Filtering

EECS 442 – David Fouhey

Fall 2019, University of Michigan

http://web.eecs.umich.edu/~fouhey/teaching/EECS442_F19/

Note: I'll ask the front row on the right to participate in a demo. All you have to do is say a number that I'll give to you. If you don't want to, it's fine, but don't sit in the front.

Let’s Take An Image

Let's Fix Things

- We have noise in our image
- Let's replace each pixel with a *weighted* average of its neighborhood
- Weights are *filter kernel*

	Out	

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

Slide Credit: D. Lowe

1D Case

Signal/ Front Row	10	12	9	11	10	11	12
Filter/ David	1/3	1/3	1/3				
Output	10.33	10.66	10	10.66	11		

Applying a Linear Filter

Input

I11	I12	I13	I14	I15	I16
I21	I22	I23	I24	I25	I26
I31	I32	I33	I34	I35	I36
I41	I42	I43	I44	I45	I46
I51	I52	I53	I54	I55	I56

Filter

F11	F12	F13
F21	F22	F23
F31	F32	F33

Output

O11	O12	O13	O14
O21	O22	O23	O24
O31	O32	O33	O34

Applying a Linear Filter

Input & Filter

F11	F12	F13	I14	I15	I16
F21	F22	F23	I24	I25	I26
F31	F32	F33	I34	I35	I36
I41	I42	I43	I44	I45	I46
I51	I52	I53	I54	I55	I56

Output

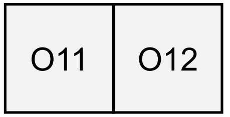
O11

$$O11 = I11*F11 + I12*F12 + \ldots + I33*F33$$

Applying a Linear Filter

Input & Filter

Output



$$O12 = I12*F11 + I13*F12 + \ldots + I34*F33$$

Applying a Linear Filter

Input

I11	I12	I13	I14	I15	I16
I21	I22	I23	I24	I25	I26
I31	I32	I33	I34	I35	I36
I41	I42	I43	I44	I45	I46
I51	I52	I53	I54	I55	I56

Filter

F11	F12	F13
F21	F22	F23
F31	F32	F33

Output

How many times can we apply a 3x3 filter to a 5x6 image?

Applying a Linear Filter

Input

I11	I12	I13	I14	I15	I16
I21	I22	I23	I24	I25	I26
I31	I32	I33	I34	I35	I36
I41	I42	I43	I44	I45	I46
I51	I52	I53	I54	I55	I56

Filter

F11	F12	F13
F21	F22	F23
F31	F32	F33

Output

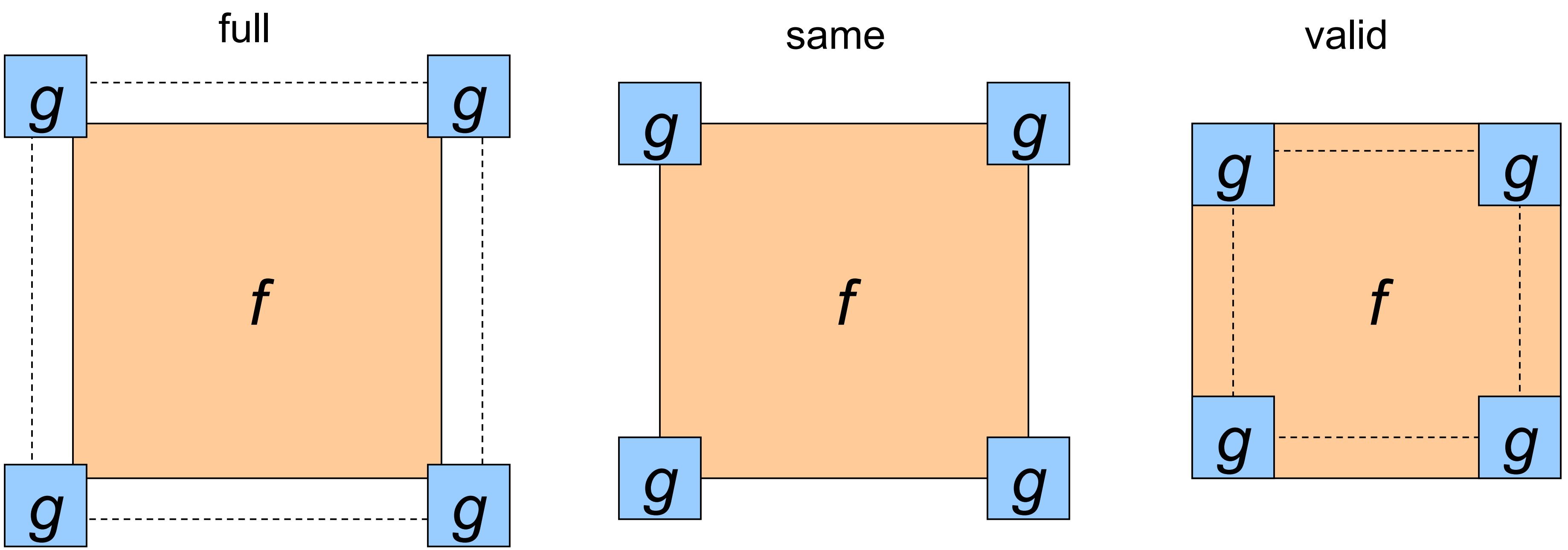
O11	O12	O13	O14
O21	O22	O23	O24
O31	O32	O33	O34

$$Oij = Iij*F11 + Ii(j+1)*F12 + \ldots + I(i+2)(j+2)*F33$$

Painful Details – Edge Cases

Convolution doesn't keep the whole image.
Suppose **f** is the image and **g** the filter.

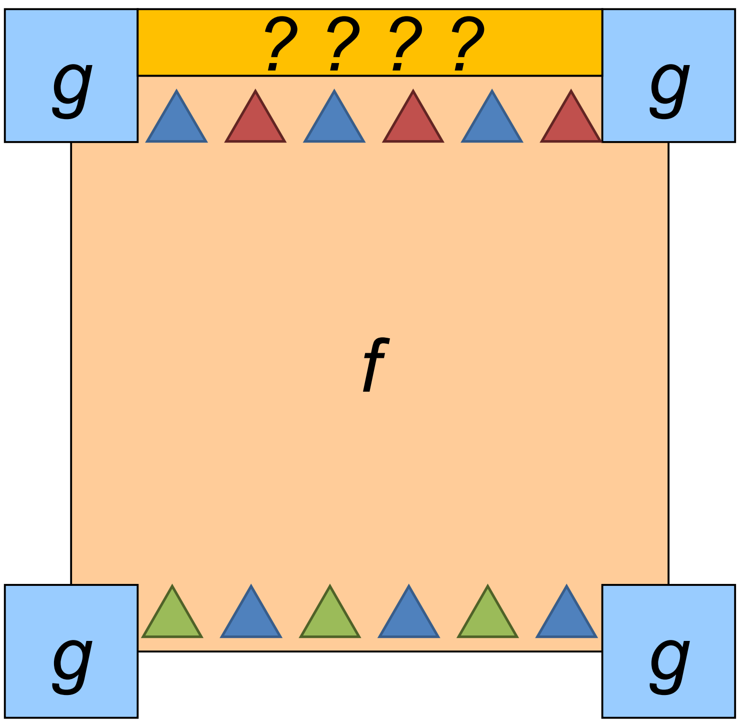
Full – any part of g touches f. **Same** – same size as f;
Valid – only when filter doesn't fall off edge.



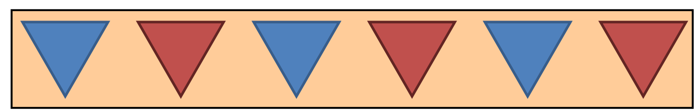
f/g Diagram Credit: D. Lowe

Painful Details – Edge Cases

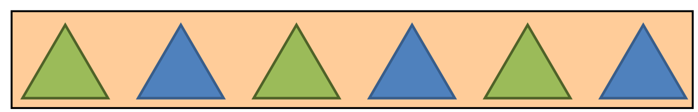
What to about the "?" region?



Symm: fold sides over



Circular/Wrap: wrap around



pad/fill: add value, often 0

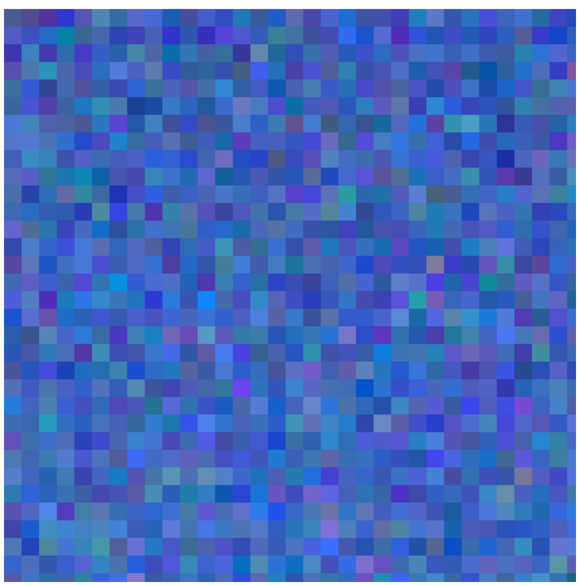
f/g Diagram Credit: D. Lowe

Painful Details – Does it Matter?

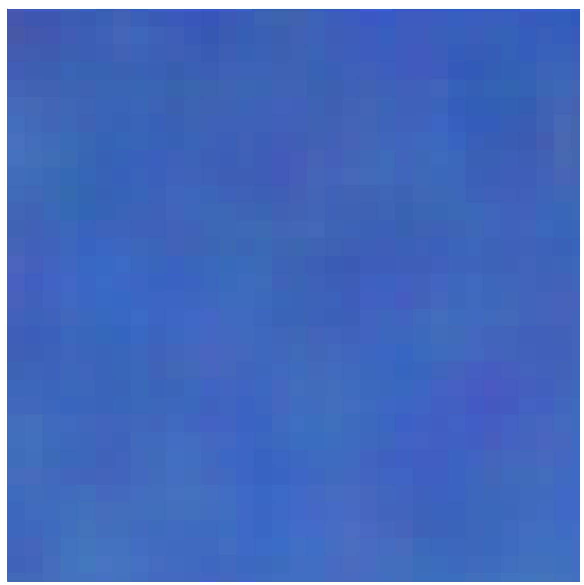
(I've applied the filter per-color channel)

Which padding did I use and *<u>why</u>*?

Input Image



Box Filtered ???

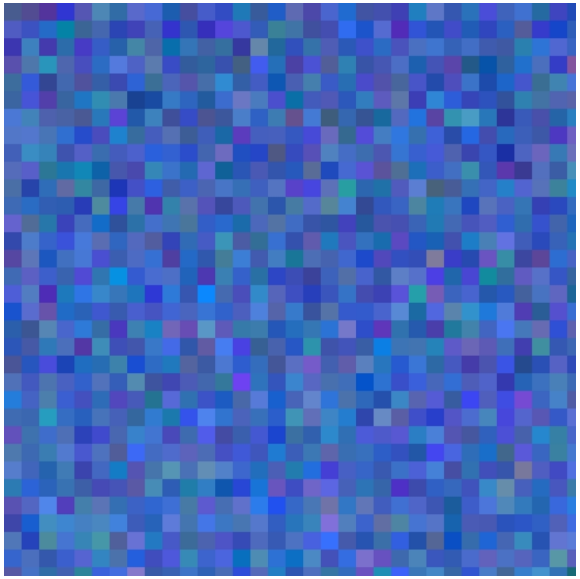
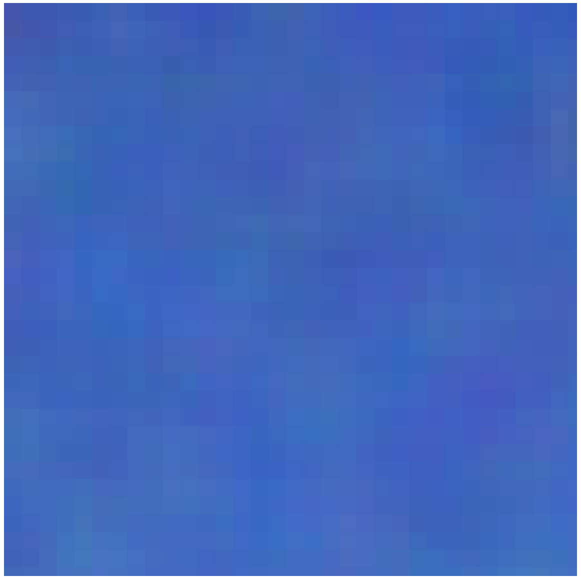
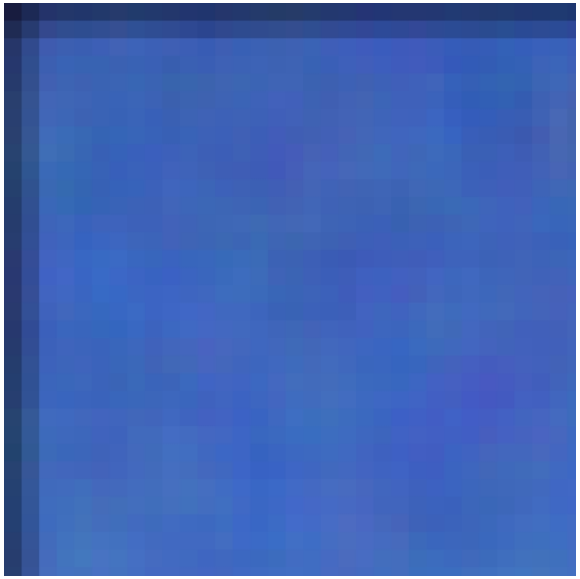


Box Filtered ???

Note – this is a zoom of the filtered, not a filter of the zoomed

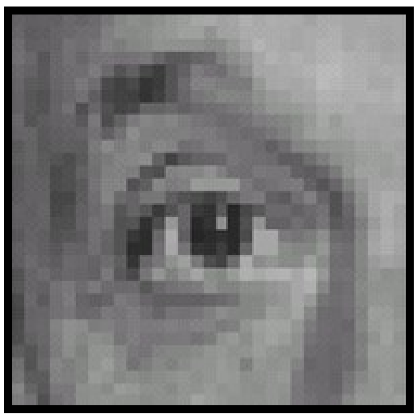
Painful Details – Does it Matter?

