Filtering Images in the Spatial Domain
Chapter 3b G&W

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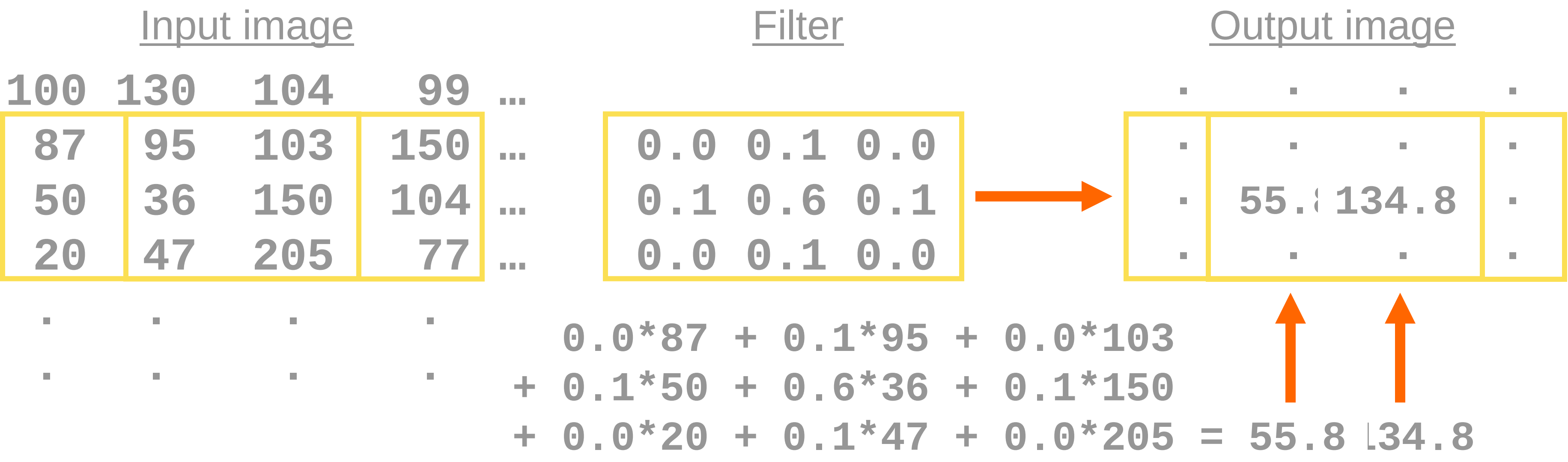
Overview

- Correlation and convolution
- Linear filtering
  - Smoothing, kernels, models
  - Detection
  - Derivatives
- Nonlinear filtering
  - Median filtering
  - Bilateral filtering
  - Neighborhood statistics and nonlocal filtering

Cross Correlation

- Operation on image neighborhood and small …
  - “mask”, “filter”, “stencil”, “kernel”
- Linear operations within a moving window



Input image

100	130	104	99	…
87	95	103	150	…
50	36	150	104	…
20	47	205	77	…
.	.	.	.	
.	.	.	.	

Filter

0.0	0.1	0.0
0.1	0.6	0.1
0.0	0.1	0.0

Output image

.	.	.	.
.	.	.	.
.	55.8	134.8	.
.	.	.	.

```
  0.0*87 + 0.1*95 + 0.0*103
+ 0.1*50 + 0.6*36 + 0.1*150
+ 0.0*20 + 0.1*47 + 0.0*205 = 55.8 134.8
```

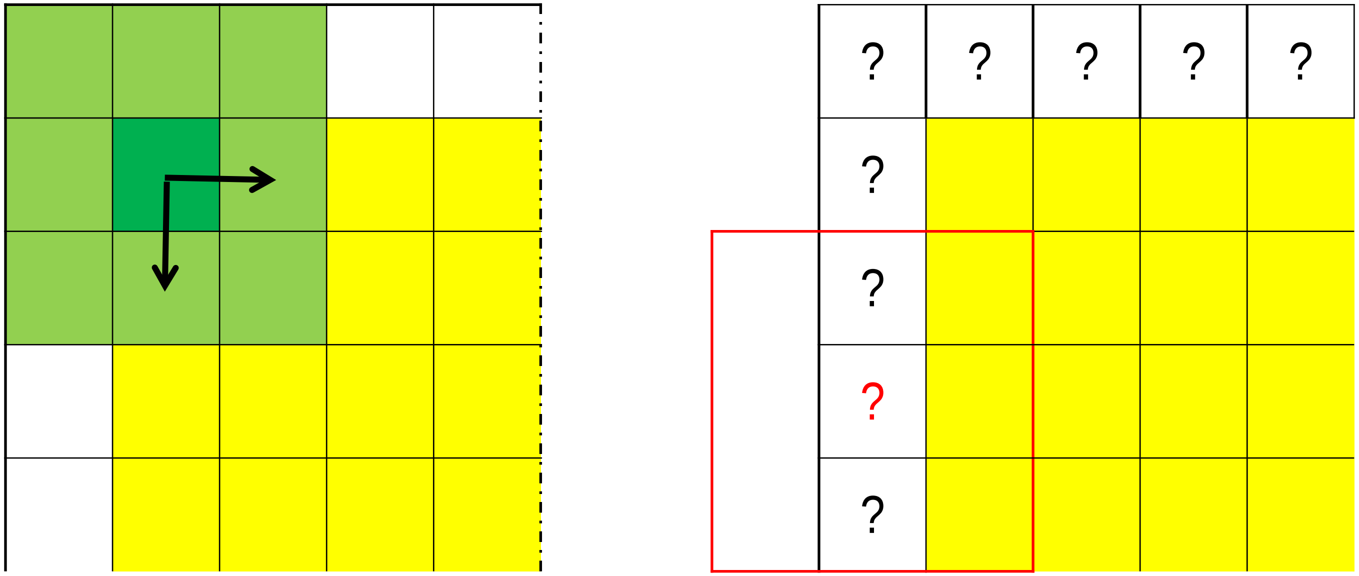
Cross Correlation

- 1D $$g(x) = \sum_{s=-a}^{a} w(s) f(x+s)$$
- 2D $$g(x,y) = \sum_{s=-a}^{a} \sum_{t=-b}^{b} w(s,t) f(x+s, y+t)$$

$$w(s,t) = \boxed{\begin{array}{ccccc} w(-a,-b) & \cdots & & \cdots & w(a,-b) \\ \vdots & & & & \vdots \\ & \cdots & w(0,0) & \cdots & \\ \vdots & & & & \vdots \\ w(-a,b) & \cdots & & \cdots & w(a,b) \end{array}}$$

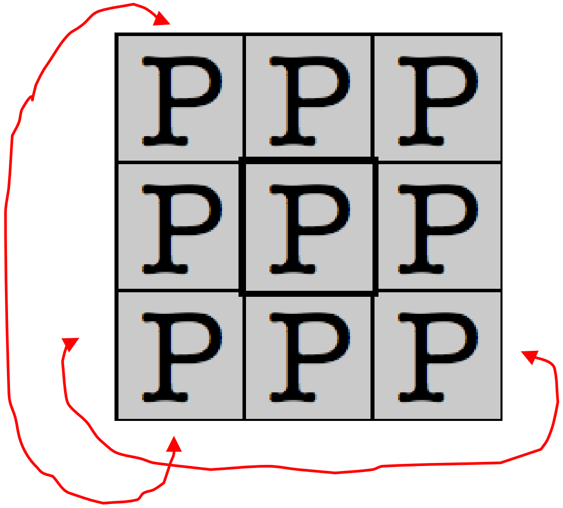
Correlation: Technical Details

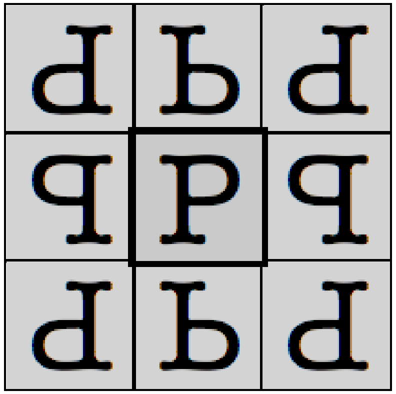
- How to filter boundary?



Correlation: Technical Details

- Boundary conditions
  - – Boundary not filtered (keep it 0)
  - – Pad image with amount (a,b)
    - Constant value or repeat edge values
  - – Cyclical boundary conditions
    - Wrap or mirroring





Correlation: Technical Details

- Boundaries
  - Can also modify kernel – no longer correlation
- For analysis
  - Image domains infinite
  - Data compact (goes to zero far away from origin)

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

Correlation: Properties

- Shift invariant

$$g = w \circ f \qquad g(x,y) = w(x,y) \circ f(x,y)$$

$$w(x,y) \circ f(x-x_0, y-y_0) = \sum_{s=-\infty}^{\infty} \sum_{t=-\infty}^{\infty} w(s,t) f(x-x_0+s, y-y_0+t) = g(x-x_0, y-y_0)$$

Correlation: Properties

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- Linear $w \circ (\alpha e + \beta f) = \alpha w \circ e + \beta w \circ f$

Compact notation

$$C_{wf} = w \circ f$$

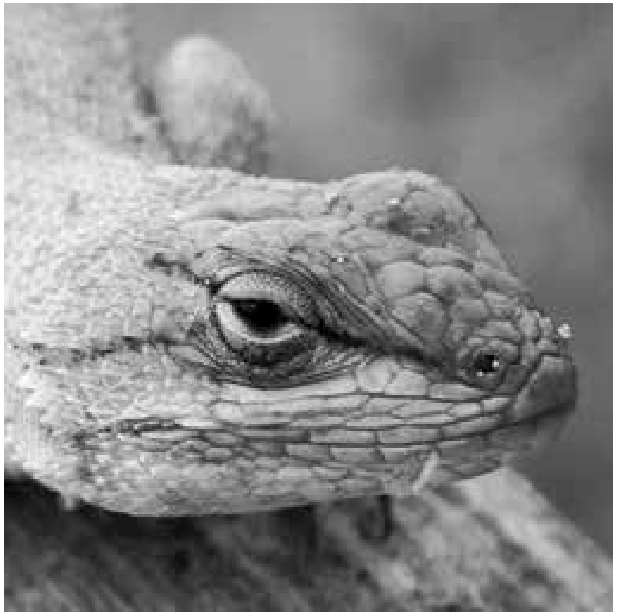
Filters: Considerations

- Normalize
  - Sums to one
  - Sums to zero (some cases, see later)
- Symmetry
  - Left, right, up, down
  - Rotational
- Special case: auto correlation

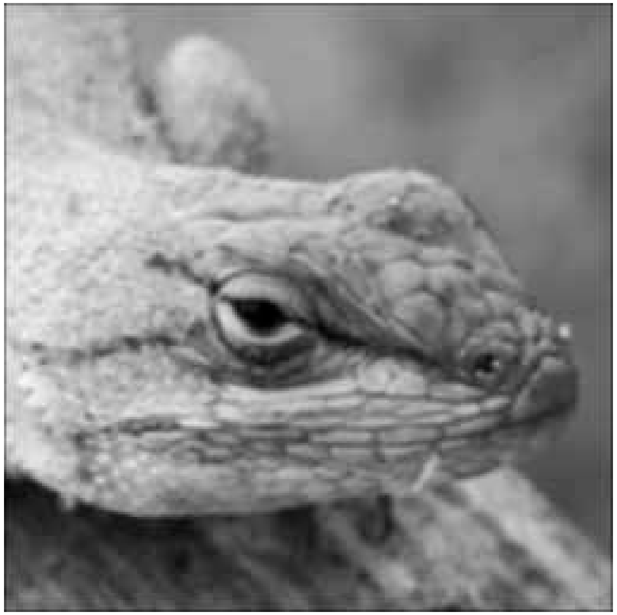
$$C_{ff} = f \circ f$$

Examples 1

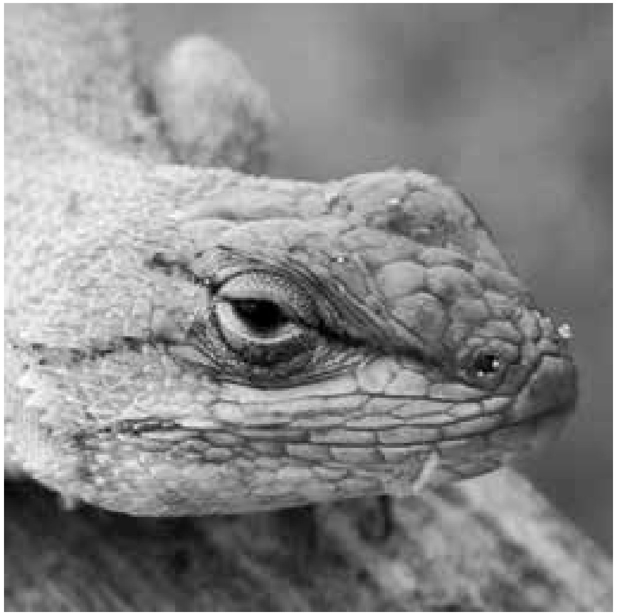
$$\begin{matrix}0 & 0 & 0\\0 & 1 & 0\\0 & 0 & 0\end{matrix}$$



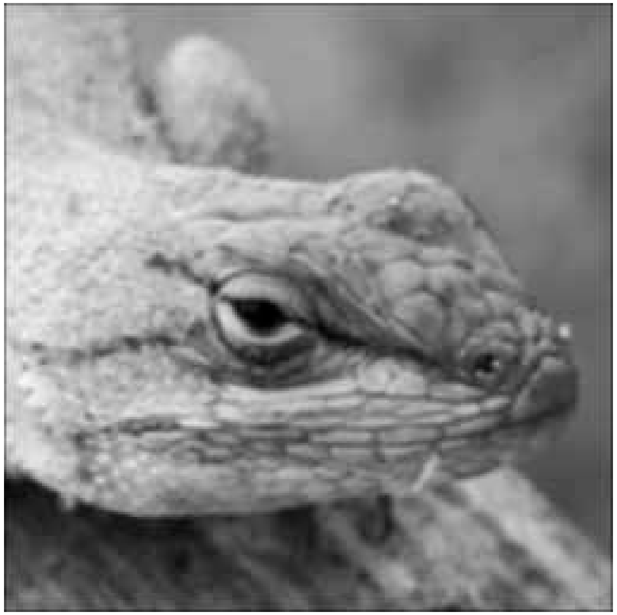
$$1/9 * \begin{matrix}1 & 1 & 1\\1 & 1 & 1\\1 & 1 & 1\end{matrix}$$

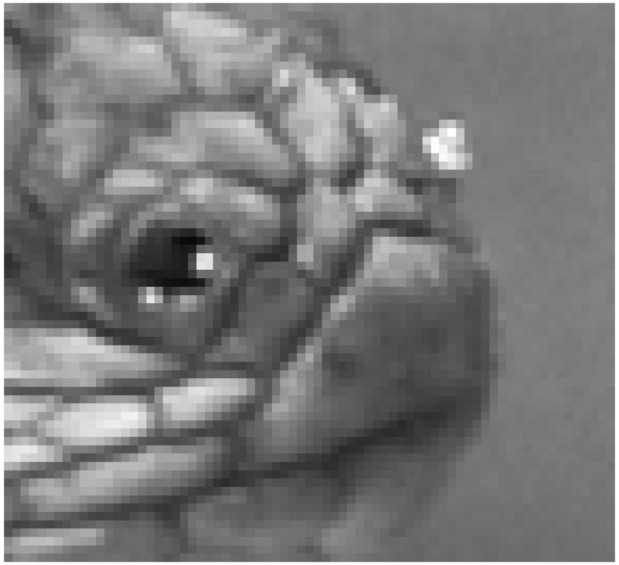


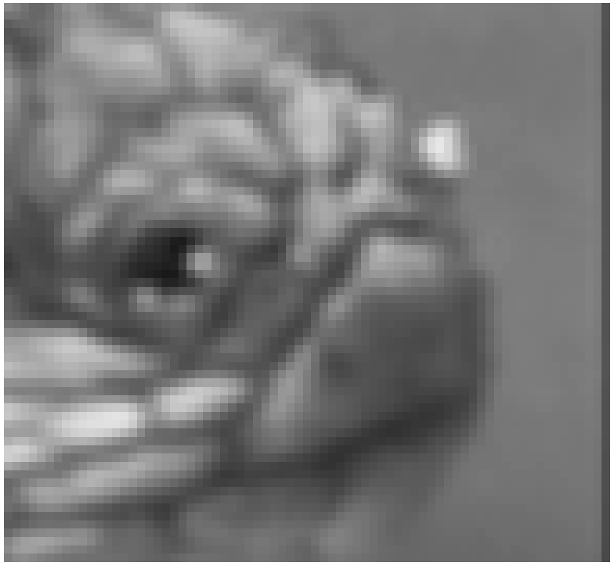
Examples 1



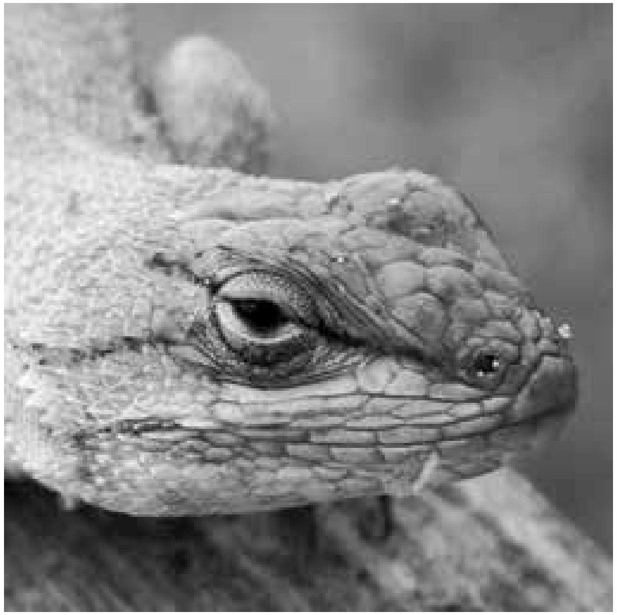
$$1/9 * \begin{matrix} 1 & 1 & 1 \\ 1 & 1 & 1 \\ 1 & 1 & 1 \end{matrix}$$



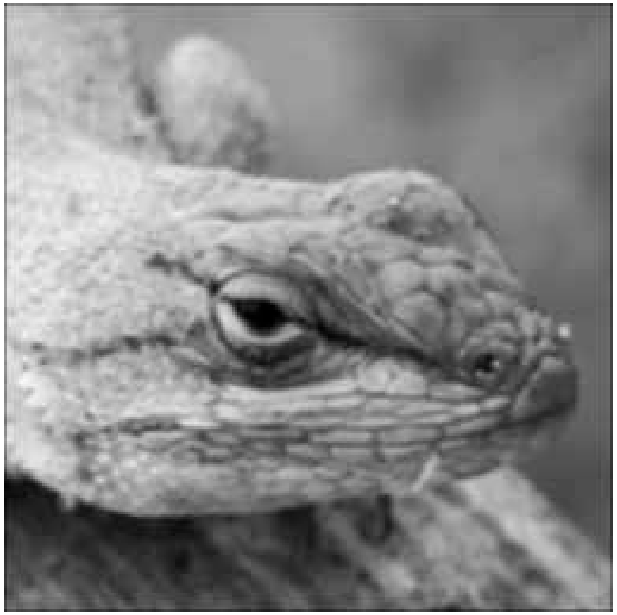


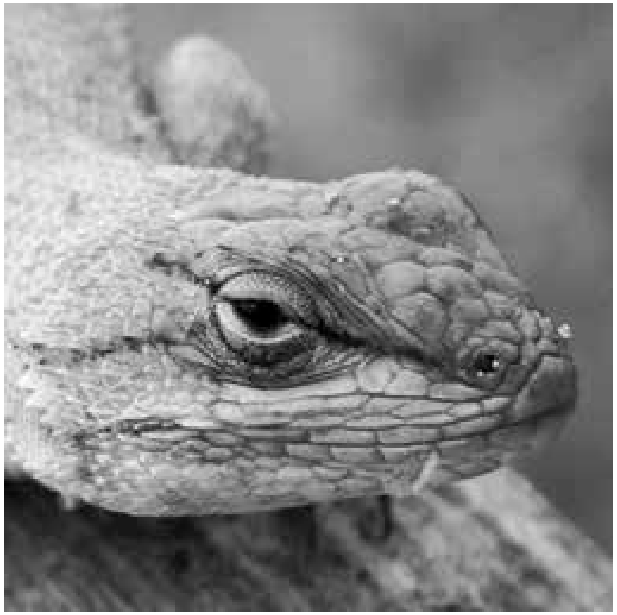


Examples 2

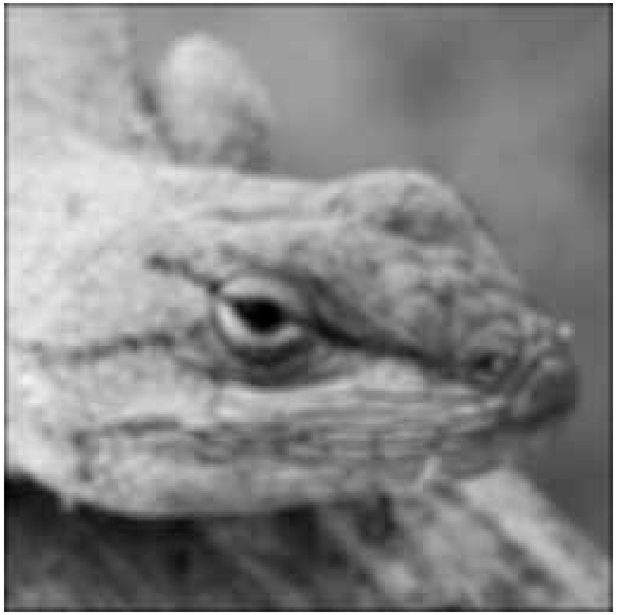


$$\frac{1}{9} * \begin{matrix} 1 & 1 & 1 \\ 1 & 1 & 1 \\ 1 & 1 & 1 \end{matrix}$$



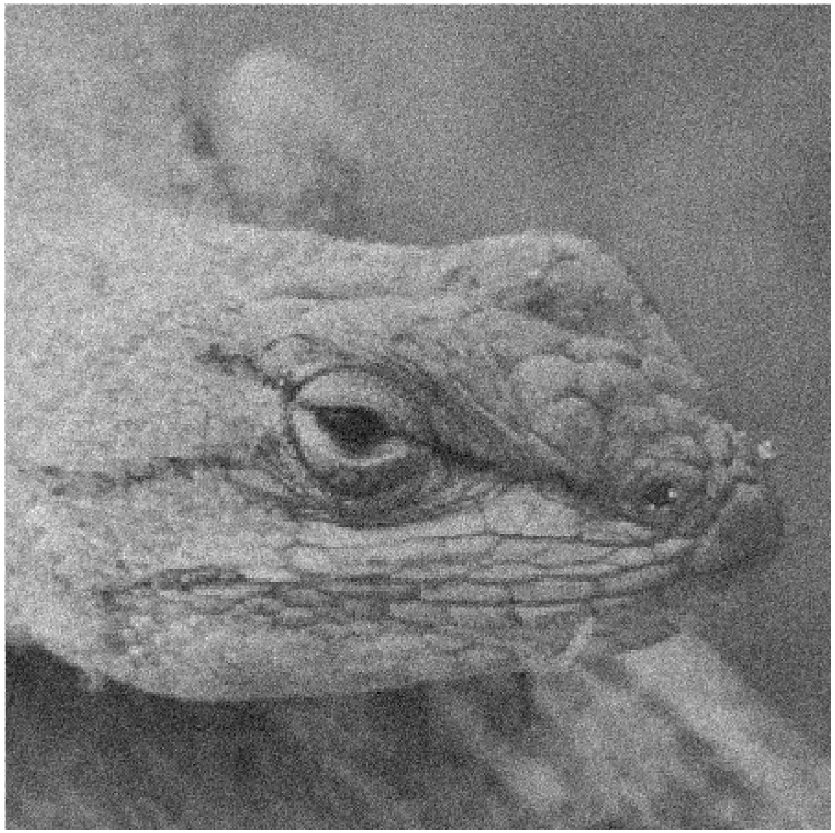


$$\frac{1}{25} * \begin{matrix} 1 & 1 & 1 & 1 & 1 \\ 1 & 1 & 1 & 1 & 1 \\ 1 & 1 & 1 & 1 & 1 \\ 1 & 1 & 1 & 1 & 1 \\ 1 & 1 & 1 & 1 & 1 \end{matrix}$$

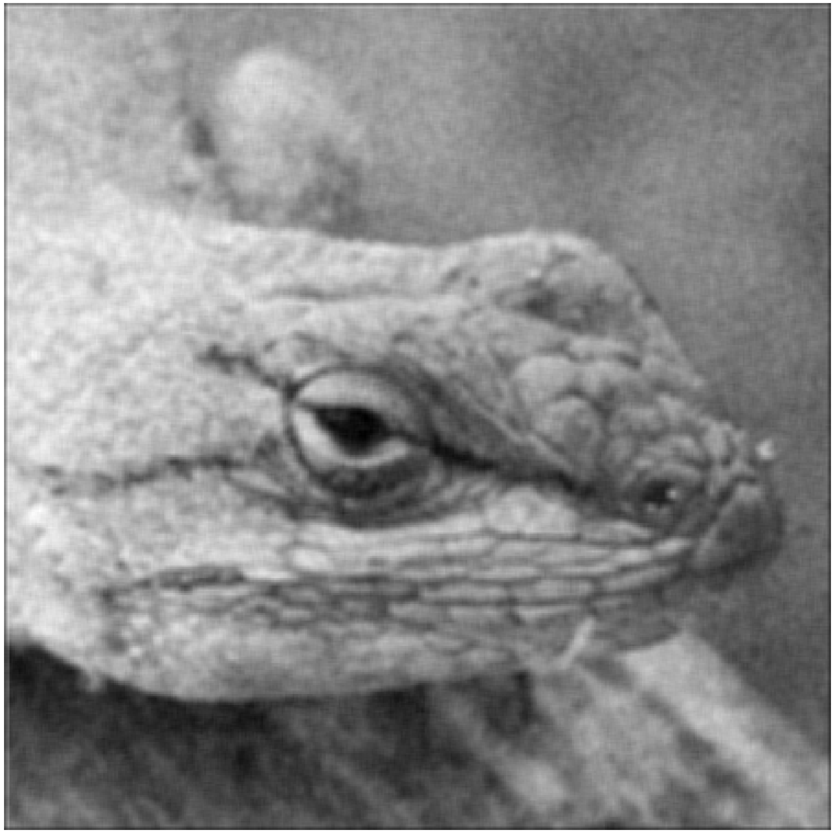


Smoothing and Noise

Noisy image



5x5 box filter



Noise Analysis

- Consider an a simple image I() with additive, uncorrelated, zero-mean noise of variance s
- What is the expected rms error of the corrupted image?
- If we process the image with a box filter of size 2a+1 what is the expected error of the filtered image?

$$\mathrm{RMSE} = \left(\frac{1}{|\mathcal{D}|} \sum_{(x,y)\in\mathcal{D}} \left(\tilde{I}(x,y) - I(x,y) \right)^2 \right)^{\frac{1}{2}}$$

Other Filters

- Disk
  - Circularly symmetric, jagged in discrete case
- Gaussians
  - Circularly symmetric, smooth for large enough stdev
  - Must normalize in order to sum to one
- Derivatives – discrete/finite differences
  - Operators

Gaussian Kernel

$$\sigma = 1;\ \mathrm{Plot}\left[\frac{1}{\sqrt{2\,\pi\,\sigma^2}}\,\mathrm{E}^{-\frac{x^2}{2\,\sigma^2}},\ \{x,\ -4,\ 4\},\ \mathrm{ImageSize} \ \text{->}\right.$$

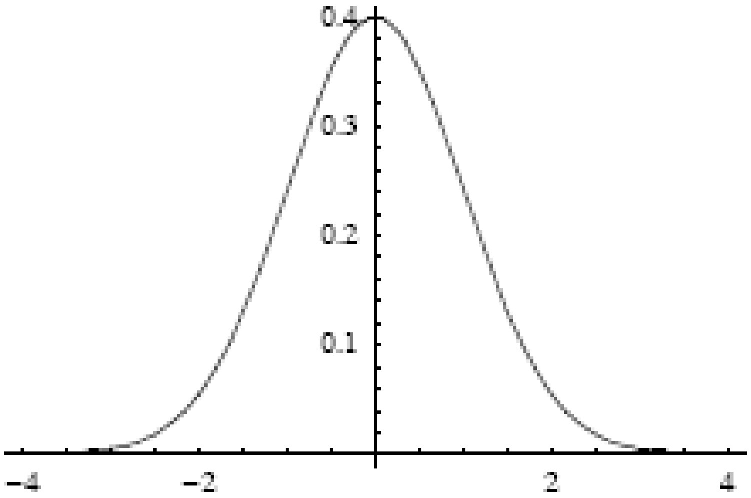


Figure 2.1 The Gaussian kernel with unit standard deviation in 1D.

