Intensity Transformation and Spatial Filtering

Spatial Domain vs. Transform Domain

- Spatial domain

  image plane itself, directly process the intensity values of the image plane

- Transform domain

  process the transform coefficients, not directly process the intensity values of the image plane

Spatial Domain Process

$$g(x, y) = T[f(x, y)])$$

$f(x, y)$: input image

$g(x, y)$: output image

T : an operator on f defined over

a neighborhood of point (x, y)

Spatial Domain Process

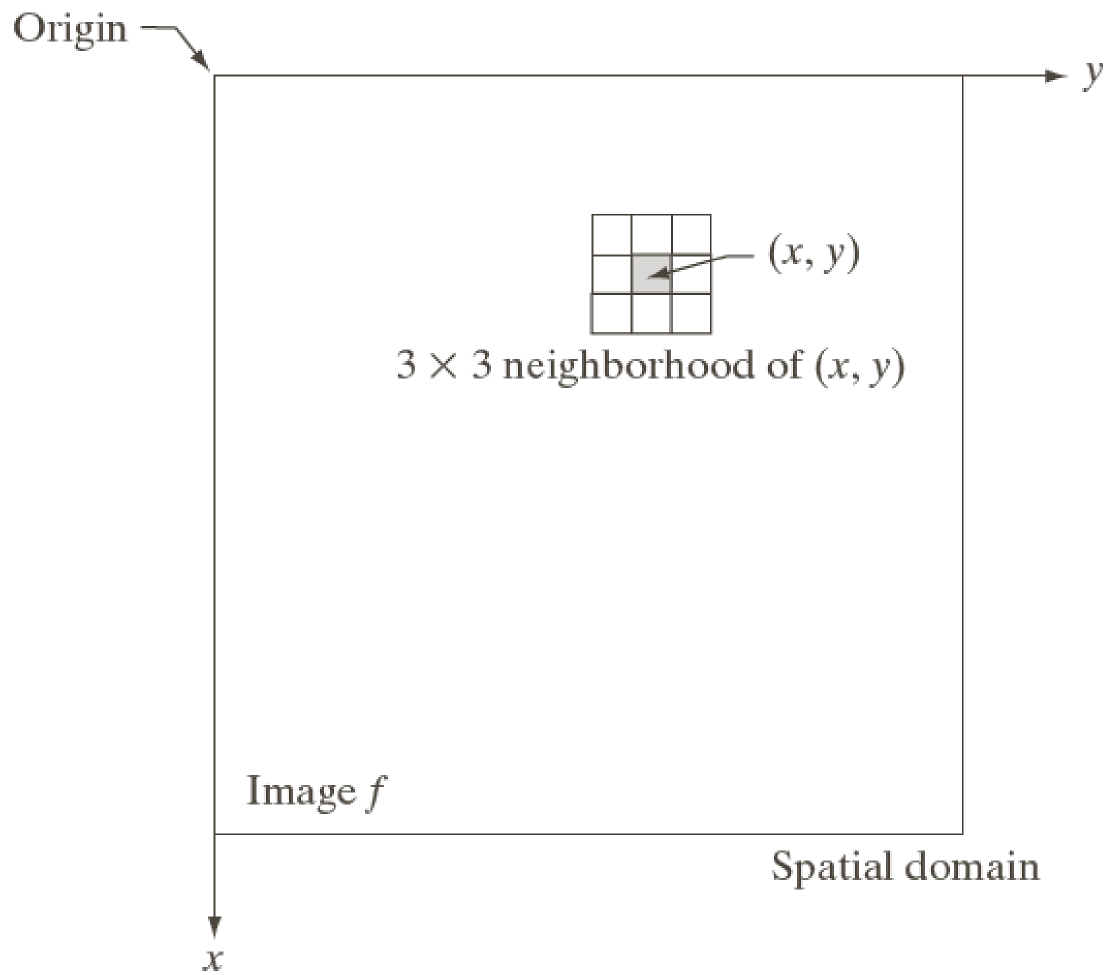
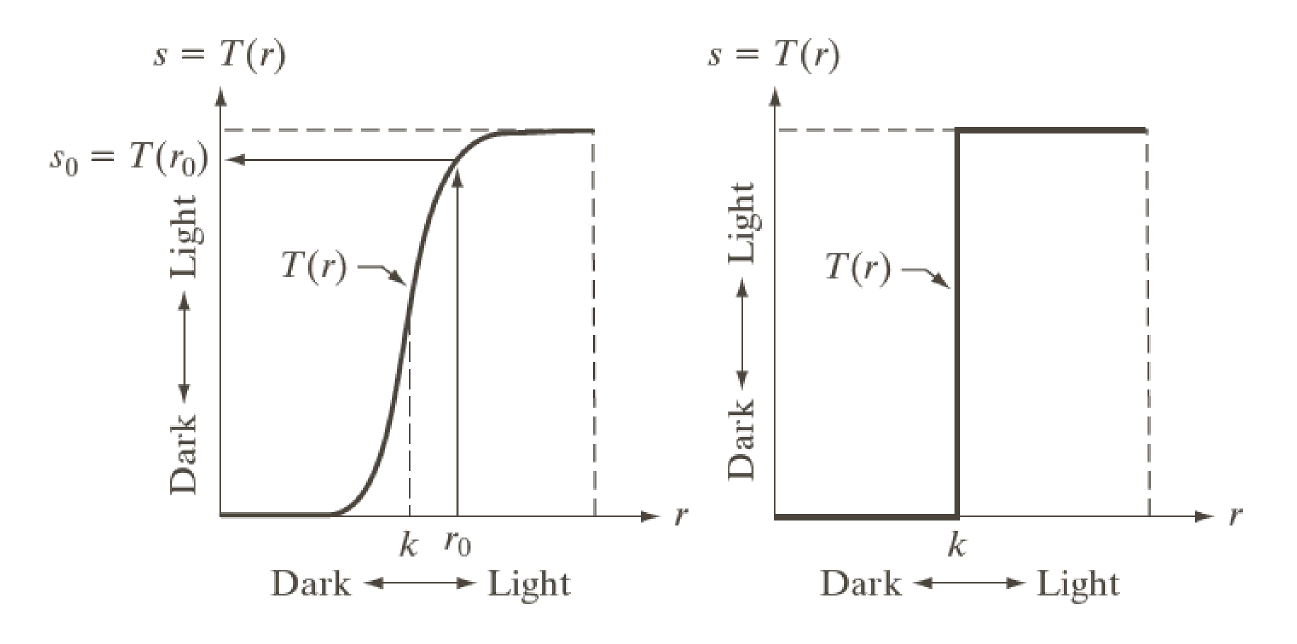


FIGURE 3.1 A 3 × 3 neighborhood about a point (x, y) in an image in the spatial domain. The neighborhood is moved from pixel to pixel in the image to generate an output image.

Spatial Domain Process

Intensity transformation function

$$s = T(r)$$



a b

FIGURE 3.2 Intensity transformation functions. (a) Contrast-stretching function. (b) Thresholding function.

Some Basic Intensity Transformation Functions

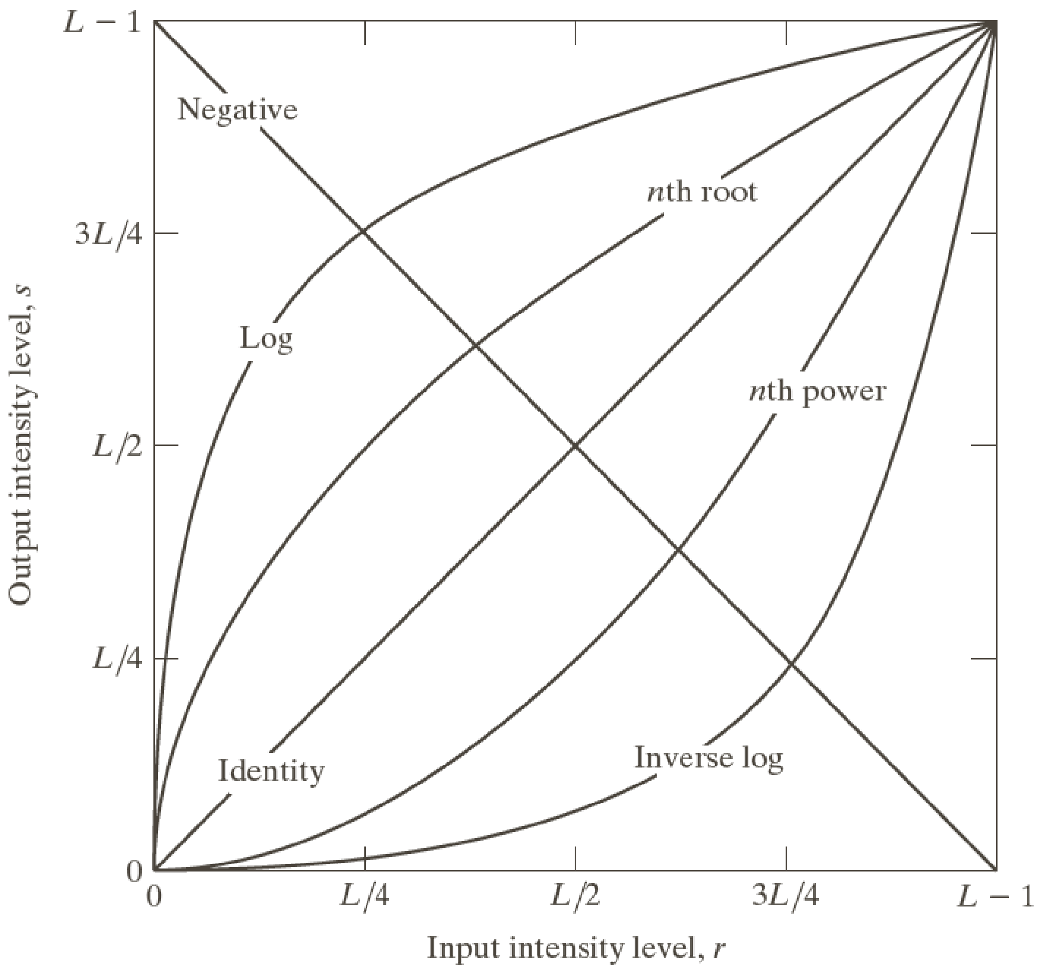


FIGURE 3.3 Some basic intensity transformation functions. All curves were scaled to fit in the range shown.