(I’ve applied the filter per-color channel)

Input Image	Box Filtered Symm Pad	Box Filtered Zero Pad
		

Note – this is a zoom of the filtered, not a filter of the zoomed

Practice with Linear Filters



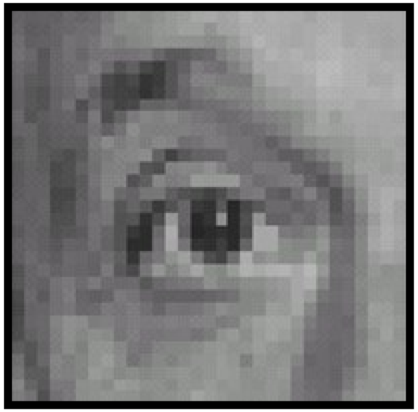
Original

0	0	0
0	1	0
0	0	0

?

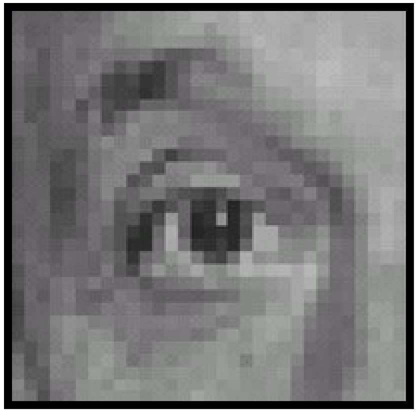
Slide Credit: D. Lowe

Practice with Linear Filters



Original

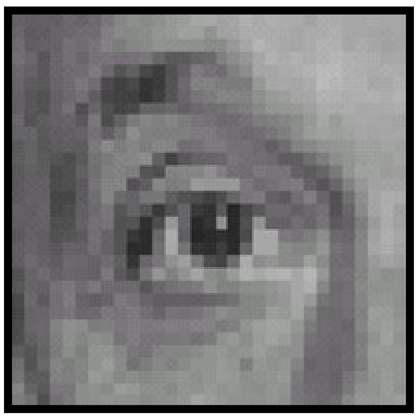
0	0	0
0	1	0
0	0	0



The Same!

Slide Credit: D. Lowe

Practice with Linear Filters



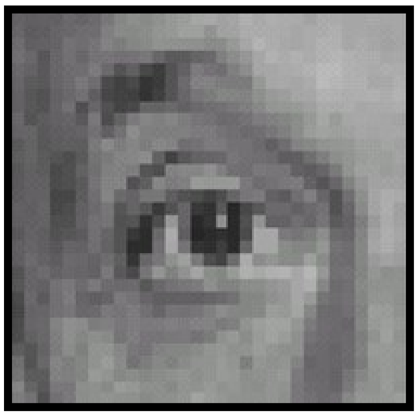
Original

0	0	0
0	0	1
0	0	0

?

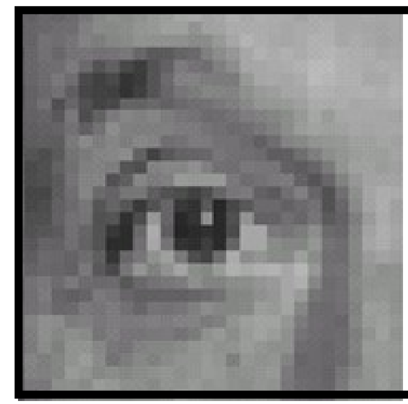
Slide Credit: D. Lowe

Practice with Linear Filters



Original

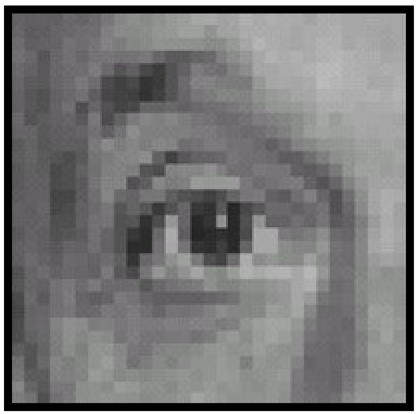
0	0	0
0	0	1
0	0	0



Shifted
<u>LEFT</u>
1 pixel

Slide Credit: D. Lowe

Practice with Linear Filters



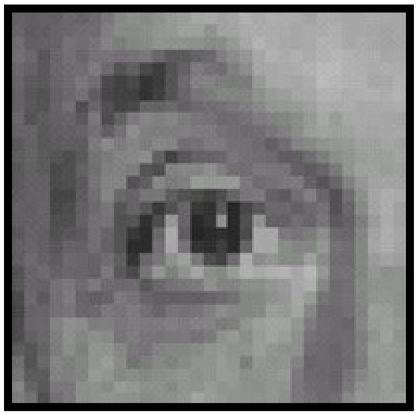
Original

0	1	0
0	0	0
0	0	0

?

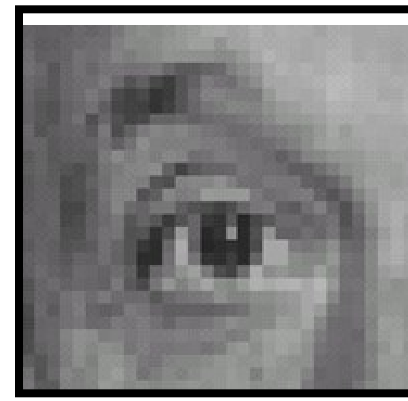
Slide Credit: D. Lowe

Practice with Linear Filters



Original

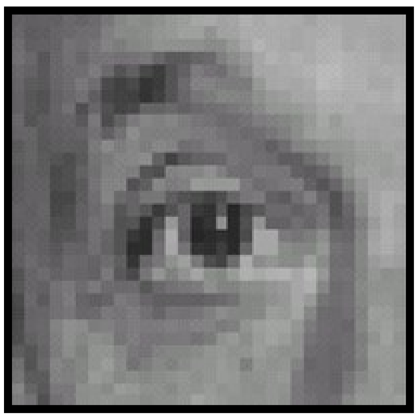
0	1	0
0	0	0
0	0	0



Shifted
DOWN
1 pixel

Slide Credit: D. Lowe

Practice with Linear Filters



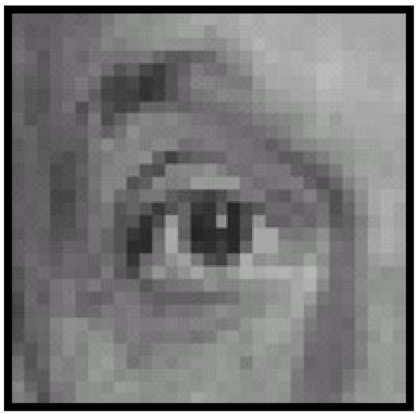
Original

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

?

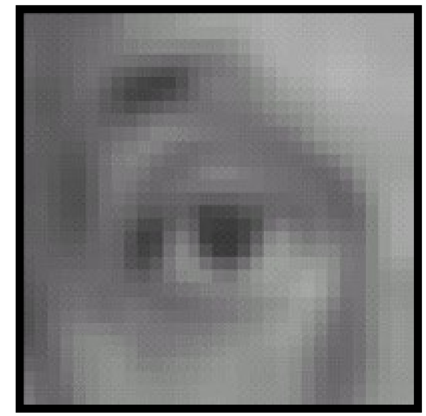
Slide Credit: D. Lowe

Practice with Linear Filters



Original

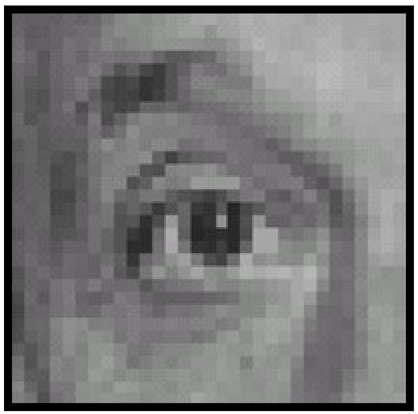
1/9	1/9	1/9
1/9	1/9	1/9
1/9	1/9	1/9



Blur
(Box Filter)

Slide Credit: D. Lowe

Practice with Linear Filters



Original

0	0	0
0	2	0
0	0	0

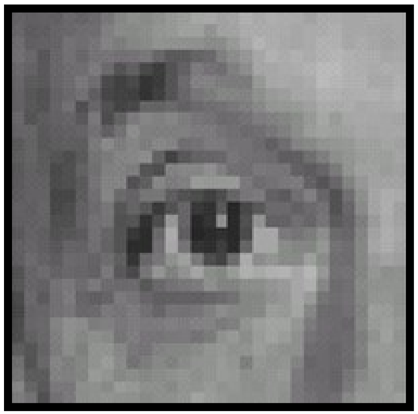
-

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

?

Slide Credit: D. Lowe

Practice with Linear Filters

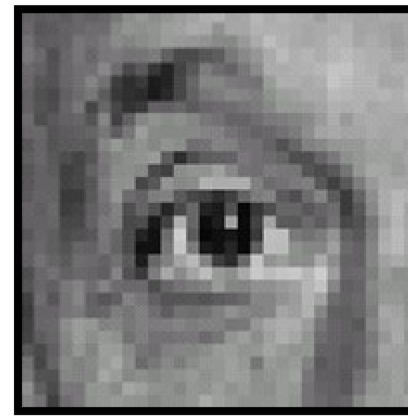


Original

0	0	0
0	2	0
0	0	0

-

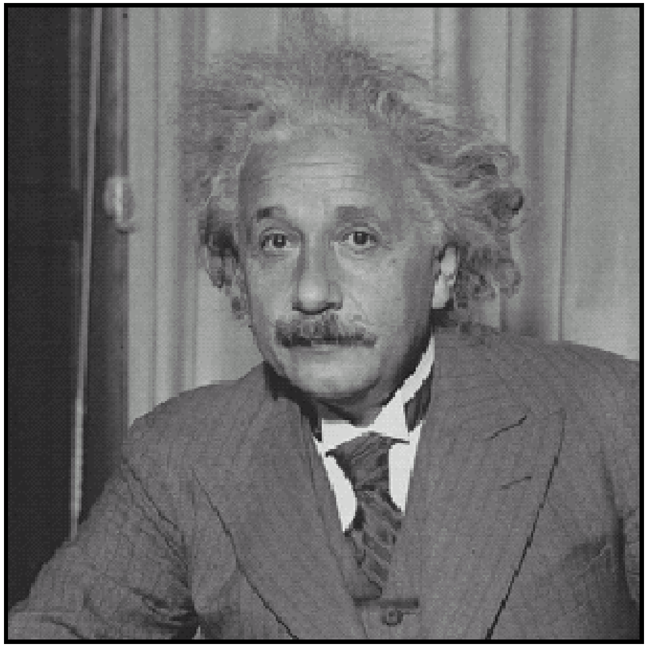
1/9	1/9	1/9
1/9	1/9	1/9
1/9	1/9	1/9



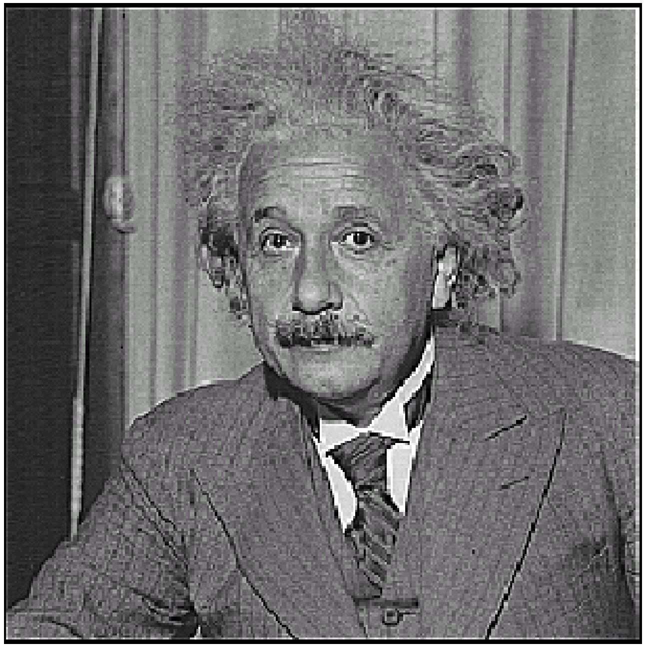
Sharpened
(Acccentuates difference from local average)

Slide Credit: D. Lowe

Sharpening



before



after

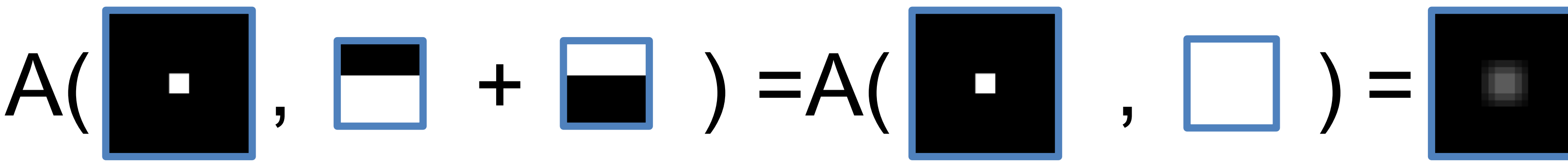
Slide Credit: D. Lowe

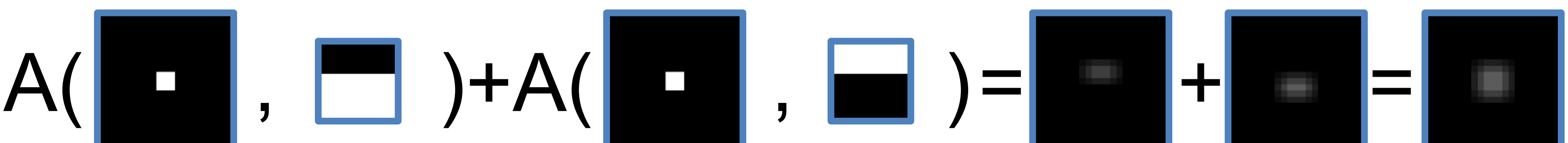
Properties – Linear

Assume: I image f1, f2 filters

Linear: apply(I,f1+f2) = apply(I,f1) + apply(I,f2)

