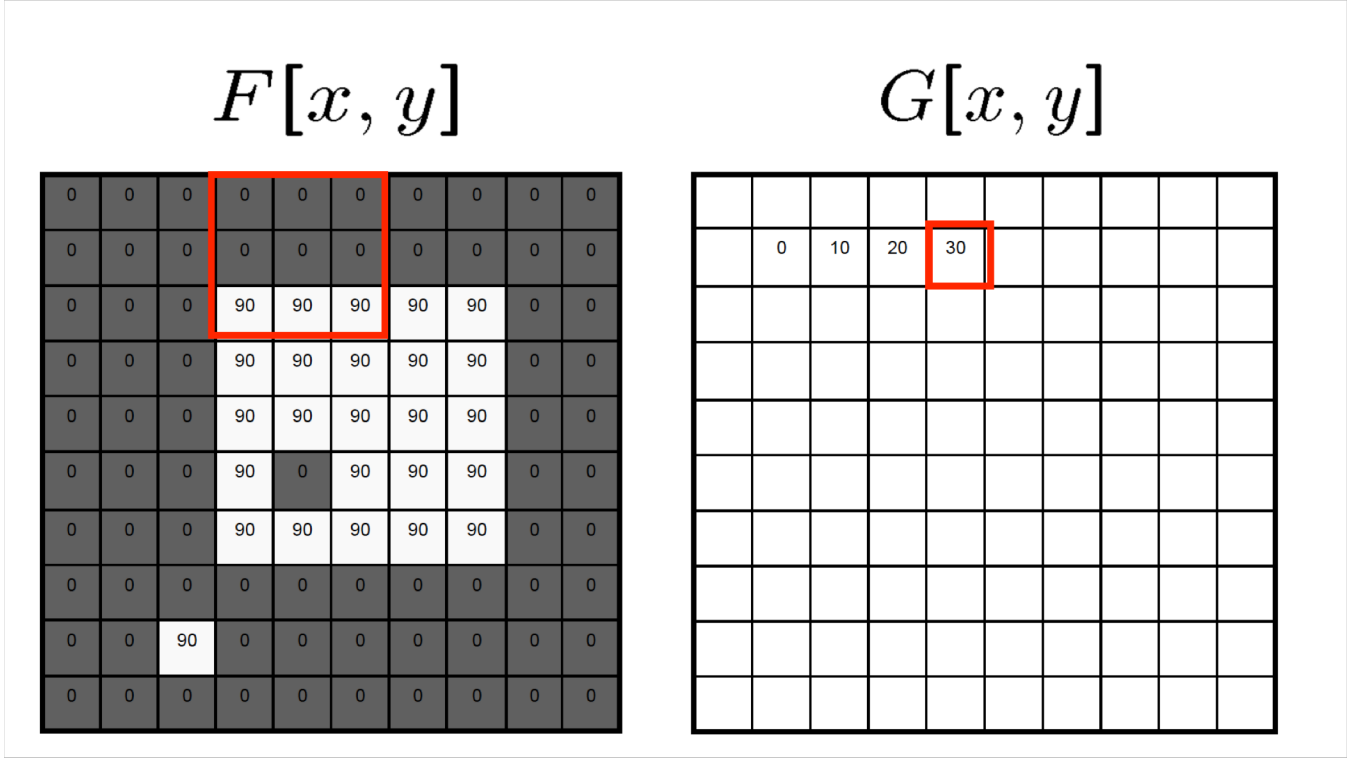
Mean filtering/Moving average



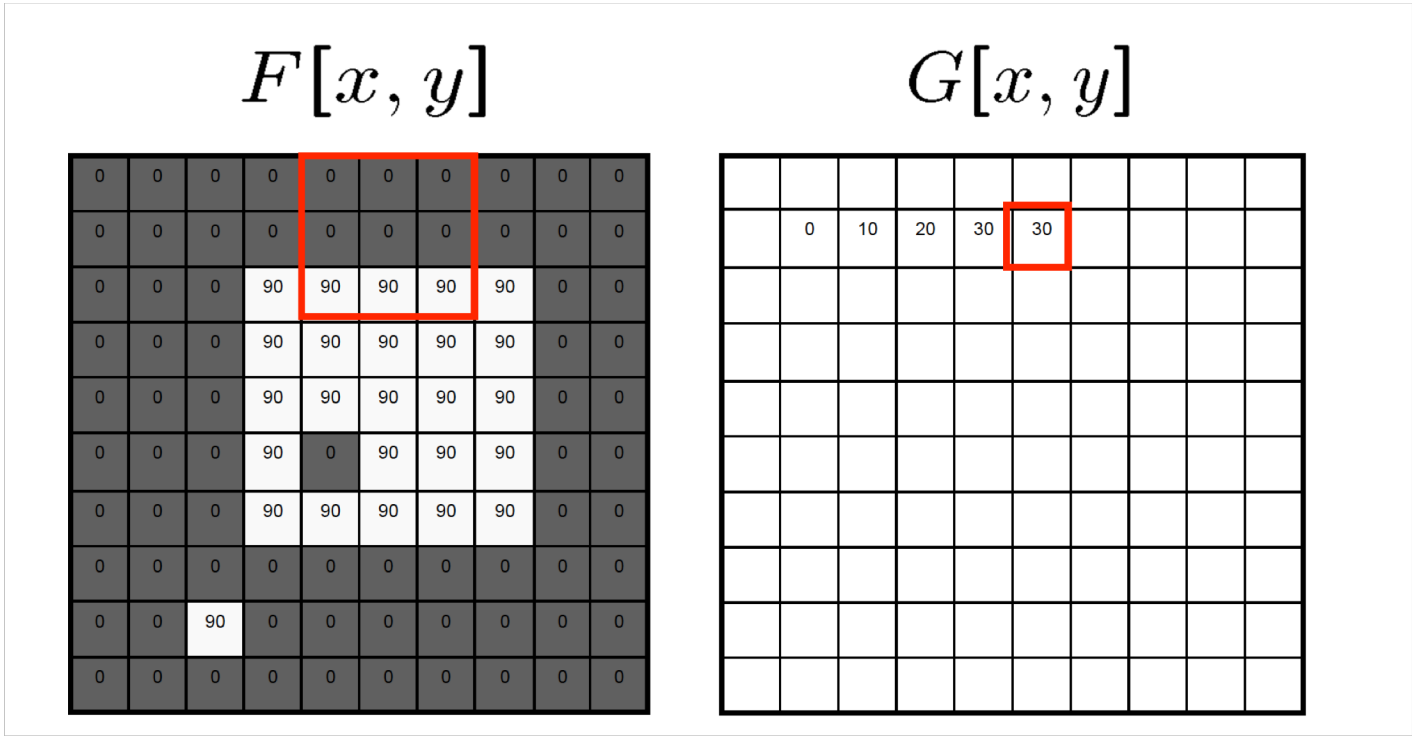
Mean filtering/Moving average



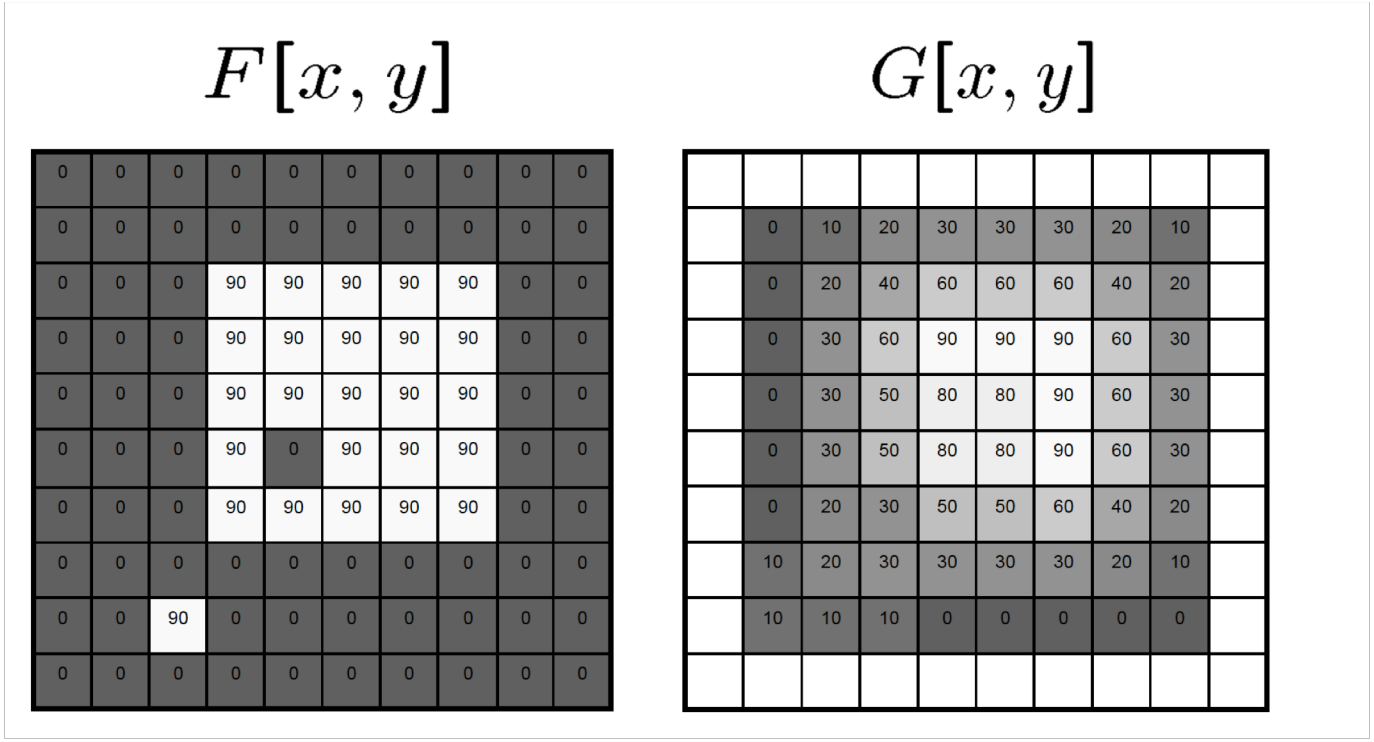
Mean filtering/Moving average



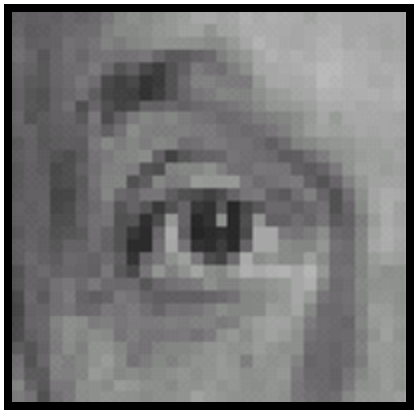
Mean filtering/Moving average



Mean filtering/Moving average