Gaussian Kernel

$$G_{1\,D}(x;\sigma) = \frac{1}{\sqrt{2\pi}\;\sigma}\,e^{-\frac{x^2}{2\sigma^2}},\; G_{2\,D}(x,\,y;\sigma) = \frac{1}{2\,\pi\sigma^2}\,e^{-\frac{x^2+y^2}{2\sigma^2}},\; G_{ND}(\vec{x};\sigma) = \frac{1}{\left(\sqrt{2\pi}\;\sigma\right)^N}\,e^{-\frac{|\vec{x}|^2}{2\sigma^2}}$$

Normalization to 1.0

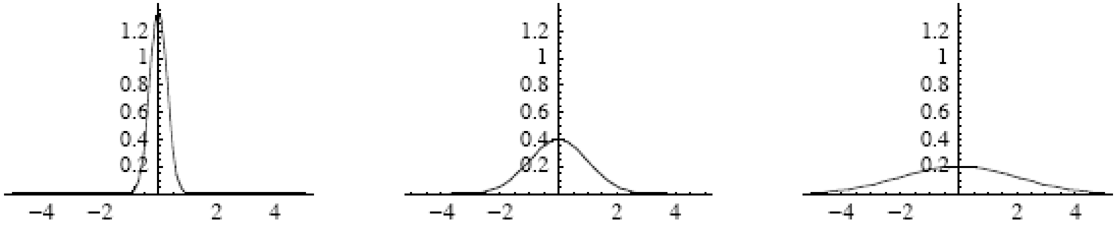


Figure 3.2 The Gaussian function at scales $\sigma = .3$, $\sigma = 1$ and $\sigma = 2$. The kernel is normalized, so the total area under the curve is always unity.

Convolution

Java demo: http://www.jhu.edu/signals/convolve/
http://www.jhu.edu/signals/discreteconv2/index.html

- Discrete

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

- Continuous

$$g(x,y) = w(x,y) * f(x,y) = \int_{-\infty}^{\infty} \int_{-\infty}^{\infty} w(s,t) f(x-s, y-t) ds dt$$

- Same as cross correlation with kernel transposed around each axis
- The two operations (correlation and convolution) are the same if the kernel is symmetric about axes

$$g = w \circ f = w^* * f$$

w^* reflection of w

Convolution: Properties

- Shift invariant, linear
- Commutative

$$f * g = g * f$$

- Associative

$$f * (g * h) = (f * g) * h$$

- Others (discussed later):
  - Derivatives, convolution theorem, spectrum…

Computing Convolution

- Compute time
  - MxM mask
  - NxN image

$O(M^2N^2)$

“for” loops are nested 4 deep

Computing Convolution

- Compute time
  - MxM mask
  - NxN image

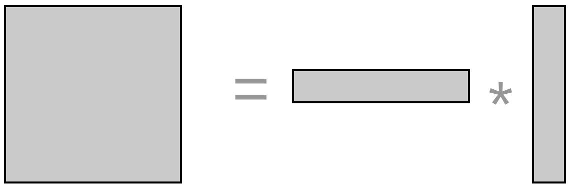
$O(M^2N^2)$

"for" loops are nested 4 deep

- Special case: *separable*

$$w = \overbrace{w_x * w_y}^{\text{Two 1D kernels}}$$

$$w * f = \underbrace{(w_x * w_y) * f}_{O(M^2N^2)} = \underbrace{w_x * (w_y * f)}_{O(MN^2)}$$



Separable Kernels

- Examples
  - Box/rectangle
  - Bilinear interpolation
  - Combinations of partial derivatives
    - $d^2f/dxdy$
  - Gaussian
    - Only filter that is both circularly symmetric and separable

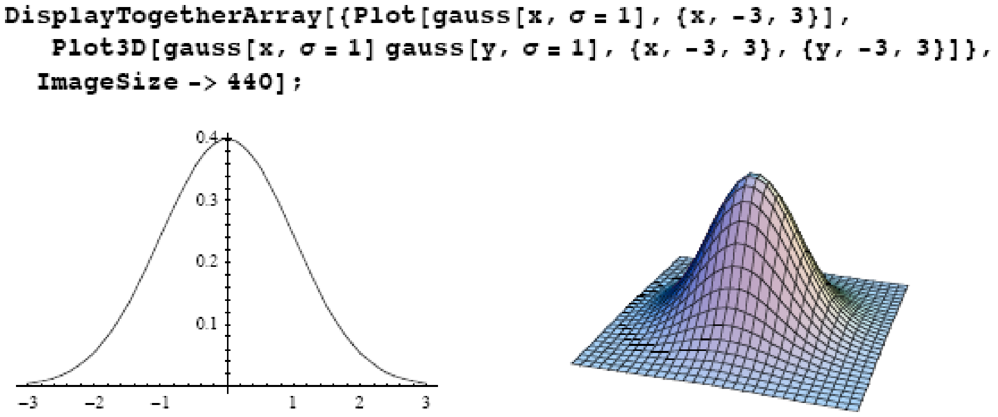
- Counter examples
  - Disk
  - Cone
  - Pyramid

Separability

$$
\begin{aligned}
G_\sigma(x,y) &= \frac{1}{2\pi\sigma^2}\exp^{-\dfrac{x^2+y^2}{2\sigma^2}} \\
&= \left(\frac{1}{\sqrt{2\pi}\sigma}\exp^{-\dfrac{x^2}{2\sigma^2}}\right)\left(\frac{1}{\sqrt{2\pi}\sigma}\exp^{-\dfrac{y^2}{2\sigma^2}}\right)
\end{aligned}
$$

The 2D Gaussian can be expressed as the product of two functions, one a function of *x* and the other a function of *y*

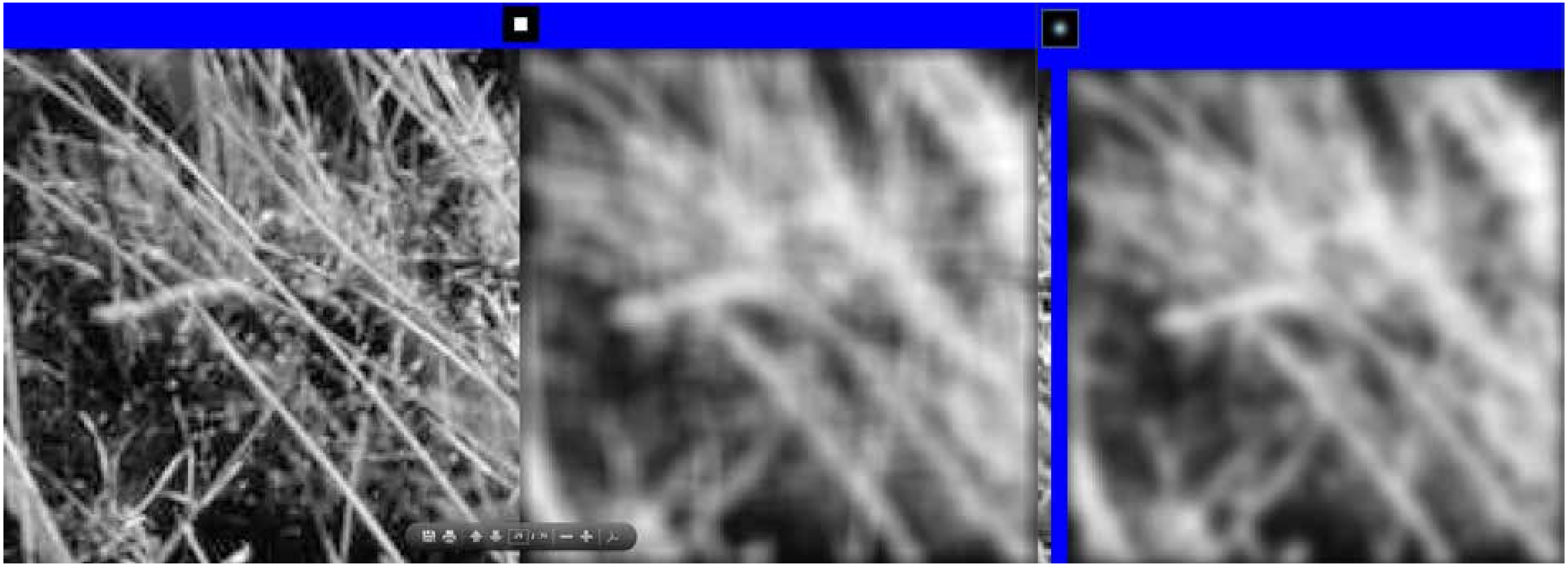
In this case, the two functions are the (identical) 1D Gaussian



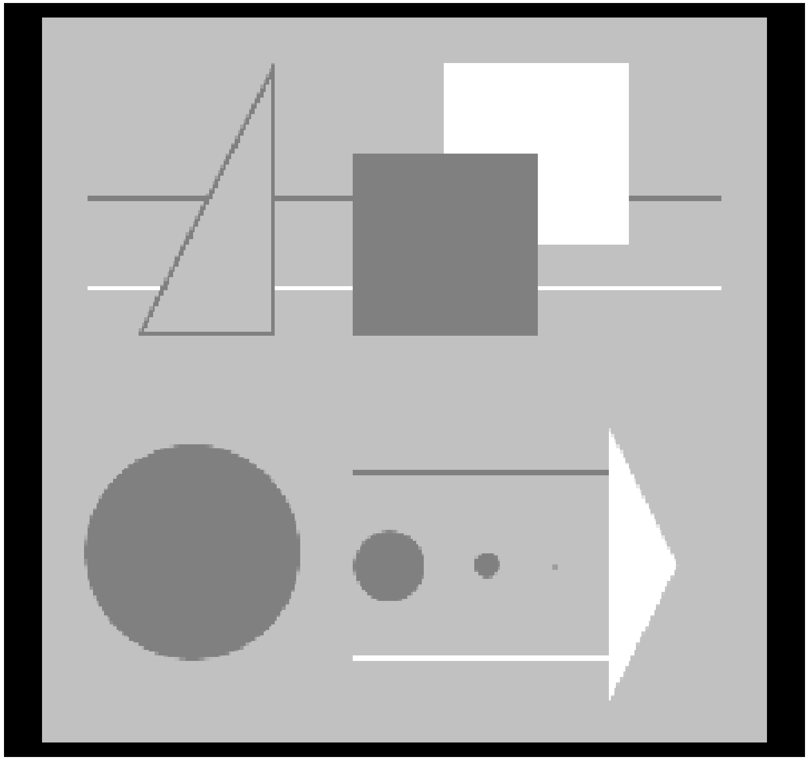
```
DisplayTogetherArray[{Plot[gauss[x, σ = 1], {x, -3, 3}],
   Plot3D[gauss[x, σ = 1] gauss[y, σ = 1], {x, -3, 3}, {y, -3, 3}]},
  ImageSize -> 440];
```

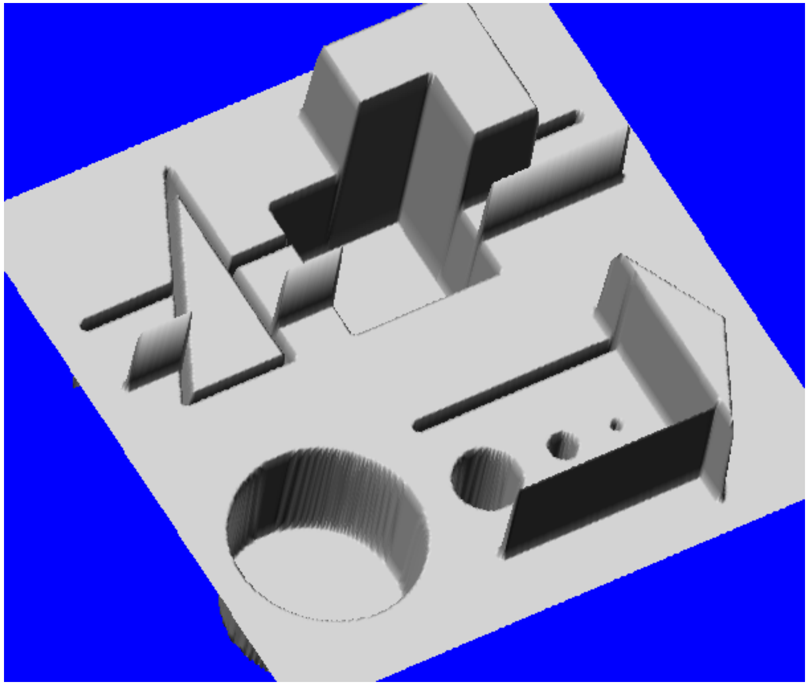
Figure 3.7 A product of Gaussian functions gives a higher dimensional Gaussian function. This is a consequence of the separability.

Box versus Gaussian



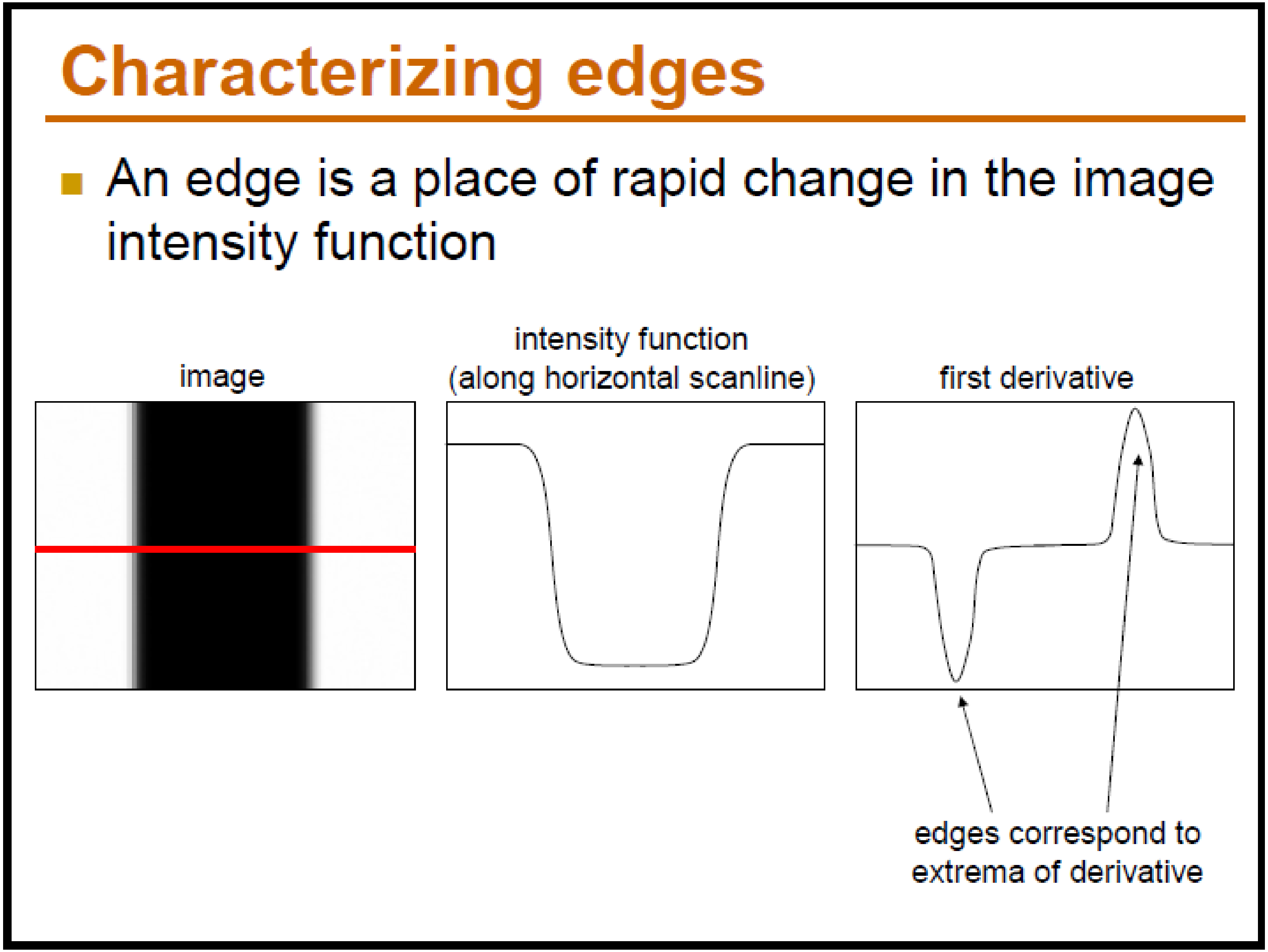
Digital Images: Boundaries are “Lines” or “Discontinuities”





Example: Characterization of discontinuities?

Source: http://web.media.mit.edu/~maov/classes/vision09/lect/09_Image_Filtering_Edge_Detection_09.pdf



Characterizing edges

- An edge is a place of rapid change in the image intensity function

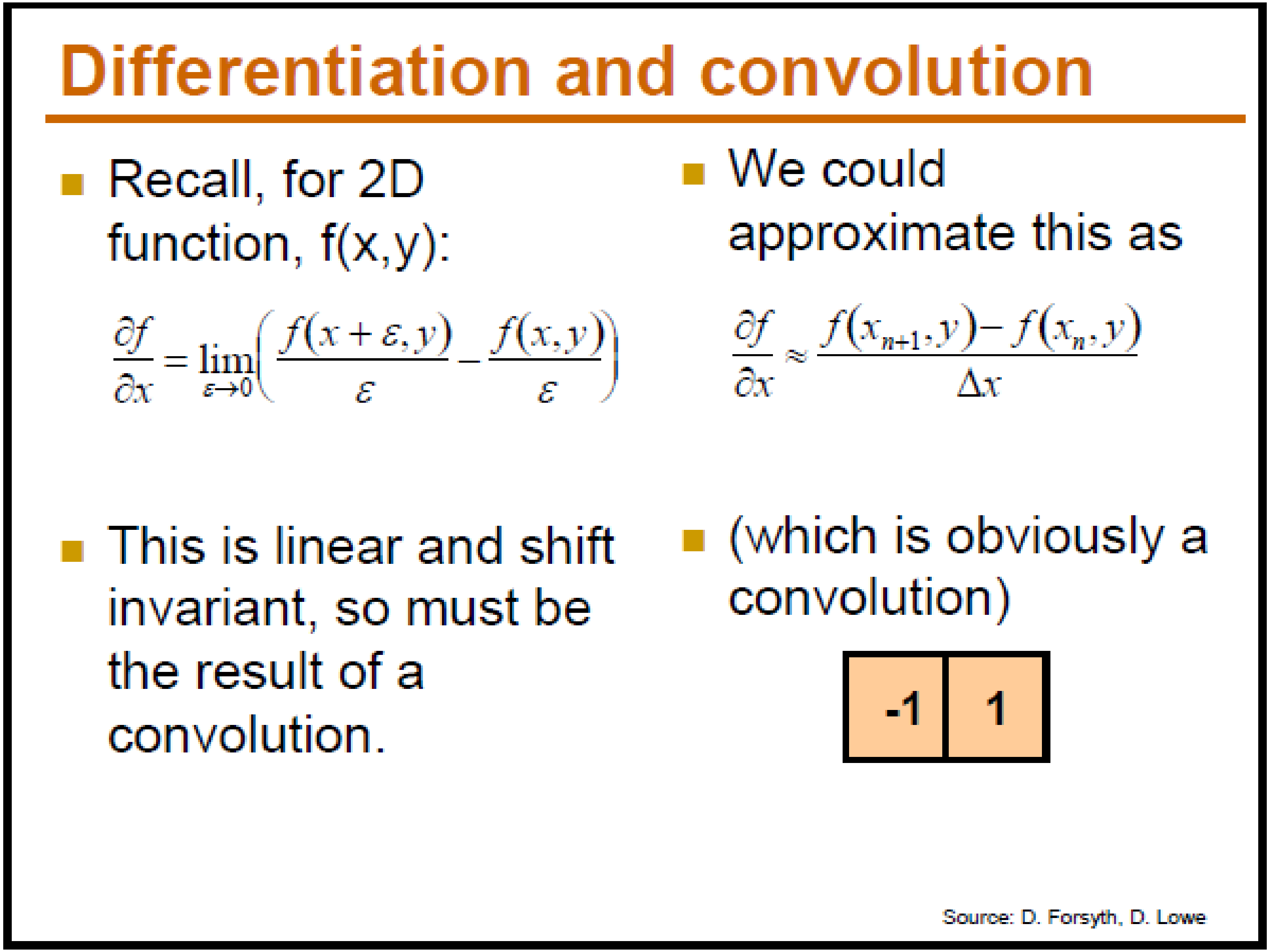
image

intensity function (along horizontal scanline)

first derivative

edges correspond to extrema of derivative

Source: http://web.media.mit.edu/~maov/classes/vision09/lect/09_Image_Filtering_Edge_Detection_09.pdf



Differentiation and convolution

- Recall, for 2D function, f(x,y):

$$\frac{\partial f}{\partial x} = \lim_{\varepsilon \to 0}\left(\frac{f(x+\varepsilon, y)}{\varepsilon} - \frac{f(x,y)}{\varepsilon}\right)$$

- This is linear and shift invariant, so must be the result of a convolution.