Image Negatives

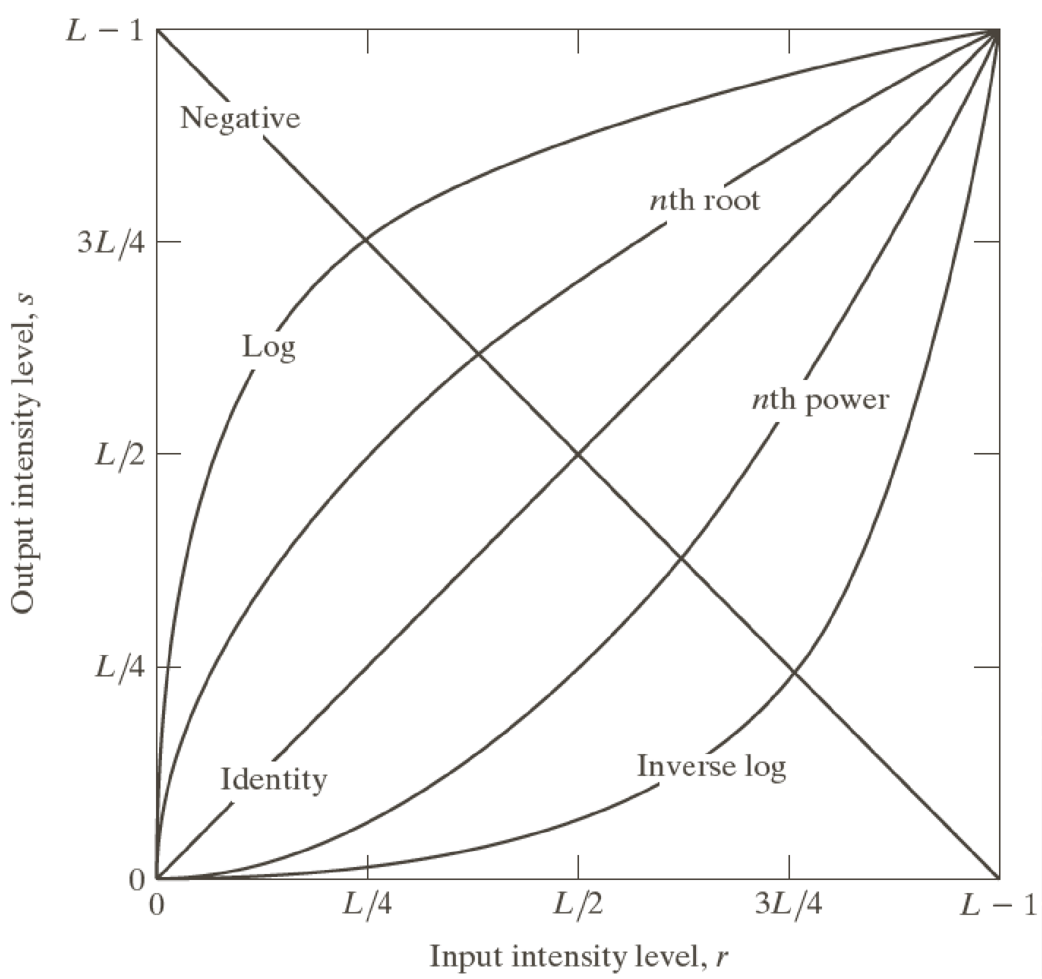


Image negatives

$$s = L - 1 - r$$

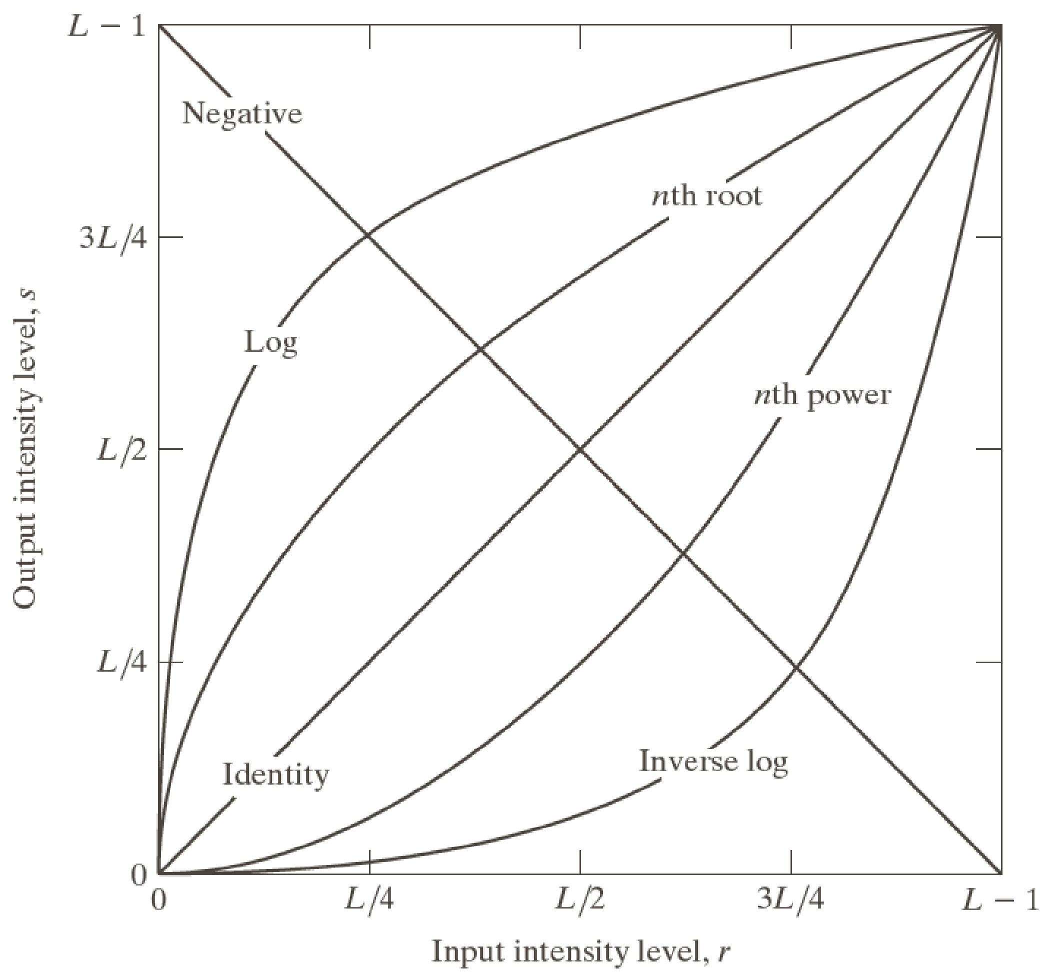
Example: Image Negatives

a b

FIGURE 3.4
(a) Original digital mammogram.
(b) Negative image obtained using the negative transformation in Eq. (3.2-1).
(Courtesy of G.E. Medical Systems.)

Small lesion

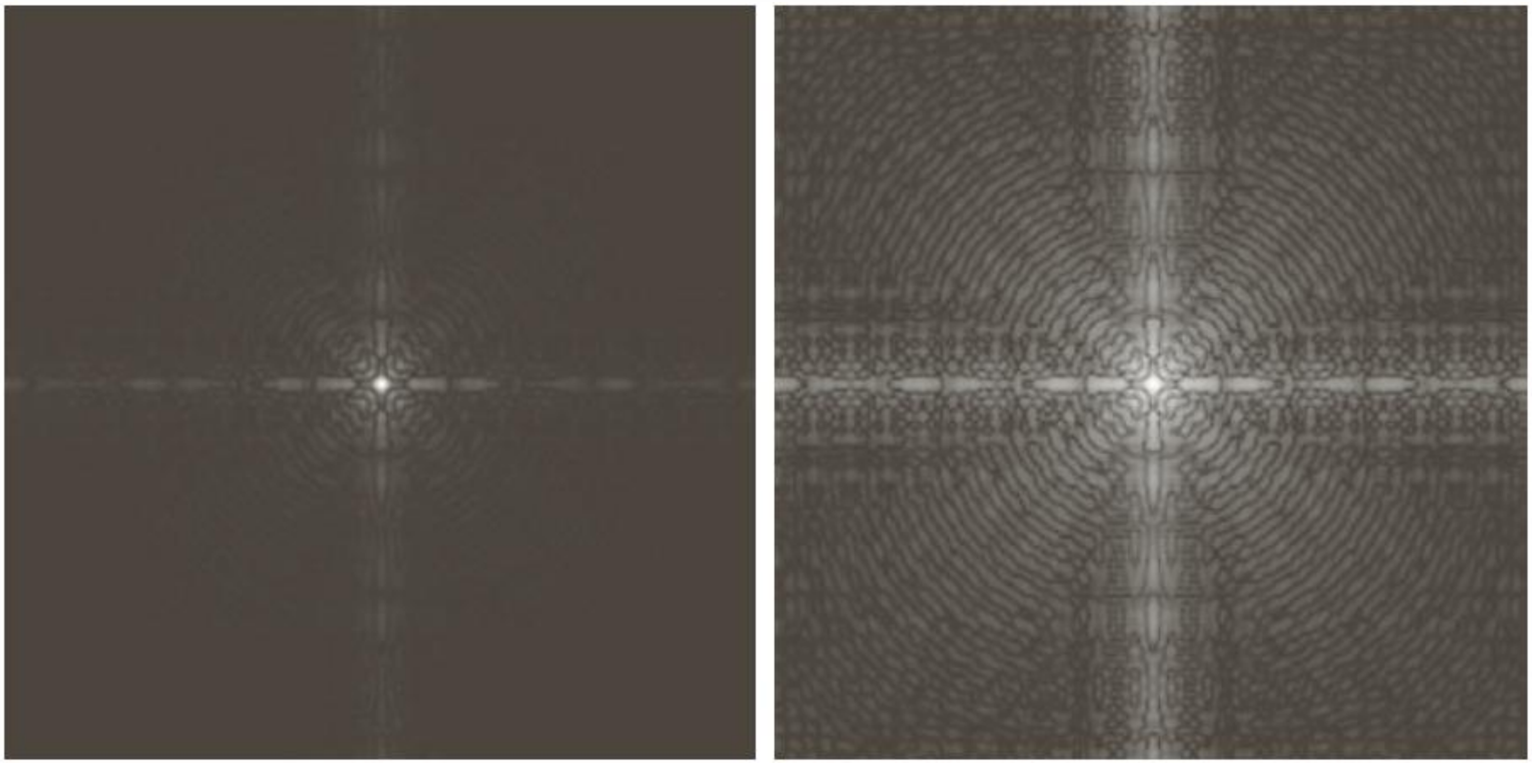
Log Transformations



Log Transformations

$$s = c\log(1+r)$$

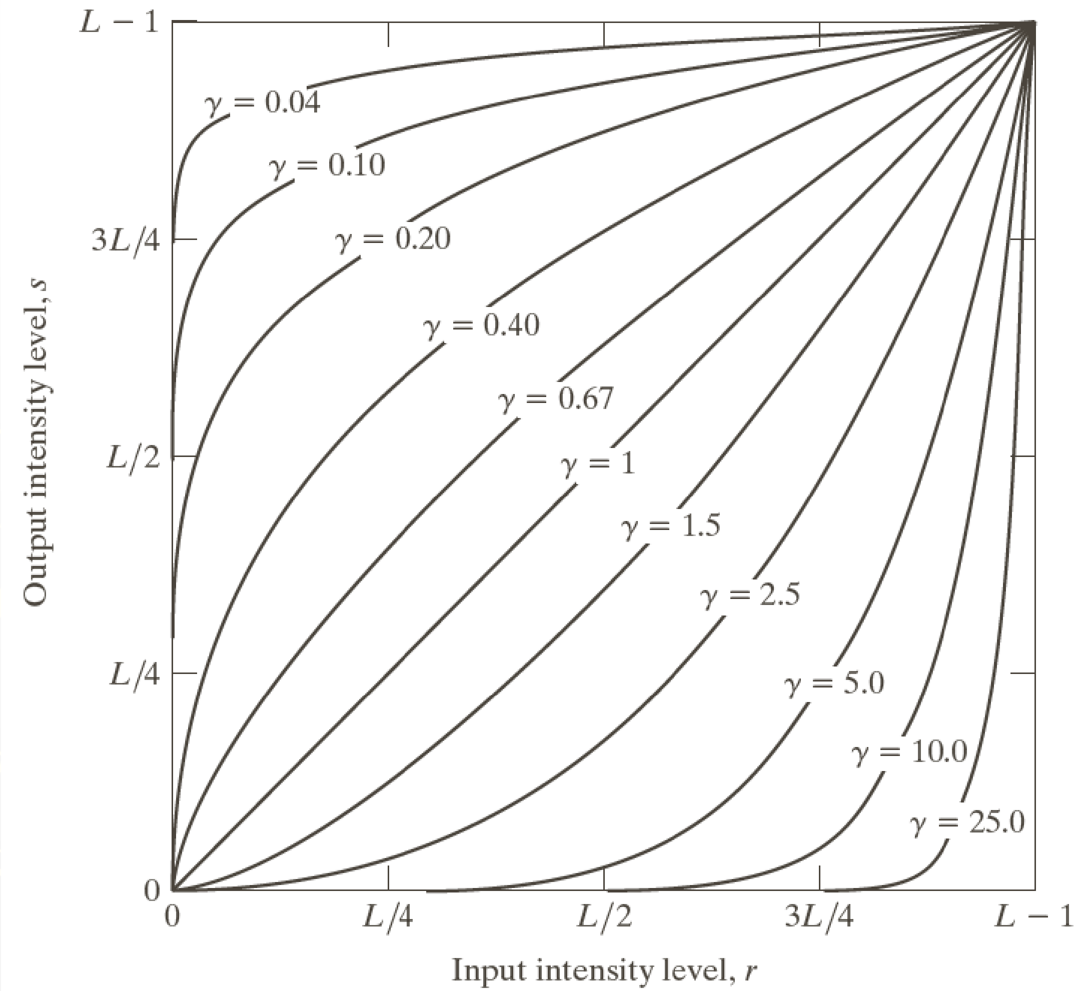
Example: Log Transformations



a b

FIGURE 3.5
(a) Fourier spectrum.
(b) Result of applying the log transformation in Eq. (3.2-2) with $c = 1$.