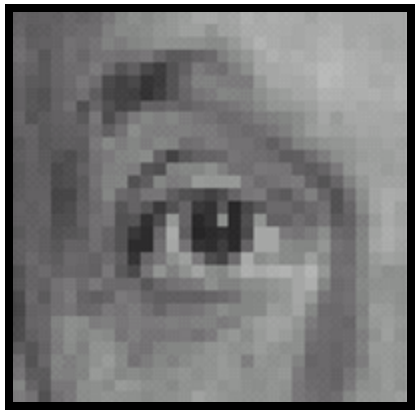


Linear filters: examples



Original

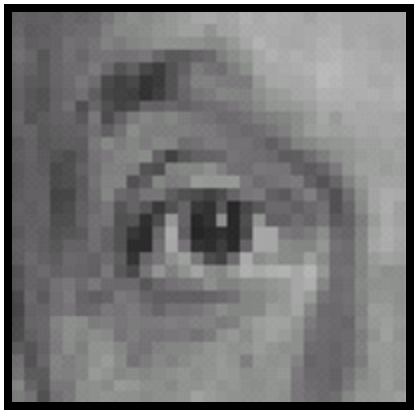
$$*\begin{bmatrix} 0 & 0 & 0 \\ 0 & 1 & 0 \\ 0 & 0 & 0 \end{bmatrix} =$$



Identical image

Source: D. Lowe

Linear filters: examples

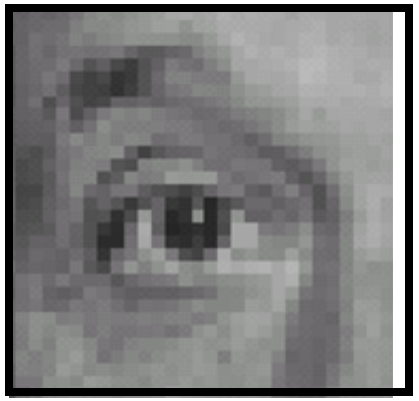


Original