- We could approximate this as

$$\frac{\partial f}{\partial x} \approx \frac{f(x_{n+1}, y) - f(x_n, y)}{\Delta x}$$

- (which is obviously a convolution)

-1	1

Source: D. Forsyth, D. Lowe

Source: http://web.media.mit.edu/~maov/classes/vision09/lect/09_Image_Filtering_Edge_Detection_09.pdf

Derivatives: Finite Differences

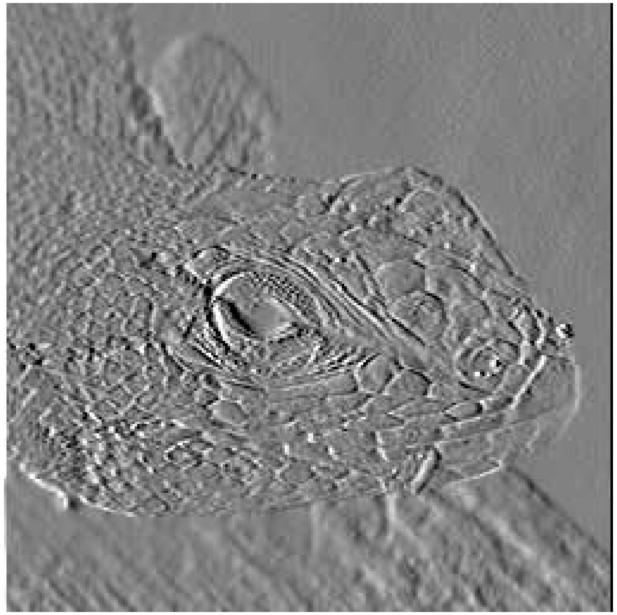
$$\frac{\partial f}{\partial x} \approx \frac{1}{2h}\left(f(x+1,y) - f(x-1,y)\right)$$

$$\frac{\partial f}{\partial x} \approx w_{dx} \circ f \qquad w_{dx} = \begin{array}{|c|c|c|}\hline -\frac{1}{2} & 0 & \frac{1}{2} \\ \hline \end{array}$$

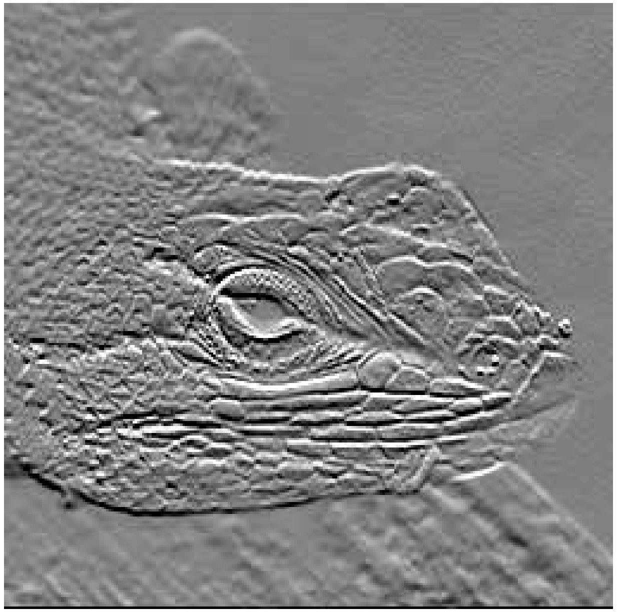
$$\frac{\partial f}{\partial y} \approx w_{dy} \circ f \qquad w_{dy} = \begin{array}{|c|}\hline -\frac{1}{2} \\ \hline 0 \\ \hline \frac{1}{2} \\ \hline \end{array}$$

Derivative Example

$$\begin{matrix} 0 & 0 & 0 \\ -1 & 0 & 1 \\ 0 & 0 & 0 \end{matrix}$$



$$\begin{matrix} 0 & -1 & 0 \\ 0 & 0 & 0 \\ 0 & 1 & 0 \end{matrix}$$



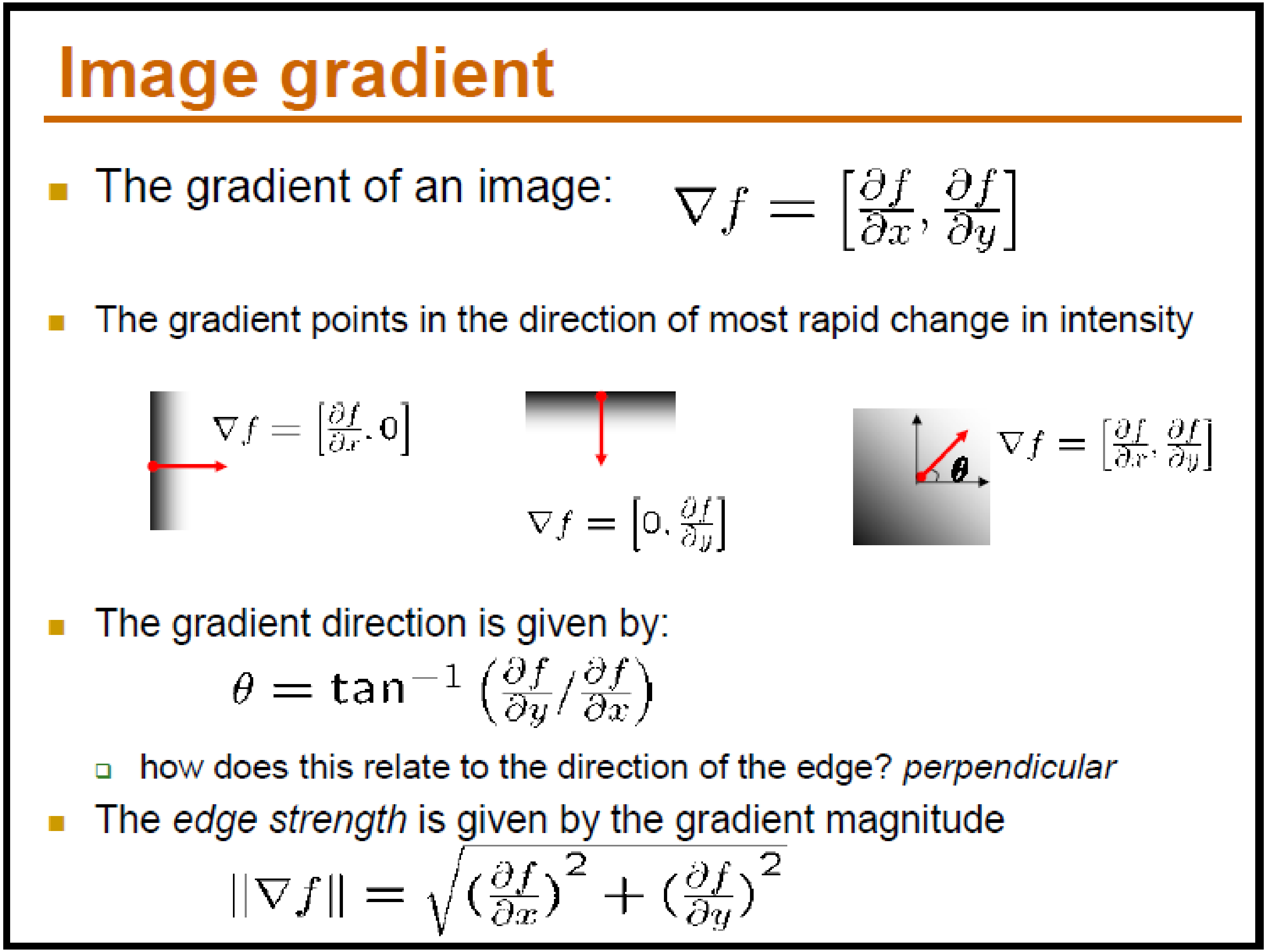


Image gradient

- The gradient of an image: $\nabla f = \left[\frac{\partial f}{\partial x}, \frac{\partial f}{\partial y}\right]$
- The gradient points in the direction of most rapid change in intensity

$\nabla f = \left[\frac{\partial f}{\partial x}, 0\right]$

$\nabla f = \left[0, \frac{\partial f}{\partial y}\right]$

$\nabla f = \left[\frac{\partial f}{\partial x}, \frac{\partial f}{\partial y}\right]$

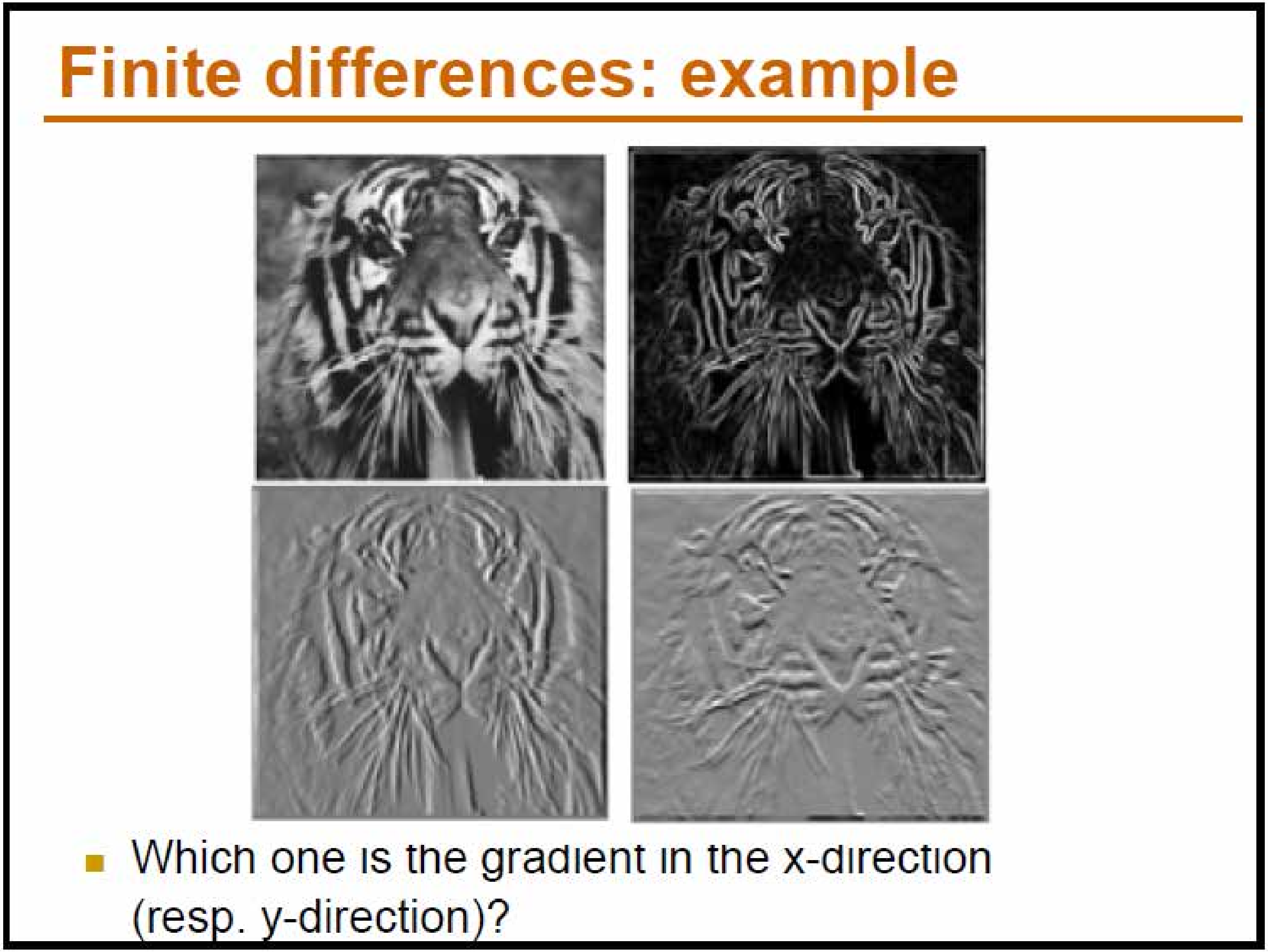
- The gradient direction is given by:

$$\theta = \tan^{-1}\left(\frac{\partial f}{\partial y} / \frac{\partial f}{\partial x}\right)$$

  - how does this relate to the direction of the edge? *perpendicular*
- The *edge strength* is given by the gradient magnitude

$$\|\nabla f\| = \sqrt{\left(\frac{\partial f}{\partial x}\right)^2 + \left(\frac{\partial f}{\partial y}\right)^2}$$

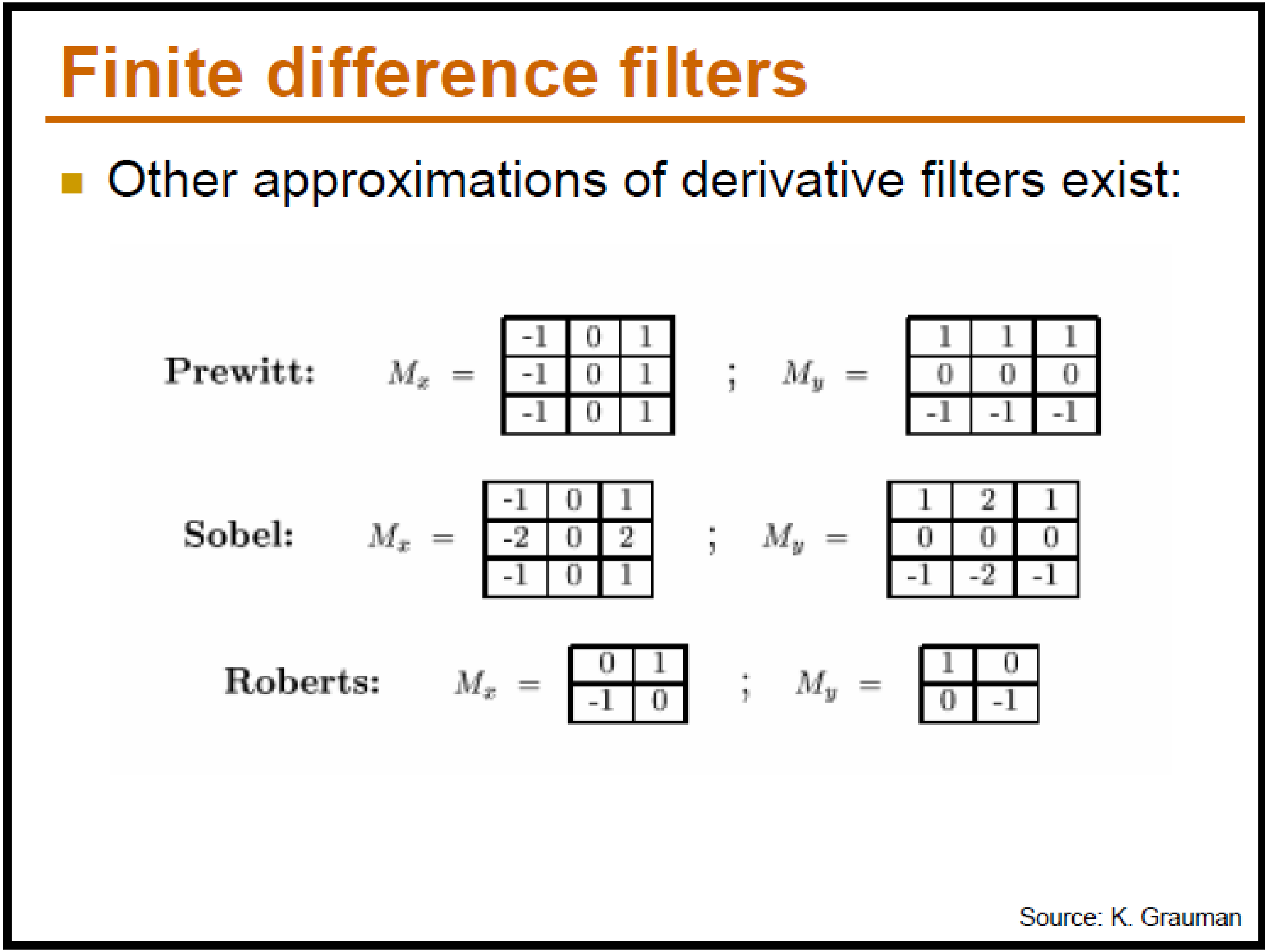
Source: http://web.media.mit.edu/~maov/classes/vision09/lect/09_Image_Filtering_Edge_Detection_09.pdf



Finite differences: example

- Which one is the gradient in the x-direction (resp. y-direction)?

Source: http://web.media.mit.edu/~maov/classes/vision09/lect/09_Image_Filtering_Edge_Detection_09.pdf



Finite difference filters

- Other approximations of derivative filters exist:

$$\textbf{Prewitt:}\quad M_x = \begin{array}{|c|c|c|}\hline -1 & 0 & 1 \\ \hline -1 & 0 & 1 \\ \hline -1 & 0 & 1 \\ \hline \end{array} \quad ; \quad M_y = \begin{array}{|c|c|c|}\hline 1 & 1 & 1 \\ \hline 0 & 0 & 0 \\ \hline -1 & -1 & -1 \\ \hline \end{array}$$

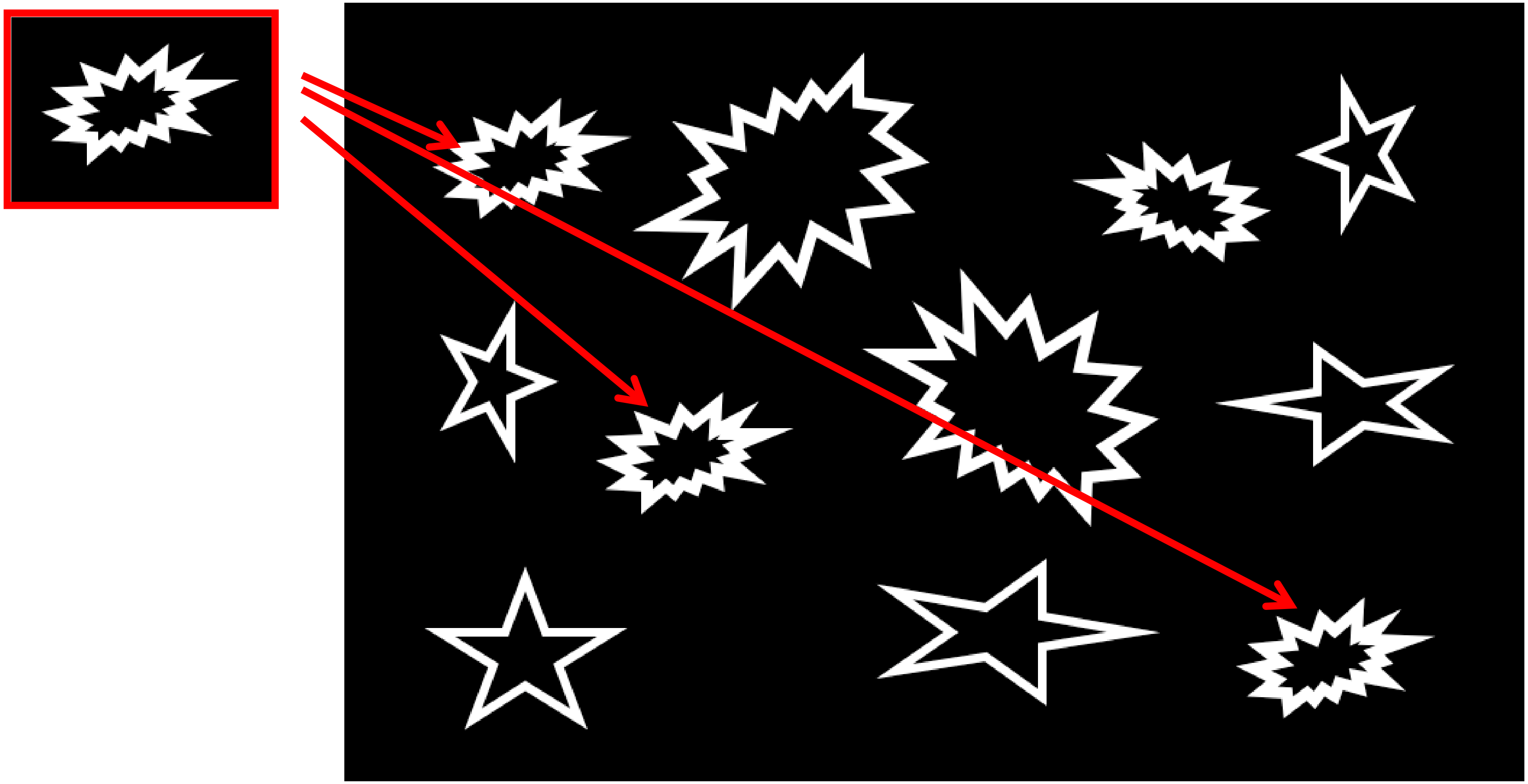
$$\textbf{Sobel:}\quad M_x = \begin{array}{|c|c|c|}\hline -1 & 0 & 1 \\ \hline -2 & 0 & 2 \\ \hline -1 & 0 & 1 \\ \hline \end{array} \quad ; \quad M_y = \begin{array}{|c|c|c|}\hline 1 & 2 & 1 \\ \hline 0 & 0 & 0 \\ \hline -1 & -2 & -1 \\ \hline \end{array}$$

$$\textbf{Roberts:}\quad M_x = \begin{array}{|c|c|}\hline 0 & 1 \\ \hline -1 & 0 \\ \hline \end{array} \quad ; \quad M_y = \begin{array}{|c|c|}\hline 1 & 0 \\ \hline 0 & -1 \\ \hline \end{array}$$

Source: K. Grauman

Source: http://web.media.mit.edu/~maov/classes/vision09/lect/09_Image_Filtering_Edge_Detection_09.pdf

Pattern Matching



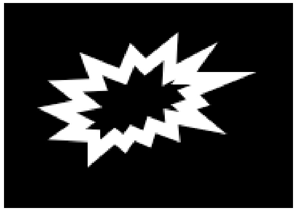
Pattern Matching/Detection

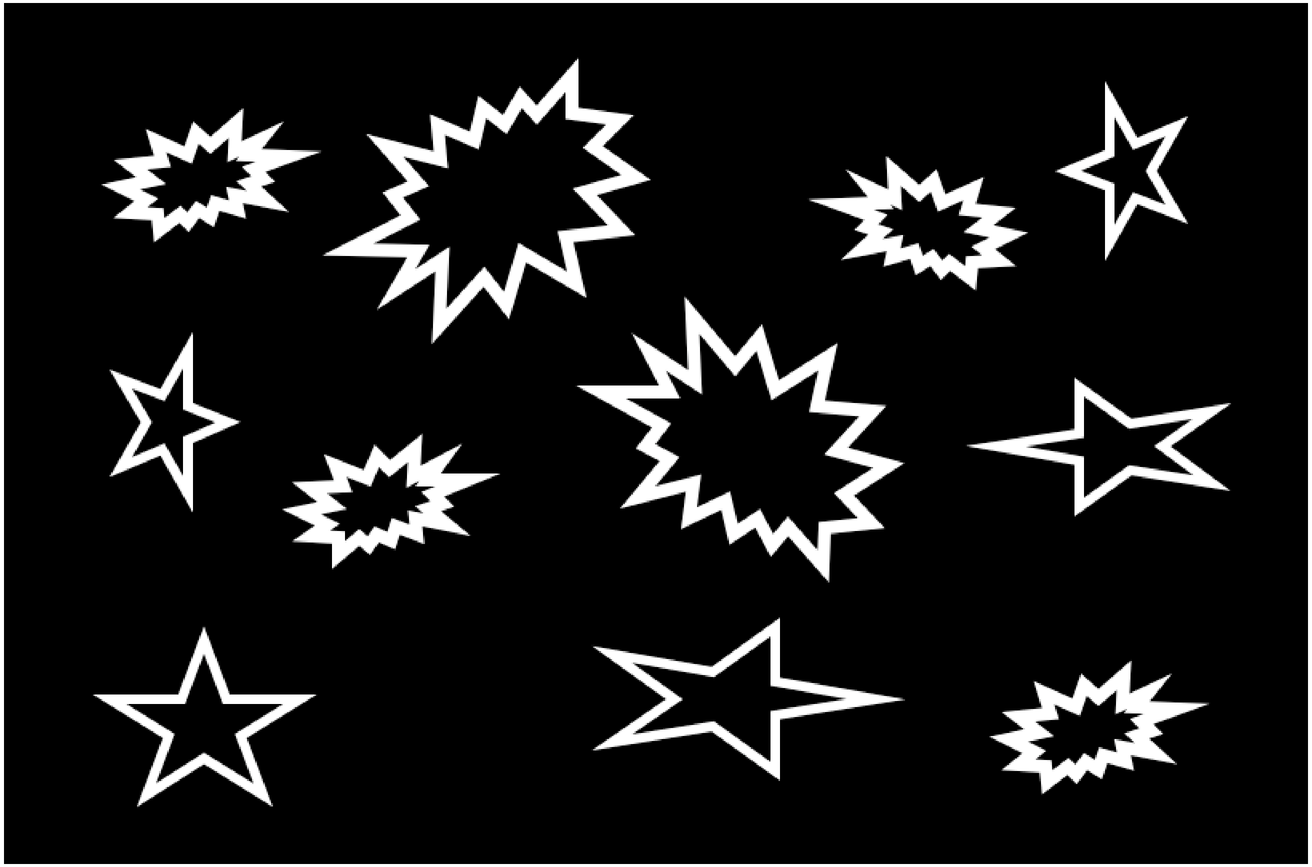
- The optimal (highest) response from a filter is the autocorrelation evaluated at position zero

$$\max_{\bar{x}} C_{ff}(\bar{x}) = C_{ff}(0) = \int f(\bar{s}) f(\bar{s}) d\bar{s}$$

- A filter responds best when it matches a pattern that looks itself
- Strategy
  - Detect objects in images by correlation with “matched” filter

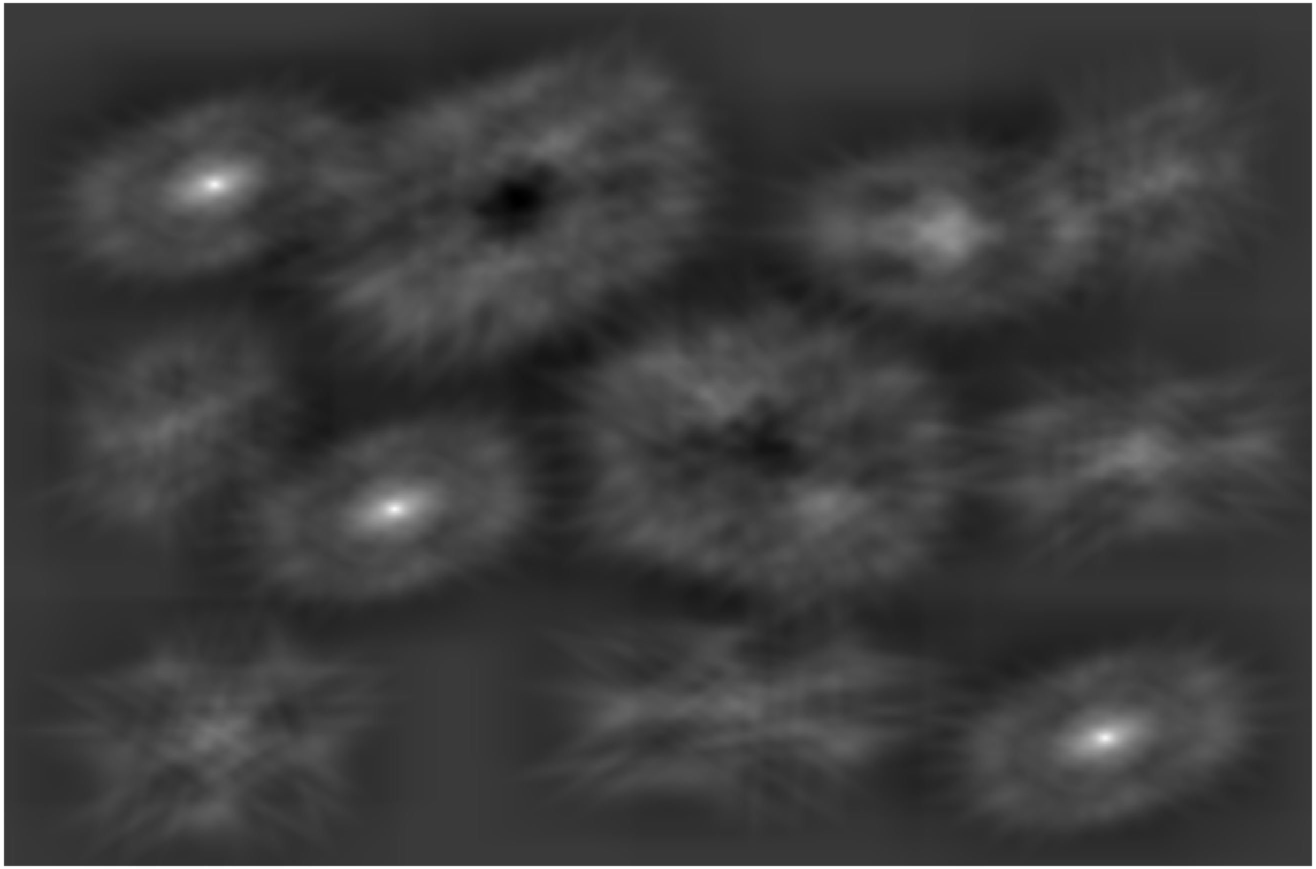
Matched Filter Example



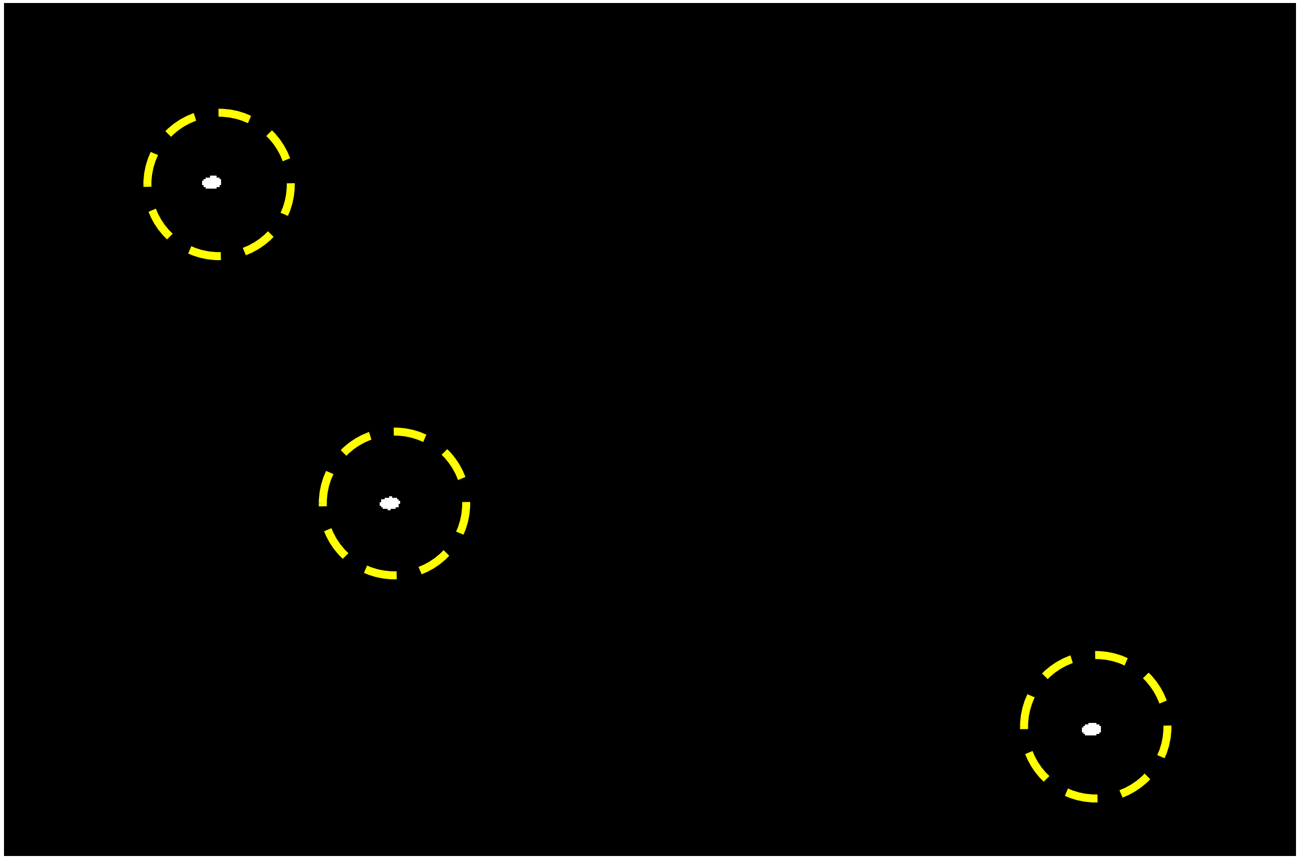


Trick: make
sure kernel
sums to zero

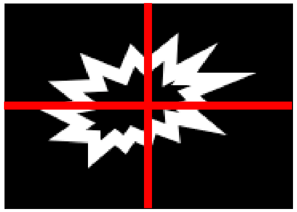
Matched Filter Example: Correlation of template with image