Power-Law (Gamma) Transformations



$$s = cr^{\gamma}$$

FIGURE 3.6 Plots of the equation $s = cr^{\gamma}$ for various values of γ ($c = 1$ in all cases). All curves were scaled to fit in the range shown.

Example: Gamma Transformations

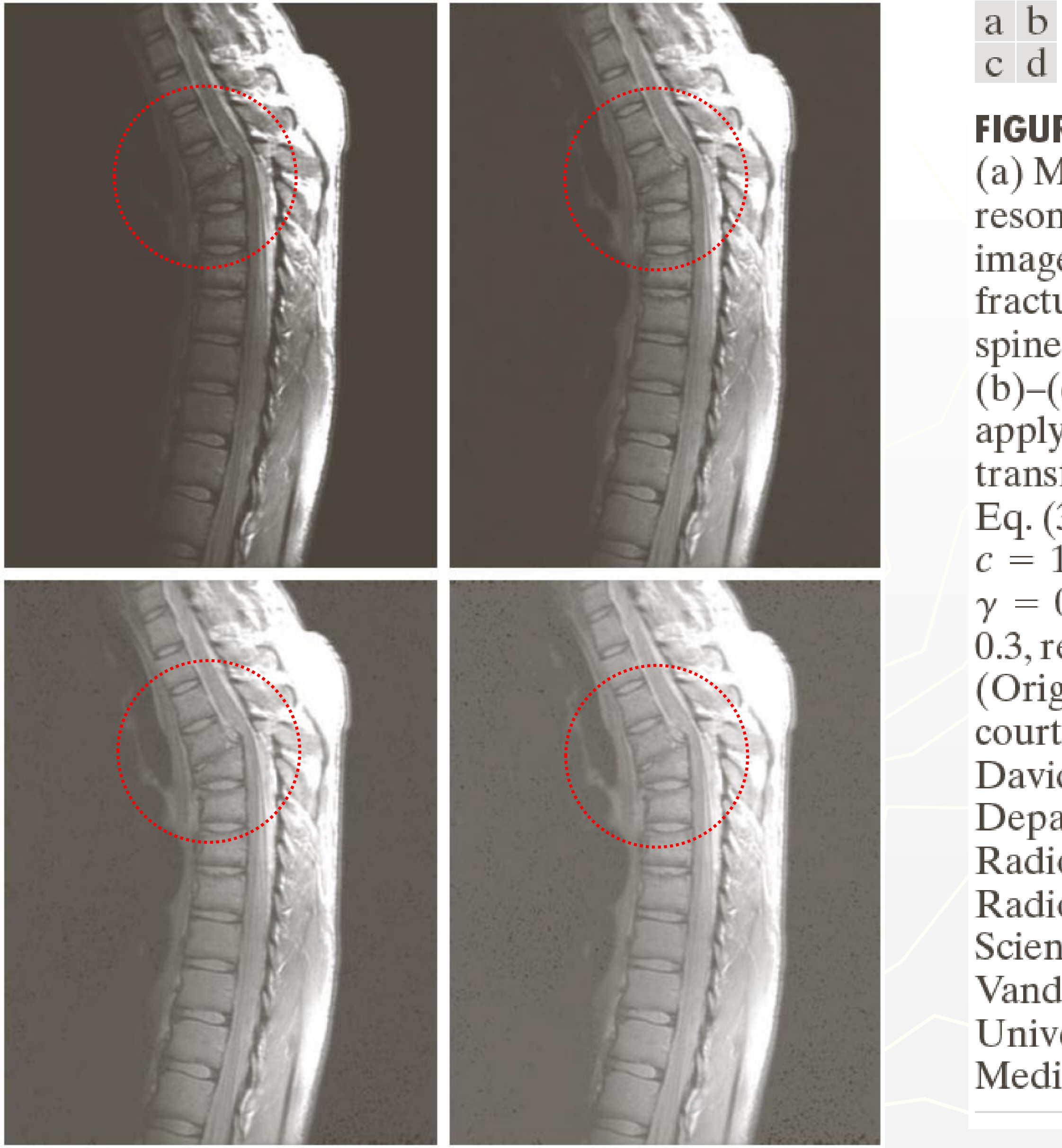


FIGURE 3.8 (a) Magnetic resonance image (MRI) of a fractured human spine. (b)–(d) Results of applying the transformation in Eq. (3.2-3) with $c = 1$ and $\gamma = 0.6, 0.4,$ and 0.3, respectively. (Original image courtesy of Dr. David R. Pickens, Department of Radiology and Radiological Sciences, Vanderbilt University Medical Center.)

Example: Gamma Transformations

a	b
c	d

FIGURE 3.9 (a) Aerial image. (b)–(d) Results of applying the transformation in Eq. (3.2-3) with $c = 1$ and $\gamma = 3.0, 4.0,$ and 5.0, respectively. (Original image for this example courtesy of NASA.)

Piecewise-Linear Transformations

- **Contrast Stretching**

  — Expands the range of intensity levels in an image so that it spans the full intensity range of the recording medium or display device.

What is contrast?

Contrast is the difference between the maximum and minimum pixel intensity.

- **Intensity-level Slicing**

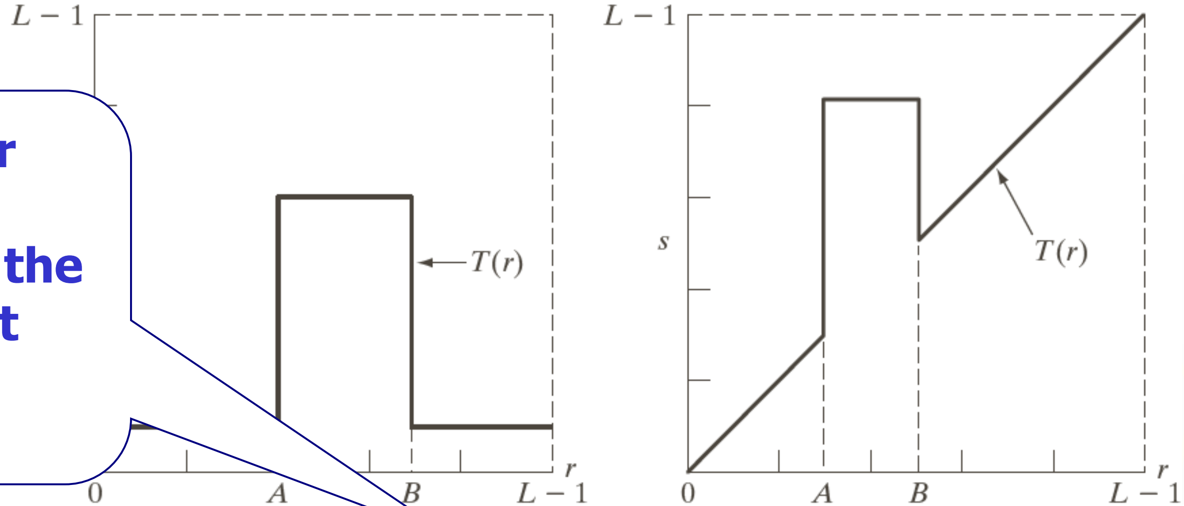
  — Highlighting a specific range of intensities in an image often is of interest.

a	b
c	d

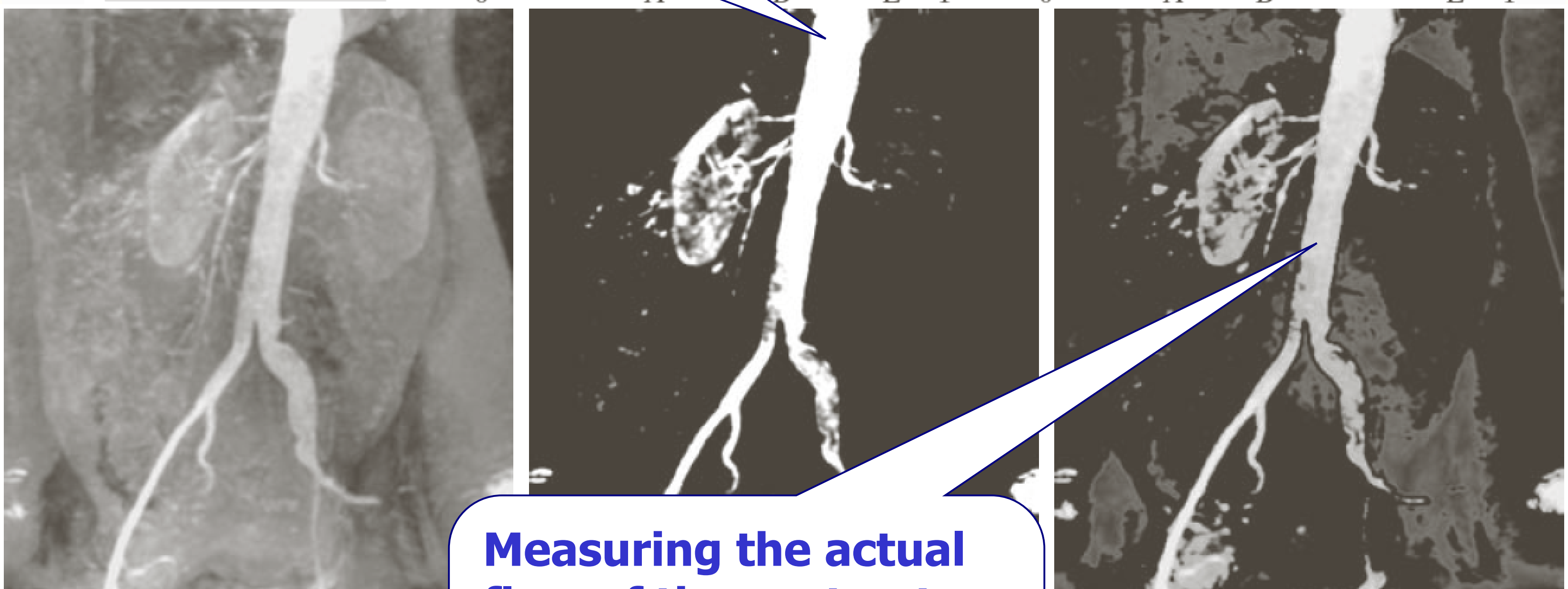
FIGURE 3.10 Contrast stretching. (a) Form of transformation function. (b) A low-contrast image. (c) Result of contrast stretching. (d) Result of thresholding. (Original image courtesy of Dr. Roger Heady, Research School of Biological Sciences, Australian National University, Canberra, Australia.)

a b

FIGURE 3.11 (a) This



Highlight the major blood vessels and study the shape of the flow of the contrast medium (to detect blockages, etc.)



Measuring the actual flow of the contrast medium as a function of time in a series of images

a b c

FIGURE 3.12 (a) Aortic angiog… …mation of the type illustrated in Fig. 3.11(a), with the range of inte… …end of the gray scale. (c) Result of using the transformation in Fig… …lack, so that grays in the area of the blood vessels and kidneys were preserved. (Original image courtesy of Dr. Thomas R. Gest, University of Michigan Medical School.)