$*$

0	0	0
1	0	0
0	0	0

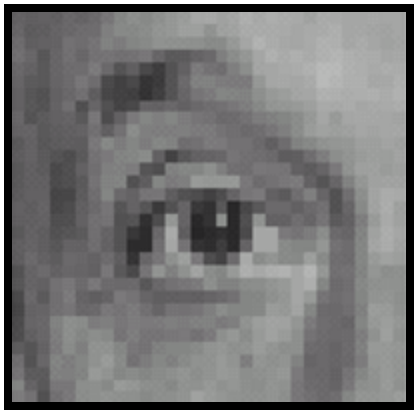
$=$



Shifted left
By 1 pixel

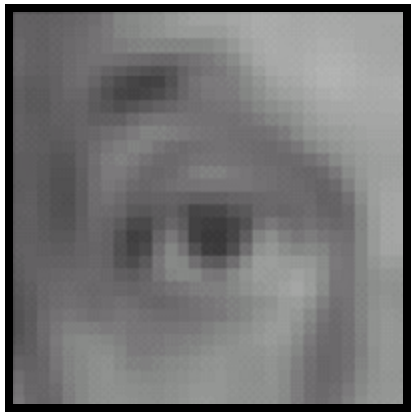
Source: D. Lowe

Linear filters: examples



Original

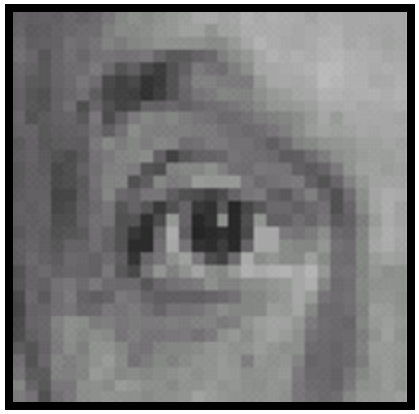
$$*\ \frac{1}{9}\begin{bmatrix}1 & 1 & 1\\ 1 & 1 & 1\\ 1 & 1 & 1\end{bmatrix} =$$