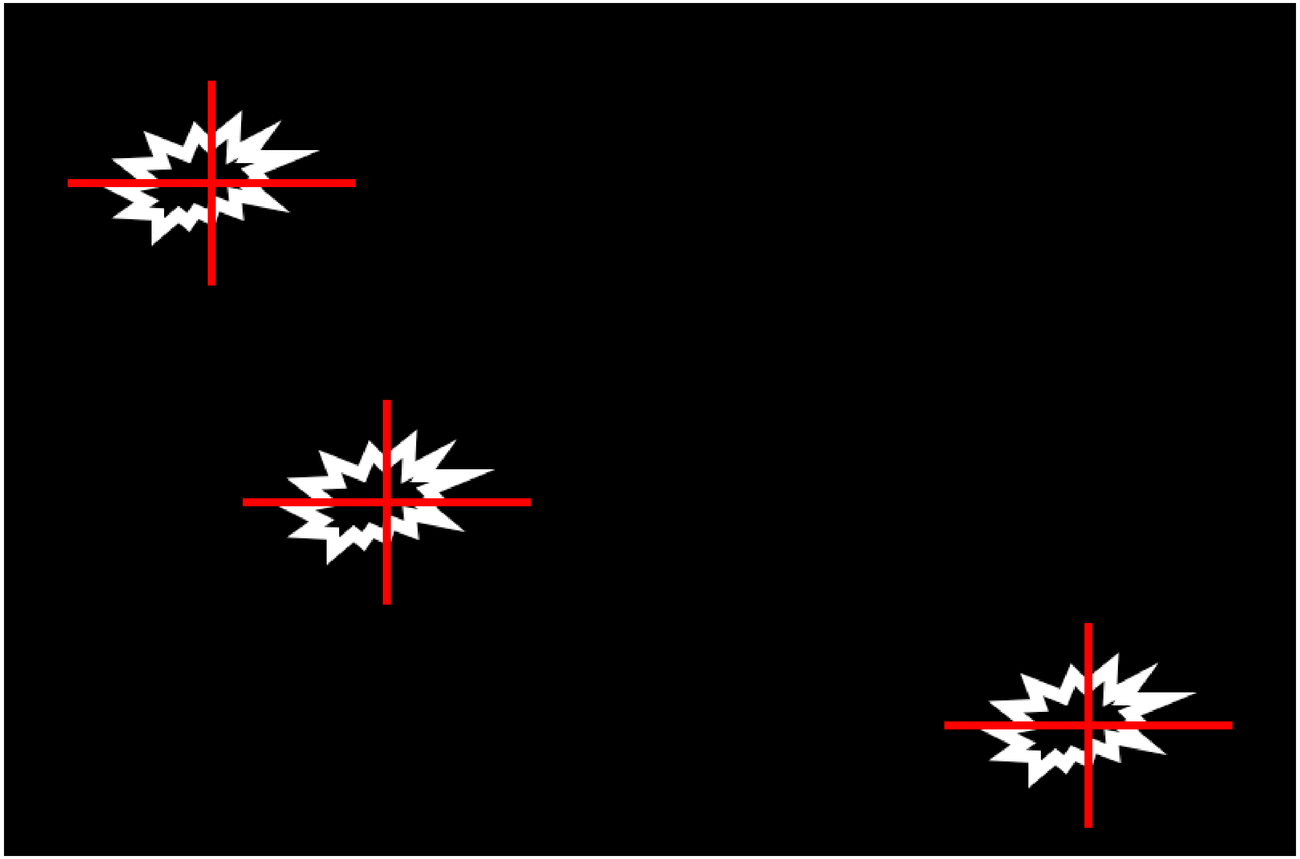


Matched Filter Example: Thresholding of correlation results



Matched Filter Example: High correlation → template found



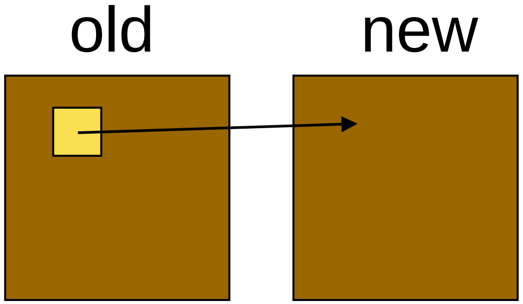


Nonlinear Methods For Filtering

- Median filtering
- Bilateral filtering
- Neighborhood statistics and nonlocal filtering

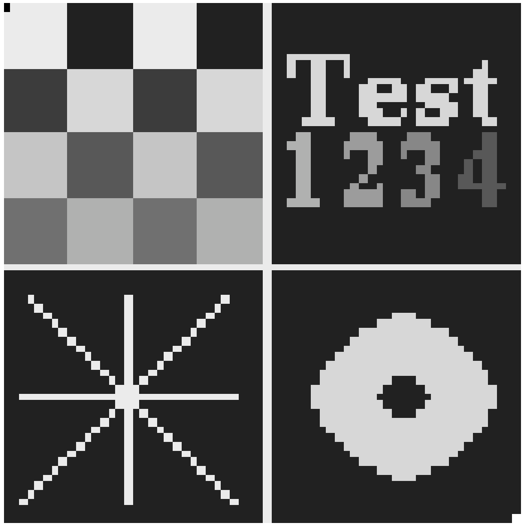
Median Filtering

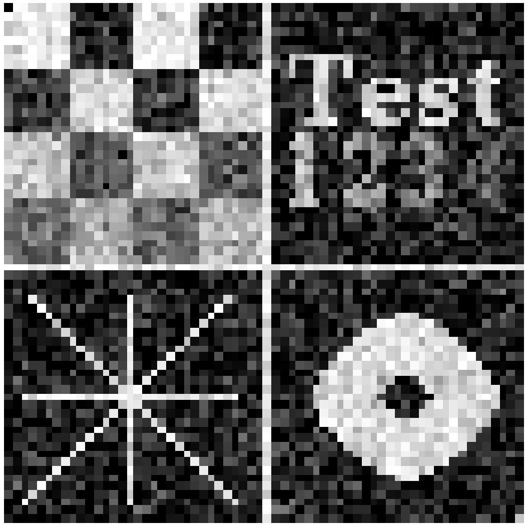
- For each neighborhood in image
  - Sliding window
  - Usually odd size (symmetric) 5x5, 7x7,…
- Sort the greyscale values
- Set the center pixel to the median
- Important: use “Jacobi” updates
  - Separate input and output buffers
  - All statistics on the original image



Median vs Gaussian

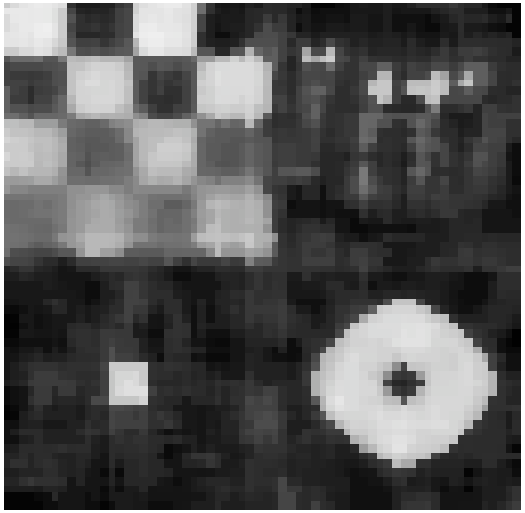
Original

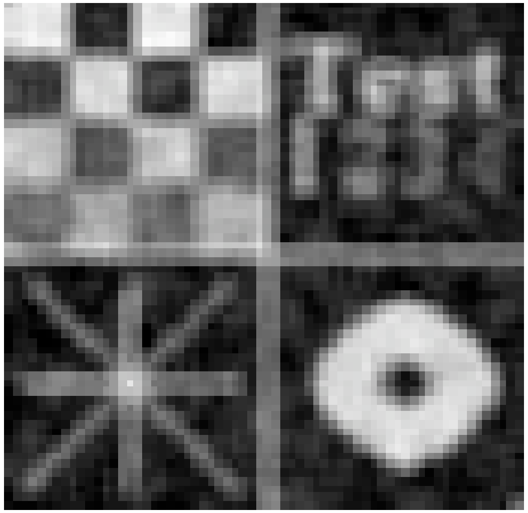




+
Gaussian
Noise

3x3
Median





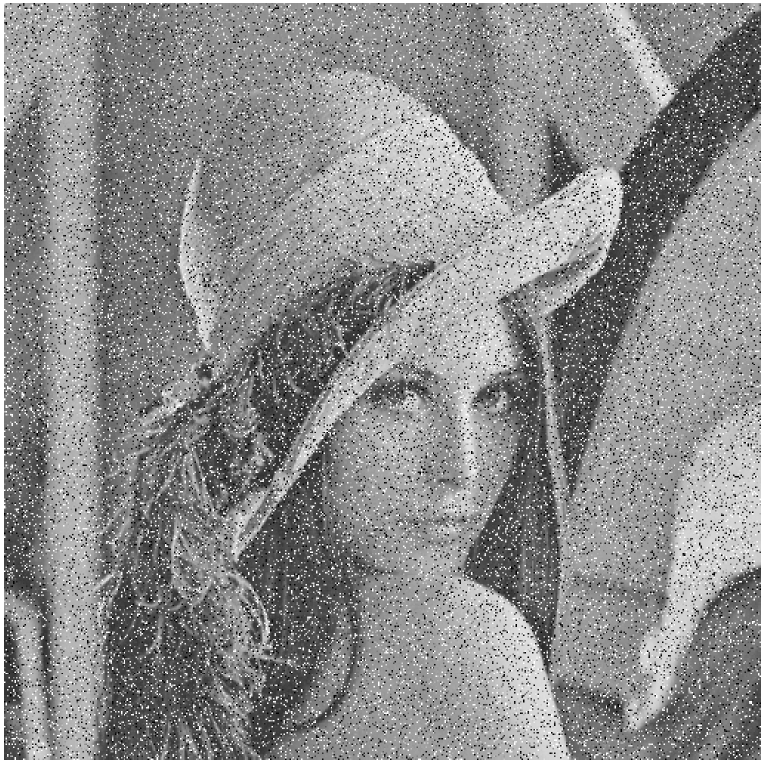
3x3 Box

Median Filter

- Issues
  - Boundaries
    - Compute on pixels that fall within window
  - Computational efficiency
    - What is the best algorithm?
- Properties
  - Removes outliers (replacement noise – salt and pepper)
  - Window size controls size of structures
  - Preserves straight edges, but rounds corners and features

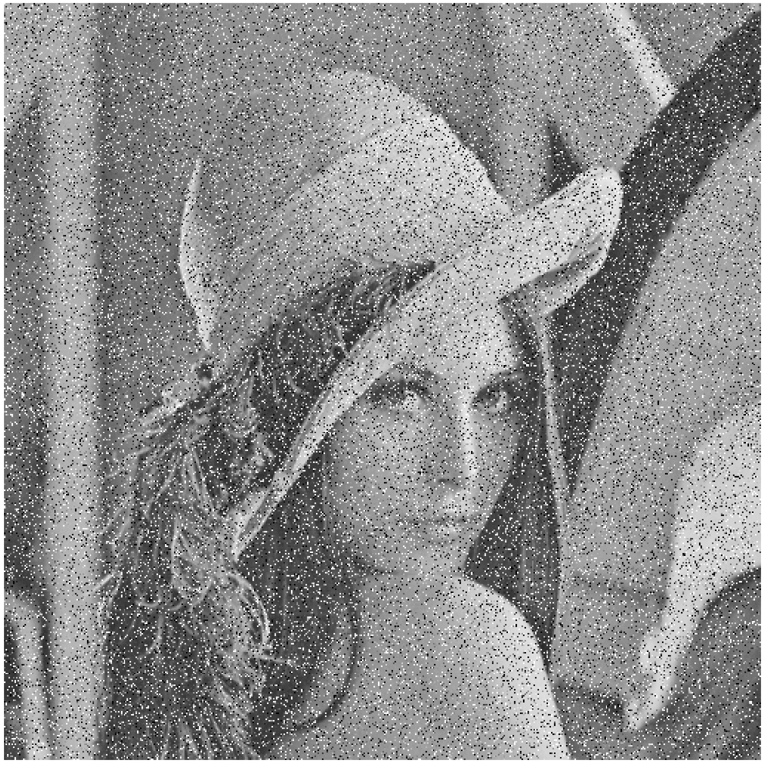
Replacement Noise

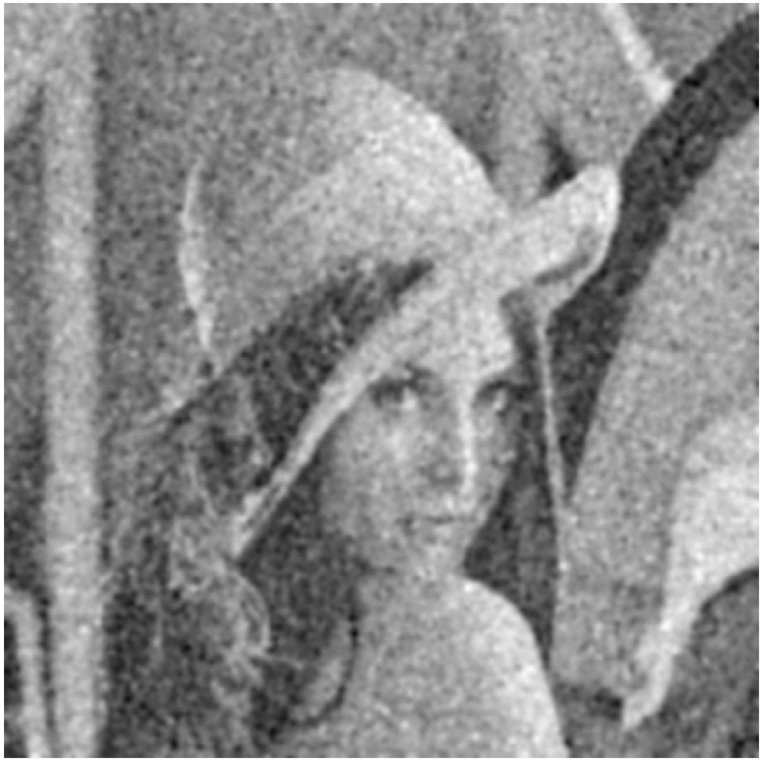
- Also: “shot noise”, “salt&pepper”
- Replace certain % of pixels with samples from pdf
- Best filtering strategy: filter to avoid outliers



Smoothing of S&P Noise

- It’s not zero mean (locally)
- Averaging produces local biases





Smoothing of S&P Noise

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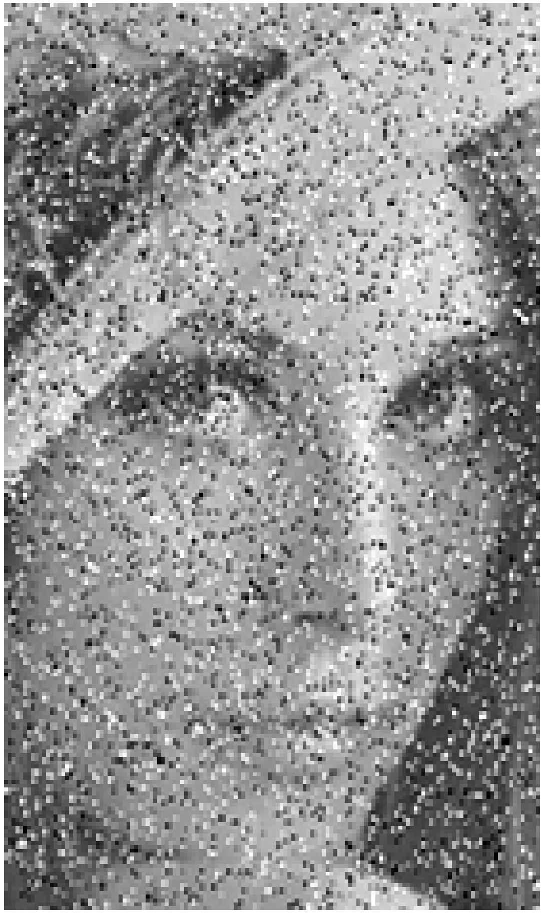
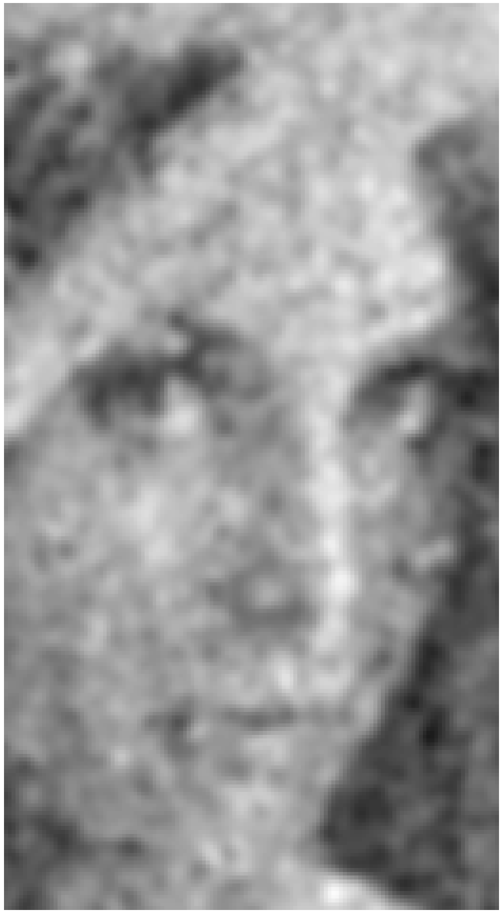
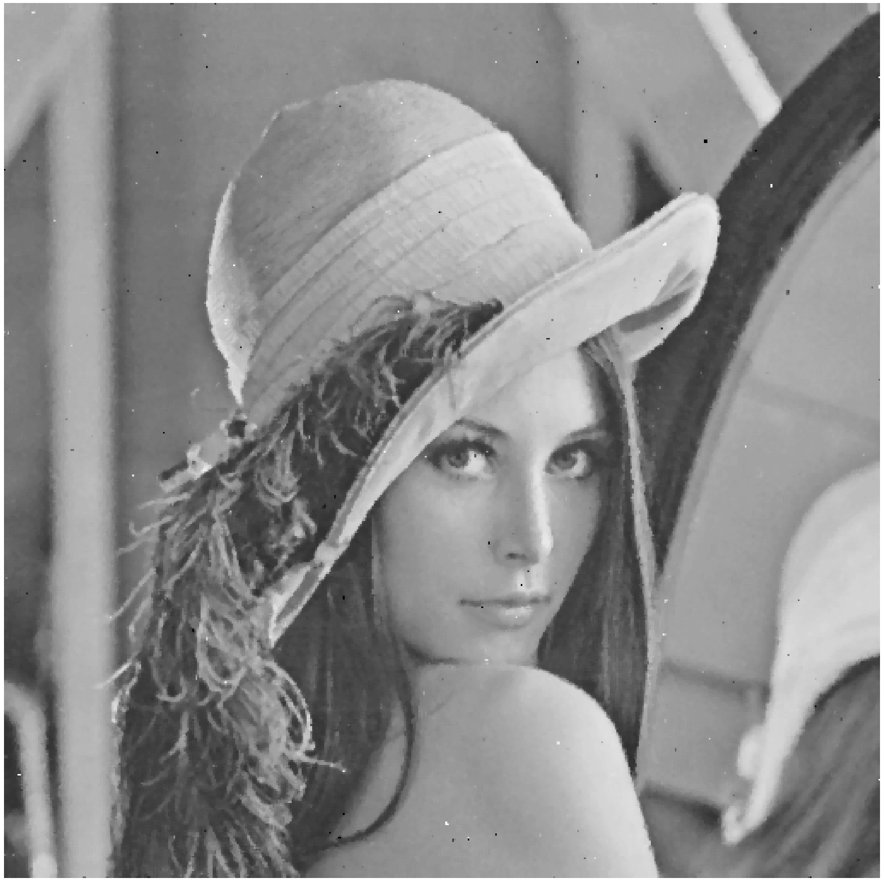
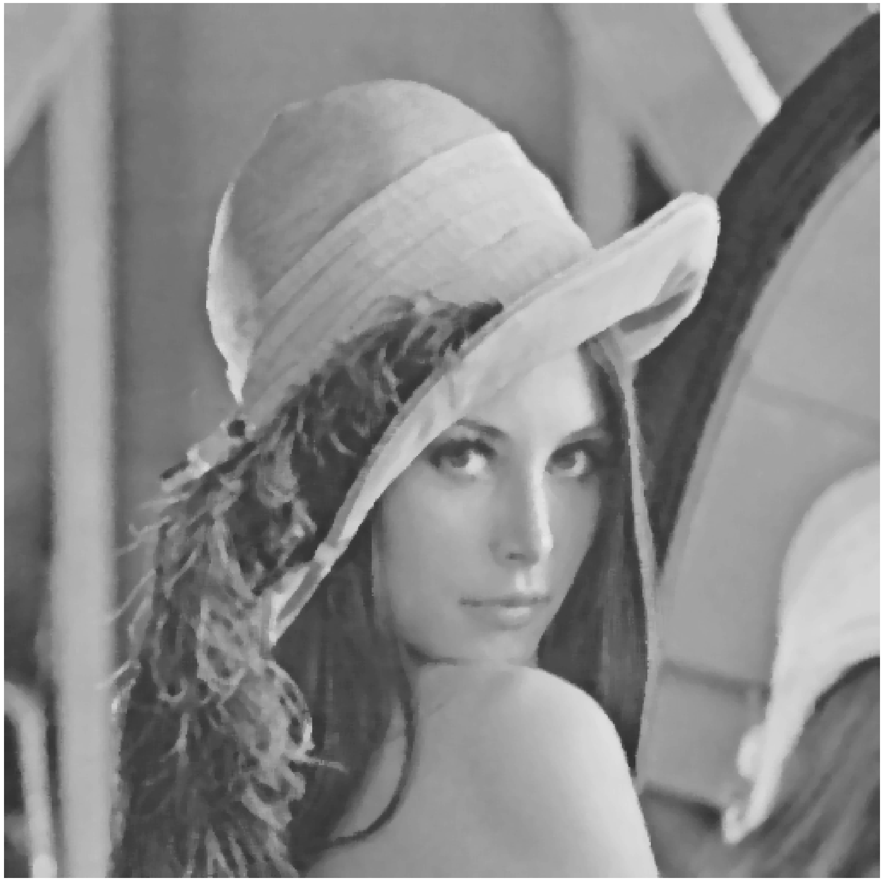