Bit-plane Slicing

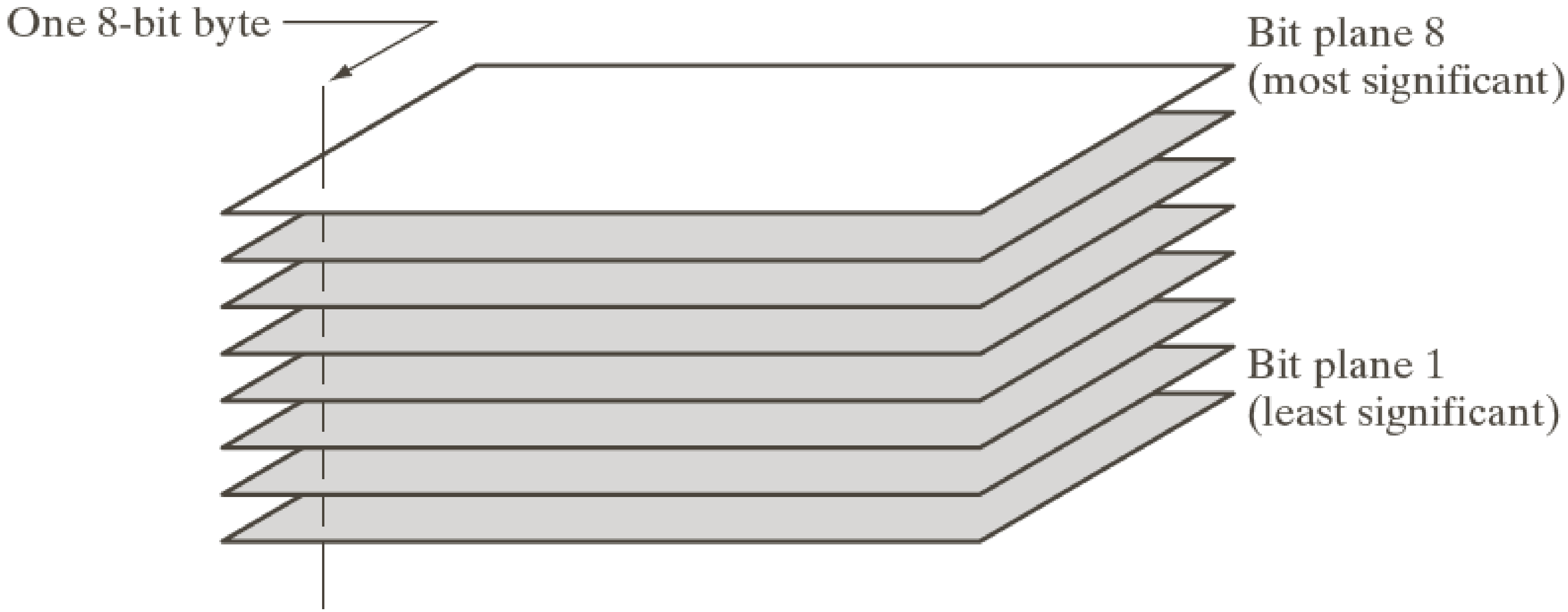
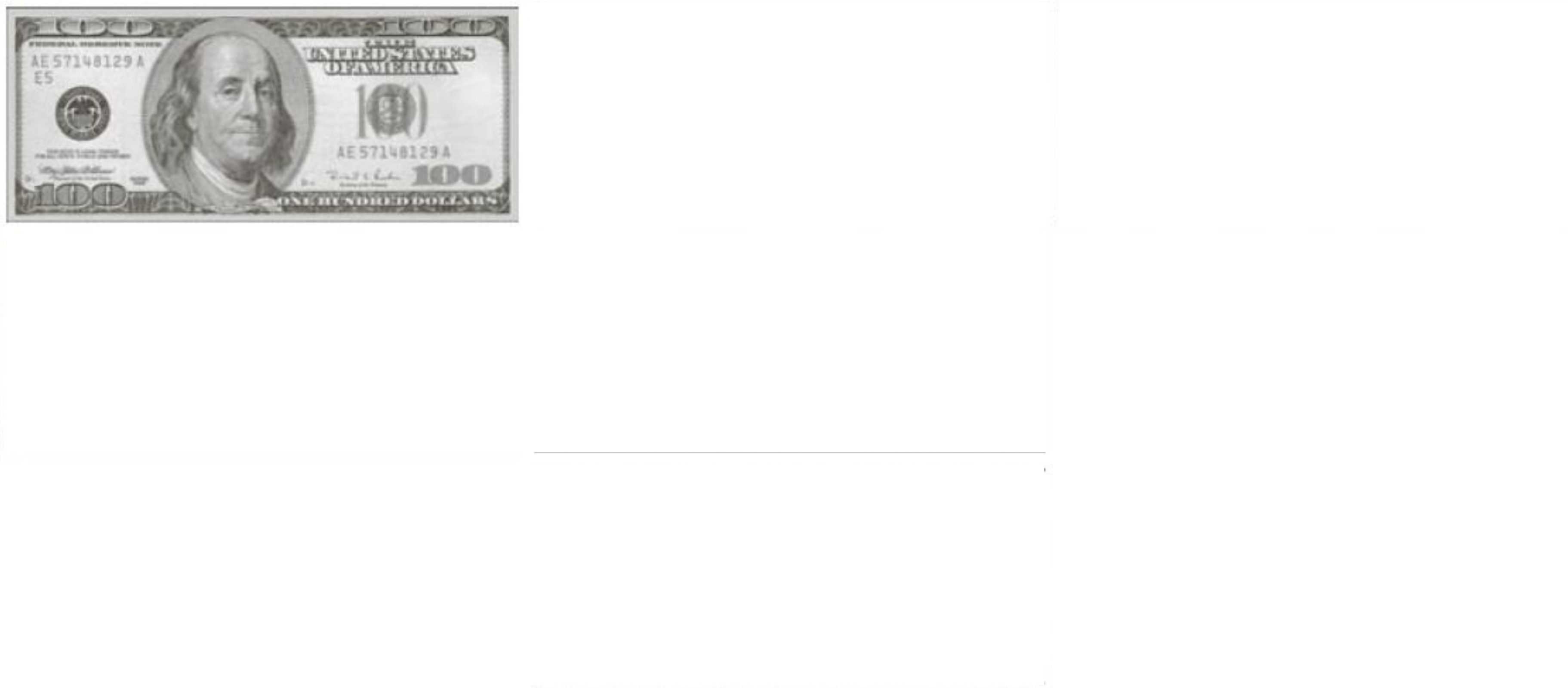


FIGURE 3.13
Bit-plane representation of an 8-bit image.

Bit-plane Slicing



a	b	c
d	e	f
g	h	i

FIGURE 3.14 (a) An 8-bit gray-scale image of size 500 × 1192 pixels. (b) through (i) Bit planes 1 through 8, with bit plane 1 corresponding to the least significant bit. Each bit plane is a binary image.

Bit-plane Slicing

a b c

FIGURE 3.15 Images reconstructed using (a) bit planes 8 and 7; (b) bit planes 8, 7, and 6; and (c) bit planes 8, 7, 6, and 5. Compare (c) with Fig. 3.14(a).

Histogram Processing

- Histogram Equalization
- Histogram Matching
- Local Histogram Processing
- Using Histogram Statistics for Image Enhancement

Histogram Processing

Histogram $h(r_k) = n_k$

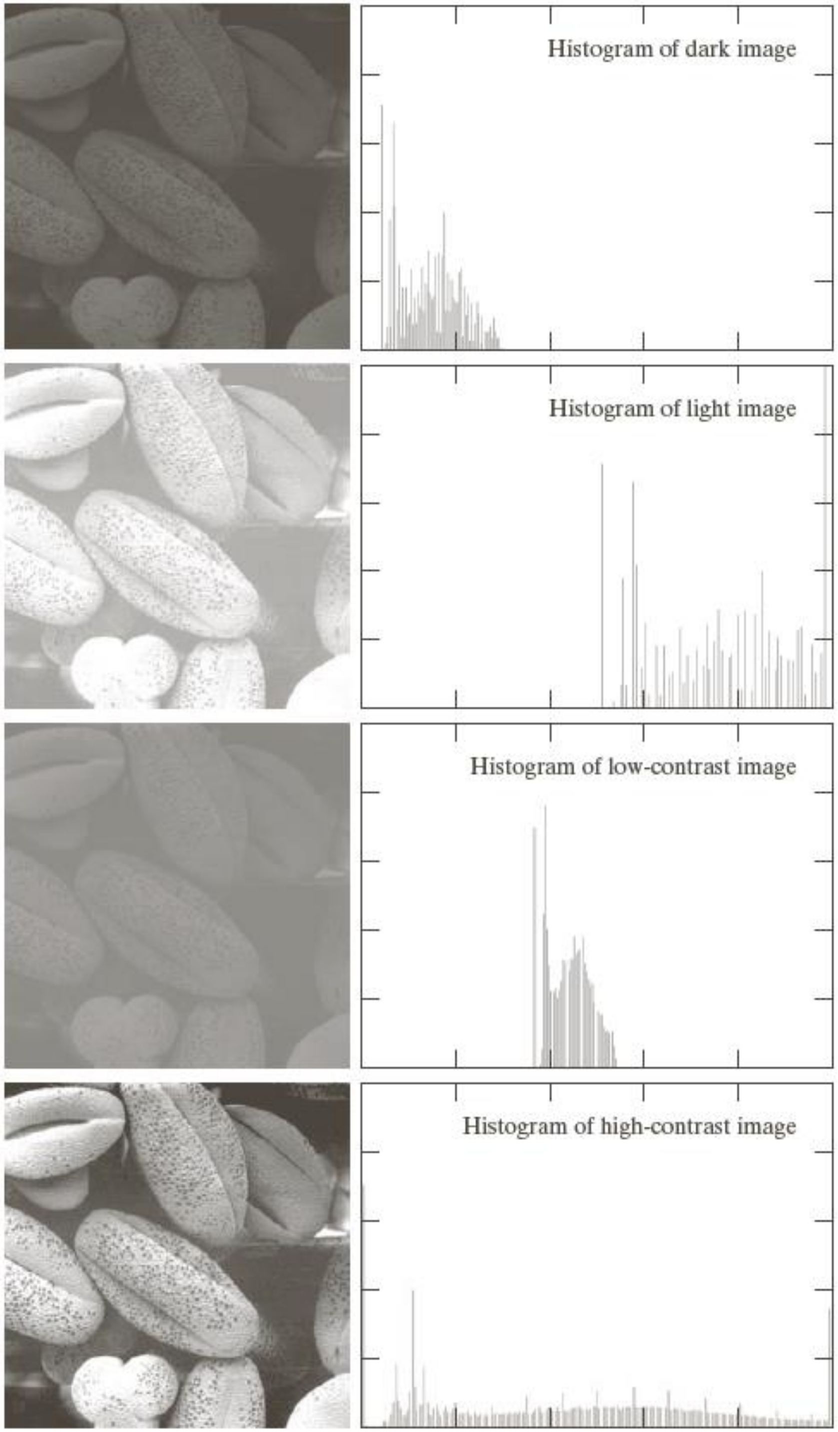
r_k is the k^{th} intensity value

n_k is the number of pixels in the image with intensity r_k

Normalized histogram $p(r_k) = \dfrac{n_k}{MN}$

n_k: the number of pixels in the image of

size $\mathrm{M} \times \mathrm{N}$ with intensity r_k


Histogram of dark image
Histogram of light image
Histogram of low-contrast image
Histogram of high-contrast image

Histogram Equalization

The intensity levels in an image may be viewed as random variables in the interval [0, L-1].

Let $p_r(r)$ and $p_s(s)$ denote the probability density function (PDF) of random variables r and s.