I is a box on black, and f1, f2 are rectangles





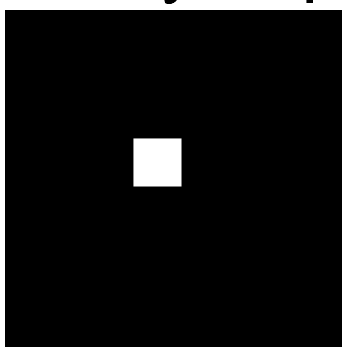
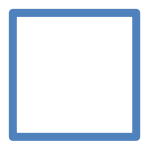
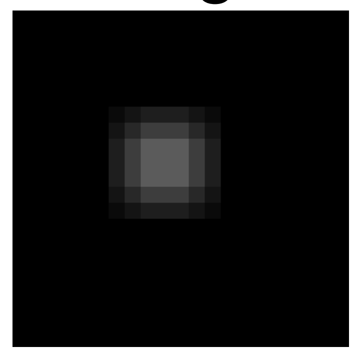
Note: I am showing filters un-normalized and blown up. They’re a smaller box filter (i.e., each entry is 1/(size^2))

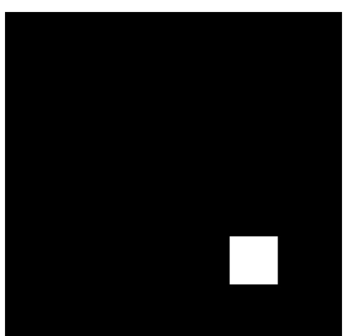
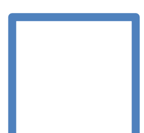
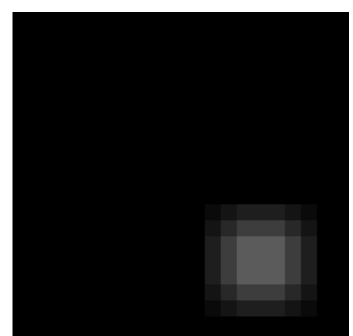
Properties – Shift-Invariant

Assume: I image, f filter

Shift-invariant: shift(apply(I,f)) = apply(shift(I,f))

Intuitively: only depends on filter neighborhood

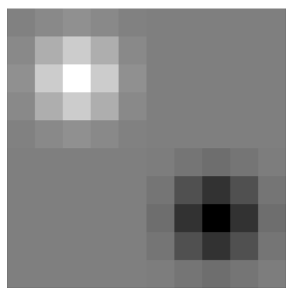
A( , ) = 

A( , ) = 

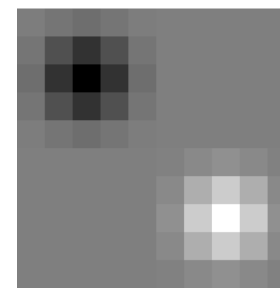
Painful Details – Signal Processing

Often called “convolution”. *Actually* cross-correlation.

Cross-Correlation
(Original Orientation)

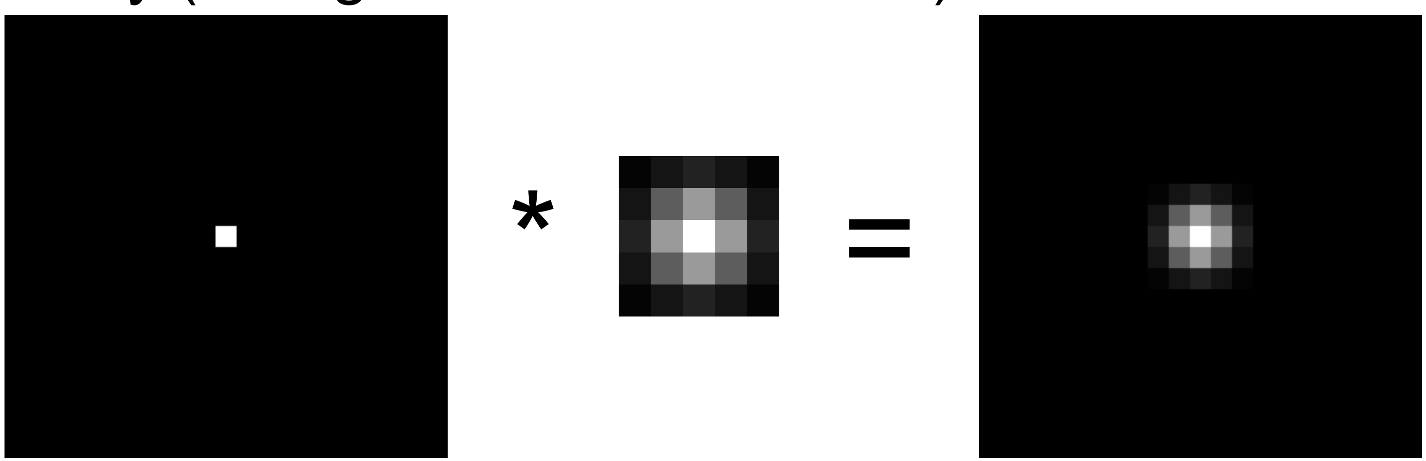


Convolution
(Flipped in x and y)



Properties of Convolution

- Any shift-invariant, linear operation is a convolution
- Commutative: $f * g = g * f$
- Associative: $(f * g) * h = f * (g * h)$
- Distributes over +: $f * (g + h) = f * g + f * h$
- Scalars factor out: $kf * g = f * kg = k (f * g)$
- Identity (a single one with all zeros):



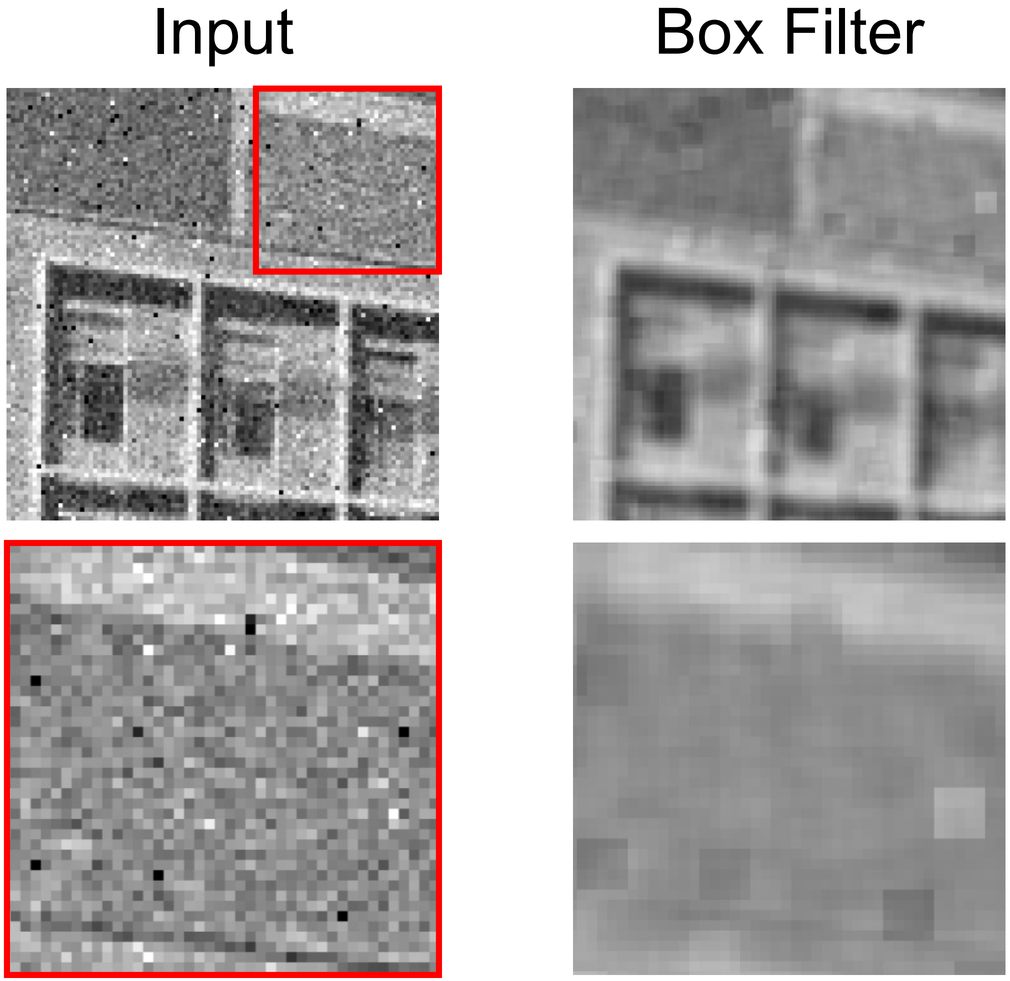
Property List: K. Grauman

Questions?

- Nearly everything onwards is a convolution.
- This is important to get right.

Smoothing With A Box

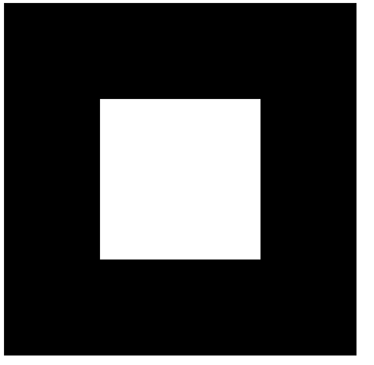
Intuition: if filter touches it, it gets a contribution.



Solution – Weighted Combination

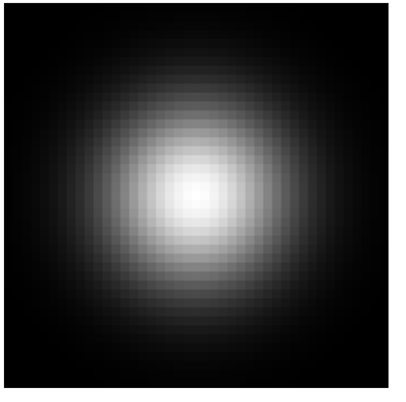
Intuition: weight contributions according to closeness to center.

$$Filter_{ij} \propto 1$$



What's this?

$$Filter_{ij} \propto \exp\left(-\frac{x^2+y^2}{2\sigma^2}\right)$$

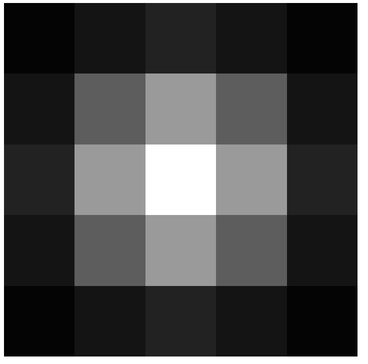


Recognize the Filter?

It's a Gaussian!

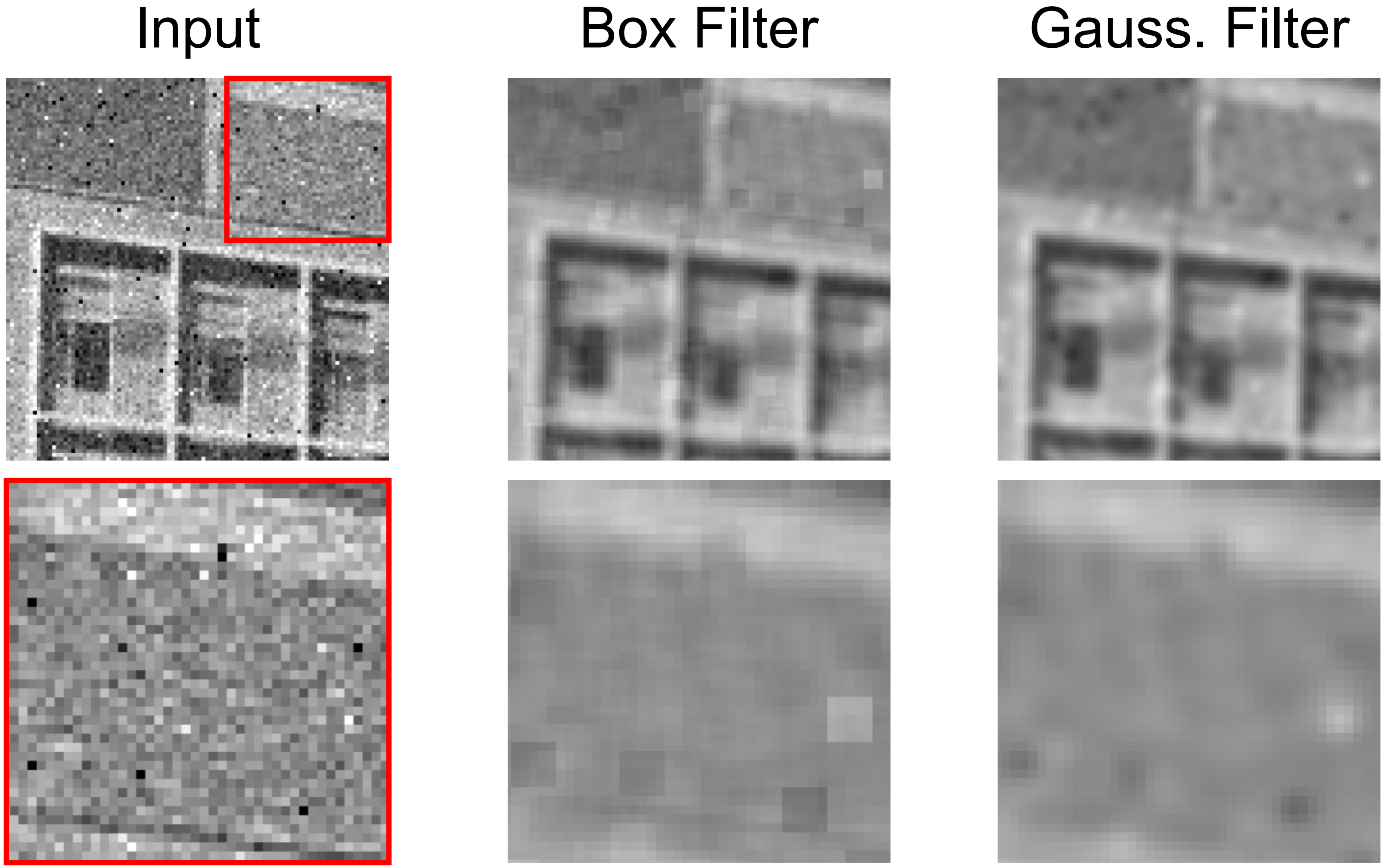
$$Filter_{ij} \propto \frac{1}{2\pi\sigma^2}\exp\left(-\frac{x^2+y^2}{2\sigma^2}\right)$$

$$\begin{bmatrix} 0.003 & 0.013 & 0.022 & 0.013 & 0.003 \\ 0.013 & 0.060 & 0.098 & 0.060 & 0.013 \\ 0.022 & 0.098 & 0.162 & 0.098 & 0.022 \\ 0.013 & 0.060 & 0.098 & 0.060 & 0.013 \\ 0.003 & 0.013 & 0.022 & 0.013 & 0.003 \end{bmatrix}$$