Median Filtering

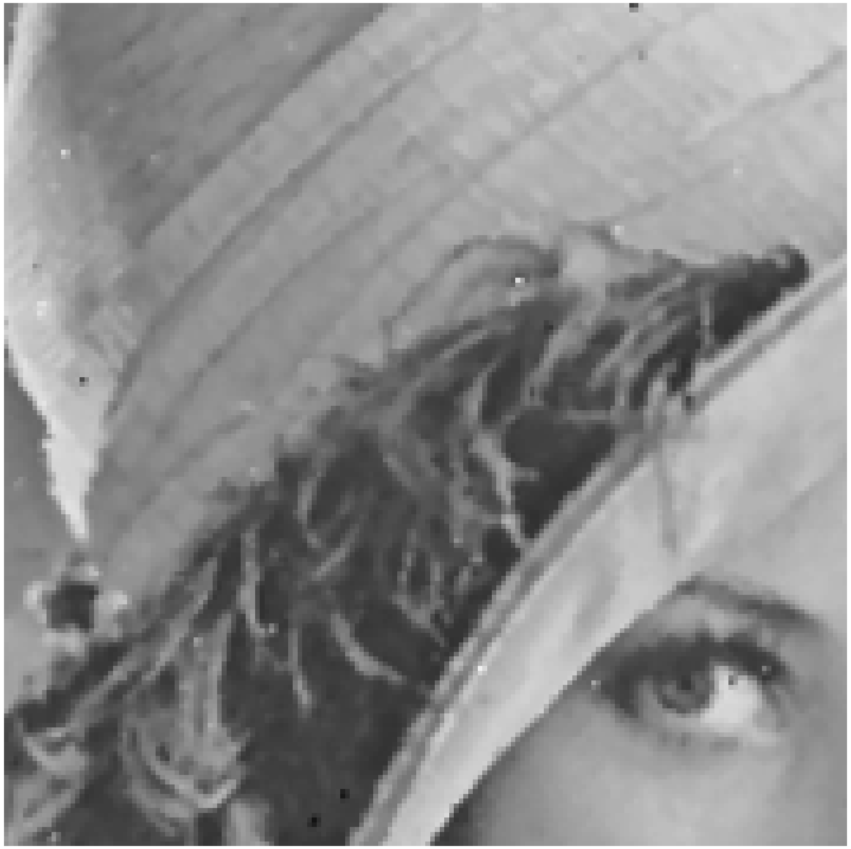


Median 3x3

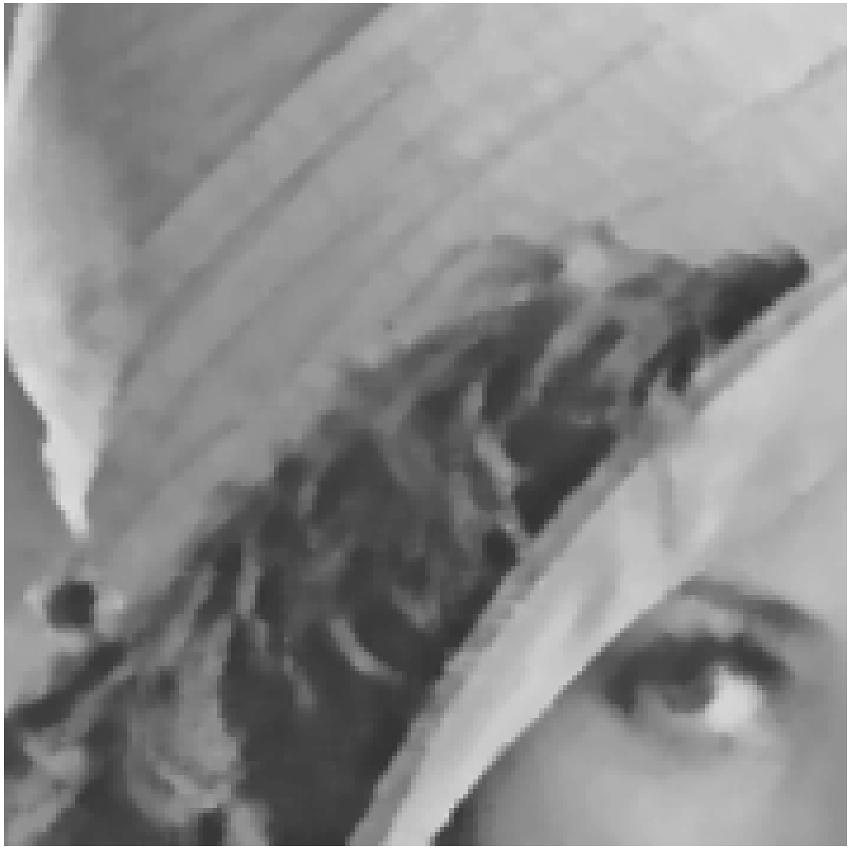


Median 5x5

Median Filtering



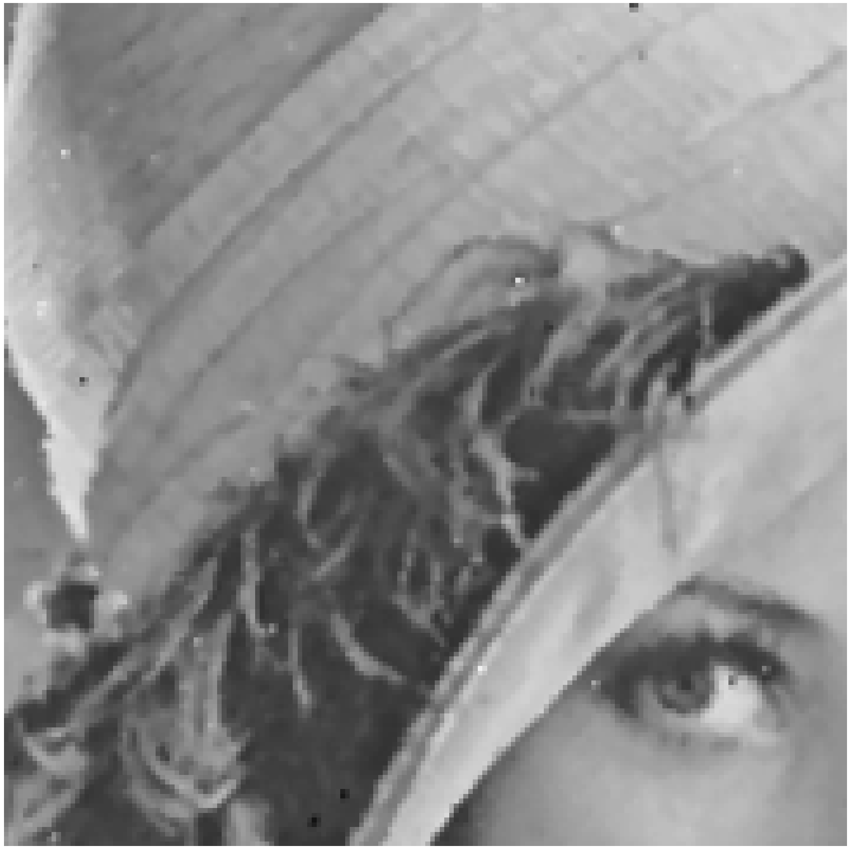
Median 3x3



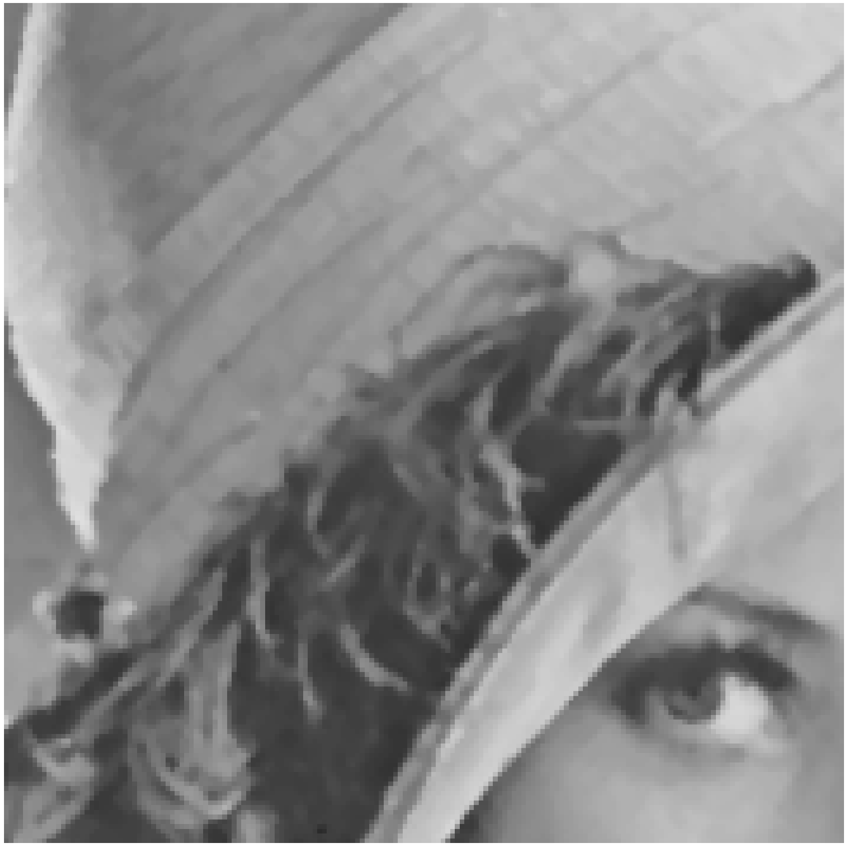
Median 5x5

Median Filtering

- Iterate



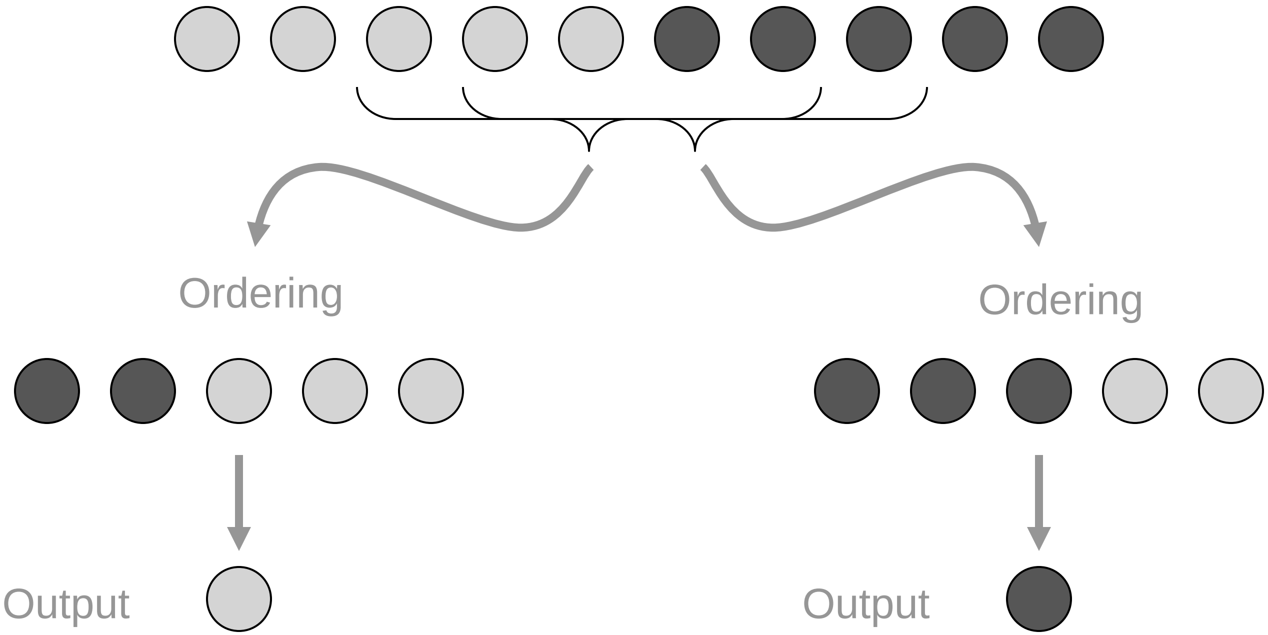
Median 3x3



2x Median 3x3

Median Filtering

- Image model: piecewise constant (flat)



Order Statistics

- Median is special case of order-statistics filters
- Instead of weights based on neighborhoods, weights are based on ordering of data

Neighborhood

$$X_1, X_2, \ldots, X_N$$

Ordering

$$X_{(1)} \leq X_{(2)} \leq \ldots \leq X_{(N)}$$

Filter

$$F(X_1, X_2, \ldots, X_N) = \alpha_1 X_{(1)} + \alpha_2 X_{(2)} + \ldots + \alpha_N X_{(N)}$$

Neighborhood average (box)

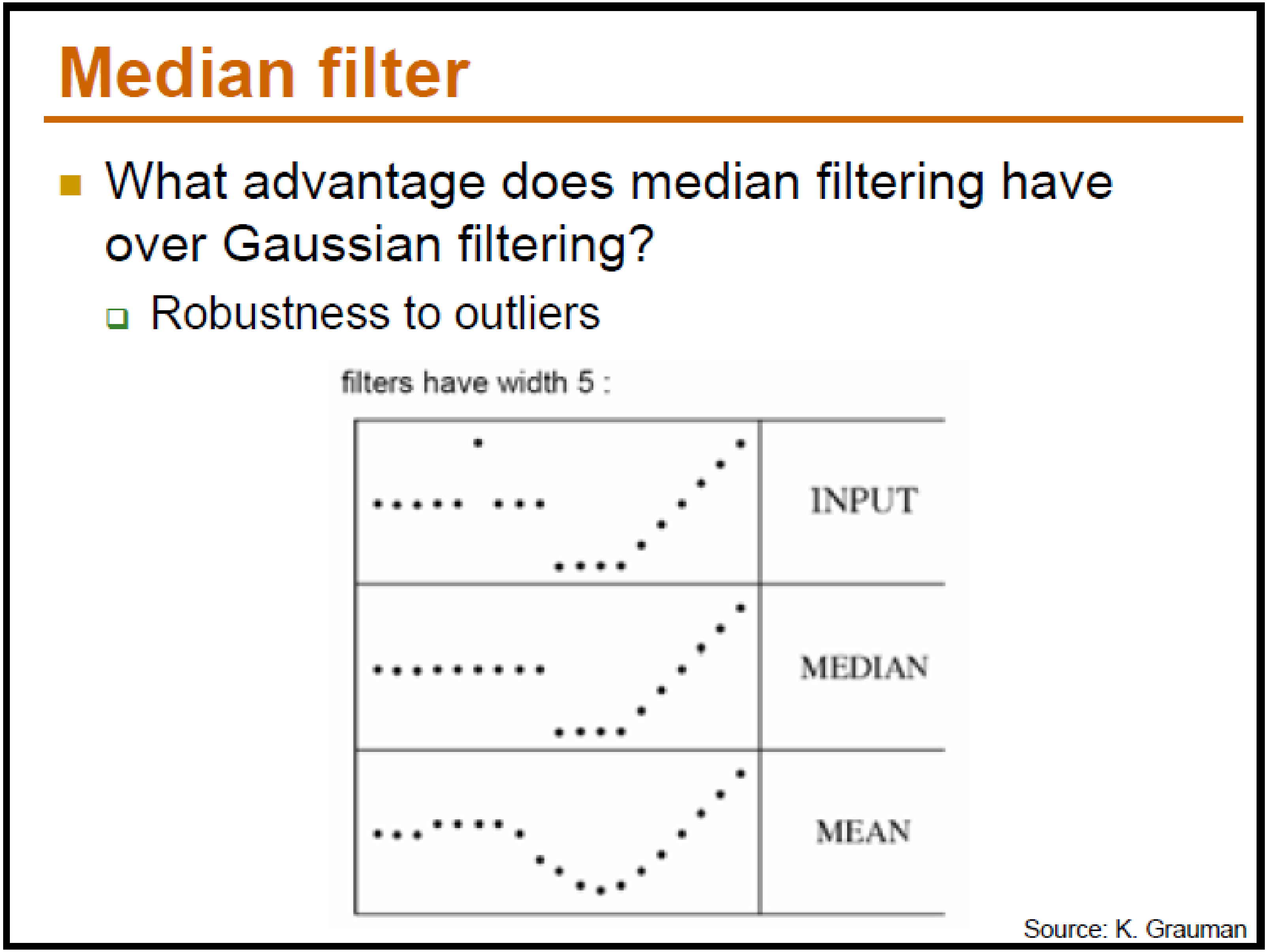
$$\alpha_i = 1/N$$

Median filter

$$\alpha_i = \begin{cases} 1 & i = (N+1)/2 \\ 0 & \text{otherwise} \end{cases}$$

Trimmed average (outlier removal)

$$\alpha_i = \begin{cases} 1/M & (N-M+1)/2 \leq i \leq (N+M+1)/2 \\ 0 & \text{otherwise} \end{cases}$$



Median filter

- What advantage does median filtering have over Gaussian filtering?
  - Robustness to outliers

filters have width 5 :

Source: K. Grauman

Source: http://web.media.mit.edu/~maov/classes/vision09/lect/09_Image_Filtering_Edge_Detection_09.pdf

Piecewise Flat Image Models

- Image piecewise flat -> average only within similar regions
- Problem: don’t know region boundaries

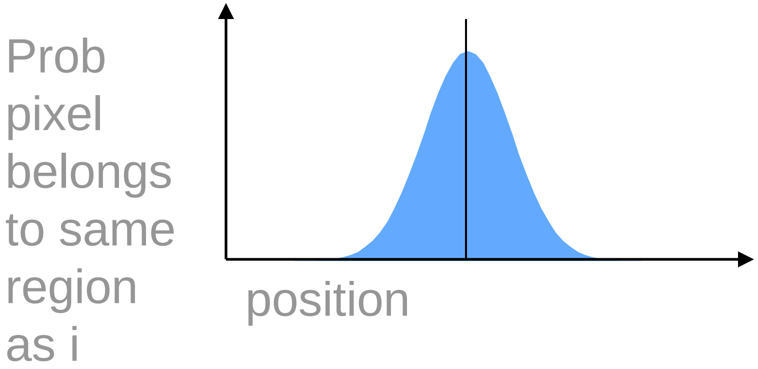
Piecewise-Flat Image Models

- Assign probabilities to other pixels in the image belonging to the same region
- Two considerations
  - Distance: far away pixels are less likely to be same region
  - Intensity: pixels with different intensities are less likely to be same region

Piecewise-Flat Images and Pixel Averaging

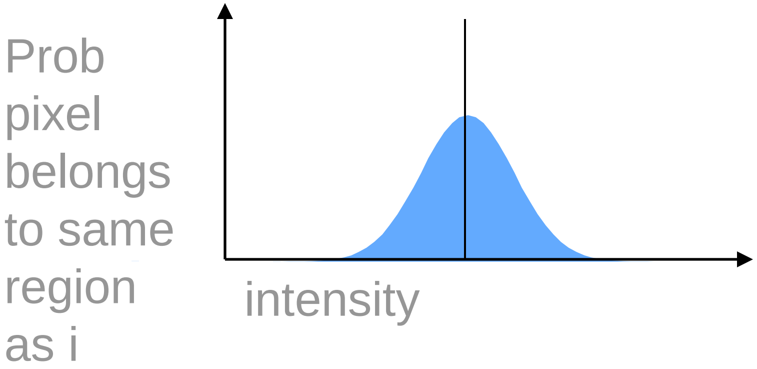
Distance (kernel/pdf)

$$G(\mathbf{x}_i - \mathbf{x}_j)$$



Distance (pdf)

$$H(f_i - f_j)$$



Bilateral Filter

- Neighborhood – sliding window
- Weight contribution of neighbors according to:

$$f_i \leftarrow k_i^{-1} \sum_{j \in N} f_j G(\mathbf{x}_i - \mathbf{x}_j) H(f_i - f_j)$$

$$k_i = \sum_{j \in N} G(\mathbf{x}_i - \mathbf{x}_j) H(f_i - f_j)$$

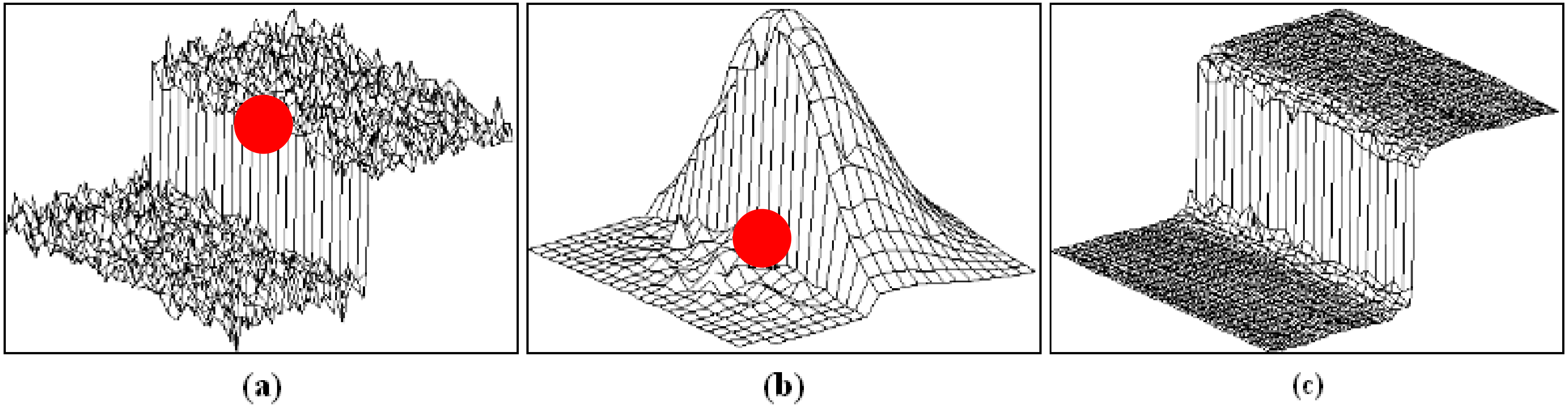
normalization: all weights add up to 1

- G is a Gaussian (or lowpass), as is H, N is neighborhood,
  - Often use G(r_{ij}) where r_{ij} is distance between pixels
  - Update must be normalized for the samples used in this (particular) summation
- Spatial Gaussian with extra weighting for intensity
  - Weighted average in neighborhood with downgrading of intensity outliers

Tomasi, Manduchi: http://en.wikipedia.org/wiki/Bilateral_filter
http://homepages.inf.ed.ac.uk/rbf/CVonline/LOCAL_COPIES/MANDUCHI1/Bilateral_Filtering.html

Bilateral Filter

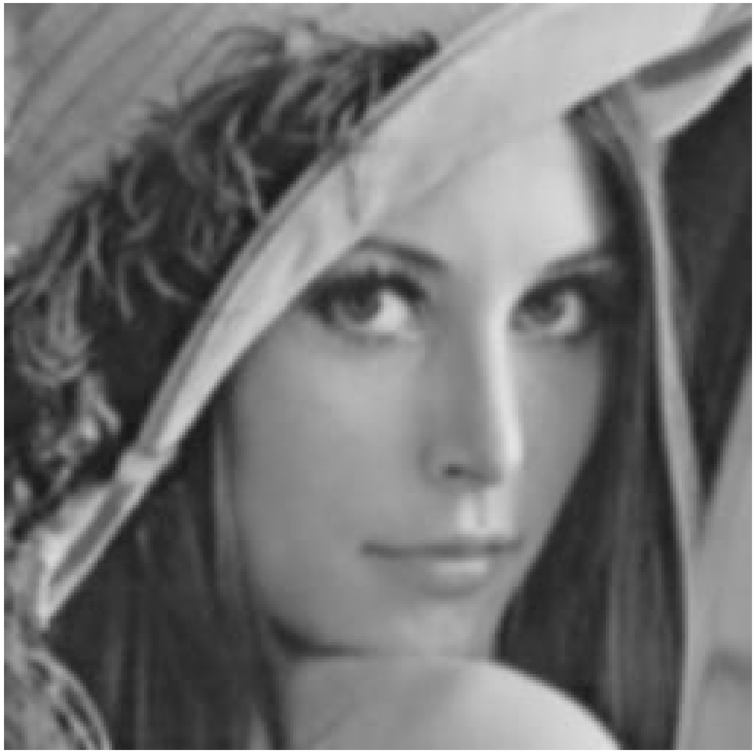
Replaces the pixel value at **x** with an average of similar and nearby pixel values.



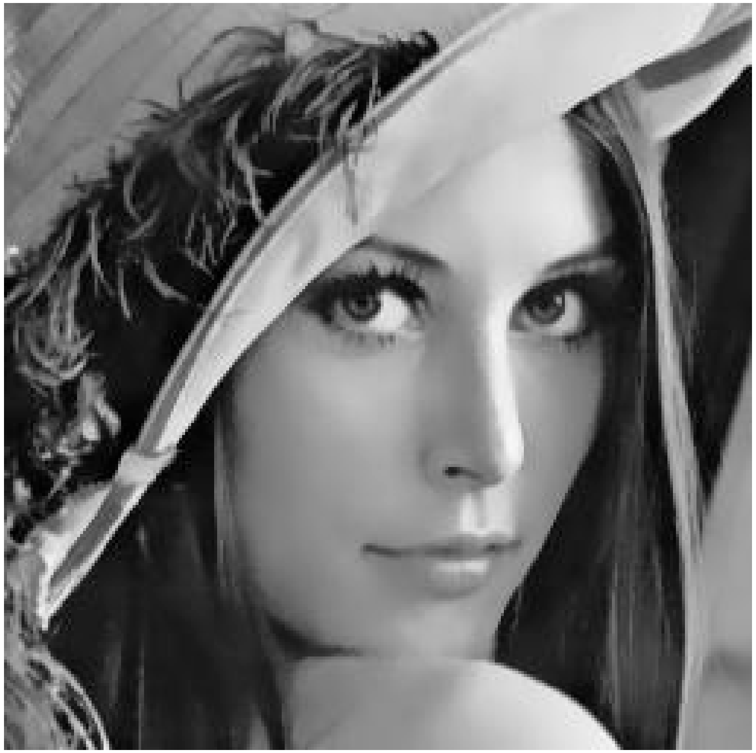
When the bilateral filter is centered, say, on a pixel on the bright side of the boundary, the similarity function *s* assumes values close to one for pixels on the same side, and values close to zero for pixels on the dark side. The similarity function is shown in figure 1(b) for a 23x23 filter support centered two pixels to the right of the step in figure 1(a).

Bilateral Filtering

Replaces the pixel value at **x** with an average of similar and nearby pixel values.