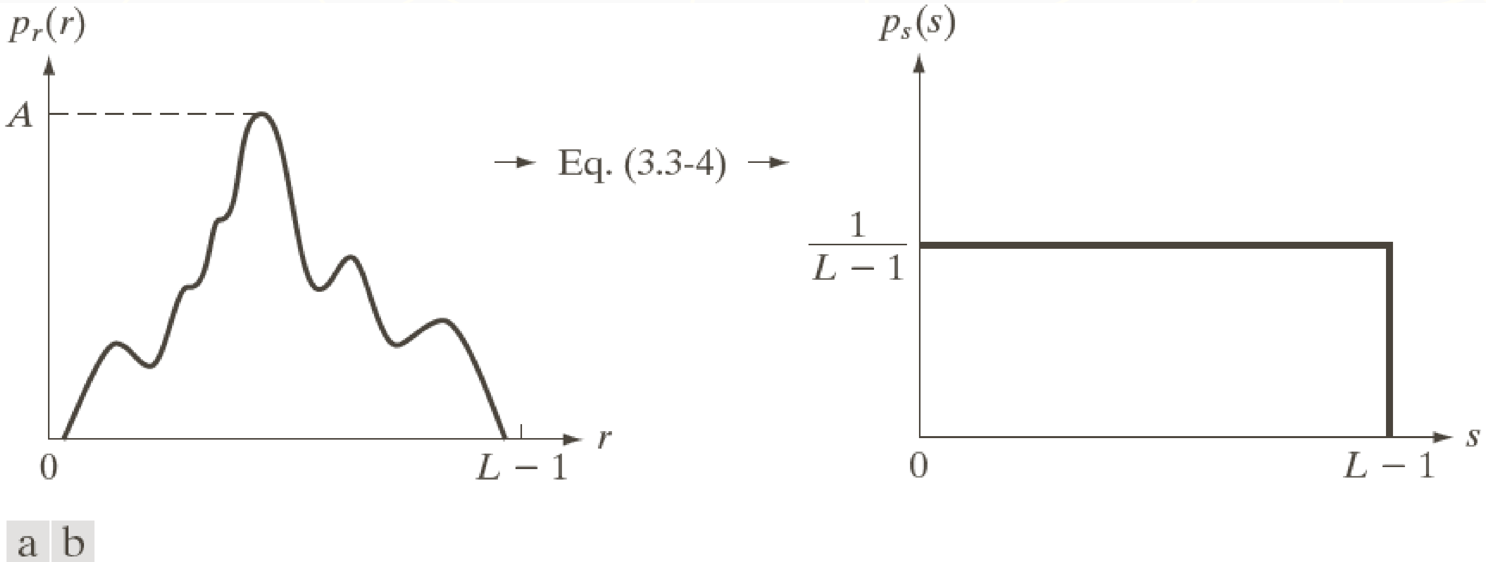


FIGURE 3.18 (a) An arbitrary PDF. (b) Result of applying the transformation in Eq. (3.3-4) to all intensity levels, r. The resulting intensities, s, have a uniform PDF, independently of the form of the PDF of the r's.

Histogram Equalization

Discrete values:

$$s_k = T(r_k) = (L-1)\sum_{j=0}^{k} p_r(r_j)$$

$$= (L-1)\sum_{j=0}^{k} \frac{n_j}{MN} = \frac{L-1}{MN}\sum_{j=0}^{k} n_j \qquad \text{k=0,1,..., L-1}$$

***** Please see the referenced book for the proof*

Example: Histogram Equalization

Suppose that a 3-bit image (L=8) of size 64 × 64 pixels (MN = 4096) has the intensity distribution shown in following table.
Get the histogram equalization transformation function and give the $p_s(s_k)$ for each s_k.

r_k	n_k	$p_r(r_k) = n_k/MN$
$r_0 = 0$	790	0.19
$r_1 = 1$	1023	0.25
$r_2 = 2$	850	0.21
$r_3 = 3$	656	0.16
$r_4 = 4$	329	0.08
$r_5 = 5$	245	0.06
$r_6 = 6$	122	0.03
$r_7 = 7$	81	0.02

Example: Histogram Equalization

r_k	n_k	$p_r(r_k) = n_k/MN$
$r_0 = 0$	790	0.19
$r_1 = 1$	1023	0.25
$r_2 = 2$	850	0.21
$r_3 = 3$	656	0.16
$r_4 = 4$	329	0.08
$r_5 = 5$	245	0.06
$r_6 = 6$	122	0.03
$r_7 = 7$	81	0.02

$$s_0 = T(r_0) = 7\sum_{j=0}^{0} p_r(r_j) = 7 \times 0.19 = 1.33 \quad \rightarrow 1$$

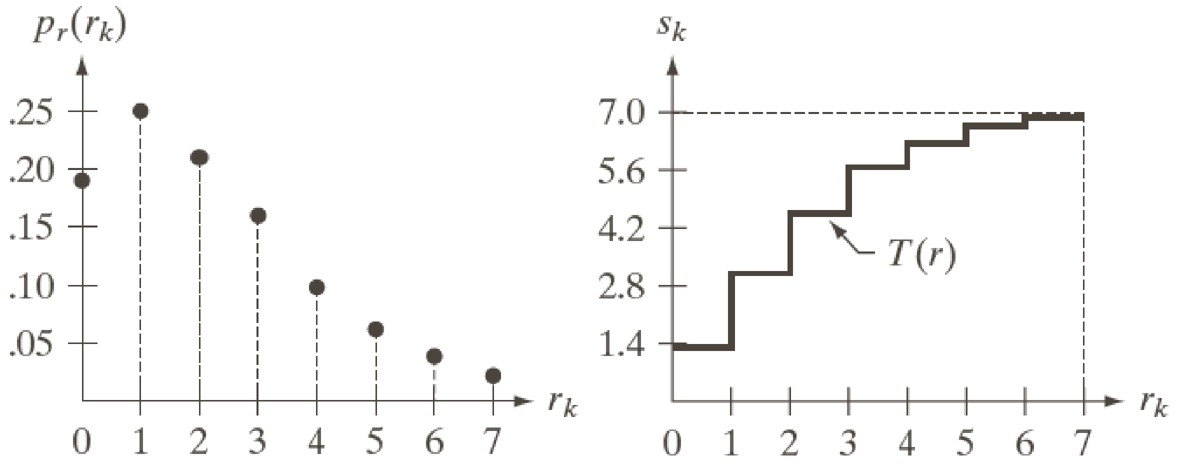
$$s_1 = T(r_1) = 7\sum_{j=0}^{1} p_r(r_j) = 7 \times (0.19 + 0.25) = 3.08 \quad \rightarrow 3$$

$$s_2 = 4.55 \quad \rightarrow 5 \qquad s_3 = 5.67 \quad \rightarrow 6$$

$$s_4 = 6.23 \quad \rightarrow 6 \qquad s_5 = 6.65 \quad \rightarrow 7$$

$$s_6 = 6.86 \quad \rightarrow 7 \qquad s_7 = 7.00 \quad \rightarrow 7$$

Example: Histogram Equalization



a b c

FIGURE 3.19 Illustration of histogram equalization of a 3-bit (8 intensity levels) image. (a) Original histogram. (b) Transformation function. (c) Equalized histogram.

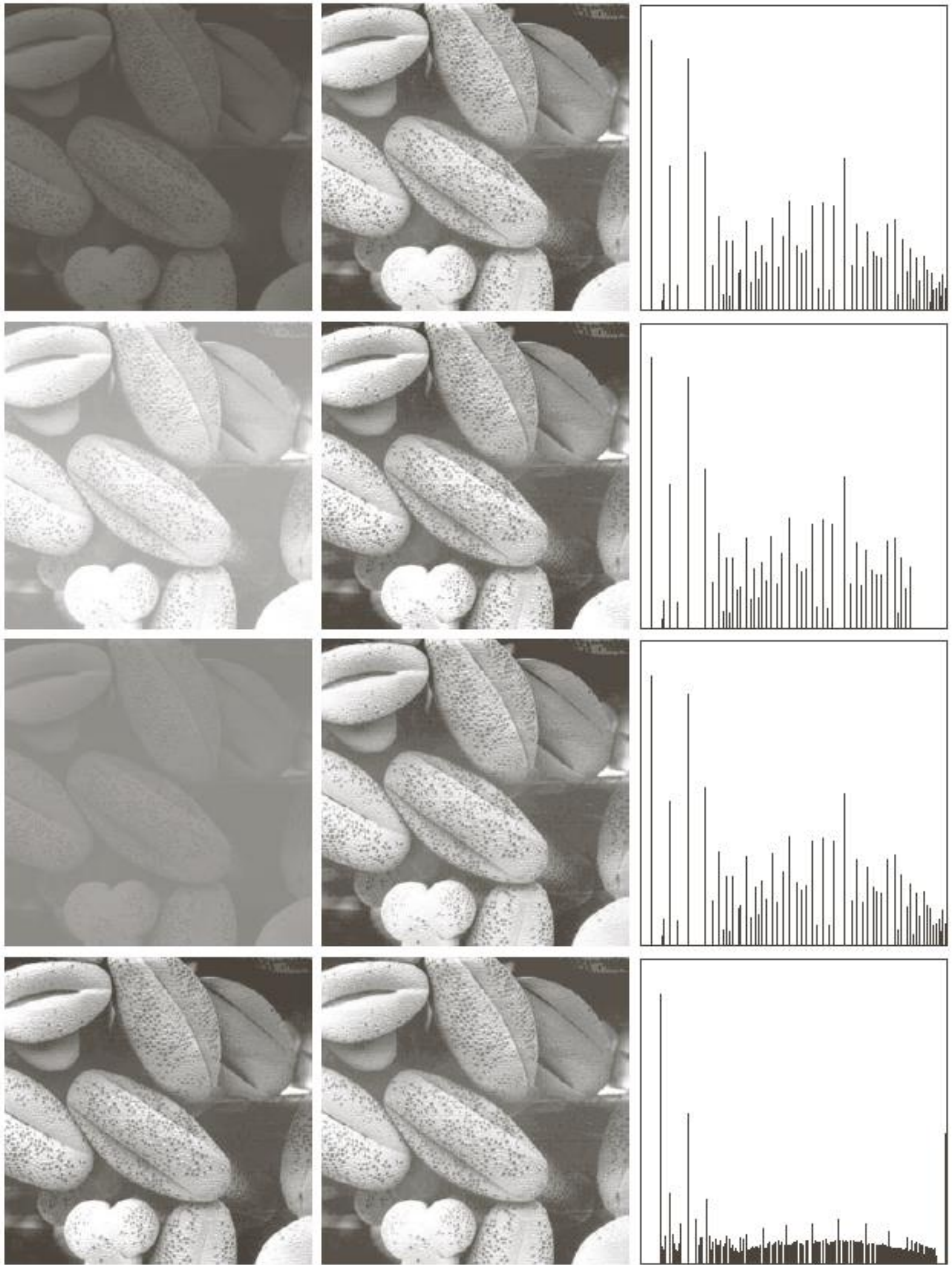


FIGURE 3.20 Left column: images from Fig. 3.16. Center column: corresponding histogram-equalized images. Right column: histograms of the images in the center column.

Question

Is histogram equalization always good?

No

Histogram Matching

Histogram matching (histogram specification)

— generate a processed image that has a specified histogram

Let $p_r(r)$ and $p_z(z)$ denote the continous probability density functions of the variables r and z. $p_z(z)$ is the specified probability density function.