Blur (with a mean filter)

Source: D. Lowe

Linear filters: examples



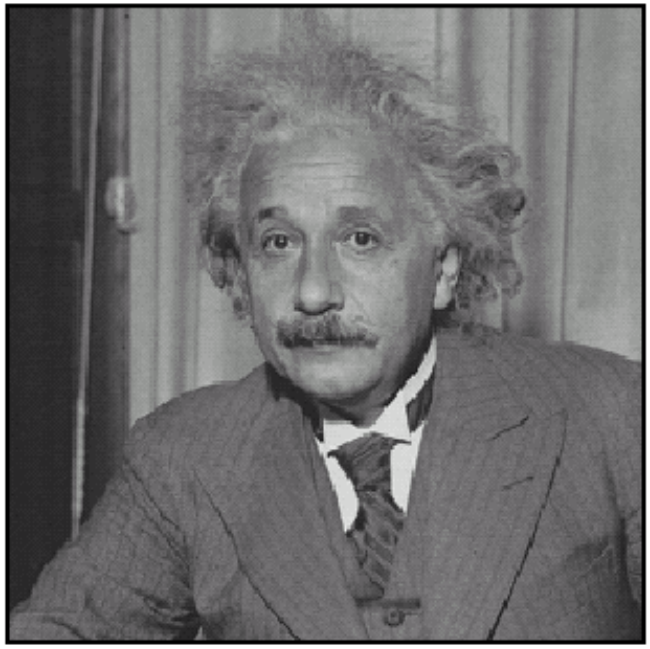
Original

$$* \left(\begin{bmatrix} 0 & 0 & 0 \\ 0 & 2 & 0 \\ 0 & 0 & 0 \end{bmatrix} - \frac{1}{9} \begin{bmatrix} 1 & 1 & 1 \\ 1 & 1 & 1 \\ 1 & 1 & 1 \end{bmatrix} \right) =$$

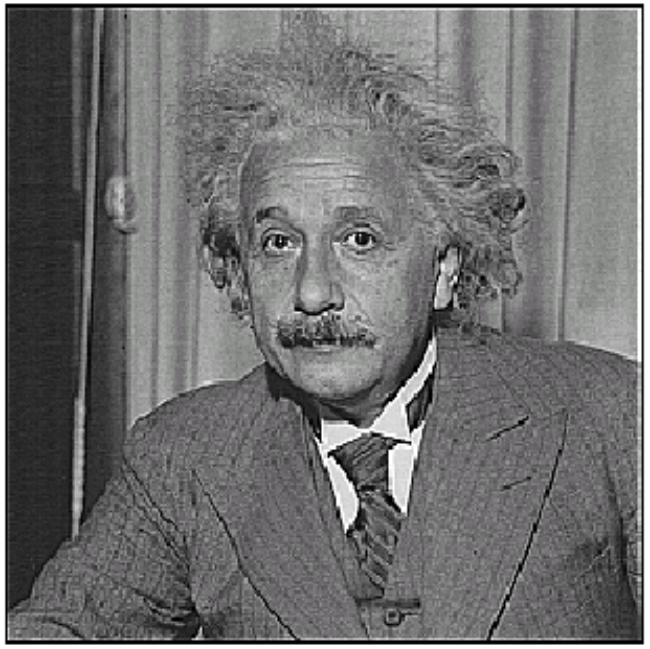
Sharpening filter
(accentuates edges)