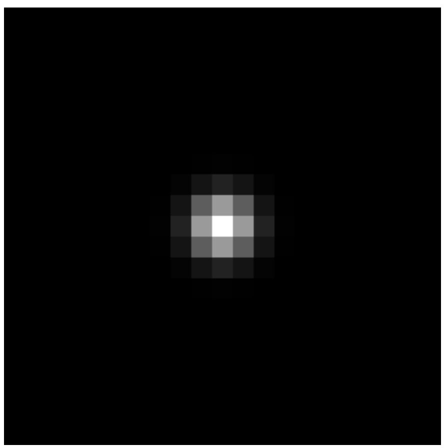
Smoothing With A Box & Gauss

Still have some speckles, but it's not a big box

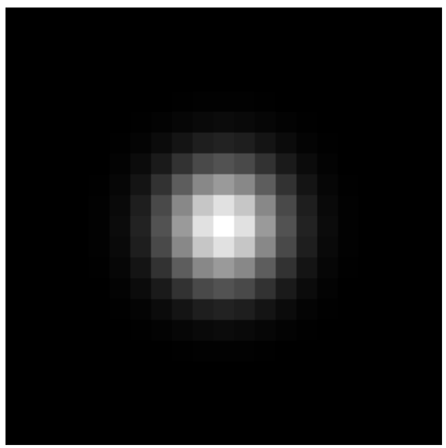


Gaussian Filters

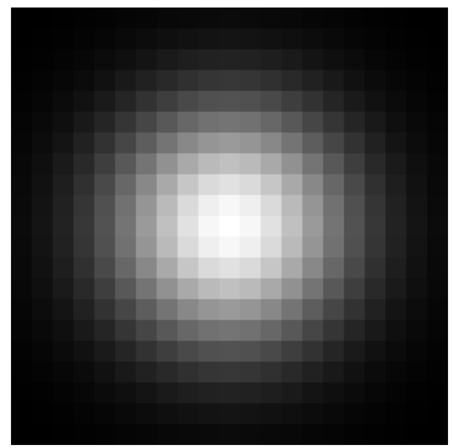
$\sigma = 1$
filter = 21x21



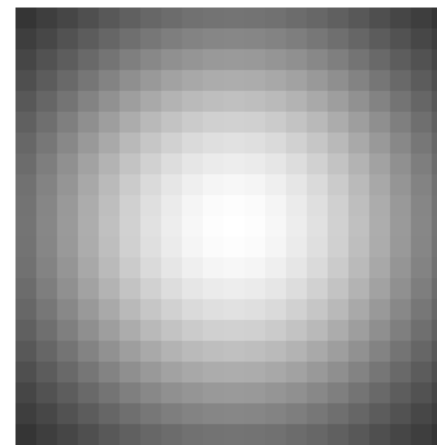
$\sigma = 2$
filter = 21x21



$\sigma = 4$
filter = 21x21

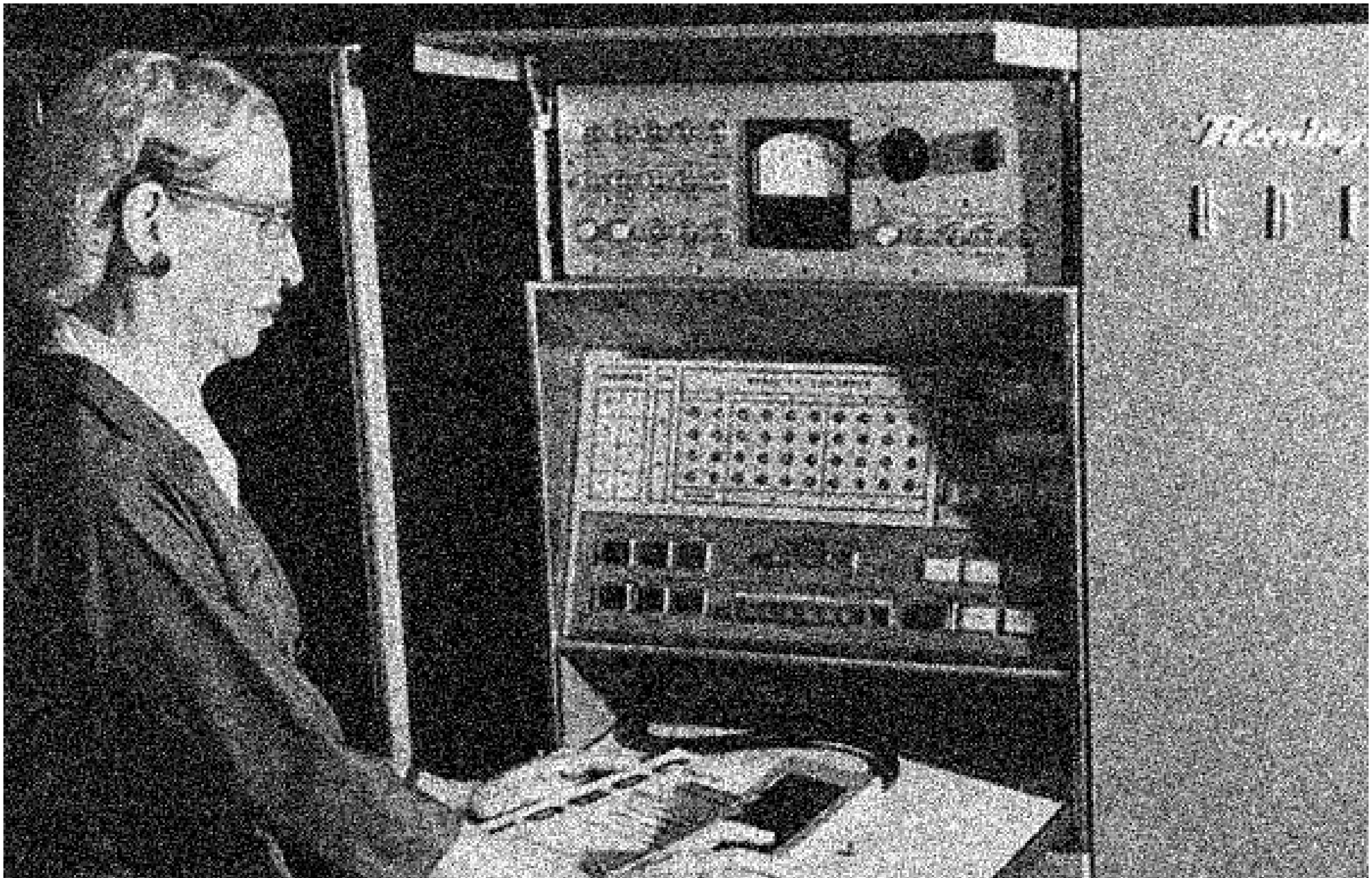


$\sigma = 8$
filter = 21x21



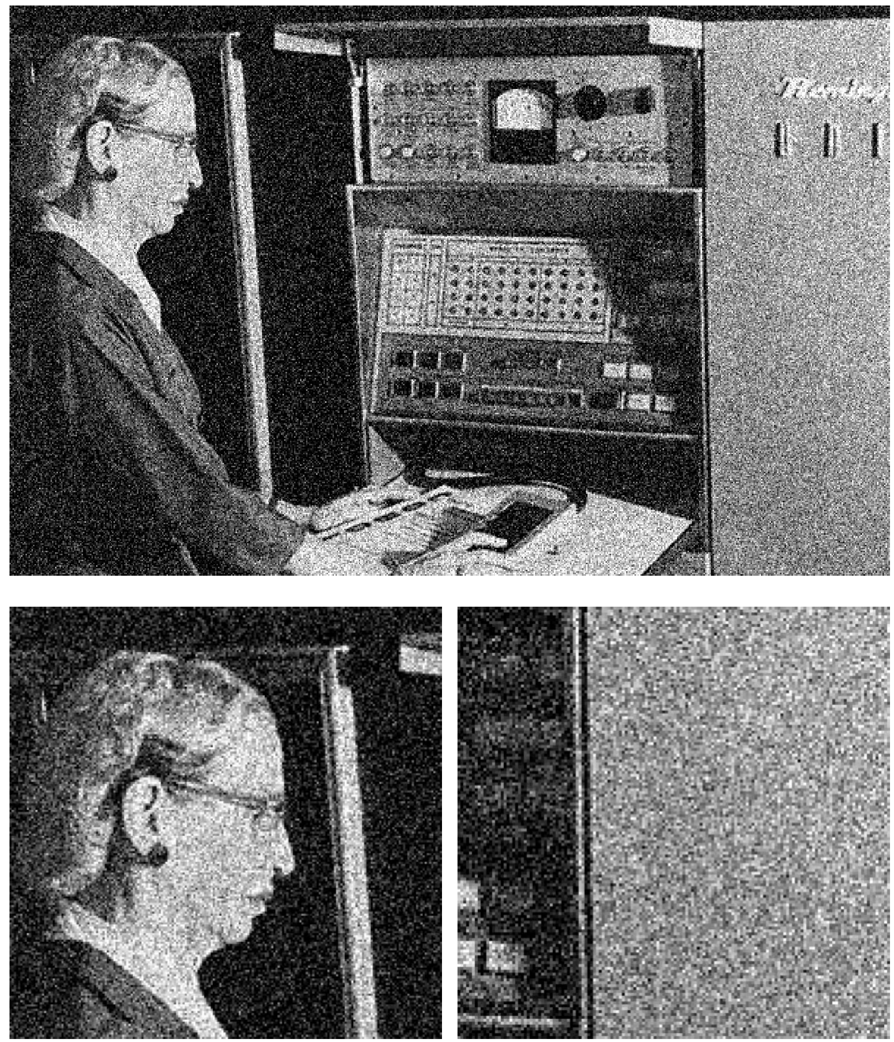
Note: filter visualizations are independently normalized throughout the slides so you can see them better

Applying Gaussian Filters



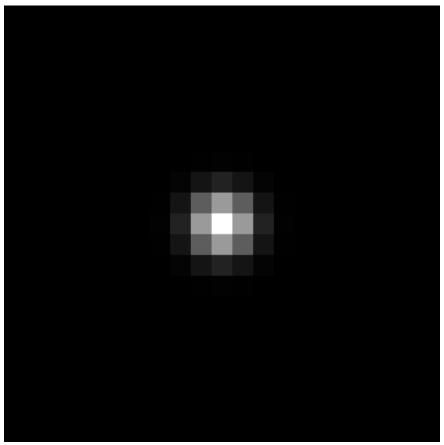
Applying Gaussian Filters

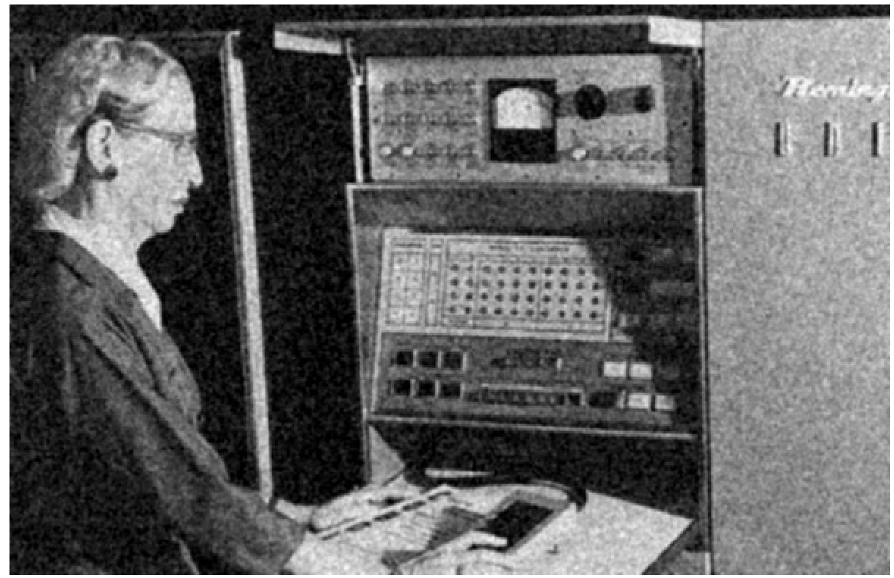
Input Image
(no filter)