Let s be the random variable with the probability

$$s = T(r) = (L-1)\int_0^r p_r(w)dw$$

Define a random variable z with the probability

$$G(z) = (L-1)\int_0^z p_z(t)dt = s$$

Local Histogram Processing

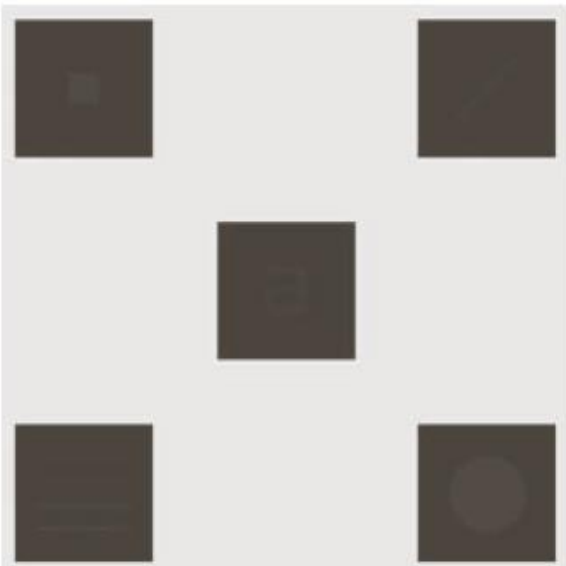
Define a neighborhood and move its center from pixel to pixel

At each location, the histogram of the points in the neighborhood is computed. Either histogram equalization or histogram specification transformation function is obtained

Map the intensity of the pixel centered in the neighborhood

Move to the next location and repeat the procedure

Local Histogram Processing: Example



a b c

FIGURE 3.26 (a) Original image. (b) Result of global histogram equalization. (c) Result of local histogram equalization applied to (a), using a neighborhood of size 3×3.

Spatial Filtering

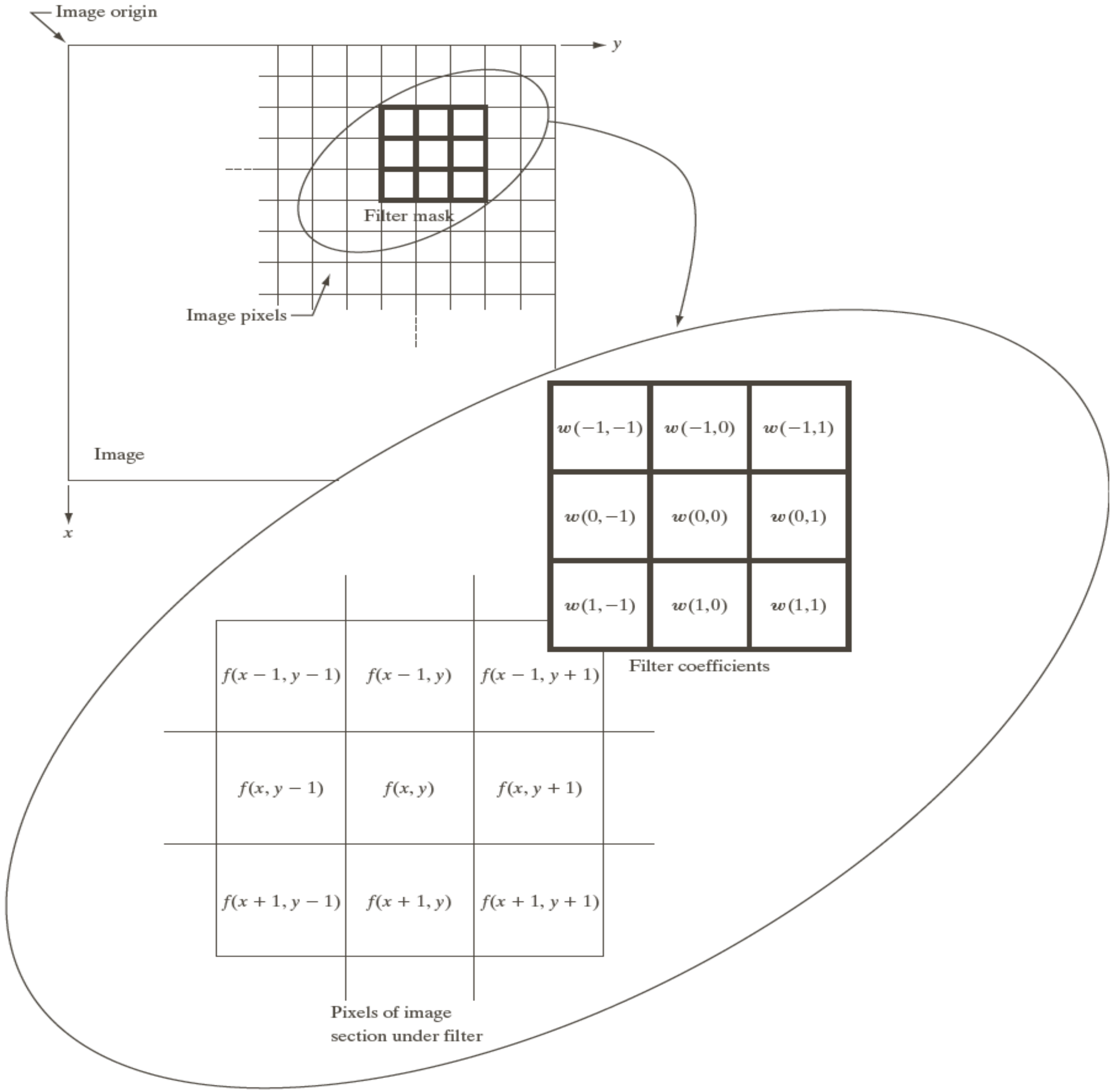
A spatial filter (*also known as spatial masks, kernels, templates, and windows*) consists of (a) **a neighborhood**, and (b) **a predefined operation**

Filtering creates a new pixel with coordinates equal to the coordinates of the center of the neighbourhood

Linear spatial filtering of an image of size *MxN* with a filter of size *mxn* is given by the expression

$$g(x,y)=\sum_{s=-a}^{a}\sum_{t=-b}^{b}w(s,t)f(x+s,y+t)$$

Spatial Filtering



Spatial Correlation

The correlation of a filter $w(x, y)$ of size $m \times n$

with an image $f(x, y)$, denoted as $w(x, y) \star f(x, y)$

$$w(x, y) \star f(x, y) = \sum_{s=-a}^{a} \sum_{t=-b}^{b} w(s,t) f(x+s, y+t)$$

Spatial Convolution

The convolution of a filter $w(x, y)$ of size $m \times n$ with an image $f(x, y)$, denoted as $w(x, y) \star f(x, y)$

$$w(x, y) \star f(x, y) = \sum_{s=-a}^{a} \sum_{t=-b}^{b} w(s,t) f(x-s, y-t)$$

Origin $f(x, y)$

$$\begin{array}{ccccc} 0 & 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 & 0 \\ 0 & 0 & 1 & 0 & 0 \\ 0 & 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 & 0 \end{array}$$

$w(x, y)$

$$\begin{array}{ccc} 1 & 2 & 3 \\ 4 & 5 & 6 \\ 7 & 8 & 9 \end{array}$$

(a)

FIGURE 3.30 Correlation (middle row) and convolution (last row) of a 2-D filter with a 2-D discrete, unit impulse. The 0s are shown in gray to simplify visual analysis.

Smoothing Spatial Filters

Smoothing filters are used for blurring and for noise reduction

Blurring is used in removal of small details and bridging of small gaps in lines or curves

Smoothing spatial filters include linear filters and nonlinear filters.

Spatial Smoothing Linear Filters

The general implementation for filtering an $M \times N$ image with a weighted averaging filter of size $m \times n$ is given

$$g(x,y) = \frac{\sum_{s=-a}^{a} \sum_{t=-b}^{b} w(s,t) f(x+s, y+t)}{\sum_{s=-a}^{a} \sum_{t=-b}^{b} w(s,t)}$$

where $m = 2a+1, \quad n = 2b+1.$

Two Smoothing Averaging Filter Masks

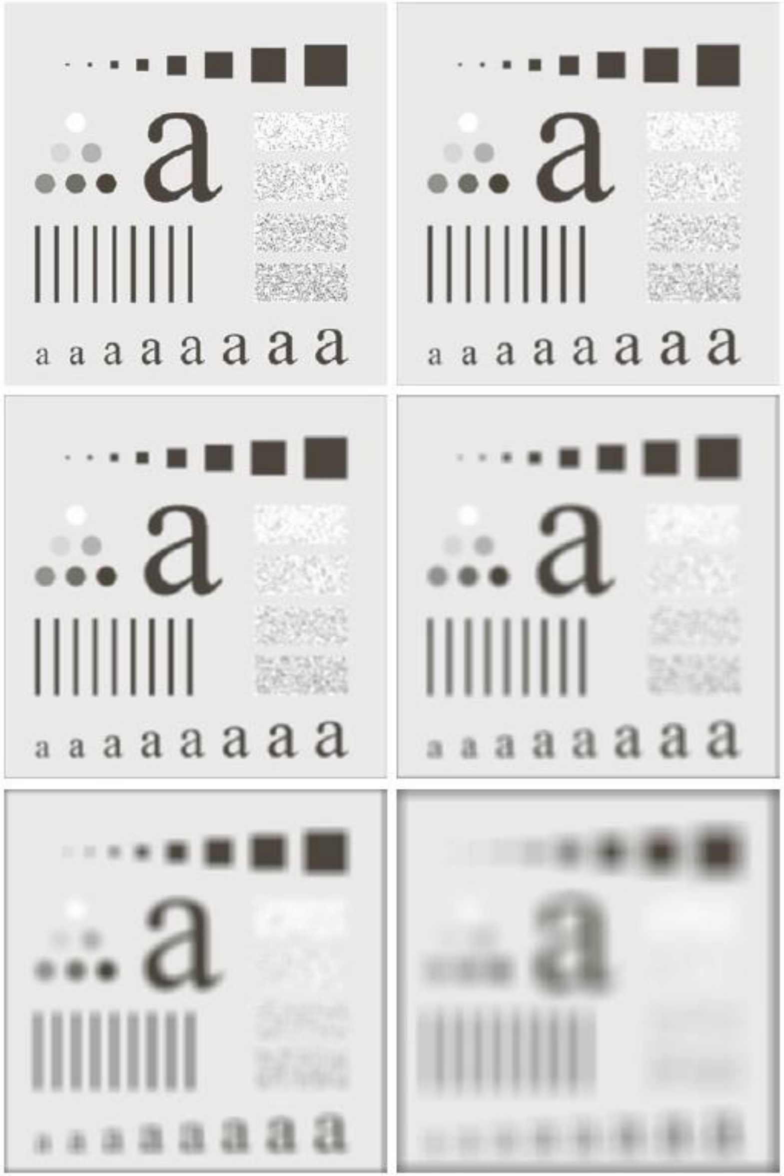
$$\frac{1}{9} \times \begin{array}{|c|c|c|}\hline 1 & 1 & 1 \\ \hline 1 & 1 & 1 \\ \hline 1 & 1 & 1 \\ \hline \end{array} \qquad \frac{1}{16} \times \begin{array}{|c|c|c|}\hline 1 & 2 & 1 \\ \hline 2 & 4 & 2 \\ \hline 1 & 2 & 1 \\ \hline \end{array}$$