Source: D. Lowe

Sharpening



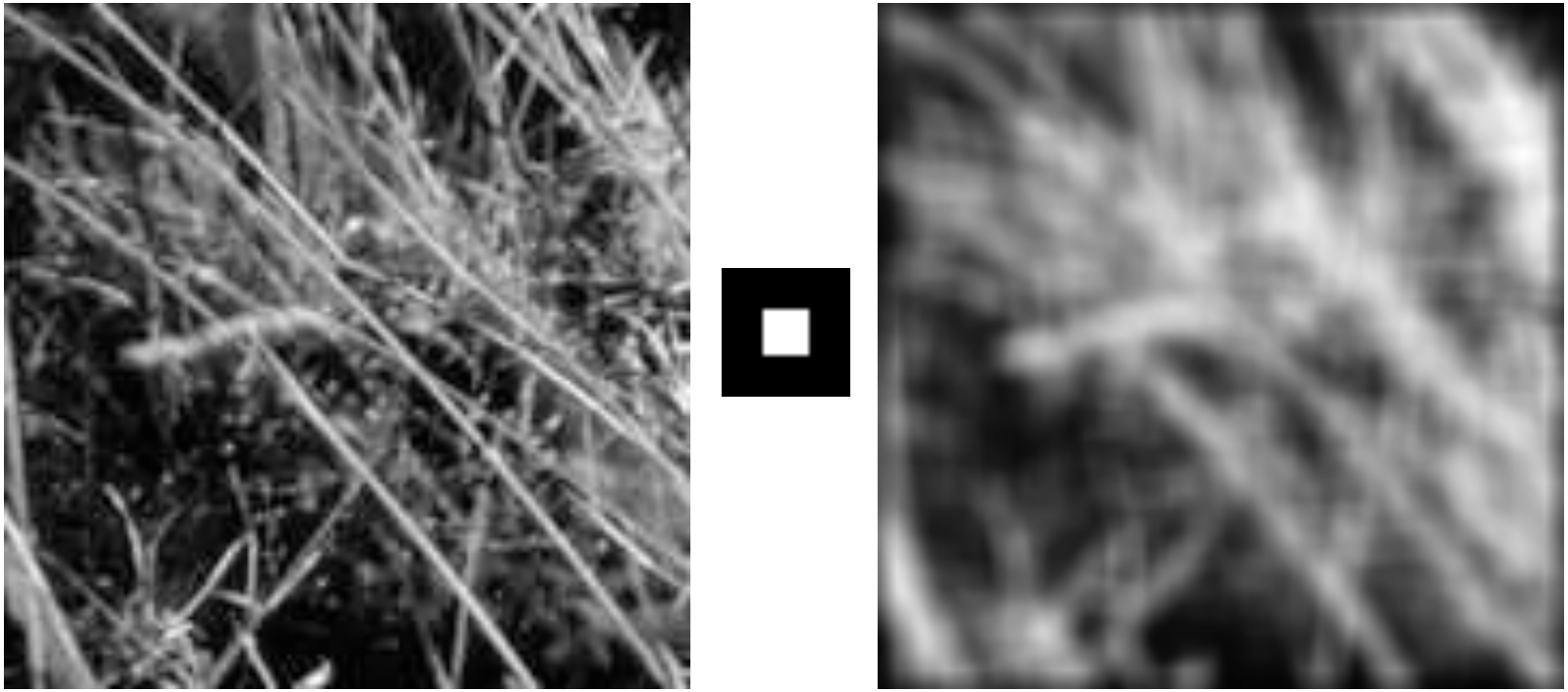
before



after

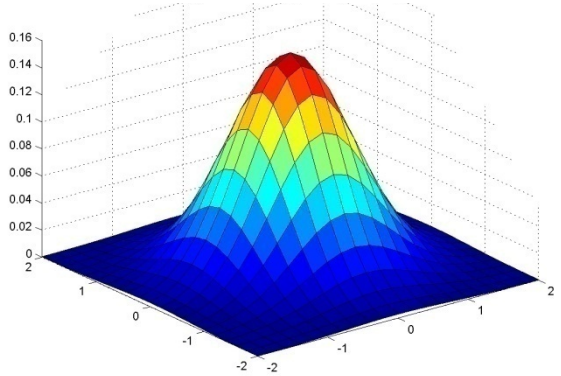
Source: D. Lowe

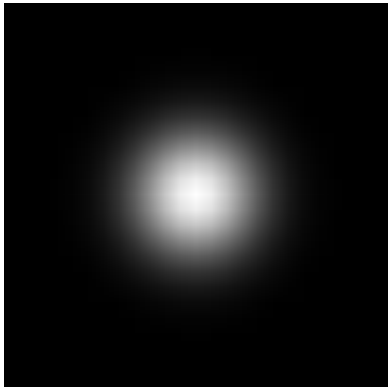
Smoothing with box filter revisited



Source: D. Forsyth

Gaussian Kernel

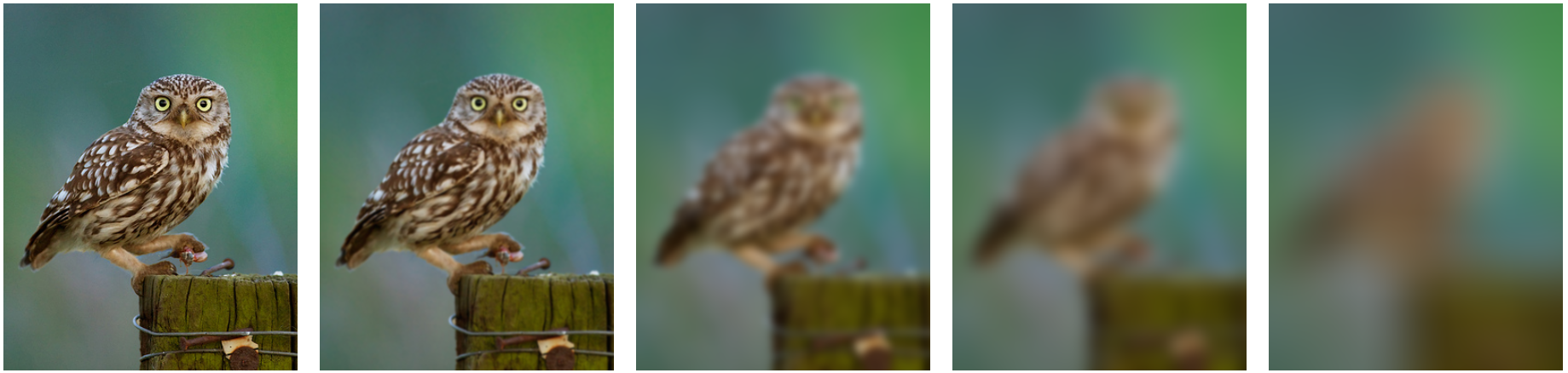




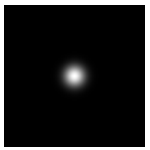
$$G_\sigma = \frac{1}{2\pi\sigma^2} e^{-\frac{(x^2+y^2)}{2\sigma^2}}$$