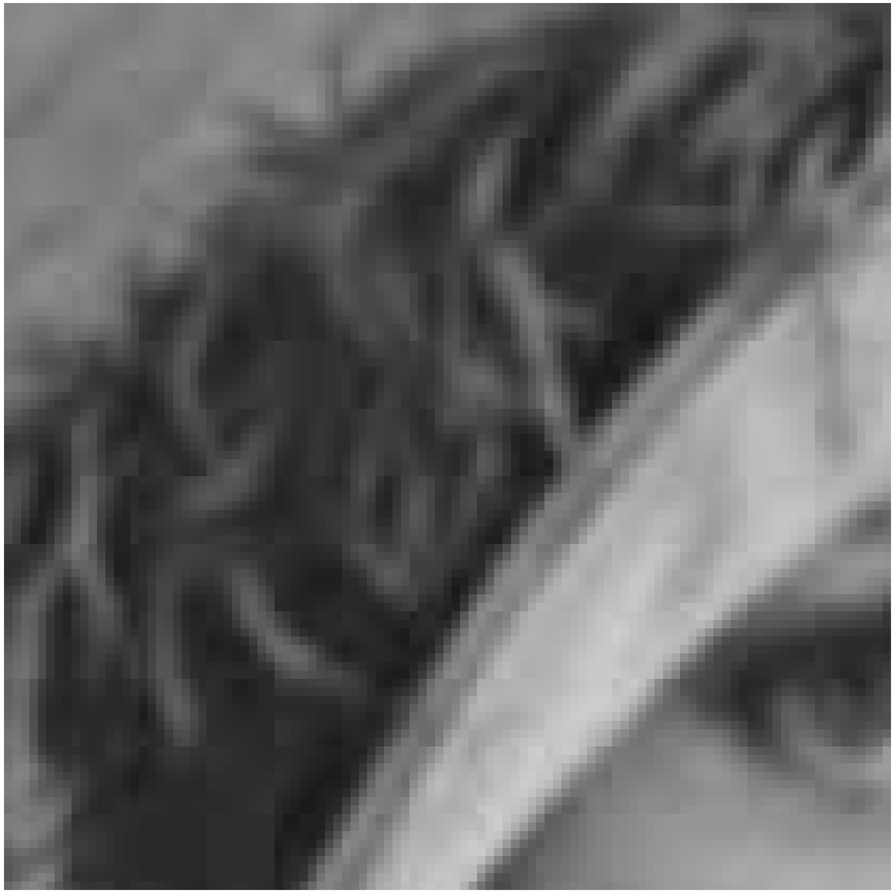


Gaussian Blurring

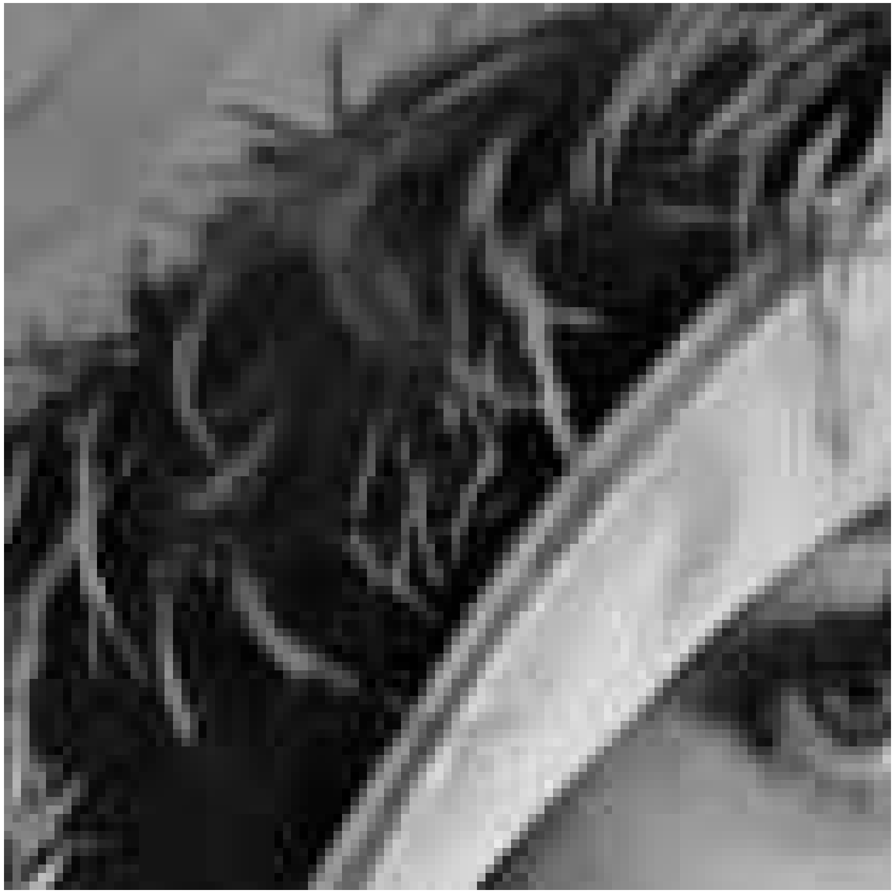


Bilateral

Bilateral Filtering



Gaussian Blurring

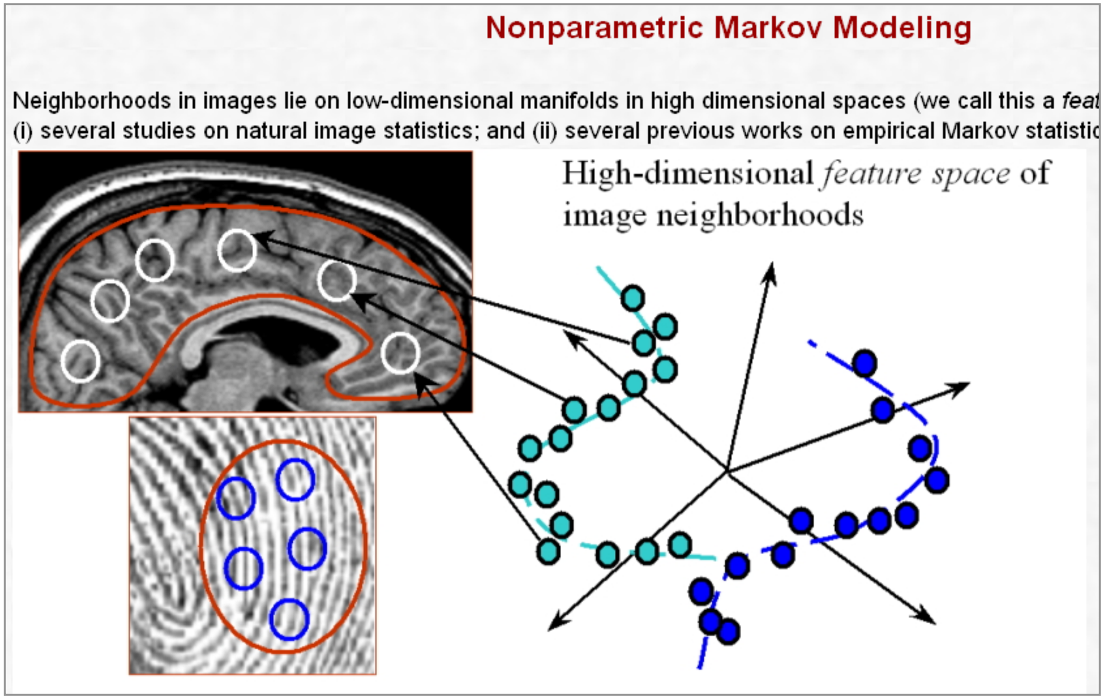


Bilateral

Nonlocal Averaging

- Recent algorithm
  - NL-means, Baudes et al., 2005
  - UINTA, Awate & Whitaker, 2005
- Different model
  - No need for piecewise-flat
  - Images consist of some set of pixels with similar neighborhoods → average several of those
    - Scattered around
      - General area of a pixel
      - All around
- Idea
  - Average sets of pixels with similar neighborhoods

UINTA: Unsupervised Information-Theoretic Adaptive Filtering : Excellent Introduction and Additional Readings (Suyash P. Awate)



Nonparametric Markov Modeling

Neighborhoods in images lie on low-dimensional manifolds in high dimensional spaces (we call this a *feat*

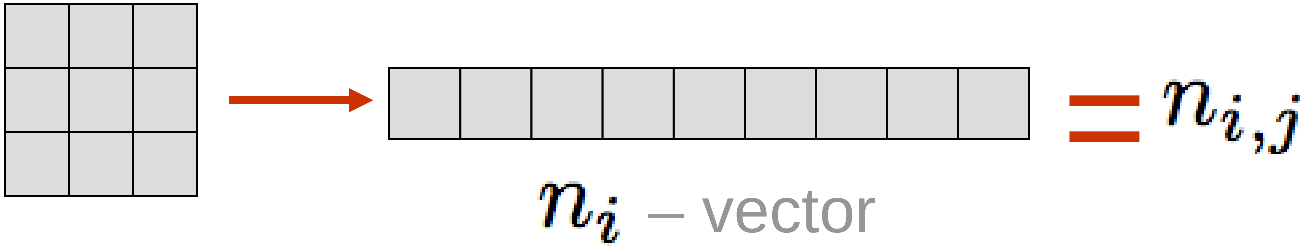
(i) several studies on natural image statistics; and (ii) several previous works on empirical Markov statistic

http://www.cs.utah.edu/~suyash/pubs/uinta/

Suyash P. Awate, Ross T. Whitaker
Unsupervised, Information-Theoretic, Adaptive Image Filtering with Applications to Image Restoration
IEEE Trans. Pattern Analysis & Machine Intelligence (TPAMI) 2006, Vol. 28, Num. 3, pp. 364-376

Nonlocal Averaging

- Strategy:
  - – Average pixels to alleviate noise
  - – Combine pixels with similar neighborhoods
- Formulation
  - – $n_{i,j}$ – vector of pixels values, indexed by j, from neighborhood around pixel i



Nonlocal Averaging Formulation

- Distance between neighborhoods

$$d_{i,k} = d(n_i, n_k) = ||n_i - n_k|| = \left(\sum_{j=1}^{N} (n_{i,j} - n_{k,j})^2 \right)^{\frac{1}{2}}$$

- Kernel weights based on distances

$$w_{i,k} = K(d_{i,k}) = e^{-\frac{d_{i,k}^2}{2s^2}}$$

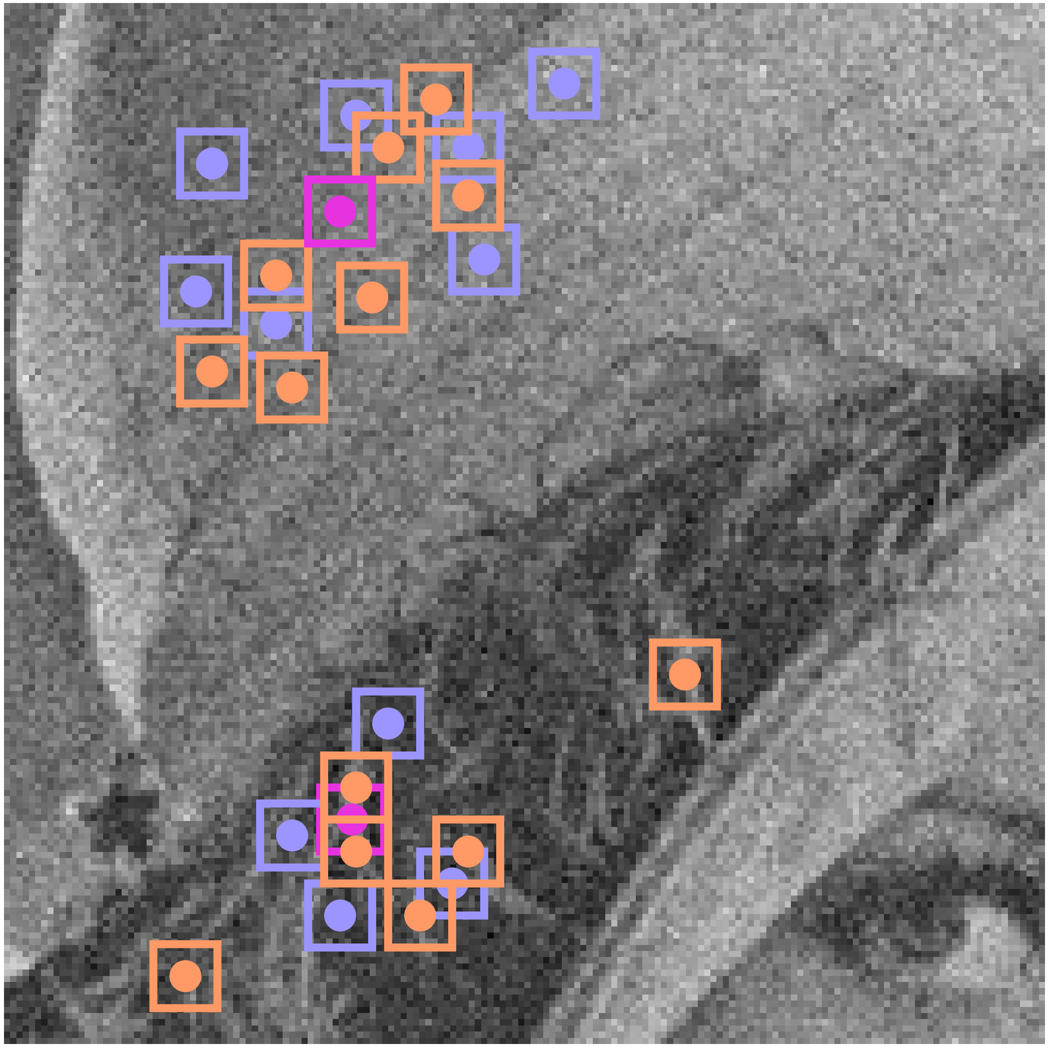
- Pixel values of k neighborhoods: f_k

Averaging Pixels Based on Weights

- For each pixel, i, choose a set of pixel locations k:
  - k = 1, …., M
  - Average them together based on neighborhood weights (prop. to intensity pattern difference)

$$g_i \leftarrow \frac{1}{\sum_{k=1}^{M} w_{i,k}} \sum_{k=1}^{M} w_{i,k} f_k$$

Nonlocal Averaging



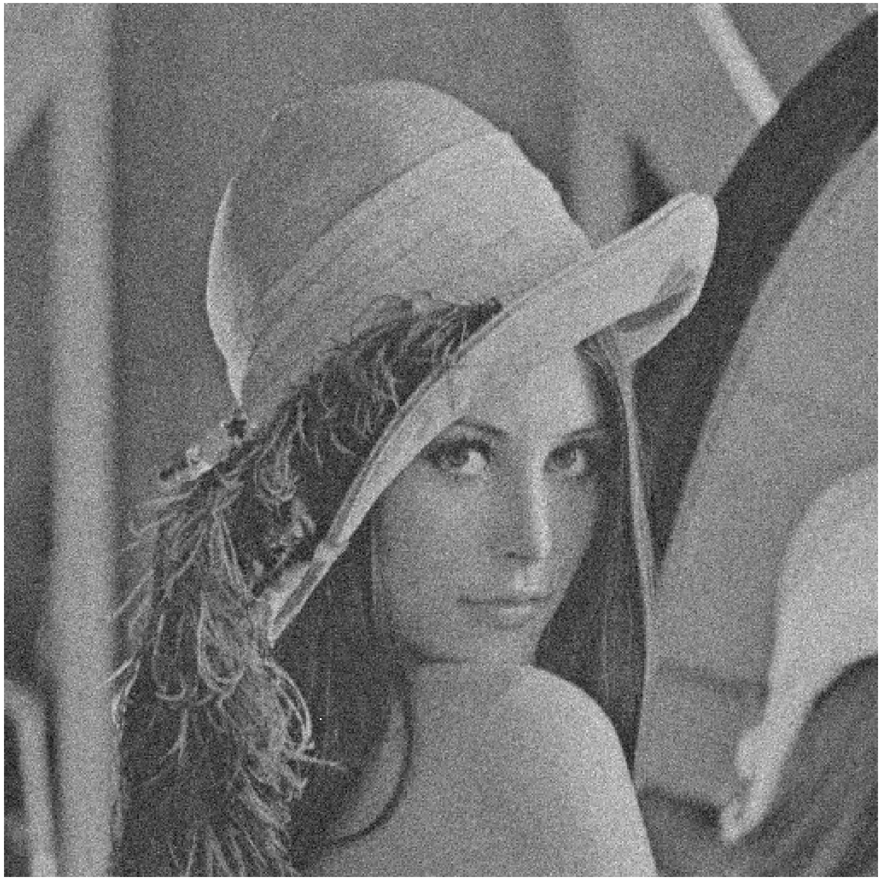
Some Details

- Window sizes: good range is 5x5->11x11
- How to choose samples:
  - Random samples from around the image
    - UINTA, Awate&Whitaker
  - Block around pixel (bigger than window, e.g. 51x51)
    - NL-means
- Iterate
  - UNITA: smaller updates and iterate

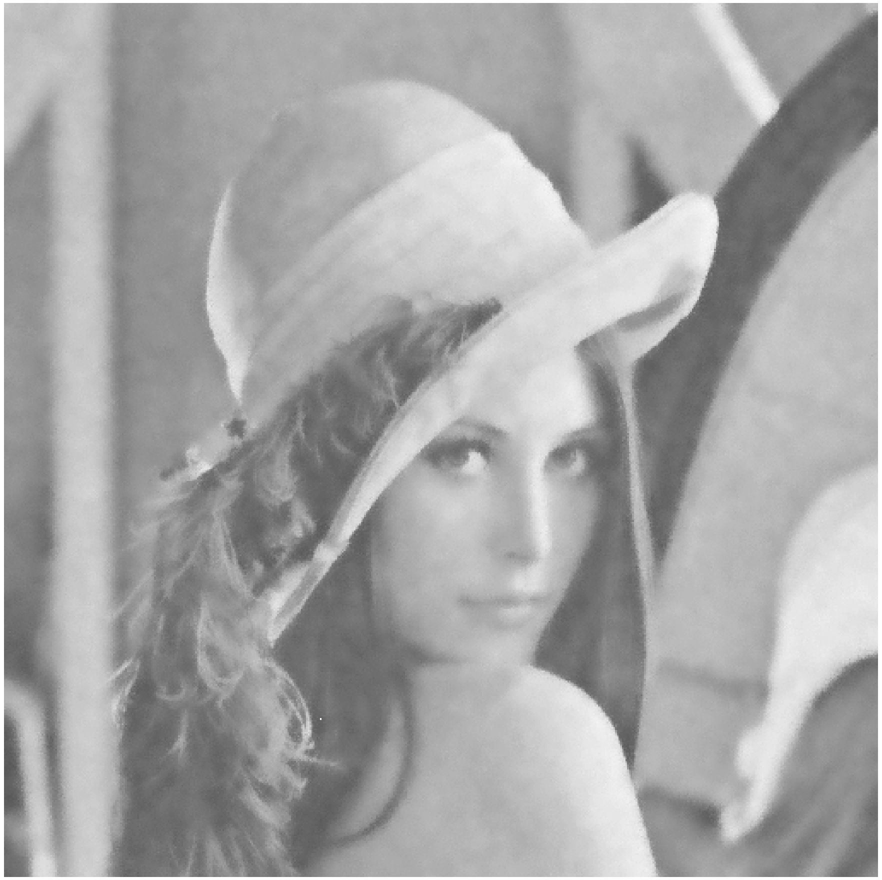
NL-Means Algorithm

- For each pixel, p
  - Loop over set of pixels nearby
  - Compare the neighorhoods of those pixels to the neighborhood of p and construct a set of weights
  - Replace the value of p with a weighted combination of values of other pixels
- Repeat… but 1 iteration is pretty good

Results

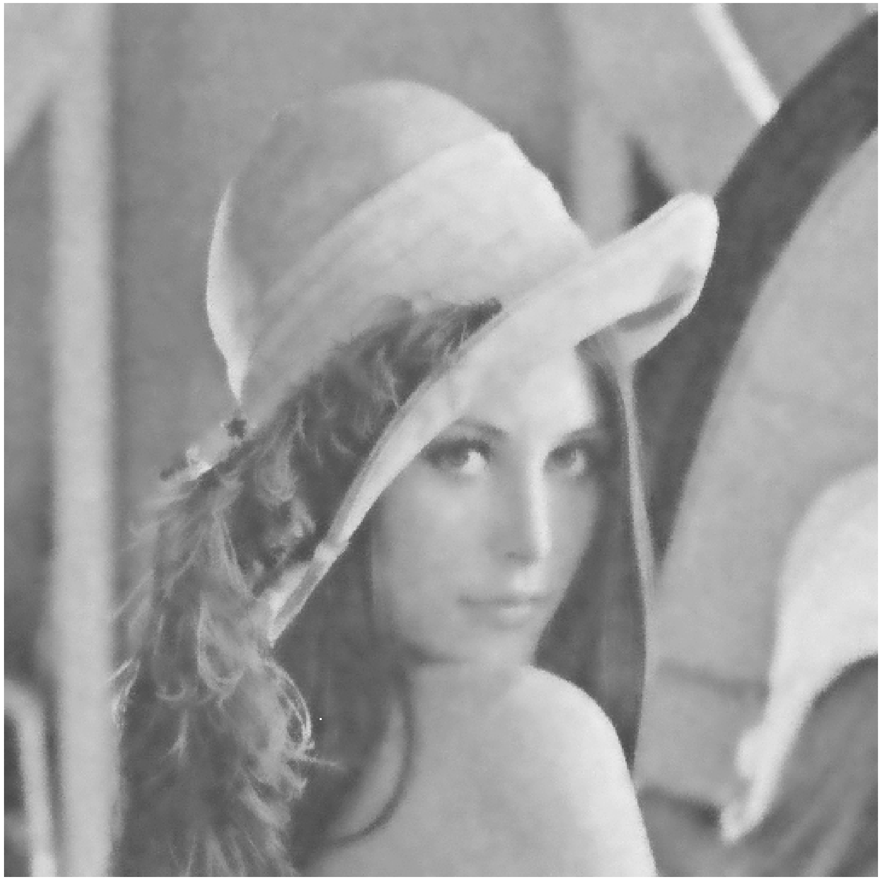


Noisy image (range 0.0-1.0)

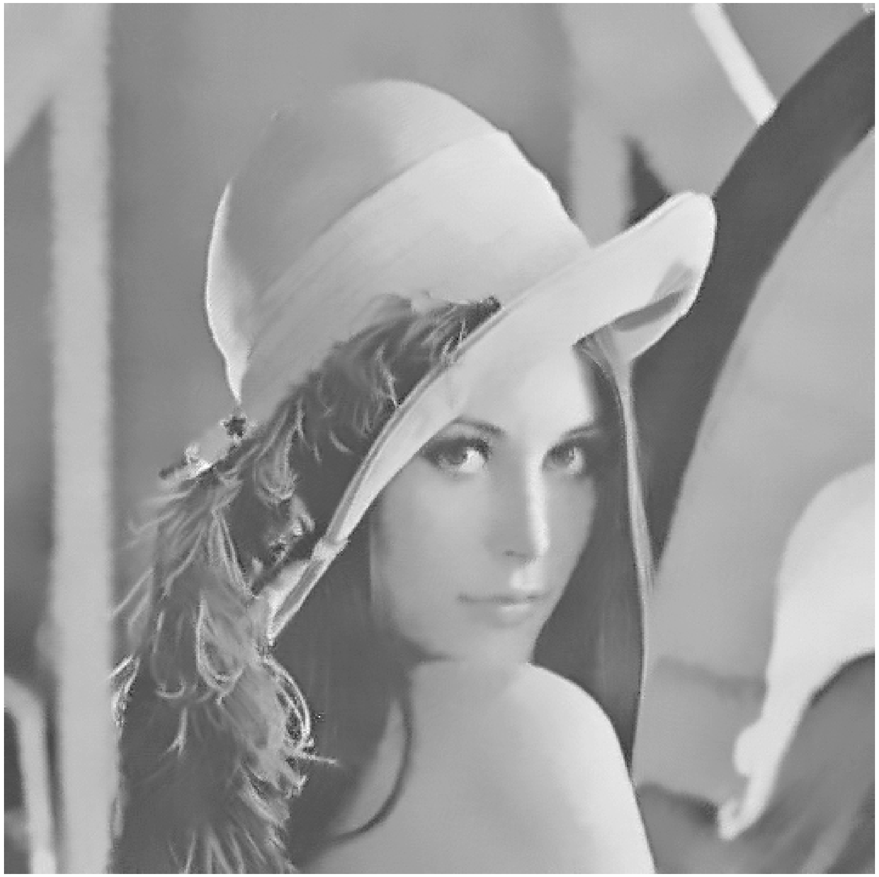


Bilateral filter (3.0, 0.1)

Results

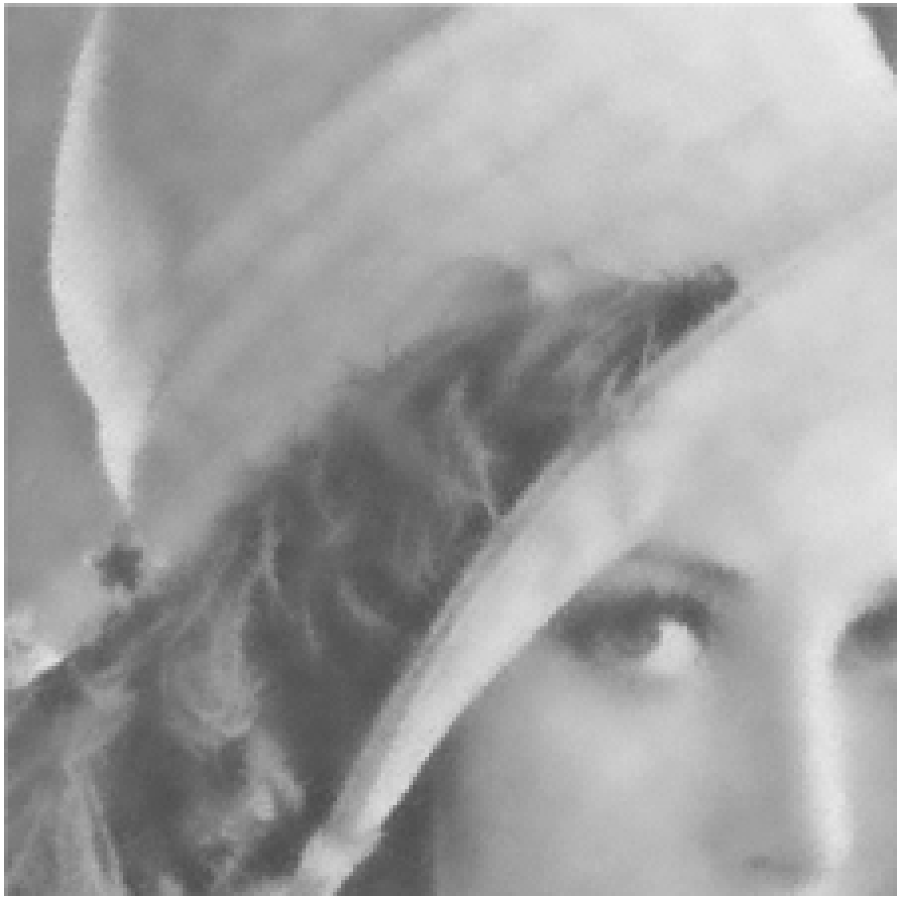


Bilateral filter (3.0, 0.1)