a b

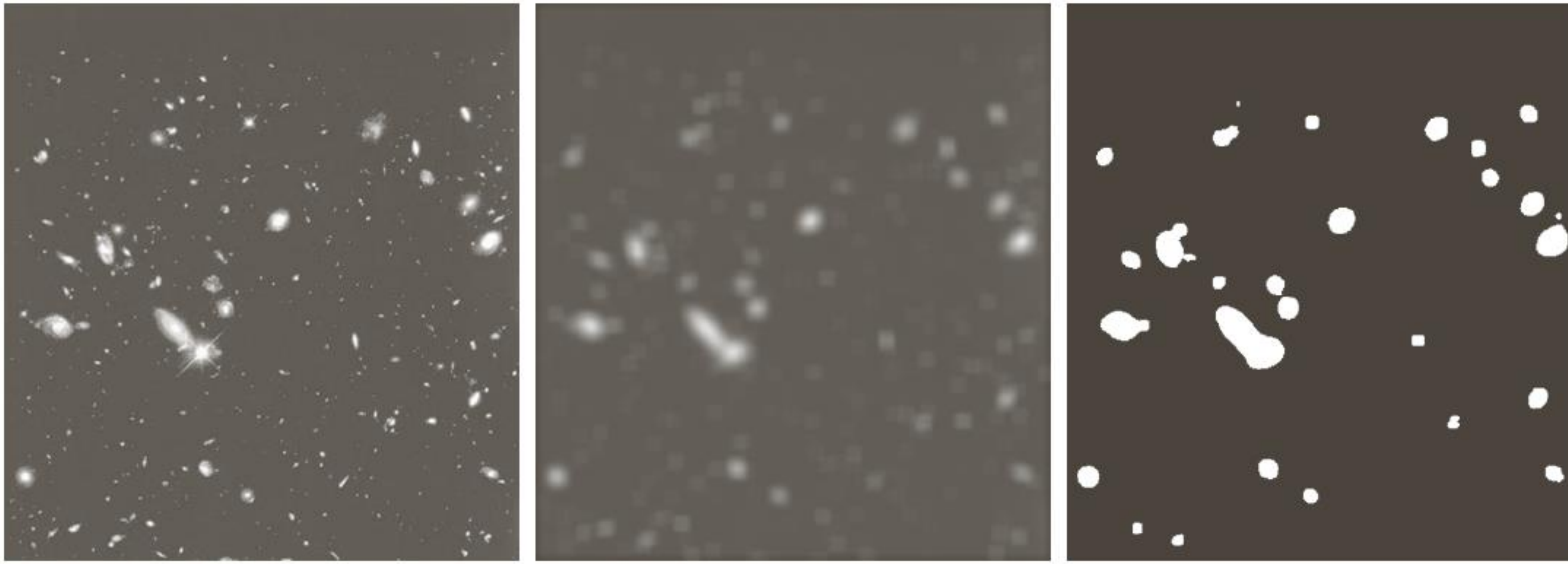
FIGURE 3.32 Two 3×3 smoothing (averaging) filter masks. The constant multiplier in front of each mask is equal to 1 divided by the sum of the values of its coefficients, as is required to compute an average.

FIGURE 3.33 (a) Original image, of size 500 × 500 pixels. (b)–(f) Results of smoothing with square averaging filter masks of sizes $m = 3, 5, 9, 15$, and 35, respectively. The black squares at the top are of sizes 3, 5, 9, 15, 25, 35, 45, and 55 pixels, respectively; their borders are 25 pixels apart. The letters at the bottom range in size from 10 to 24 points, in increments of 2 points; the large letter at the top is 60 points. The vertical bars are 5 pixels wide and 100 pixels high; their separation is 20 pixels. The diameter of the circles is 25 pixels, and their borders are 15 pixels apart; their intensity levels range from 0% to 100% black in increments of 20%. The background of the image is 10% black. The noisy rectangles are of size 50 × 120 pixels.

a b
c d
e f



Example: Gross Representation of Objects



a b c

FIGURE 3.34 (a) Image of size 528 × 485 pixels from the Hubble Space Telescope. (b) Image filtered with a 15 × 15 averaging mask. (c) Result of thresholding (b). (Original image courtesy of NASA.)

Order-statistic (Nonlinear) Filters

— Nonlinear

— Based on ordering (ranking) the pixels contained in the filter mask

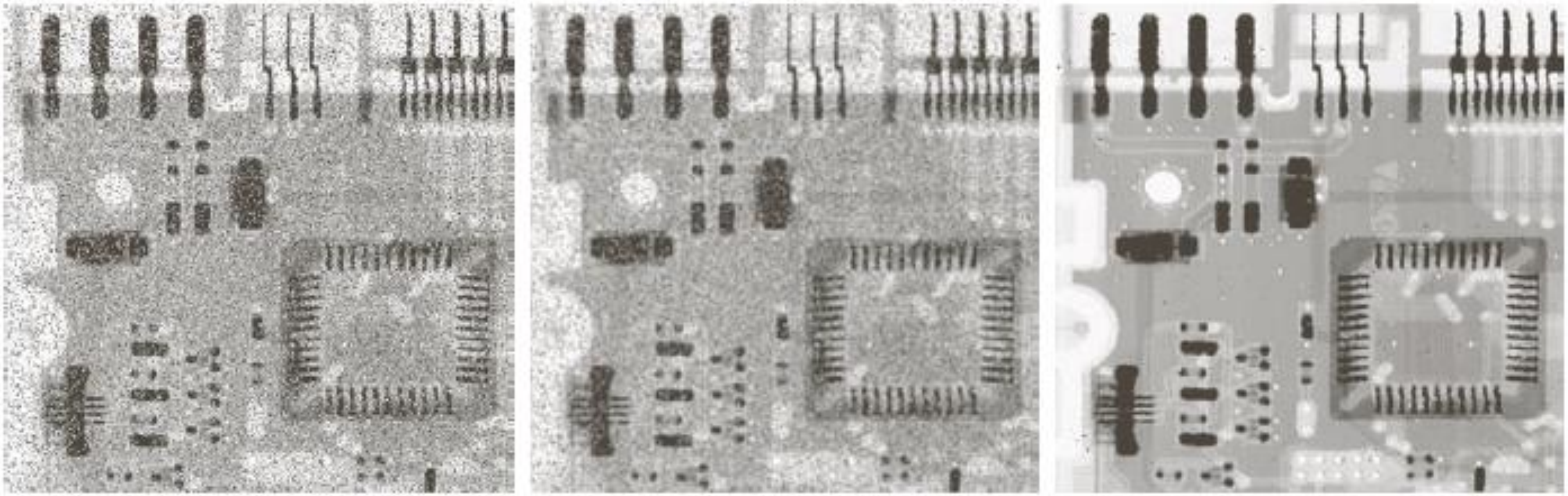
— Replacing the value of the center pixel with the value determined by the ranking result

E.g., median filter, max filter, min filter

Median filters are popular. It can remove random noise, especially *salt-and-pepper* noise.

Max filters and min filters are popular in convolutional neural network

Example: Use of Median Filtering for Noise Reduction



a b c

FIGURE 3.35 (a) X-ray image of circuit board corrupted by salt-and-pepper noise. (b) Noise reduction with a 3×3 averaging mask. (c) Noise reduction with a 3×3 median filter. (Original image courtesy of Mr. Joseph E. Pascente, Lixi, Inc.)

Sharpening Spatial Filters

- Foundation
- Laplacian Operator
- Unsharp Masking and Highboost Filtering
- Using First-Order Derivatives for Nonlinear Image Sharpening — The Gradient

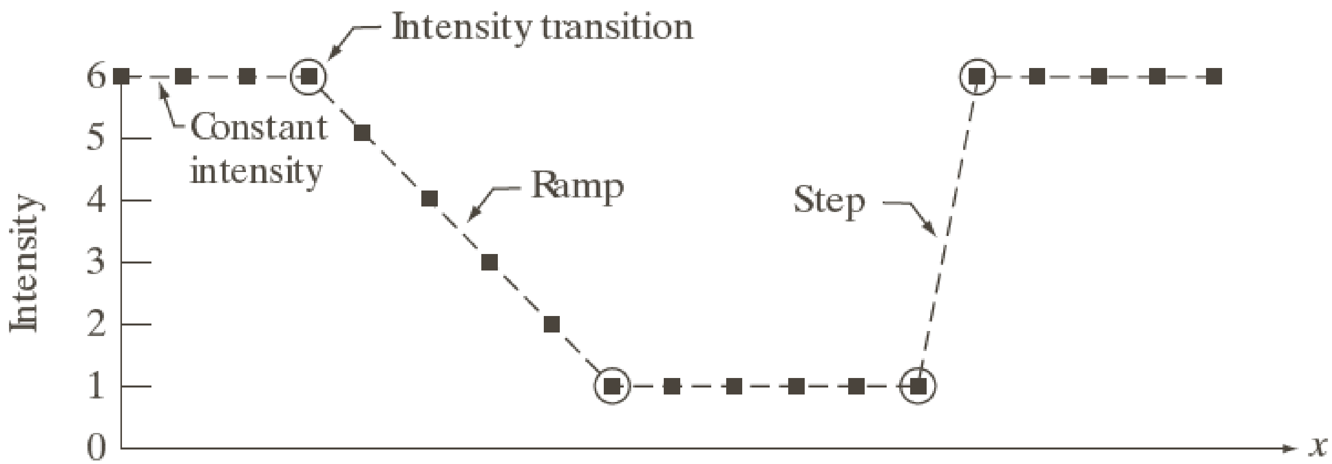
Sharpening Spatial Filters: Foundation

- The first-order derivative of a one-dimensional function f(x) is the difference

$$\frac{\partial f}{\partial x} = f(x+1) - f(x)$$

- The second-order derivative of f(x) as the difference

$$\frac{\partial^2 f}{\partial x^2} = f(x+1) + f(x-1) - 2f(x)$$



a
b
c

FIGURE 3.36 Illustration of the first and second derivatives of a 1-D digital function representing a section of a horizontal intensity profile from an image. In (a) and (c) data points are joined by dashed lines as a visualization aid.

Sharpening Spatial Filters: Laplace Operator

The second-order isotropic derivative operator is the Laplacian for a function (image) f(x,y)

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

$$\frac{\partial^2 f}{\partial x^2} = f(x+1, y) + f(x-1, y) - 2f(x, y)$$

$$\frac{\partial^2 f}{\partial y^2} = f(x, y+1) + f(x, y-1) - 2f(x, y)$$

$$\nabla^2 f = f(x+1, y) + f(x-1, y) + f(x, y+1) + f(x, y-1)$$

$$-4f(x, y)$$

Sharpening Spatial Filters: Laplace Operator

0	1	0
1	−4	1
0	1	0

1	1	1
1	−8	1
1	1	1

0	−1	0
−1	4	−1
0	−1	0

−1	−1	−1
−1	8	−1
−1	−1	−1

a	b
c	d

FIGURE 3.37 (a) Filter mask used to implement Eq. (3.6-6). (b) Mask used to implement an extension of this equation that includes the diagonal terms. (c) and (d) Two other implementations of the Laplacian found frequently in practice.

Sharpening Spatial Filters: Laplace Operator

Image sharpening in the way of using the Laplacian:

$$g(x,y) = f(x,y) + c\left[\nabla^2 f(x,y)\right]$$

where,

$f(x,y)$ is input image,

$g(x,y)$ is sharpenend images,

$c =$ -1 if $\nabla^2 f(x,y)$ corresponding to Fig. 3.37(a) or (b)

and $c = 1$ if either of the other two filters is used.