Source: C. Rasmussen

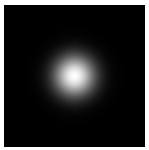
Gaussian filters



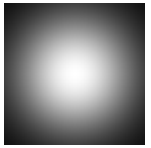
σ = 1 pixel



σ = 5 pixels

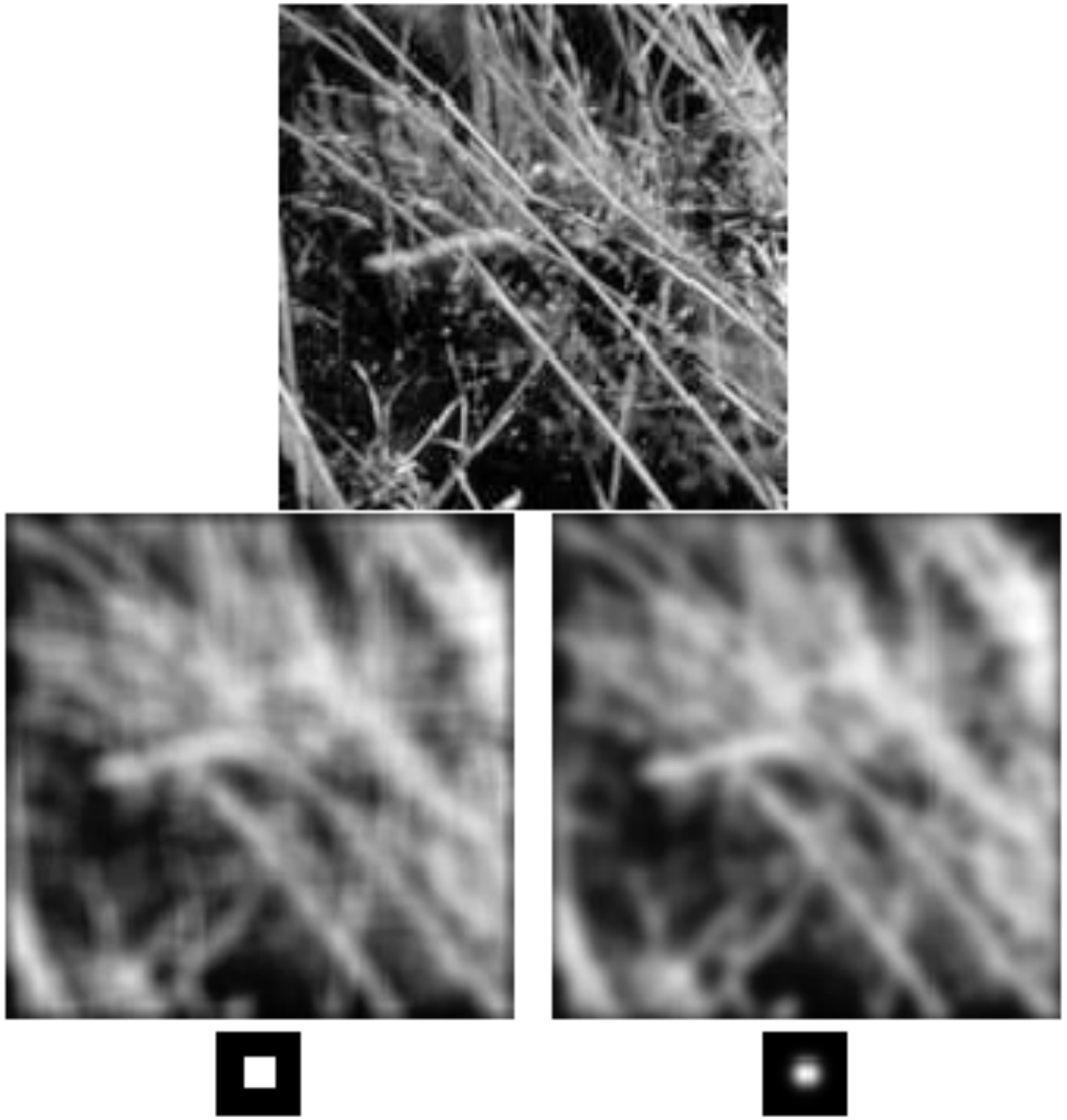


σ = 10 pixels



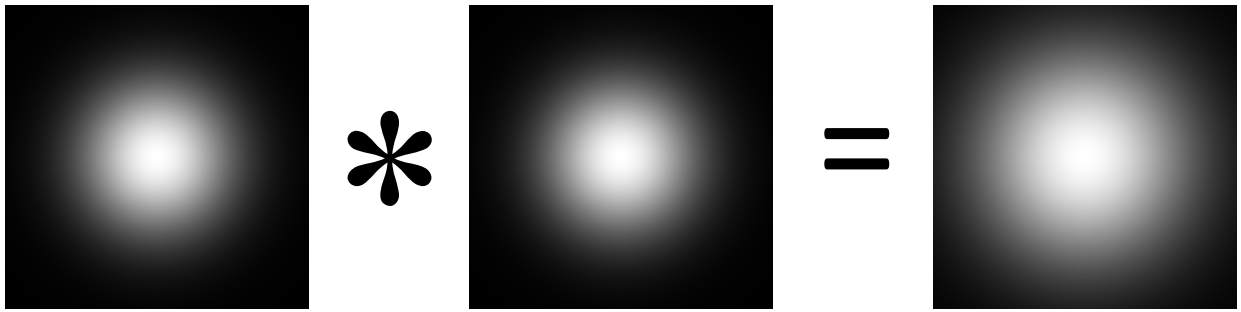
σ = 30 pixels

Mean vs. Gaussian filtering



Gaussian filter

- Removes “high-frequency” components from the image (low-pass filter)
- Convolution with self is another Gaussian