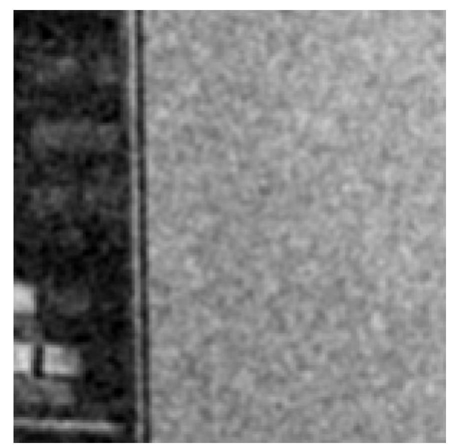


Applying Gaussian Filters

$\sigma = 1$

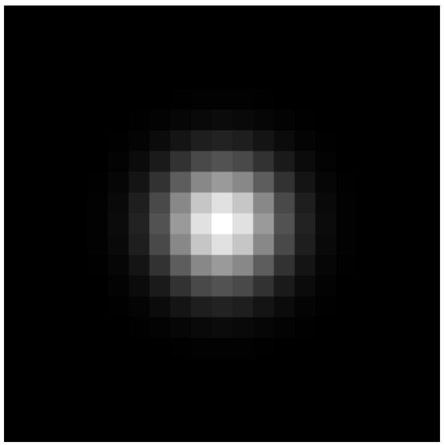


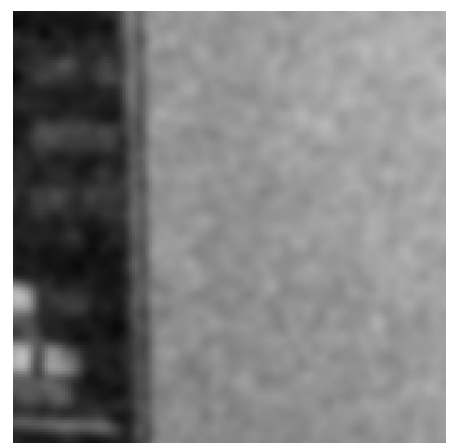




Applying Gaussian Filters

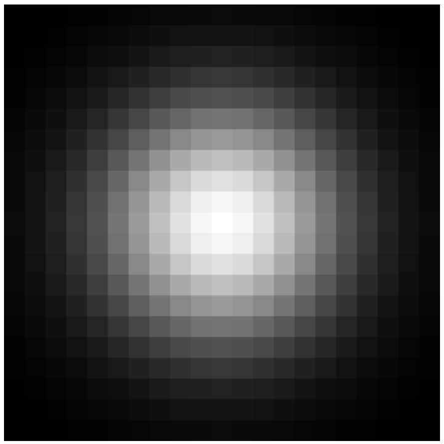
$\sigma = 2$





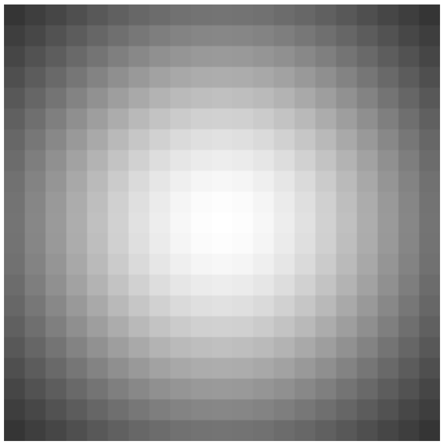
Applying Gaussian Filters

σ = 4



Applying Gaussian Filters

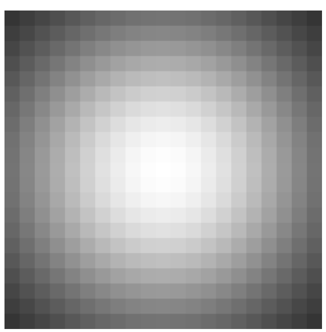
$\sigma = 8$



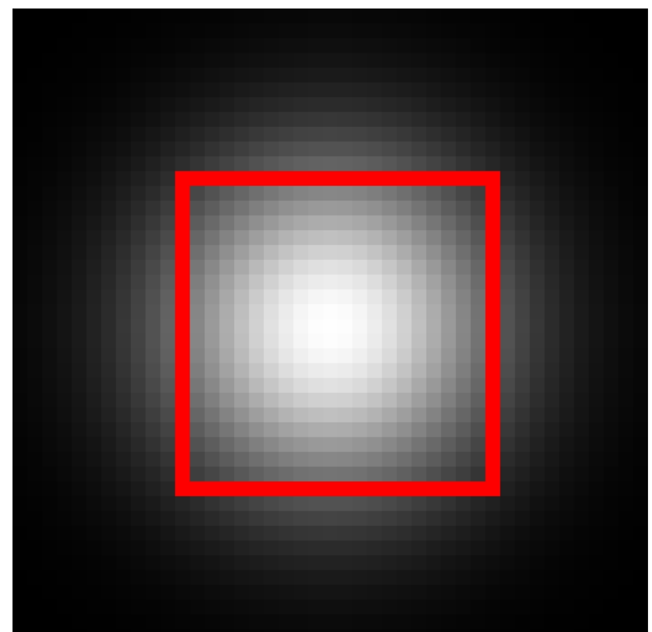
Picking a Filter Size

Too small filter → bad approximation
Want size ≈ 6σ (99.7% of energy)
Left far too small; right slightly too small!

σ = 8, size = 21



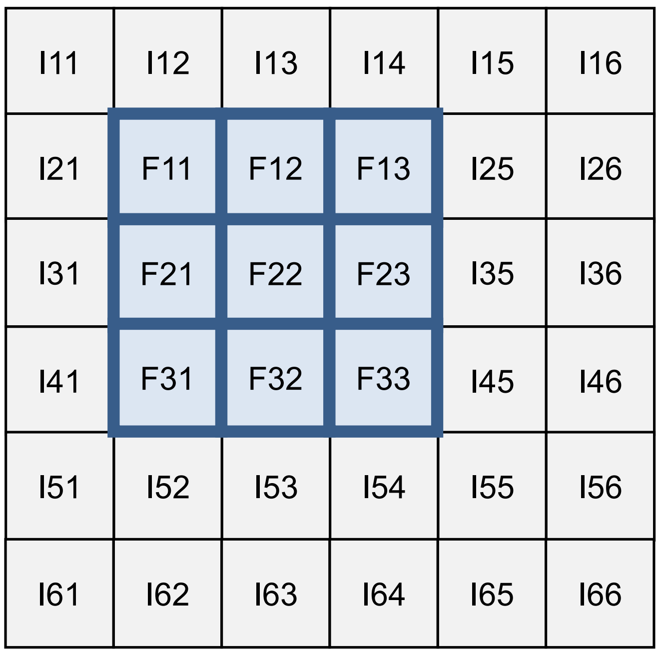
σ = 8, size = 43



Runtime Complexity

Image size = NxN = 6x6

Filter size = MxM = 3x3




```
for ImageY in range(N):
    for ImageX in range(N):
        for FilterY in range(M):
            for FilterX in range(M):
                ...
```

Time: $O(N^2M^2)$

Separability

Conv(vector, transposed vector) → outer product

$$\begin{bmatrix} Fy1 \\ Fy2 \\ Fy3 \end{bmatrix} * \begin{bmatrix} Fx1 & Fx2 & Fx3 \end{bmatrix} = \begin{bmatrix} Fx1 * Fy1 & Fx2 * Fy1 & Fx3 * Fy1 \\ Fx1 * Fy2 & Fx2 * Fy2 & Fx3 * Fy2 \\ Fx1 * Fy3 & Fx2 * Fy3 & Fx3 * Fy3 \end{bmatrix}$$

Separability

$$Filter_{ij} \propto \frac{1}{2\pi\sigma^2} \exp\left(-\frac{x^2 + y^2}{2\sigma^2}\right)$$

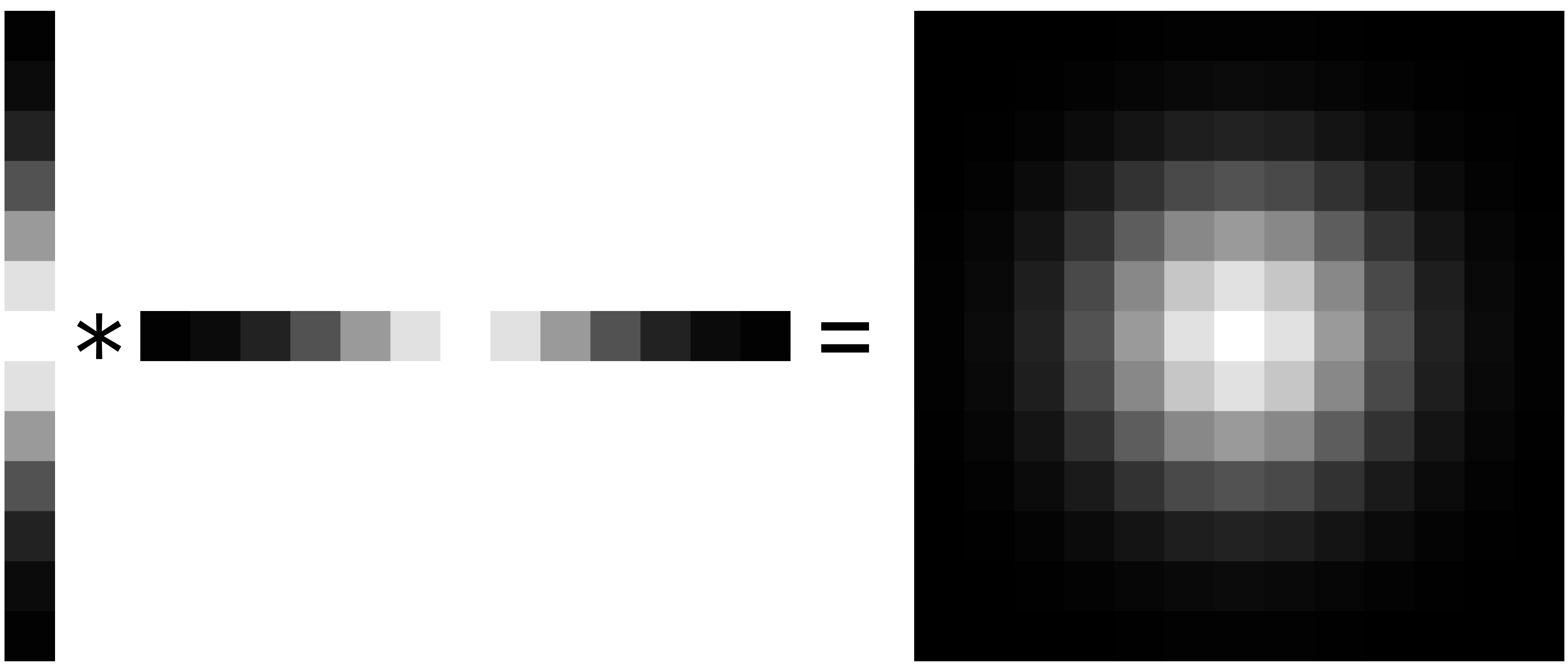
$$\rightarrow$$

$$Filter_{ij} \propto \frac{1}{\sqrt{2\pi}\sigma} \exp\left(-\frac{x^2}{2\sigma^2}\right) \frac{1}{\sqrt{2\pi}\sigma} \exp\left(-\frac{y^2}{2\sigma^2}\right)$$

Separability

$$\text{1D Gaussian} \ast \text{1D Gaussian} = \text{2D Gaussian}$$

$$\text{Image} \ast \text{2D Gauss} = \text{Image} \ast (\text{1D Gauss} \ast \text{1D Gauss})$$
$$= (\text{Image} \ast \text{1D Gauss}) \ast \text{1D Gauss}$$



Runtime Complexity

Image size = NxN = 6x6

Filter size = Mx1 = 3x1

I11	I12	I13	I14	I15	I16
I21	F1	I23	I24	I25	I26
I31	F2	I33	I34	I35	I36
I41	F3	I43	I44	I45	I46
I51	I52	I53	I54	I55	I56
I61	I62	I63	I64	I65	I66

What are my compute savings for a 13x13 filter?

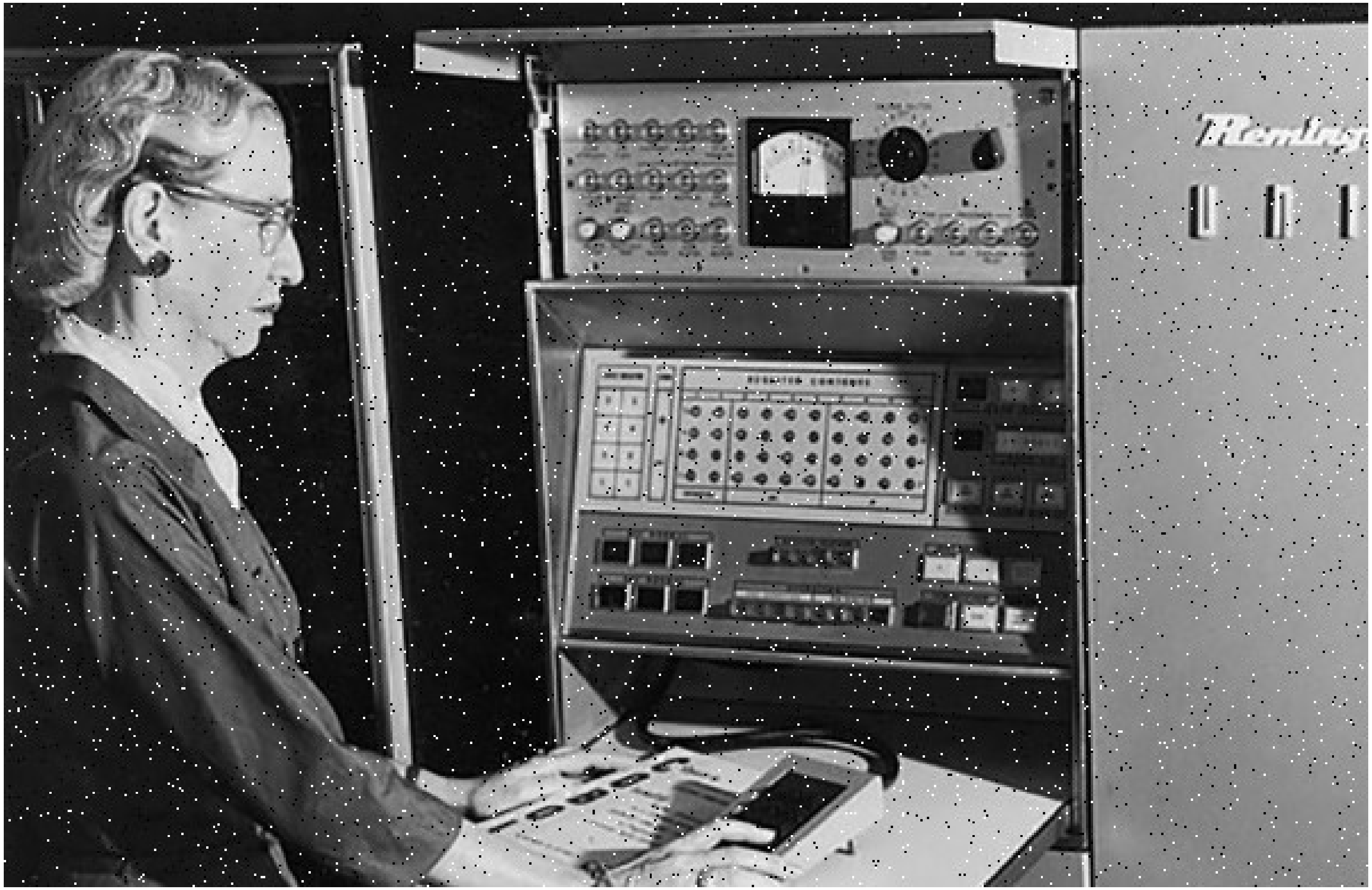
```
for ImageY in range(N):
    for ImageX in range(N):
        for FilterY in range(M):
                 …
for ImageY in range(N):
    for ImageX in range(N):
        for FilterX in range(M):

                 …
```

Time: $O(N^2M)$

Why Gaussian?