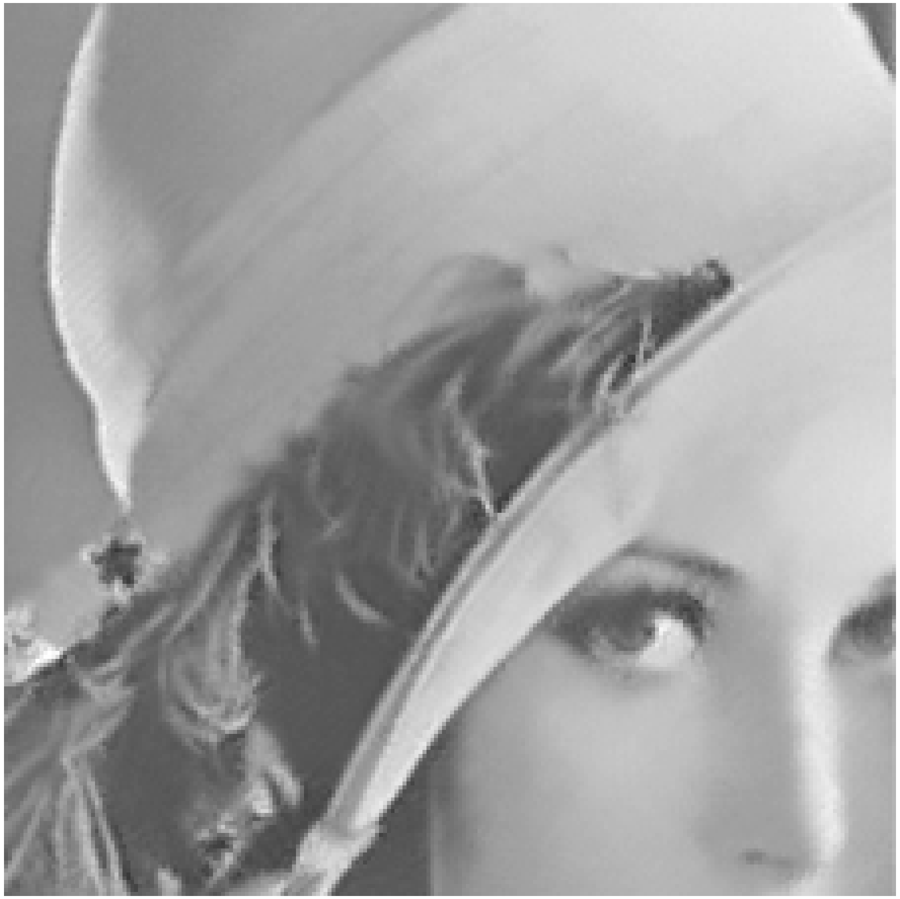


NL means (7, 31, 1.0)

Results

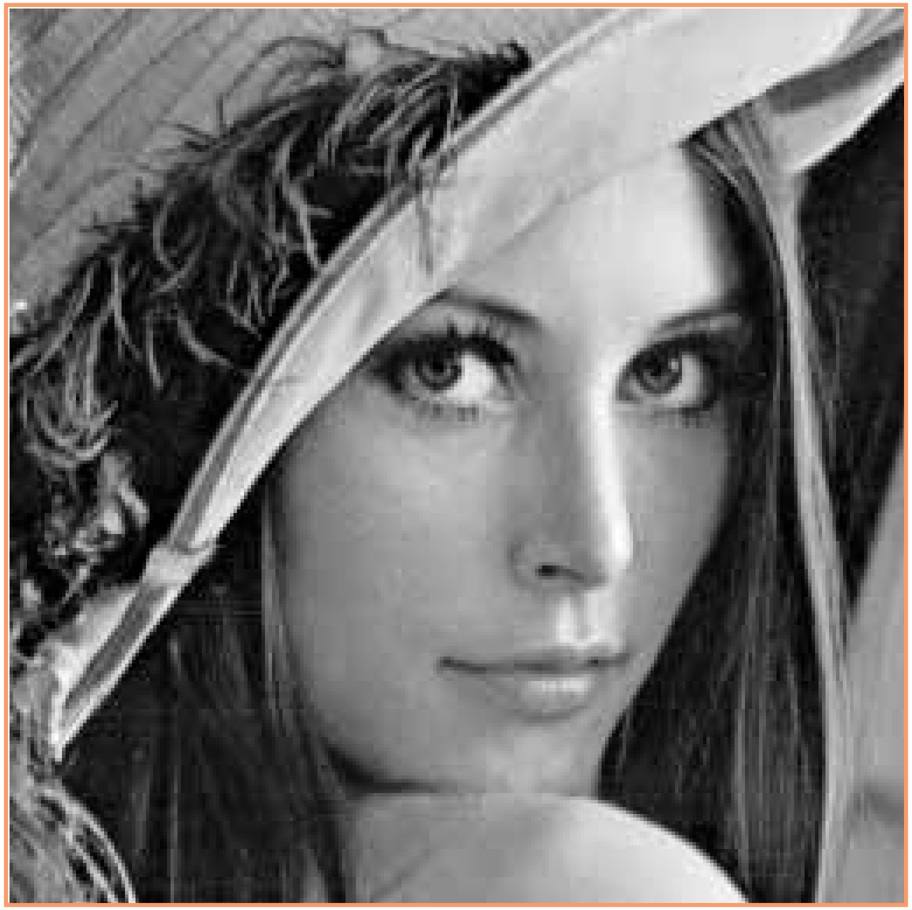


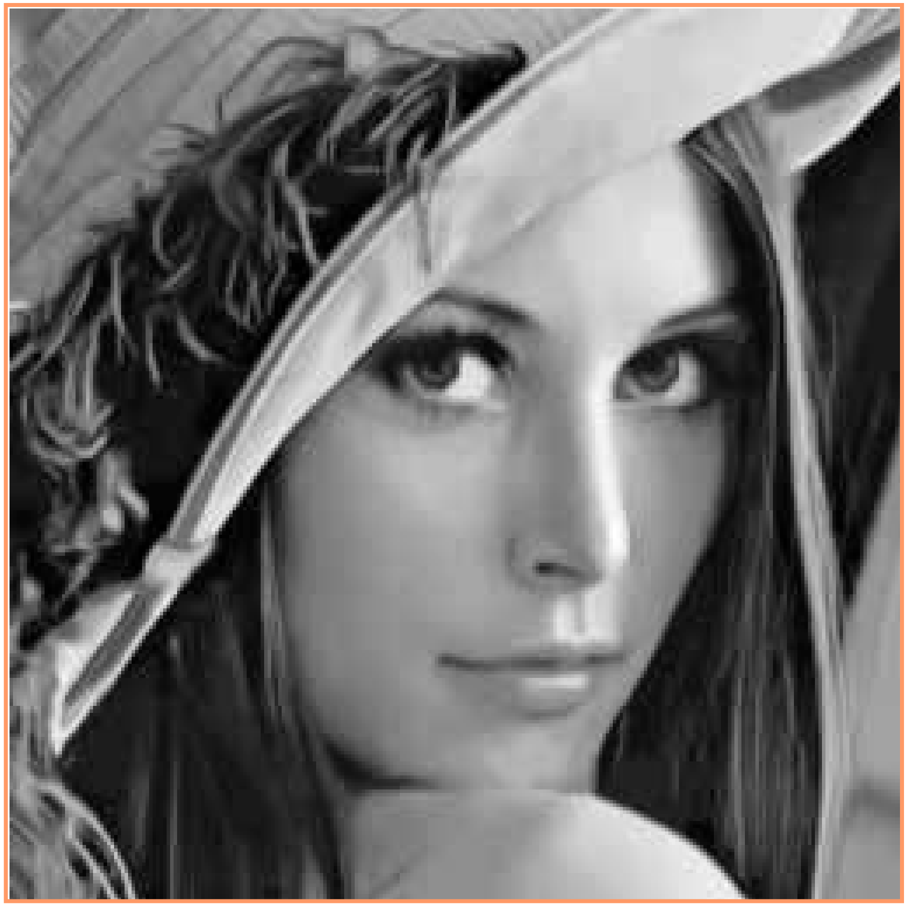
Bilateral filter (3.0, 0.1)



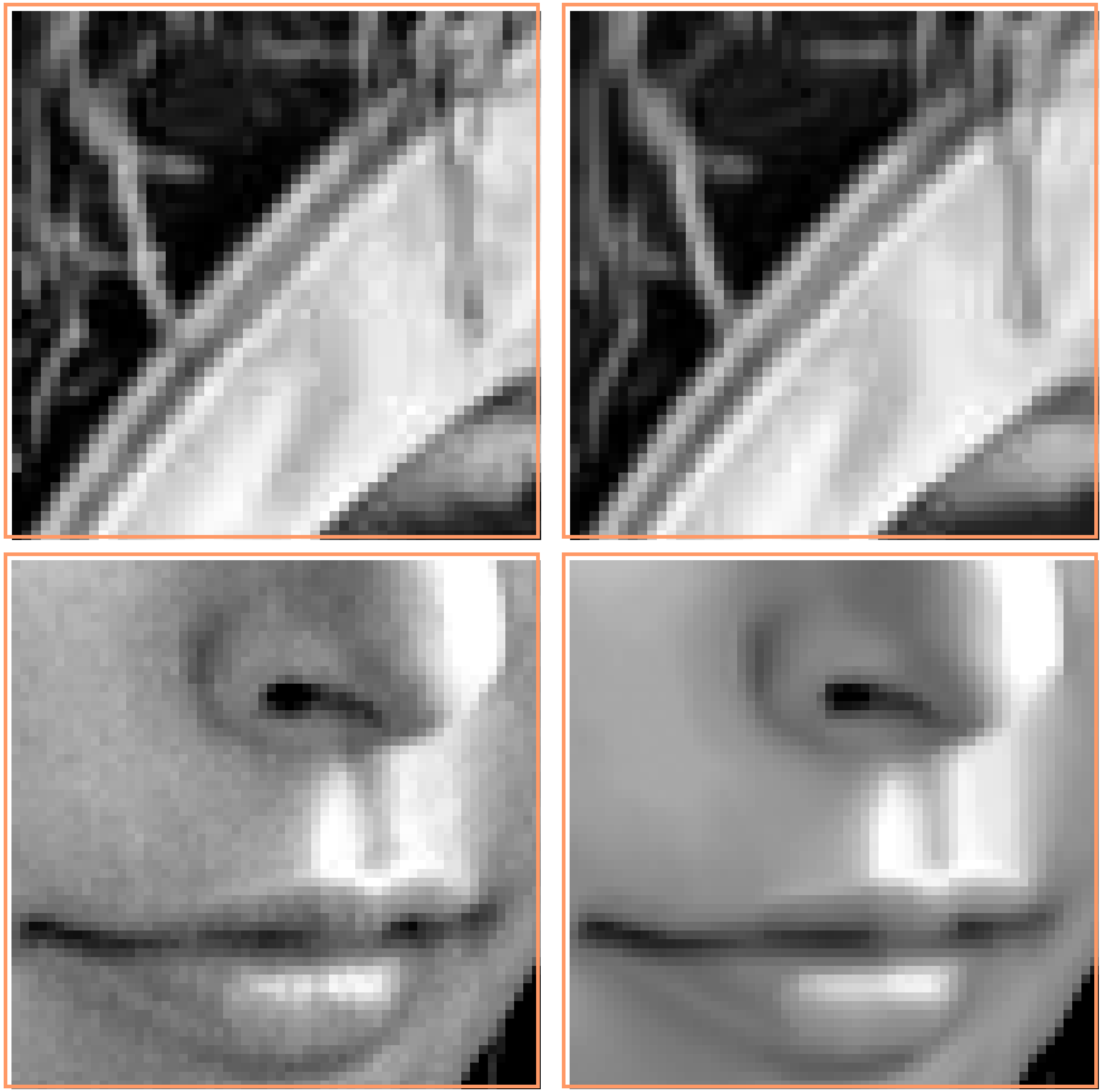
NL means (7, 31, 1.0)

Less Noisy Example

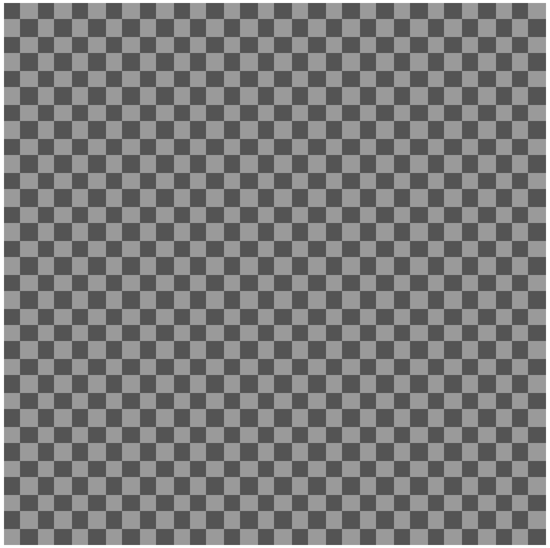




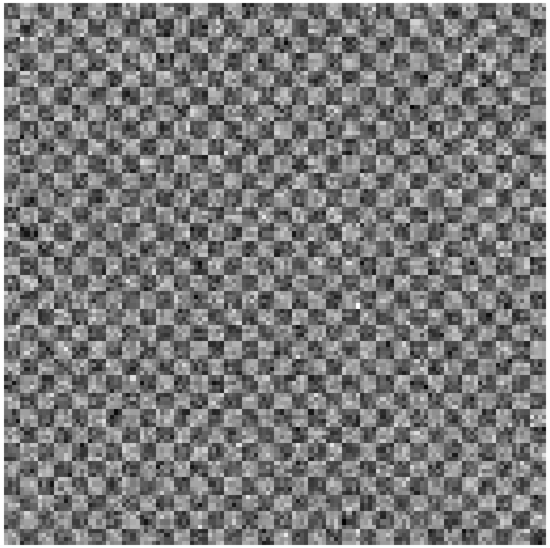
Less Noisy Example



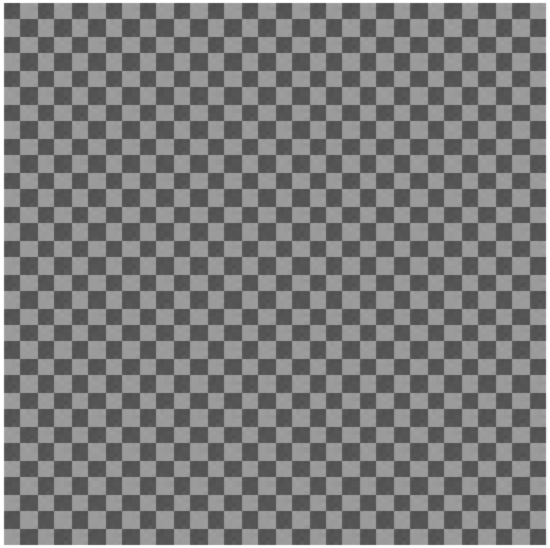
Results



Original

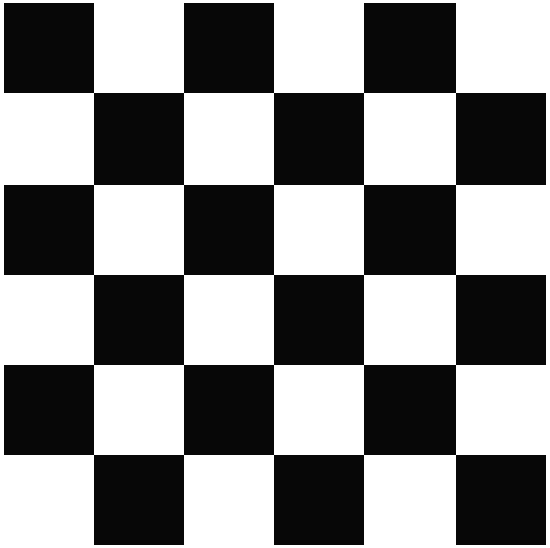


Noisy

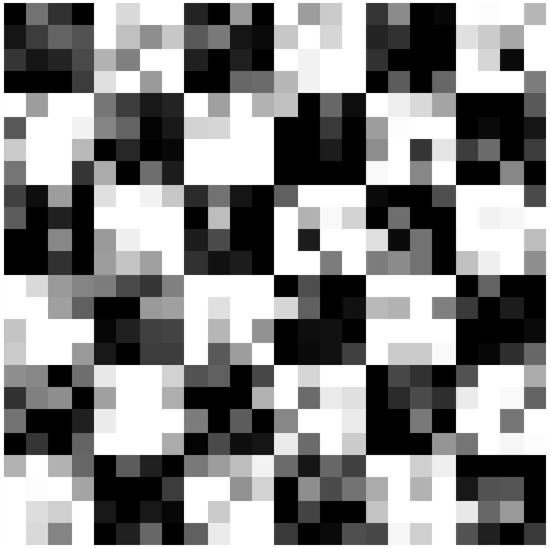


Filtered

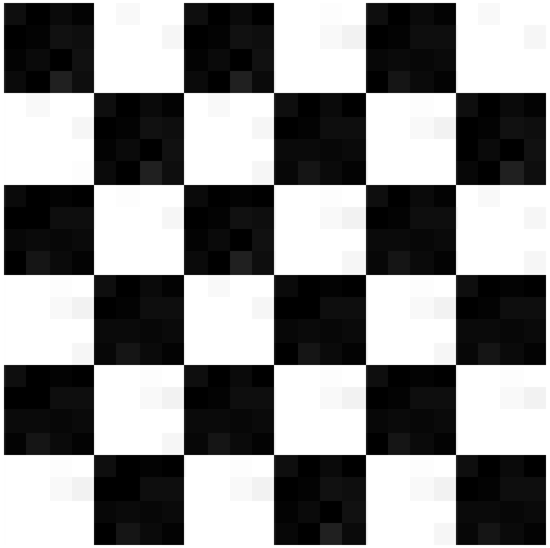
Checkerboard With Noise



Original



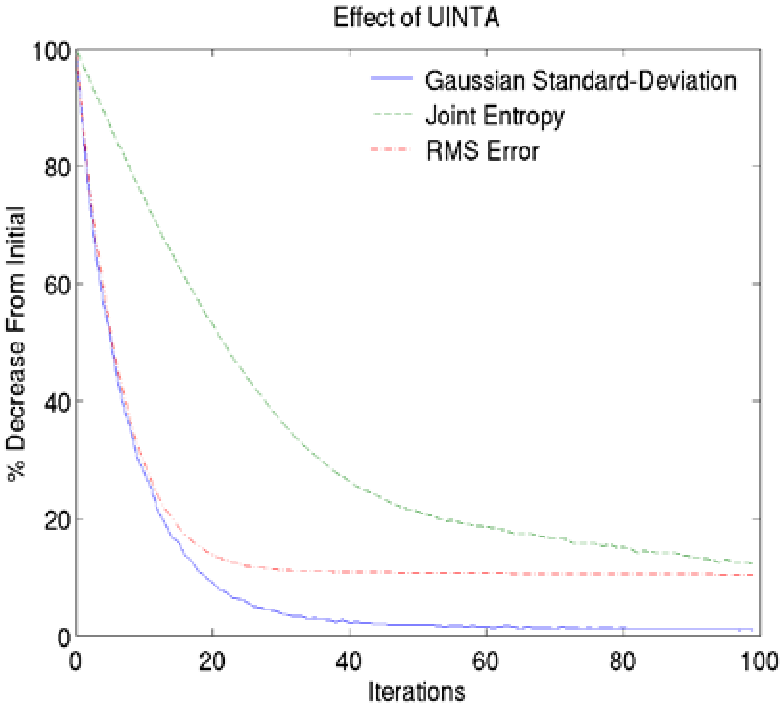
Noisy

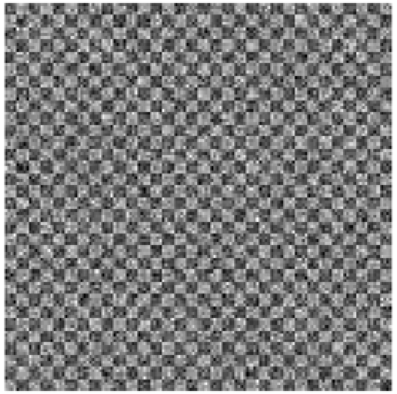


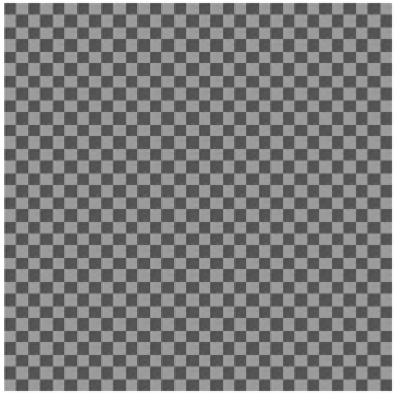
Filtered

Quality of Denoising

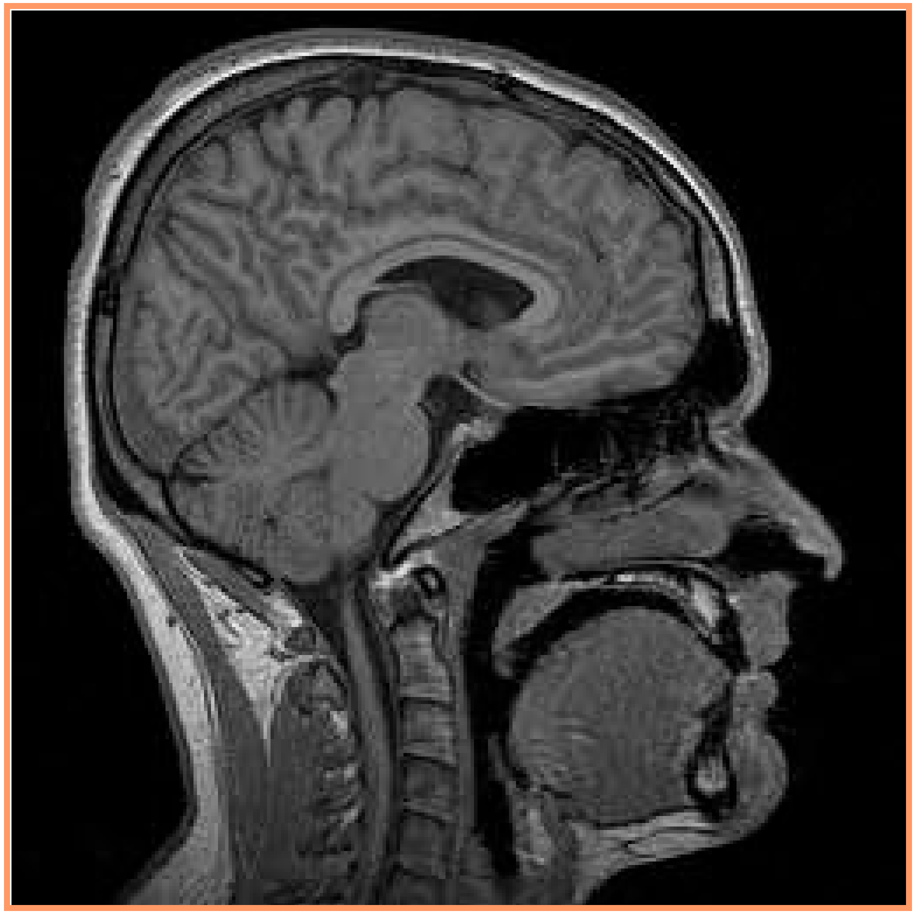
- s, joint entropy, and RMS- error vs. number of iterations