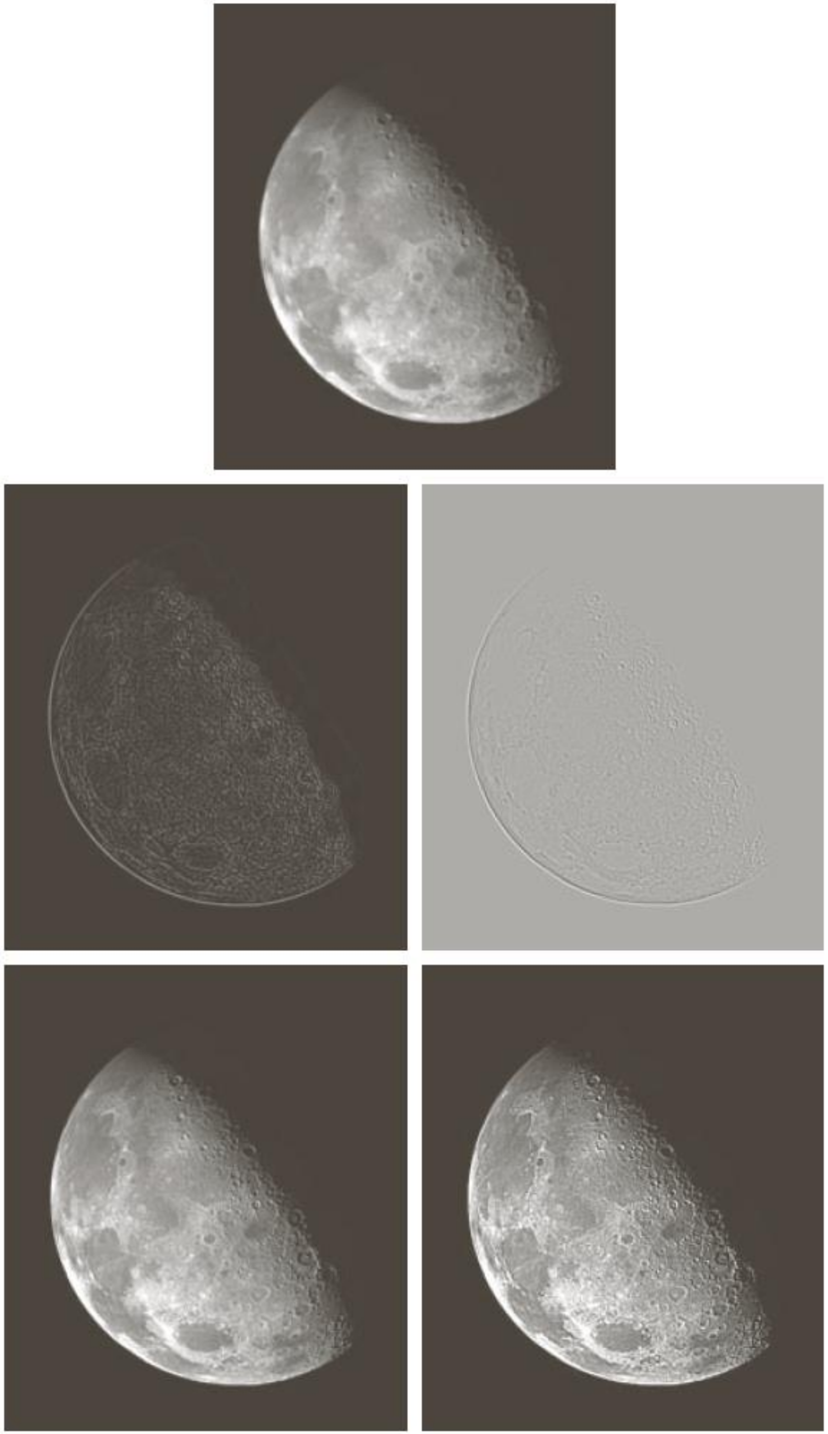


FIGURE 3.38
(a) Blurred image of the North Pole of the moon. (b) Laplacian without scaling. (c) Laplacian with scaling. (d) Image sharpened using the mask in Fig. 3.37(a). (e) Result of using the mask in Fig. 3.37(b). (Original image courtesy of NASA.)

Unsharp Masking and Highboost Filtering

- Unsharp masking

  Sharpen images consists of subtracting an unsharp (smoothed) version of an image from the original image

  e.g., printing and publishing industry

- Steps

  1. Blur the original image

  2. Subtract the blurred image from the original

  3. Add the mask to the original

Unsharp Masking and Highboost Filtering

Let $\overline{f}(x, y)$ denote the blurred image, unsharp masking is

$$g_{mask}(x, y) = f(x, y) - \overline{f}(x, y)$$

Then add a weighted portion of the mask back to the original

$$g(x, y) = f(x, y) + k * g_{mask}(x, y) \qquad k \geq 0$$

when $k > 1$, the process is referred to as highboost filtering.

Unsharp Masking: Demo

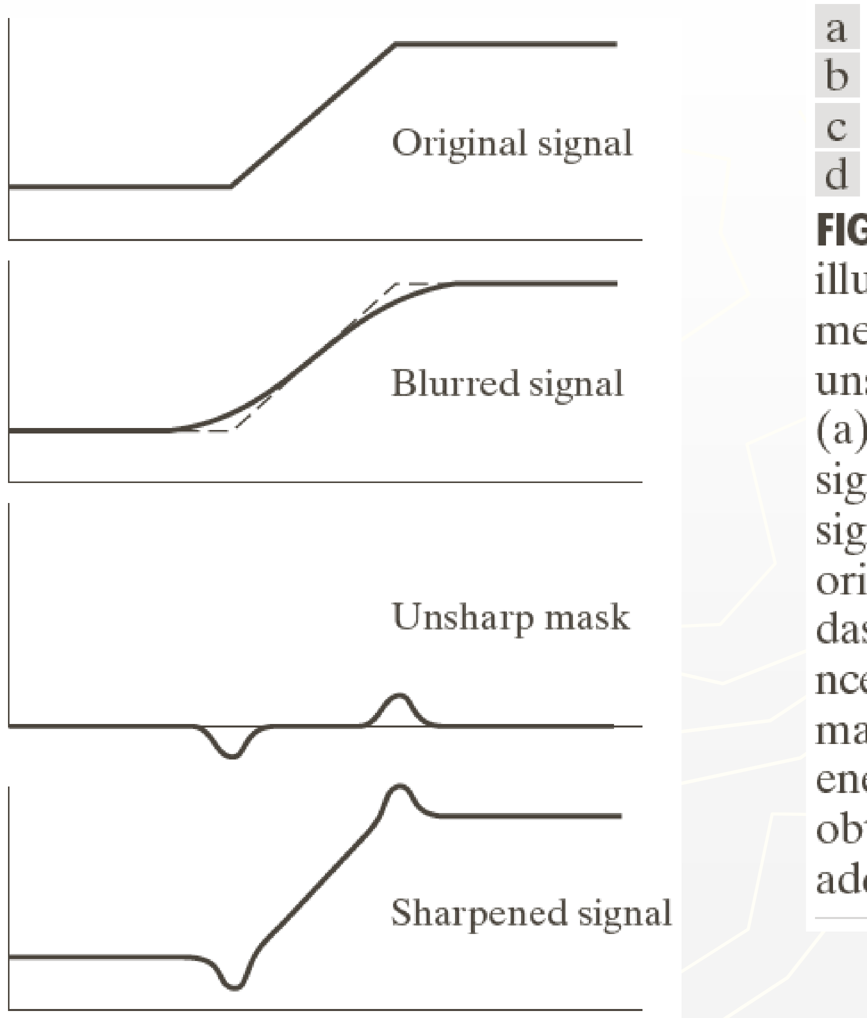


FIGURE 3.39 1-D illustration of the mechanics of unsharp masking. (a) Original signal. (b) Blurred signal with original shown dashed for reference. (c) Unsharp mask. (d) Sharpened signal, obtained by adding (c) to (a).

Unsharp Masking and Highboost Filtering: Example

a
b
c
d
e

FIGURE 3.40
(a) Original image.
(b) Result of blurring with a Gaussian filter.
(c) Unsharp mask. (d) Result of using unsharp masking.
(e) Result of using highboost filtering.

Image Sharpening based on First-Order Derivatives

For function $f(x, y)$, the gradient of f at coordinates (x, y) is defined as

$$\nabla f \equiv \text{grad}(f) \equiv \begin{bmatrix} g_x \\ g_y \end{bmatrix} = \begin{bmatrix} \dfrac{\partial f}{\partial x} \\ \dfrac{\partial f}{\partial y} \end{bmatrix}$$

The *magnitude* of vector ∇f, denoted as $M(x, y)$

Gradient Image $$M(x, y) = \text{mag}(\nabla f) = \sqrt{g_x^{\;2} + g_y^{\;2}}$$

Image Sharpening based on First-Order Derivatives

The *magnitude* of vector ∇f, denoted as $M(x, y)$

$$M(x, y) = \text{mag}(\nabla f) = \sqrt{{g_x}^2 + {g_y}^2}$$

$$M(x, y) \approx |g_x| + |g_y|$$

z_1	z_2	z_3
z_4	z_5	z_6
z_7	z_8	z_9

$$M(x, y) = |z_8 - z_5| + |z_6 - z_5|$$

Image Sharpening based on First-Order Derivatives

Roberts Cross-gradient Operators

$$M(x, y) \approx |z_9 - z_5| + |z_8 - z_6|$$

Sobel Operators

$$M(x, y) \approx |(z_7 + 2z_8 + z_9) - (z_1 + 2z_2 + z_3)|$$
$$+ |(z_3 + 2z_6 + z_9) - (z_1 + 2z_4 + z_7)|$$

z_1	z_2	z_3
z_4	z_5	z_6
z_7	z_8	z_9

Image Sharpening based on First-Order Derivatives

z_1	z_2	z_3
z_4	z_5	z_6
z_7	z_8	z_9

−1	0
0	1

0	−1
1	0

−1	−2	−1
0	0	0
1	2	1

−1	0	1
−2	0	2
−1	0	1

a
b c
d e

FIGURE 3.41 A 3 × 3 region of an image (the zs are intensity values). (b)–(c) Roberts cross gradient operators. (d)–(e) Sobel operators. All the mask coefficients sum to zero, as expected of a derivative operator.

Example

a b

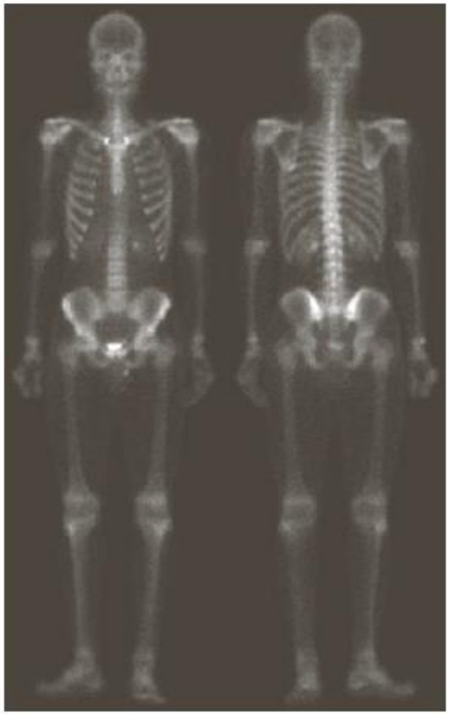
FIGURE 3.42
(a) Optical image of contact lens (note defects on the boundary at 4 and 5 o'clock). (b) Sobel gradient. (Original image courtesy of Pete Sites, Perceptics Corporation.)

Example:

Combining Spatial Enhancement Methods

Goal:

Enhance the image by sharpening it and by bringing out more of the skeletal detail



a b
c d

FIGURE 3.43
(a) Image of whole body bone scan.
(b) Laplacian of (a). (c) Sharpened image obtained by adding (a) and (b).
(d) Sobel gradient of (a).

Example:

Combining Spatial Enhancement Methods

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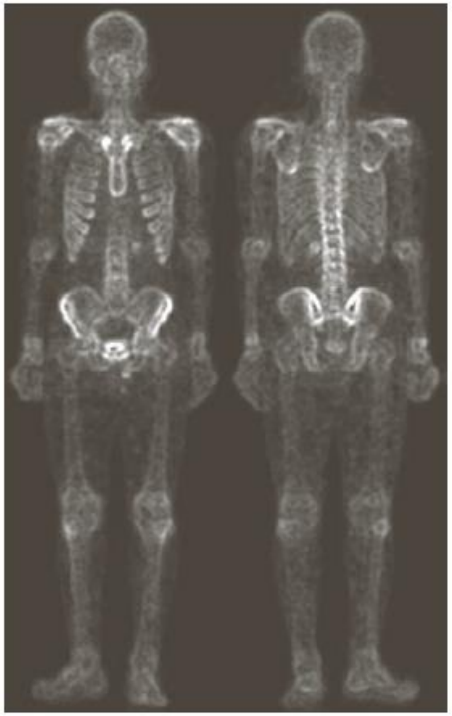
Enhance the image by sharpening it and by bringing out more of the skeletal detail



e f
g h

FIGURE 3.43 *(Continued)* (e) Sobel image smoothed with a 5×5 averaging filter. (f) Mask image formed by the product of (c) and (e). (g) Sharpened image obtained by the sum of (a) and (f). (h) Final result obtained by applying a power-law transformation to (g). Compare (g) and (h) with (a). (Original image courtesy of G.E. Medical Systems.)