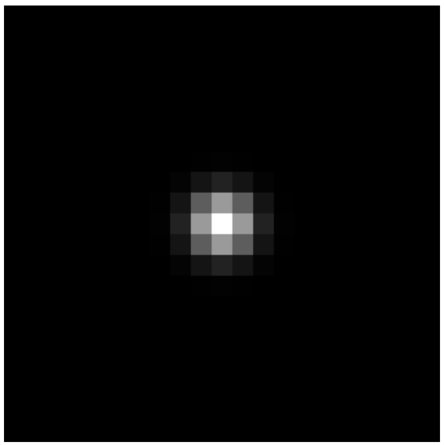
Gaussian filtering removes parts of the signal above a certain frequency. Often noise is high frequency and signal is low frequency.

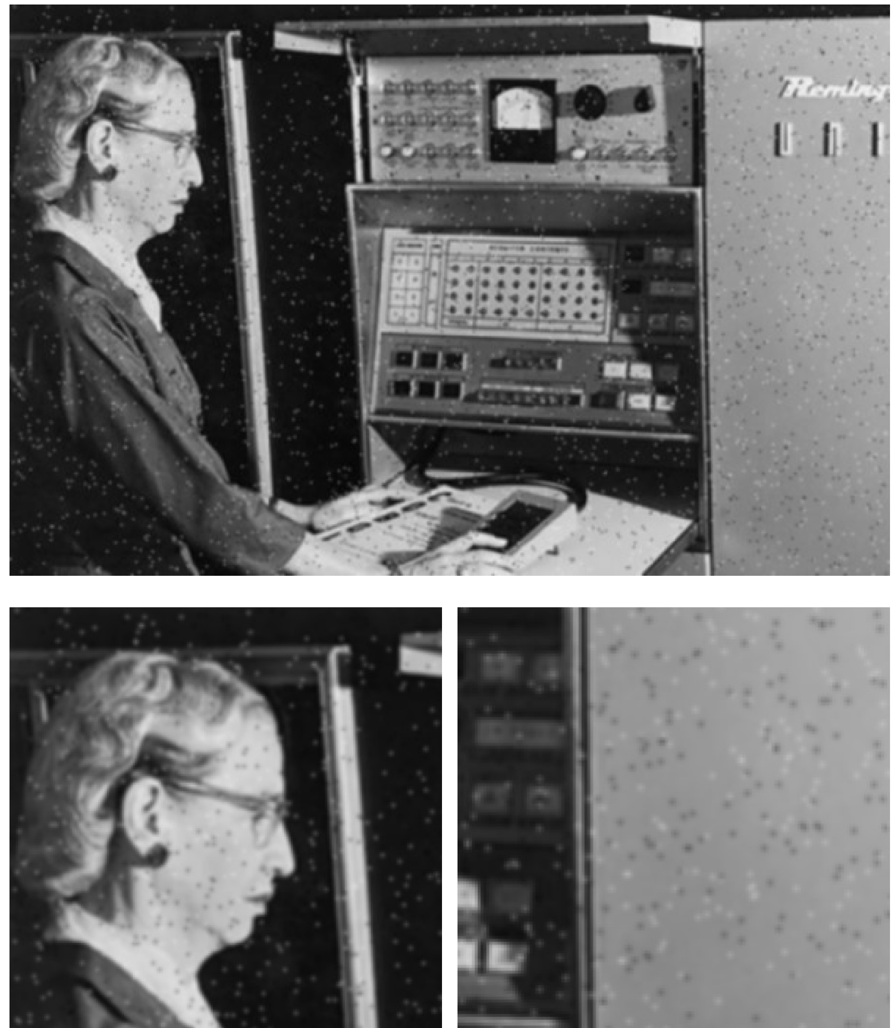
Where Gaussian Fails



Applying Gaussian Filters

$\sigma = 1$





Why Does This Fail?

Means can be arbitrarily distorted by outliers

Signal	10	12	9	8	1000	11	10	12
Filter	0.1	0.8	0.1					
Output	11.5	9.2	107.3	801.9	109.8	10.3		

What else is an "average" other than a mean?

Non-linear Filters (2D)

40	81	13	22
125	830	76	80
144	92	108	95
132	102	106	87

[040, 081, 013, 125, 830, 076, 144, 092, 108]

↓ Sort ↓

[013, 040, 076, 081, 092, 108, 125, 144, 830]

↓

92

[830, 076, 080, 092, 108, 095, 102, 106, 087]

↓ Sort ↓

[076, 080, 087, 092, 095, 102, 106, 108, 830]

↓

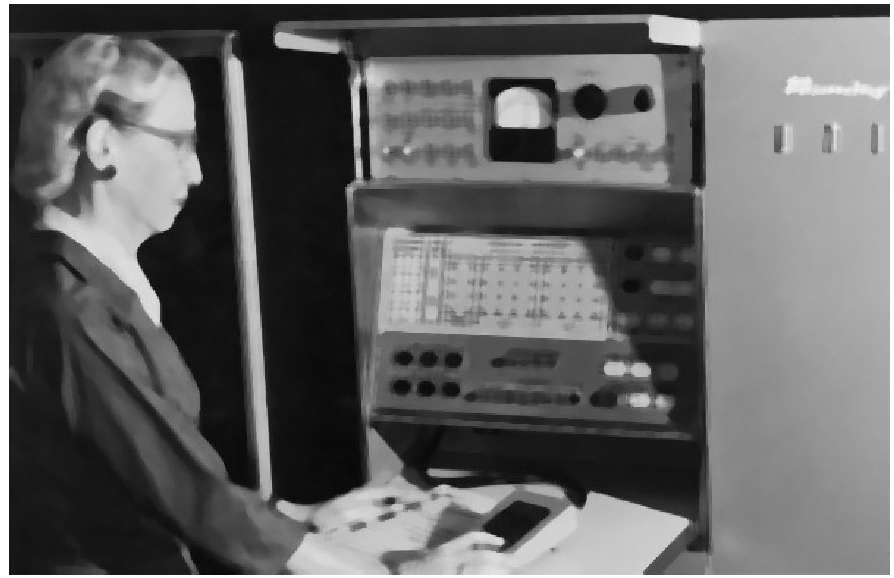
95

Applying Median Filter

Median
Filter
(size=3)

Applying Median Filter

Median
Filter
(size = 7)



Is Median Filtering Linear?