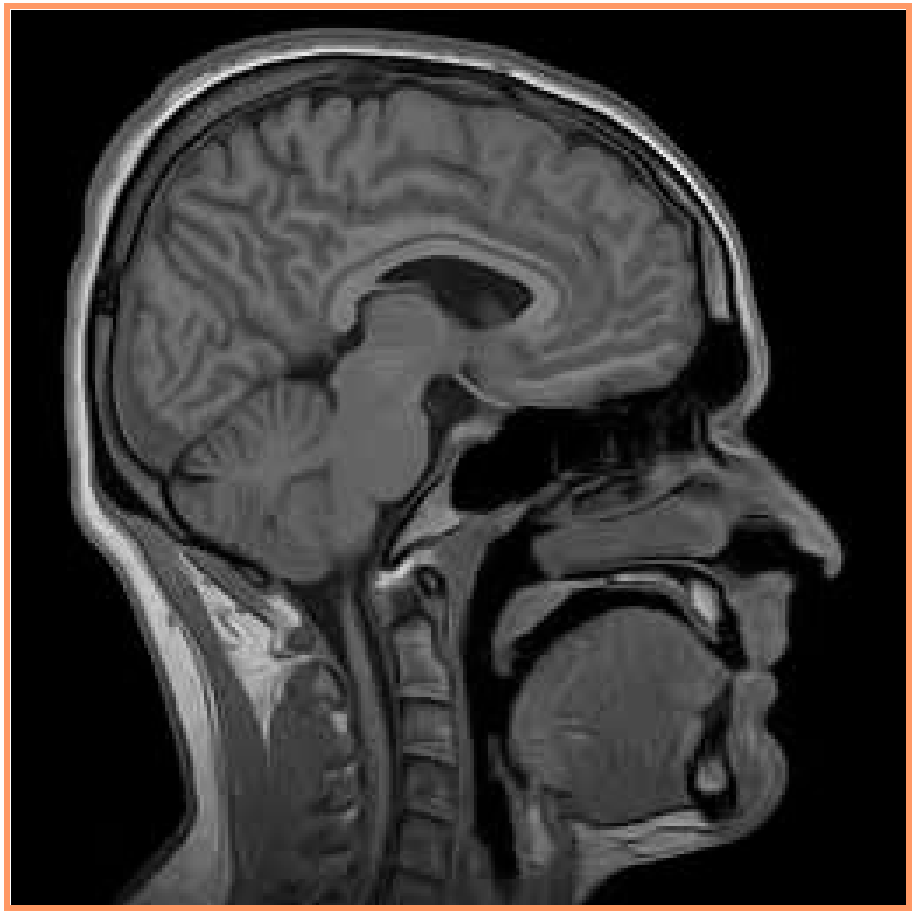




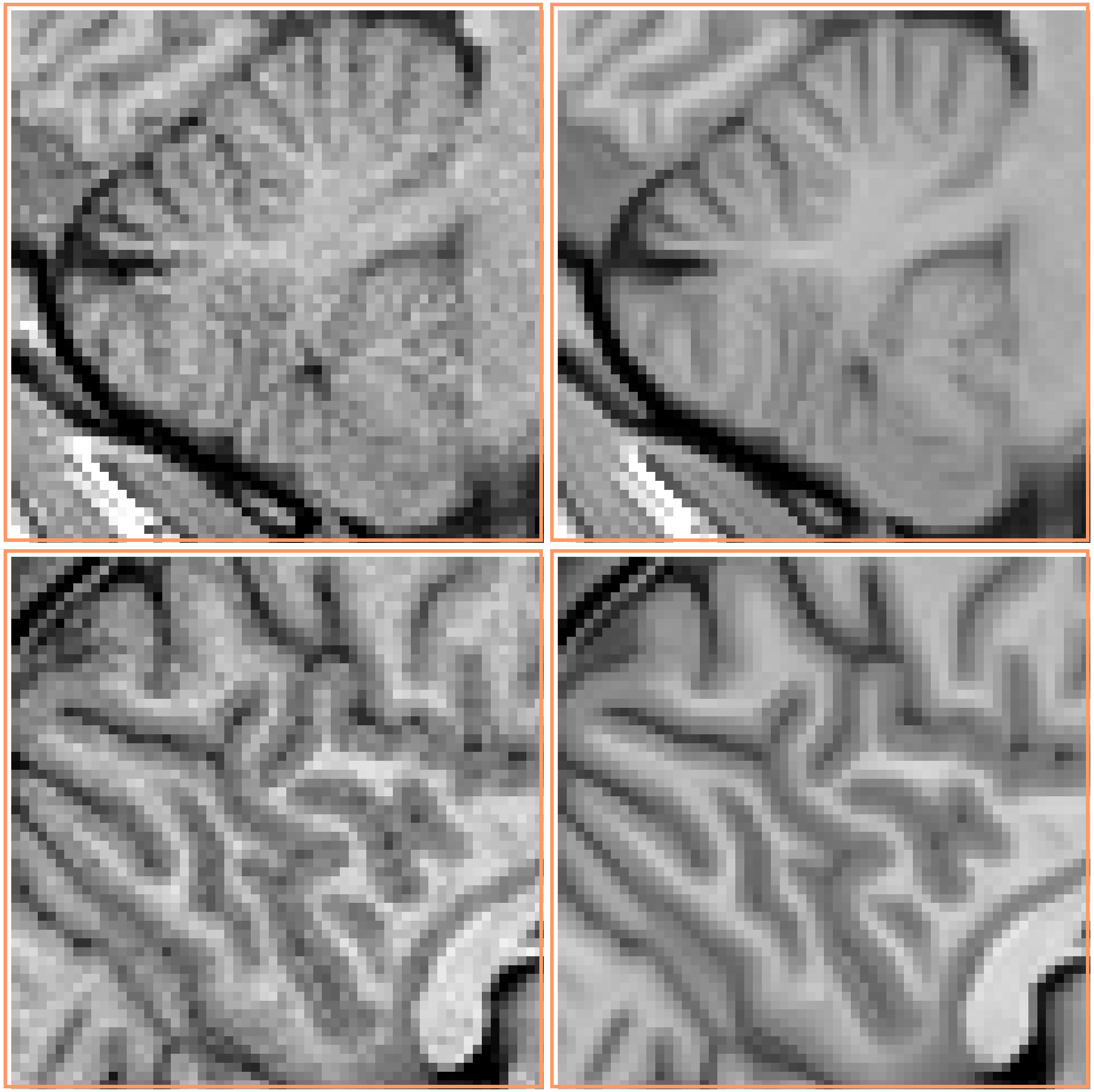


MRI Head

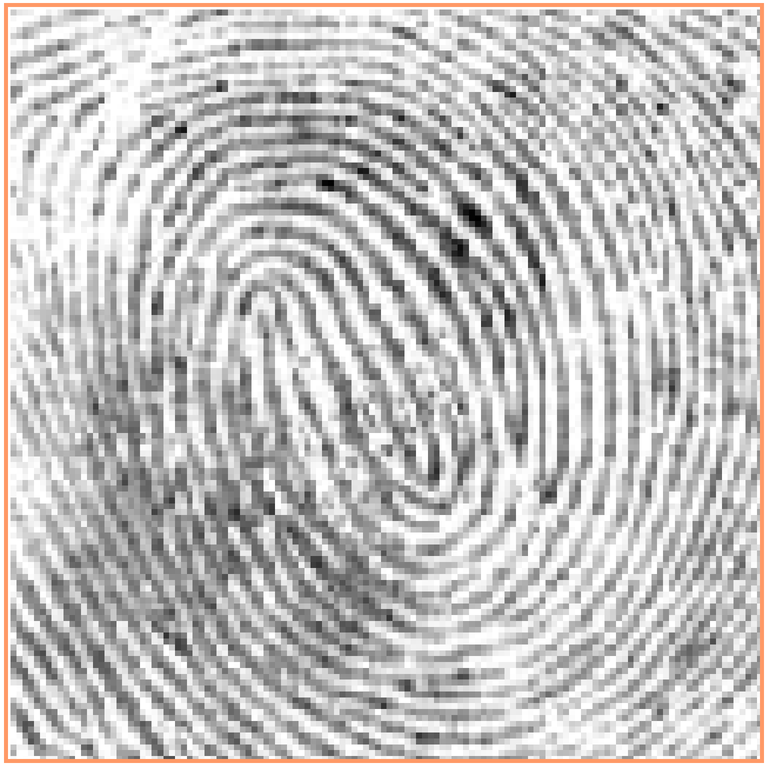


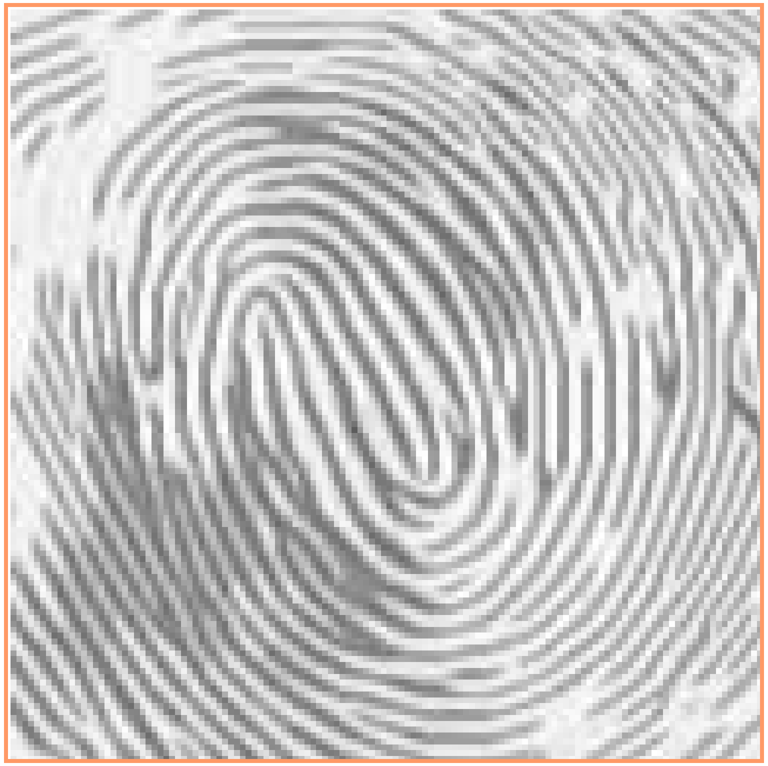


MRI Head

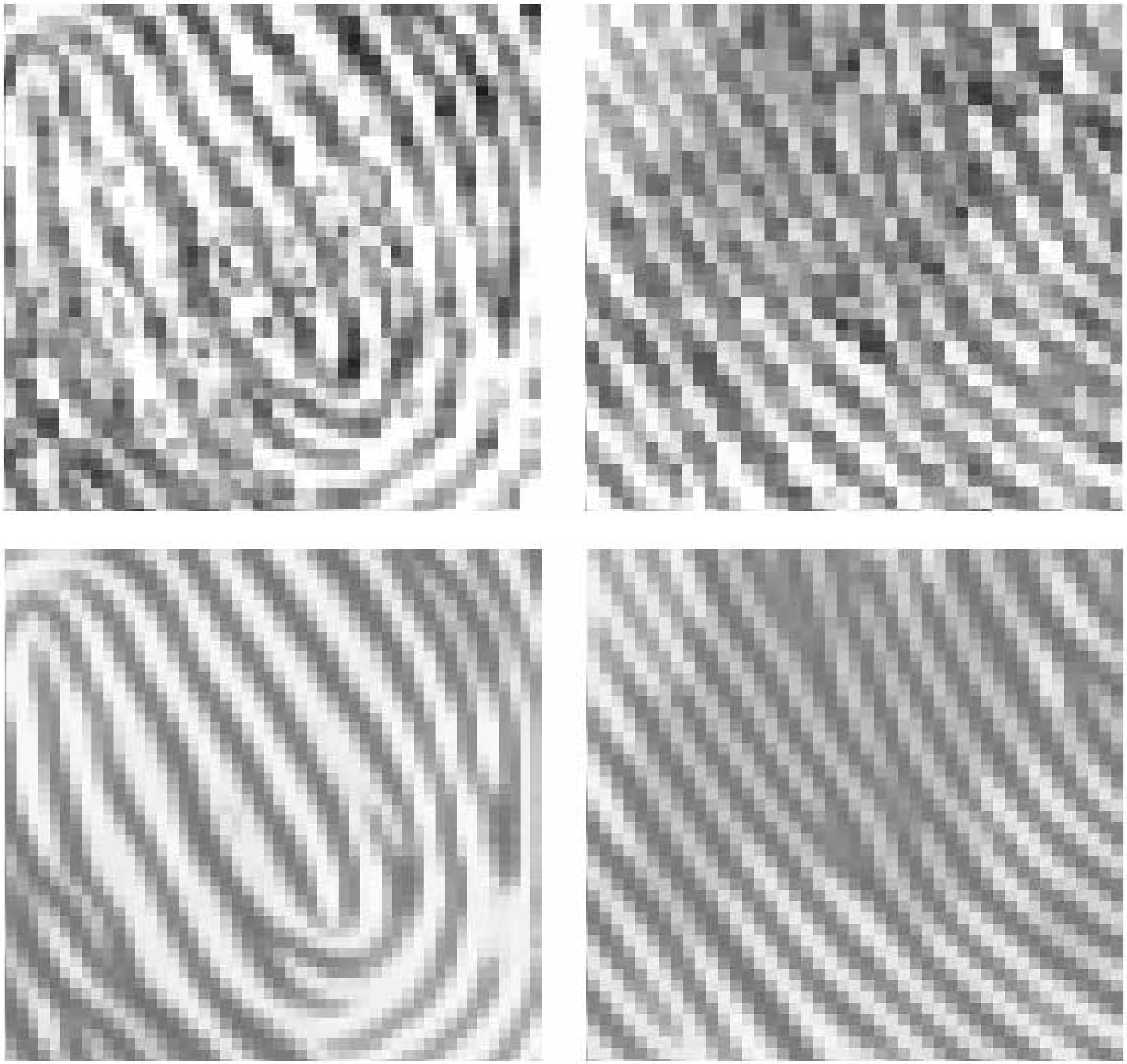


Fingerprint

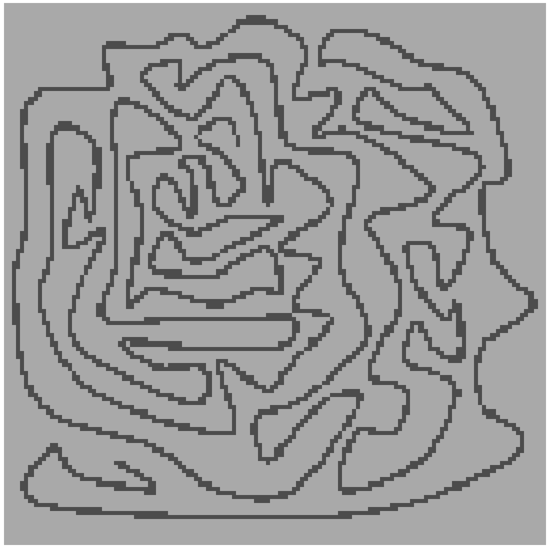




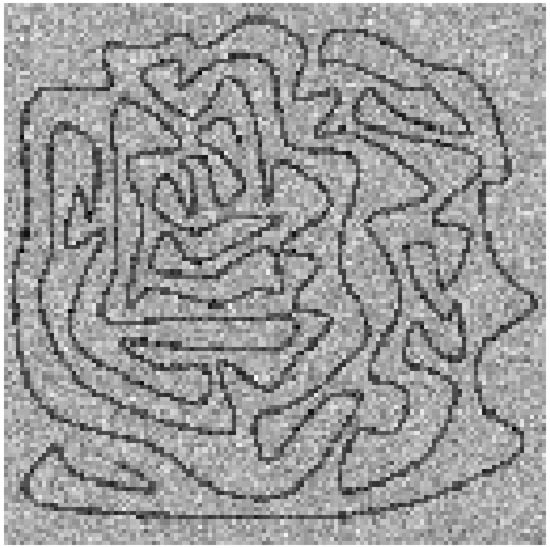
Fingerprint



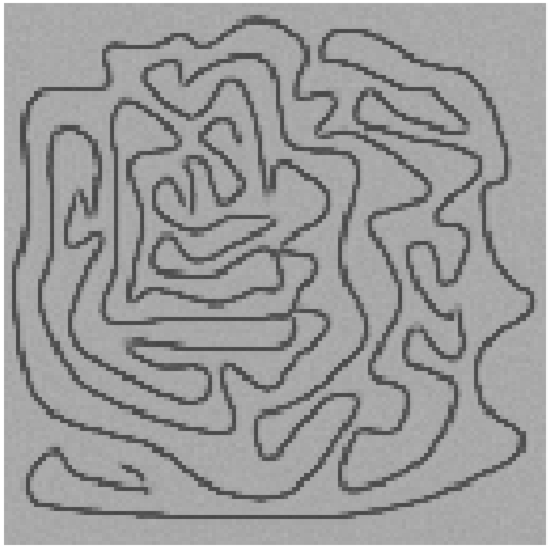
Results



Original

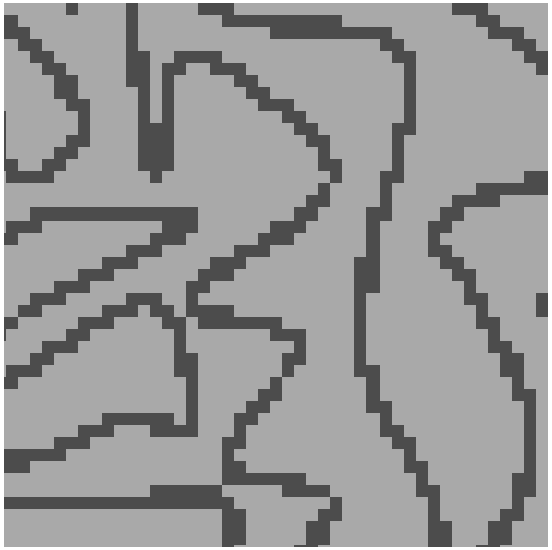


Noisy

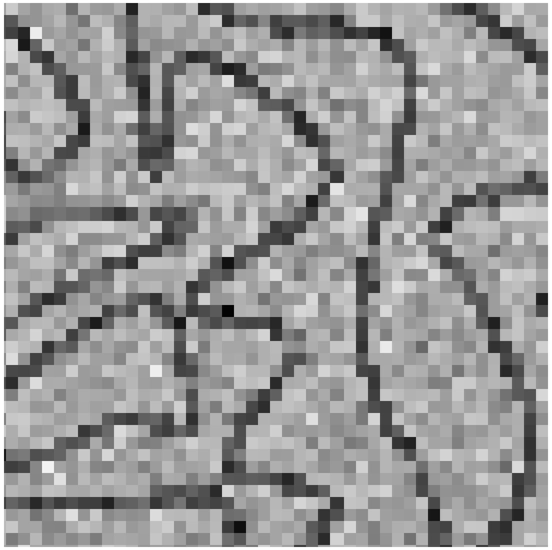


Filtered

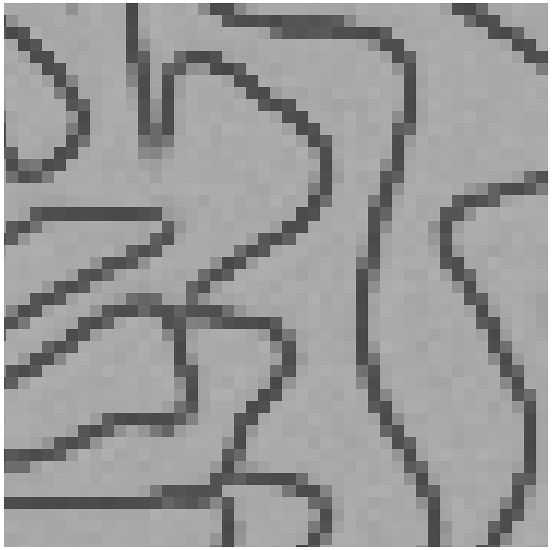
Results



Original

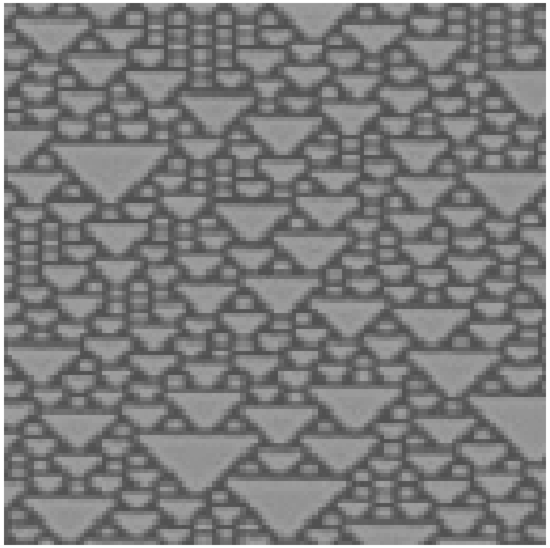


Noisy



Filtered

Results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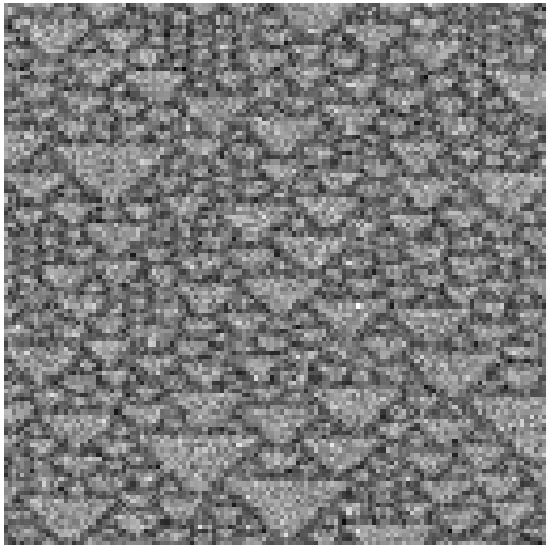
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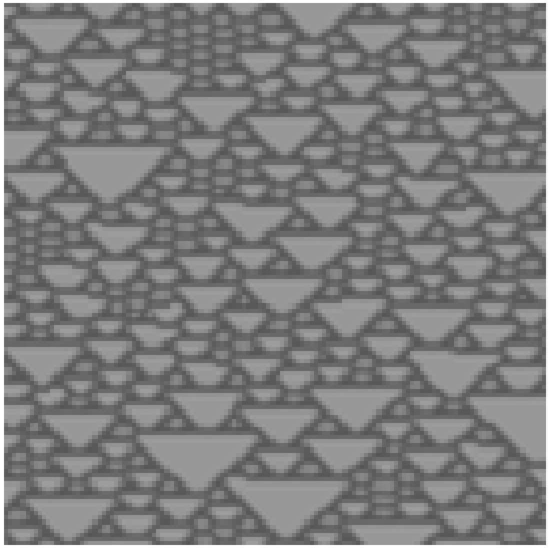
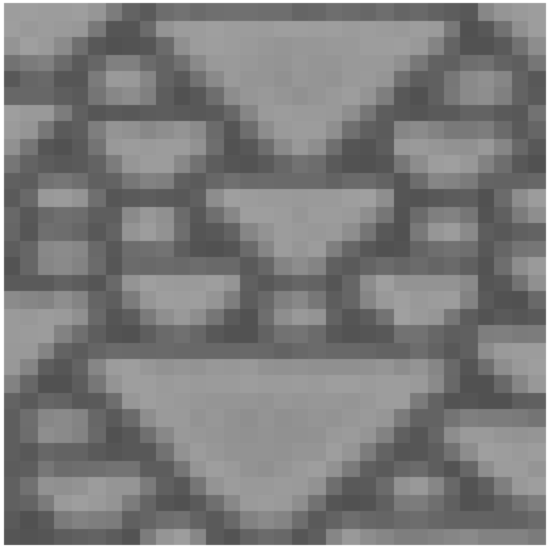

Filtered

Fractal



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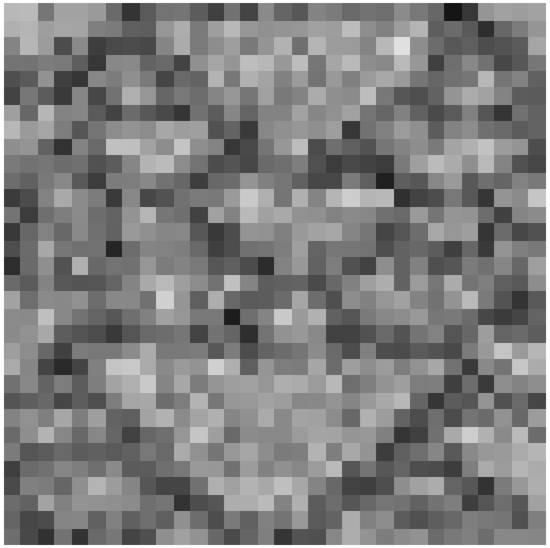

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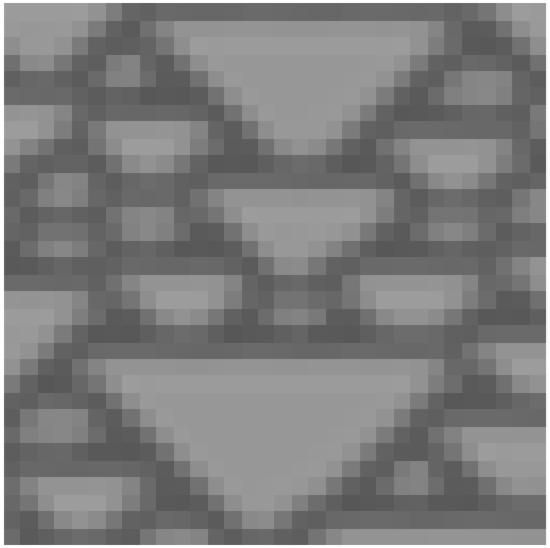
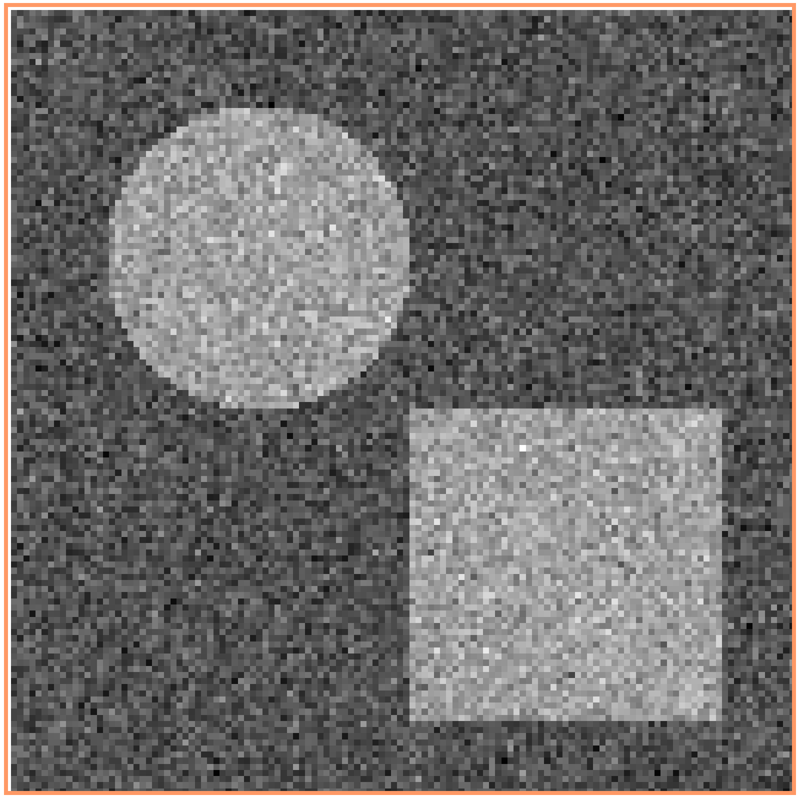
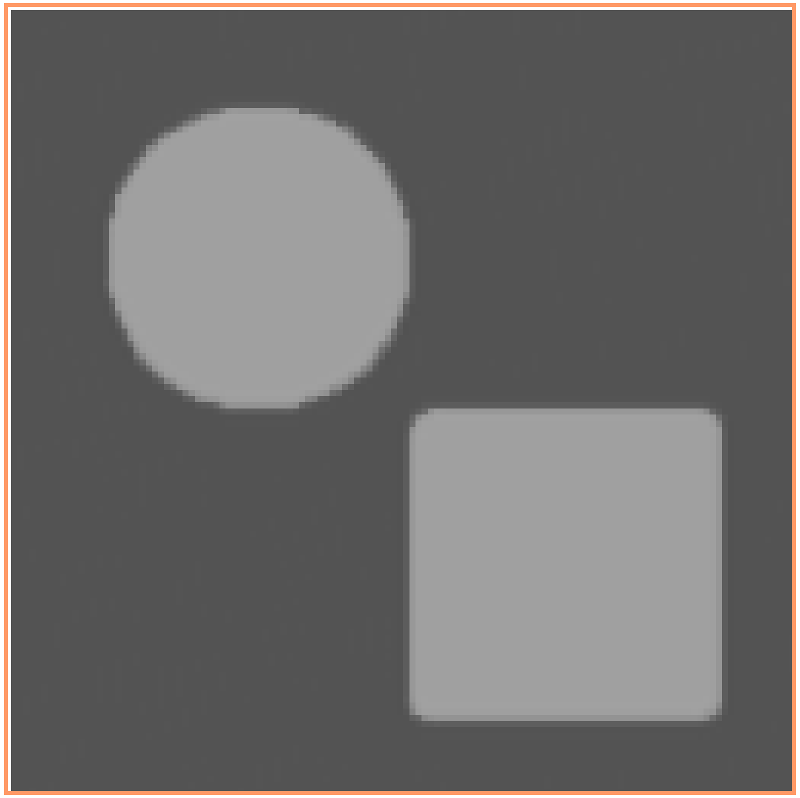


Filtered

Piecewise Constant

- Several 10s of Iterations
- Tends to obliterate rare events (e.g. corners)





Texture, Structure