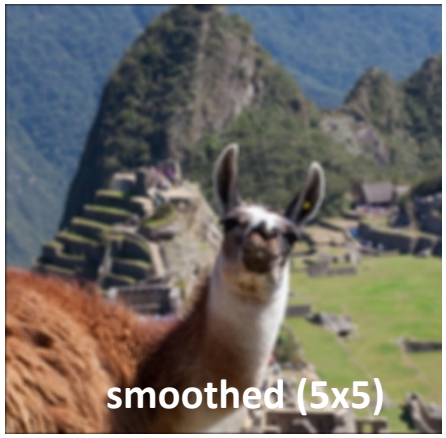
  - Convolving twice with Gaussian kernel of width σ = convolving once with kernel of width $\sigma\sqrt{2}$

Source: K. Grauman

Sharpening revisited

- What does blurring take away?

–



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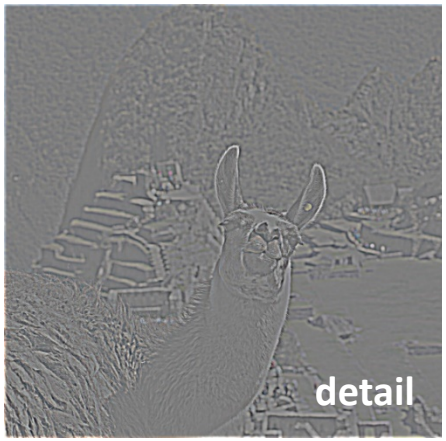

(This "detail extraction" operation is also called a ***high-pass filter***)

Let's add it back:

+ α

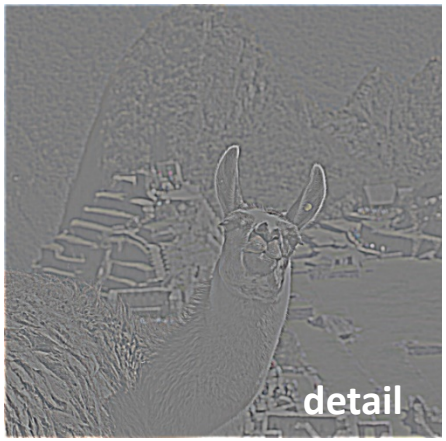

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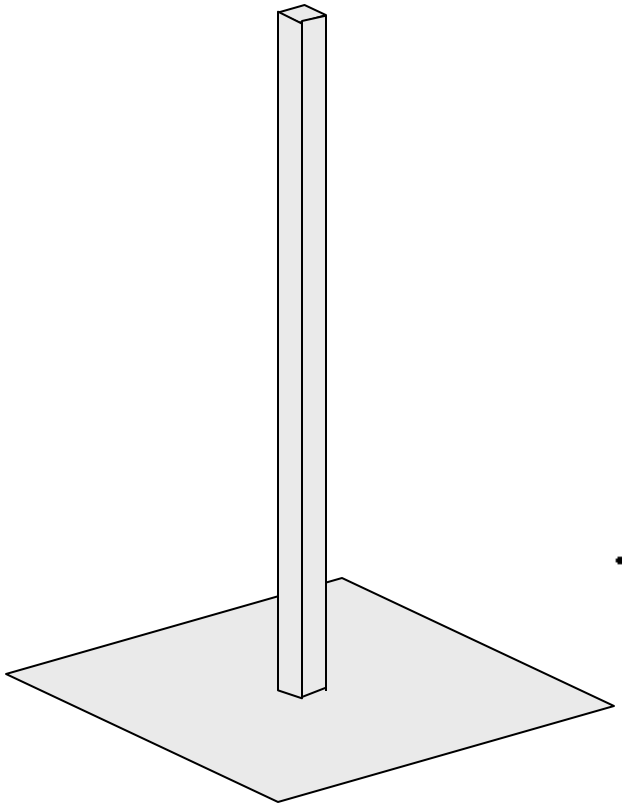
Photo credit: https://www.flickr.com/photos/geezaweezer/16089096376/

Sharpen filter

$$F = \alpha\,(F - \underbrace{F * H}_{\text{blurred image}}) =$$

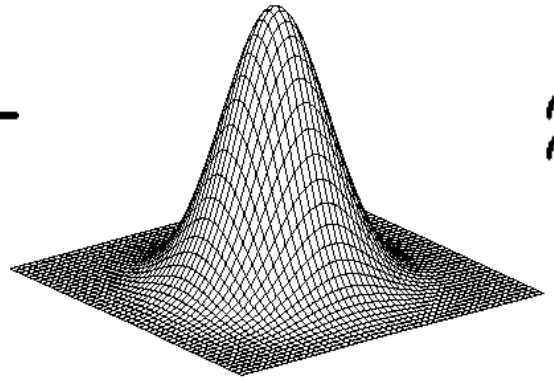
↑ image

↑ unit impulse (identity kernel with single 1 in center, zeros elsewhere)



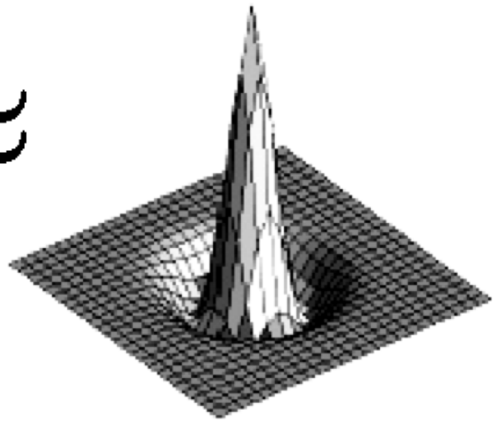
scaled impulse

—



Gaussian

≈



Laplacian of Gaussian

Sharpen filter

“Optical” Convolution

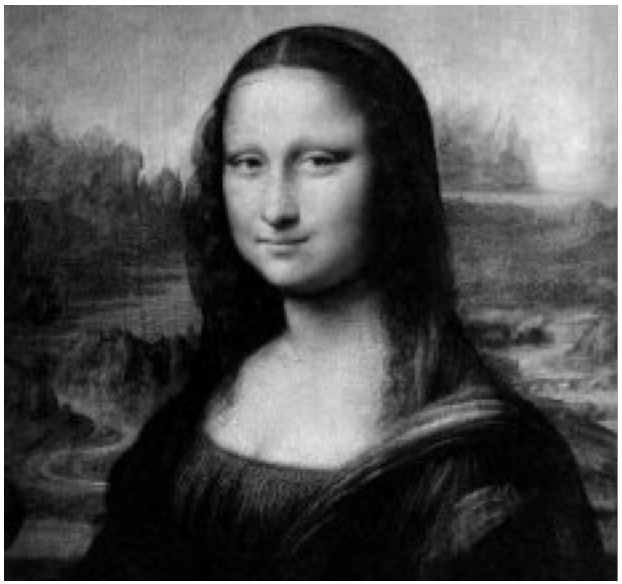
Camera shake

Source: Fergus, *et al.* “Removing Camera Shake from a Single Photograph”, SIGGRAPH 2006

Bokeh: Blur in out-of-focus regions of an image.

Source: http://lullaby.homepage.dk/diy-camera/bokeh.html

Filters: Thresholding



$$g(m,n) = \begin{cases} 255, & f(m,n) > A \\ 0 & otherwise \end{cases}$$

Linear filters

- Is thresholding a linear filter?

Questions?