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

Median Filter

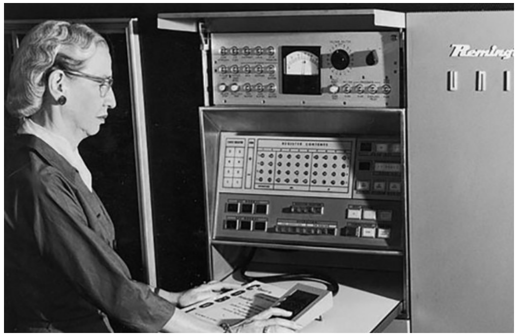
$$1 + 0 = 2$$

Example from (I believe): Kristen Grauman

Some Examples of Filtering

Filtering – Sharpening

Image

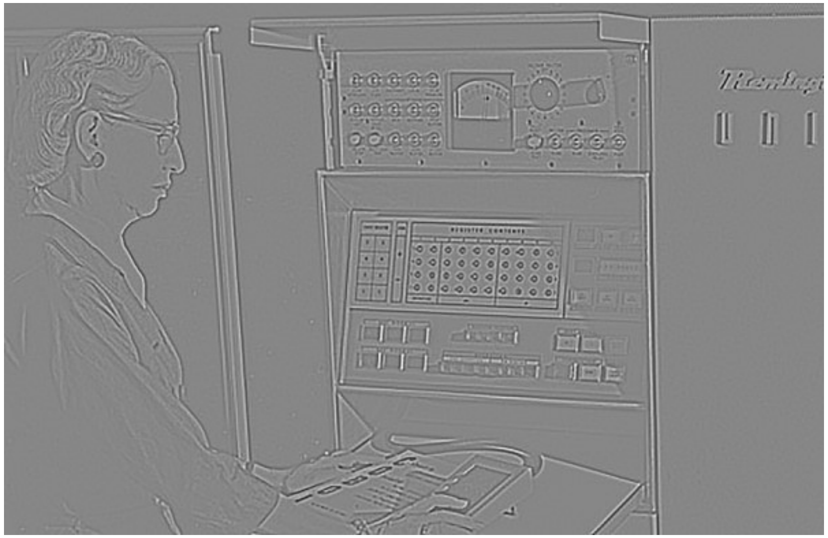


\-

Smoothed

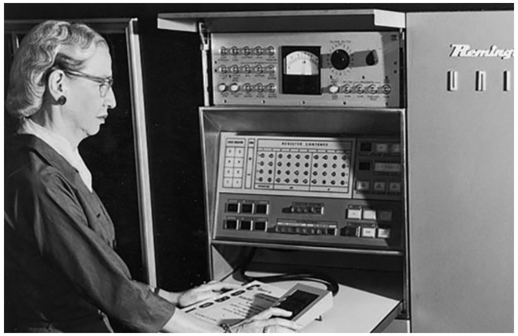
Details

=



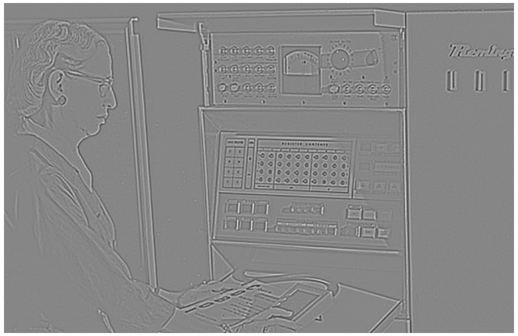
Filtering – Sharpening

Image



$+\alpha$

Details

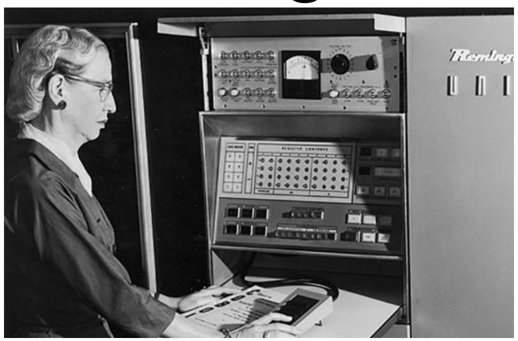


"Sharpened" α=1

=

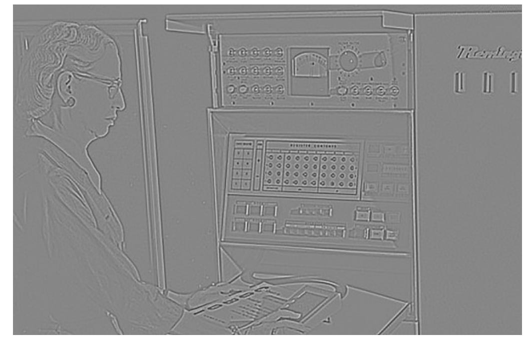
Filtering – Sharpening

Image



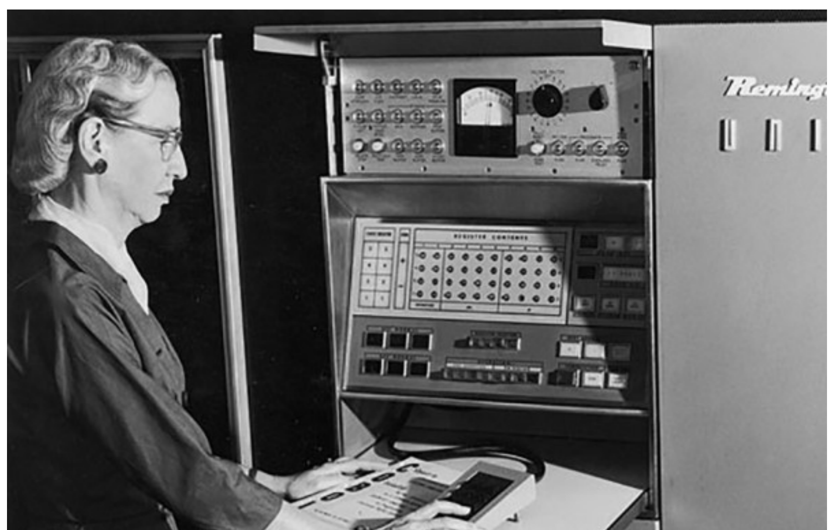
+α

Details



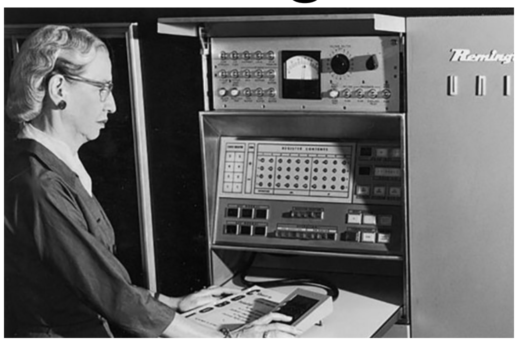
“Sharpened” α=0

=



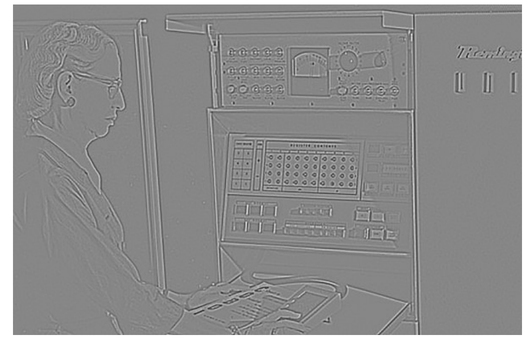
Filtering – Sharpening

Image



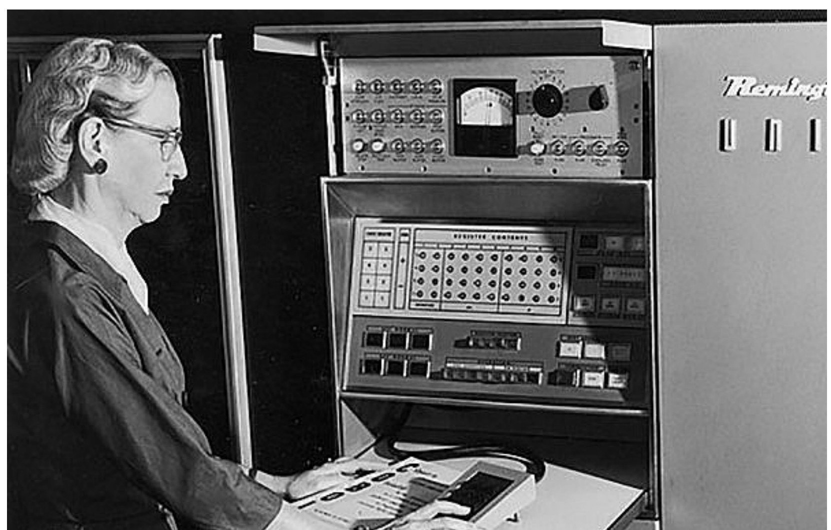
$+\alpha$

Details



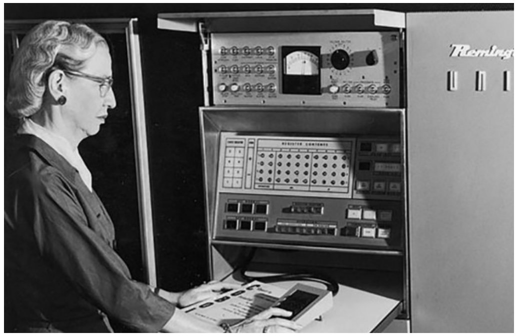
"Sharpened" $\alpha=2$

$=$



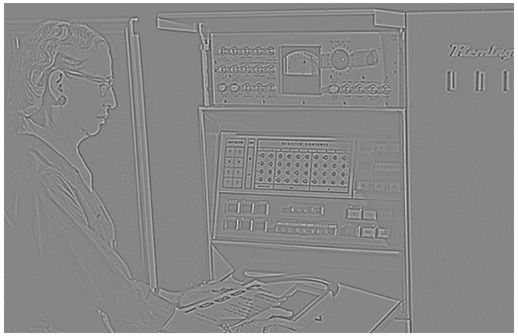
Filtering – Sharpening

Image



+α

Details

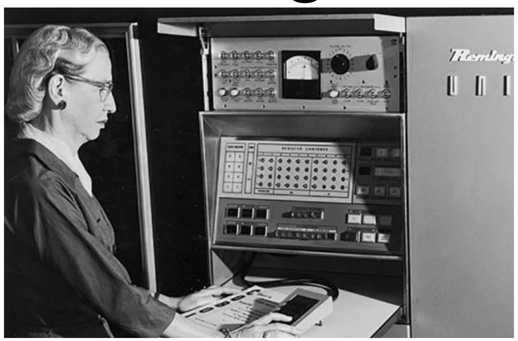


"Sharpened" α=0

=

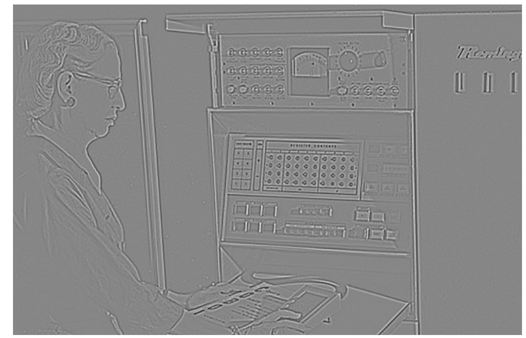
Filtering – Extreme Sharpening

Image



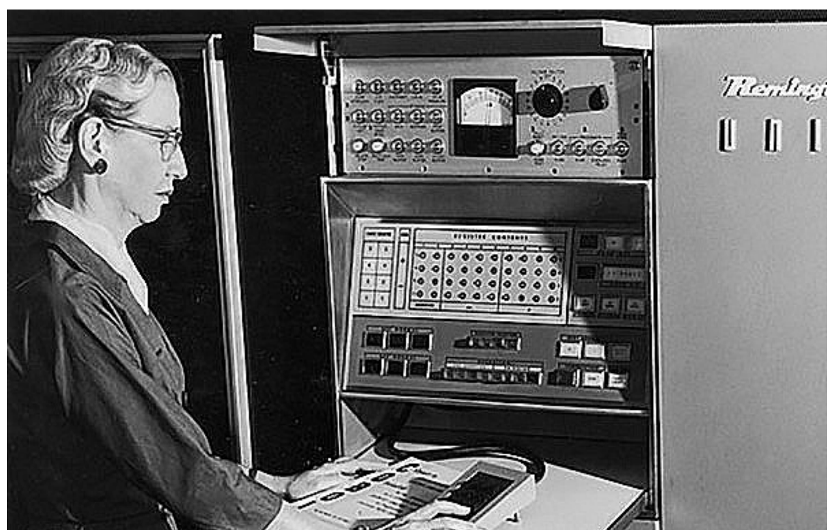
+α

Details



“Sharpened” α=10

=



Filtering

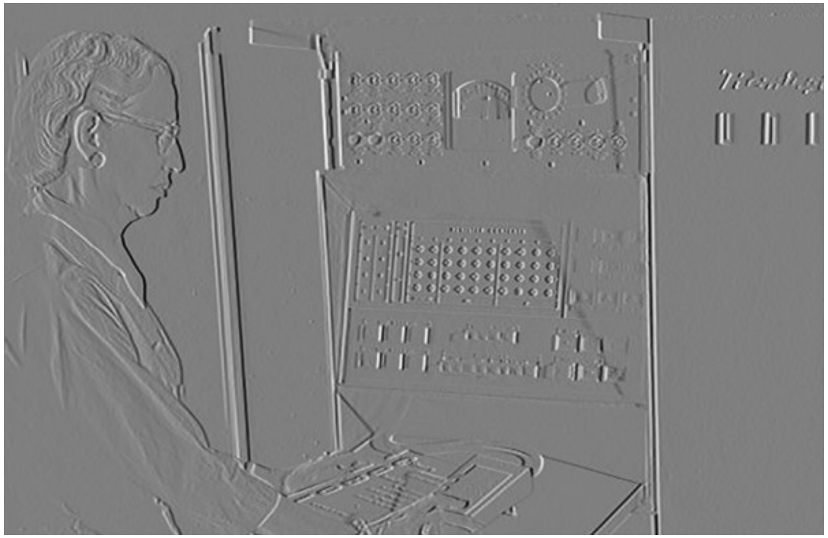
What's this Filter?

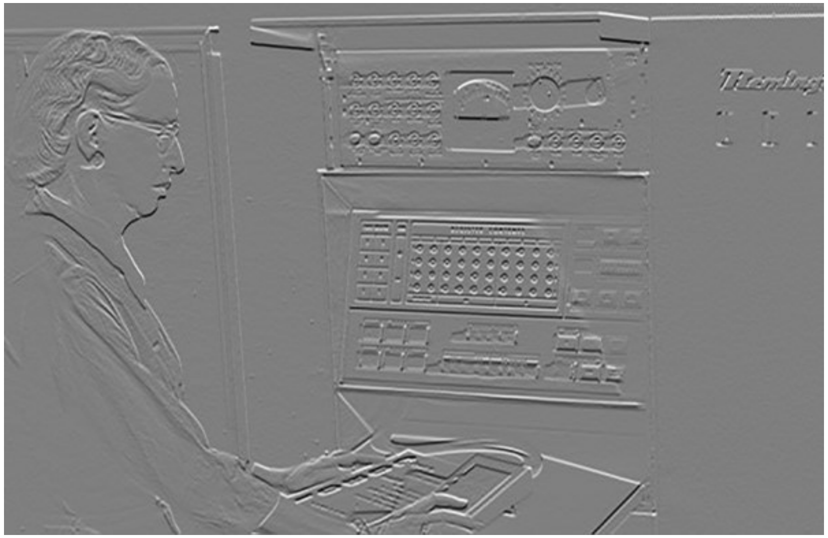
-1	0	1

Dx

$$\begin{bmatrix} -1 & 0 & 1 \end{bmatrix}^T$$

Dy





Filtering – Derivatives

$(Dx^2 + Dy^2)^{1/2}$

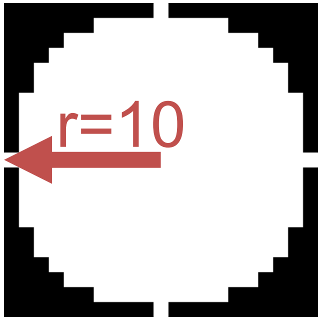
Filtering – Counting

How many “on” pixels have
10+ neighbors within 10 pixels?

Pixels

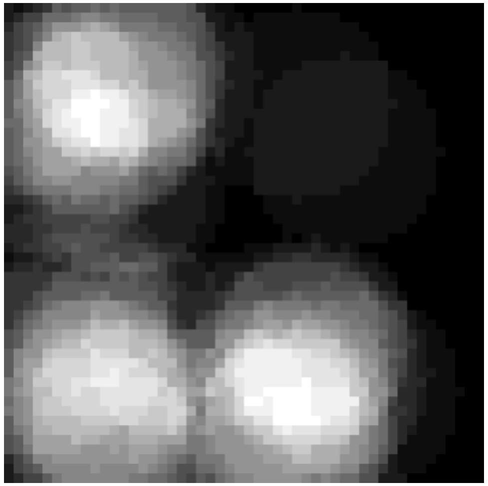
$*$

Disk



$=$

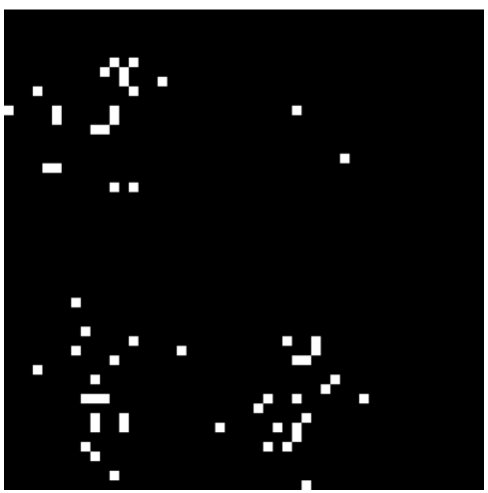
???



Filtering – Counting

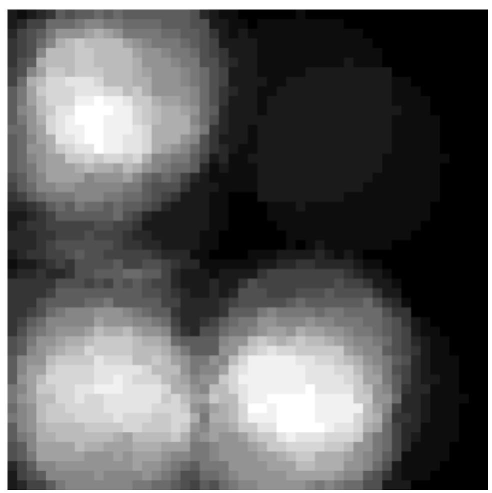
How many “on” pixels have
10+ neighbors within 10 pixels?

Pixels



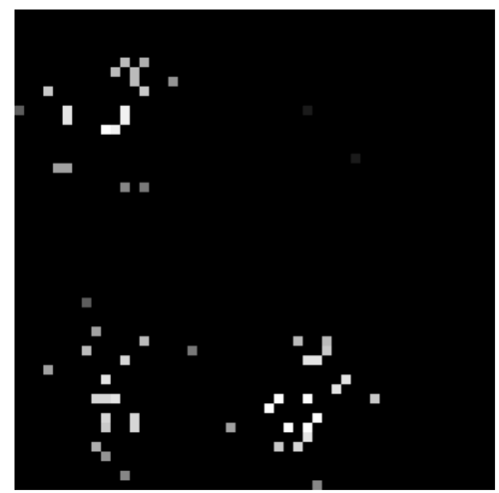
x

Density



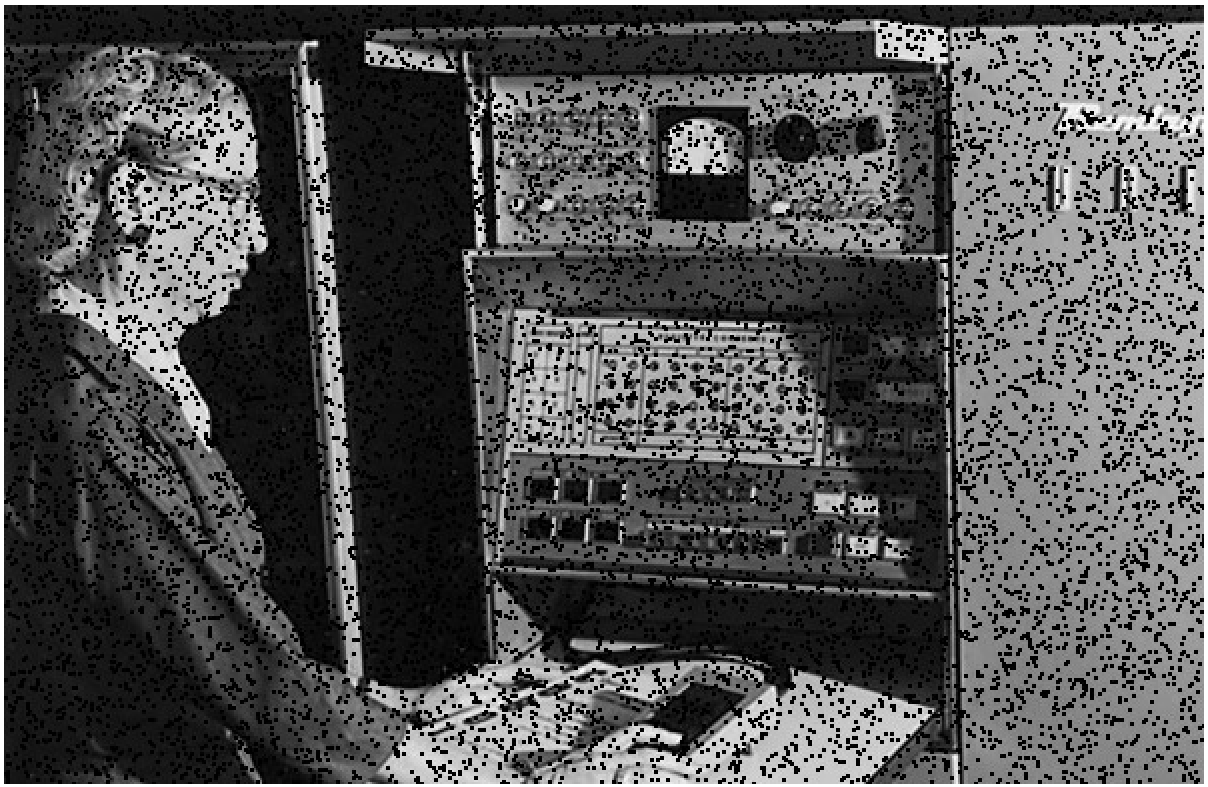
=

Answer



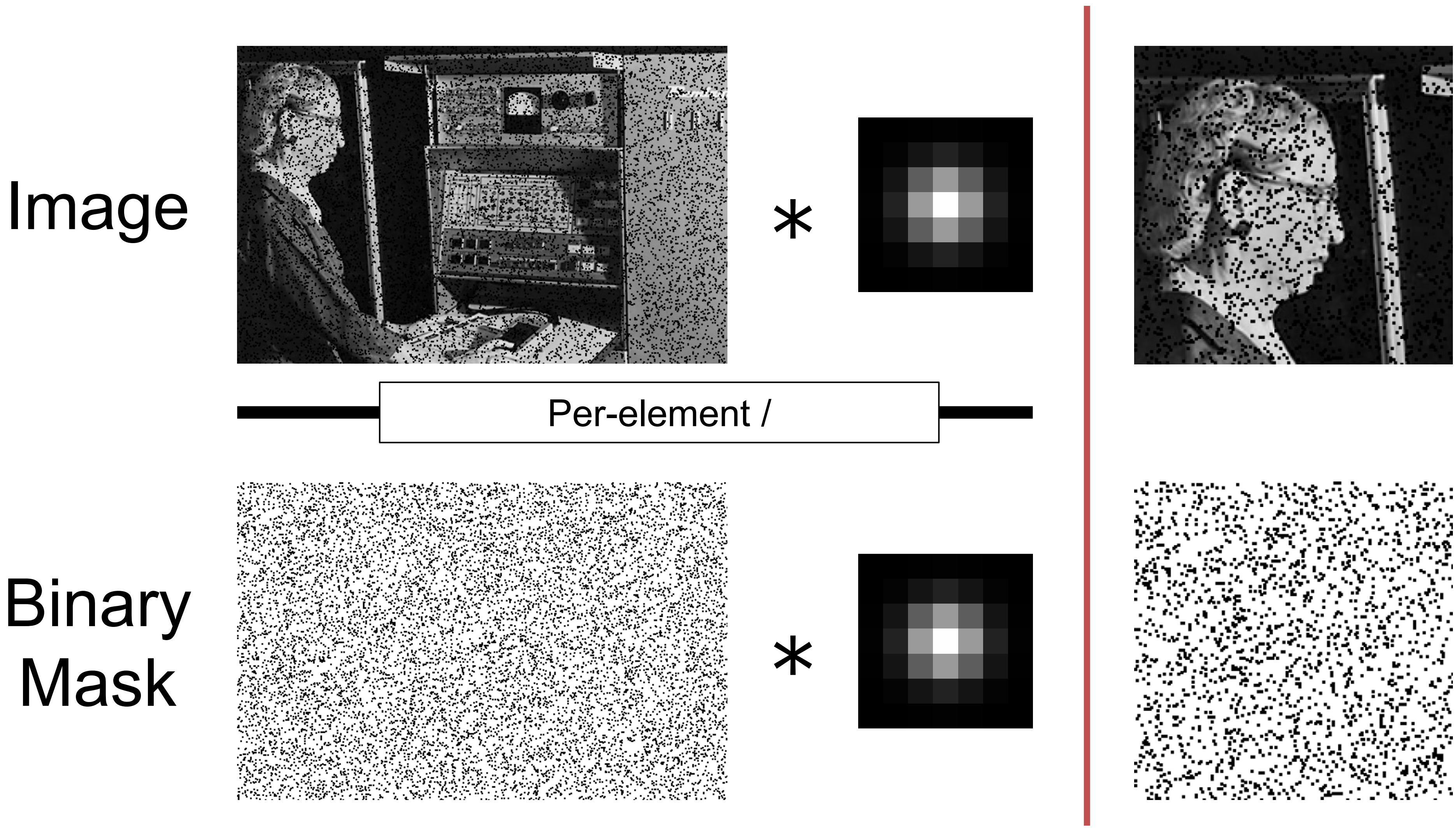
Filtering – Missing Data

Oh no! Missing data!
(and we know where)



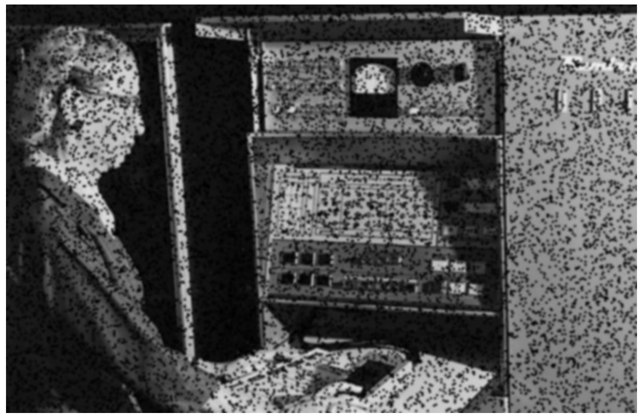
Common with many non-normal cameras (e.g., depth cameras)

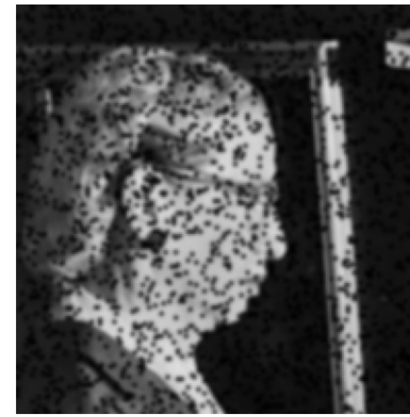
Filtering – Missing Data



Filtering – Missing Data

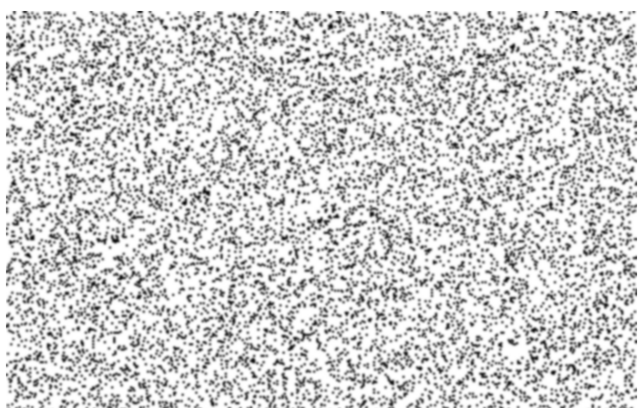
Image

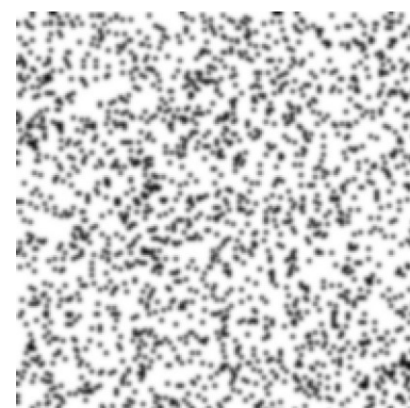




Per-element /

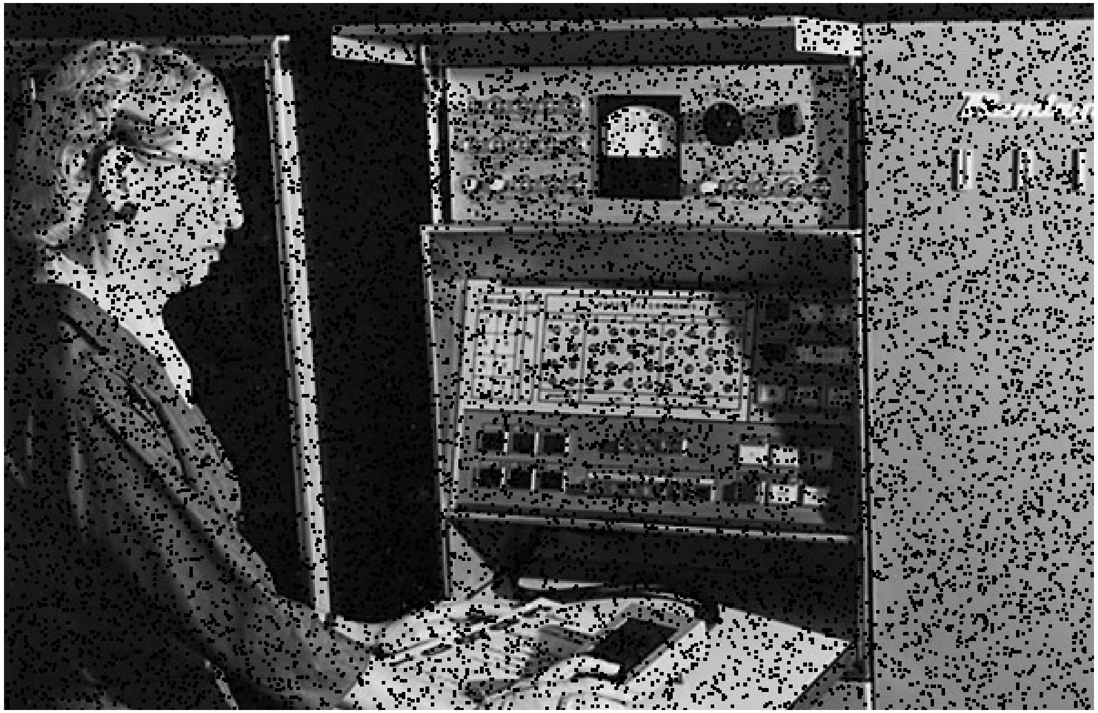
Binary Mask

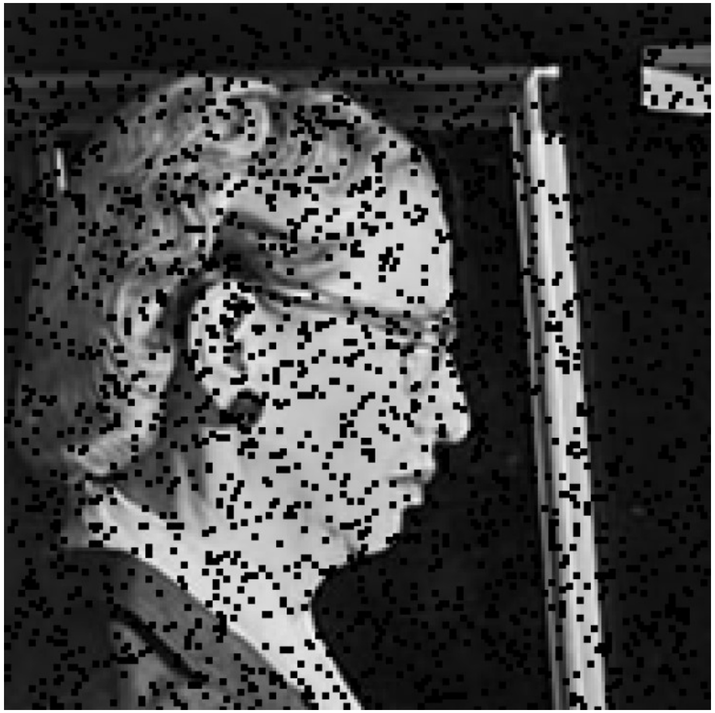




Filtering – Missing Data

Before





Filtering – Missing Data

After

Filtering – Missing Data

After (without missing data)