

اصول پردازش تصویر

*Principles of Image Processing*

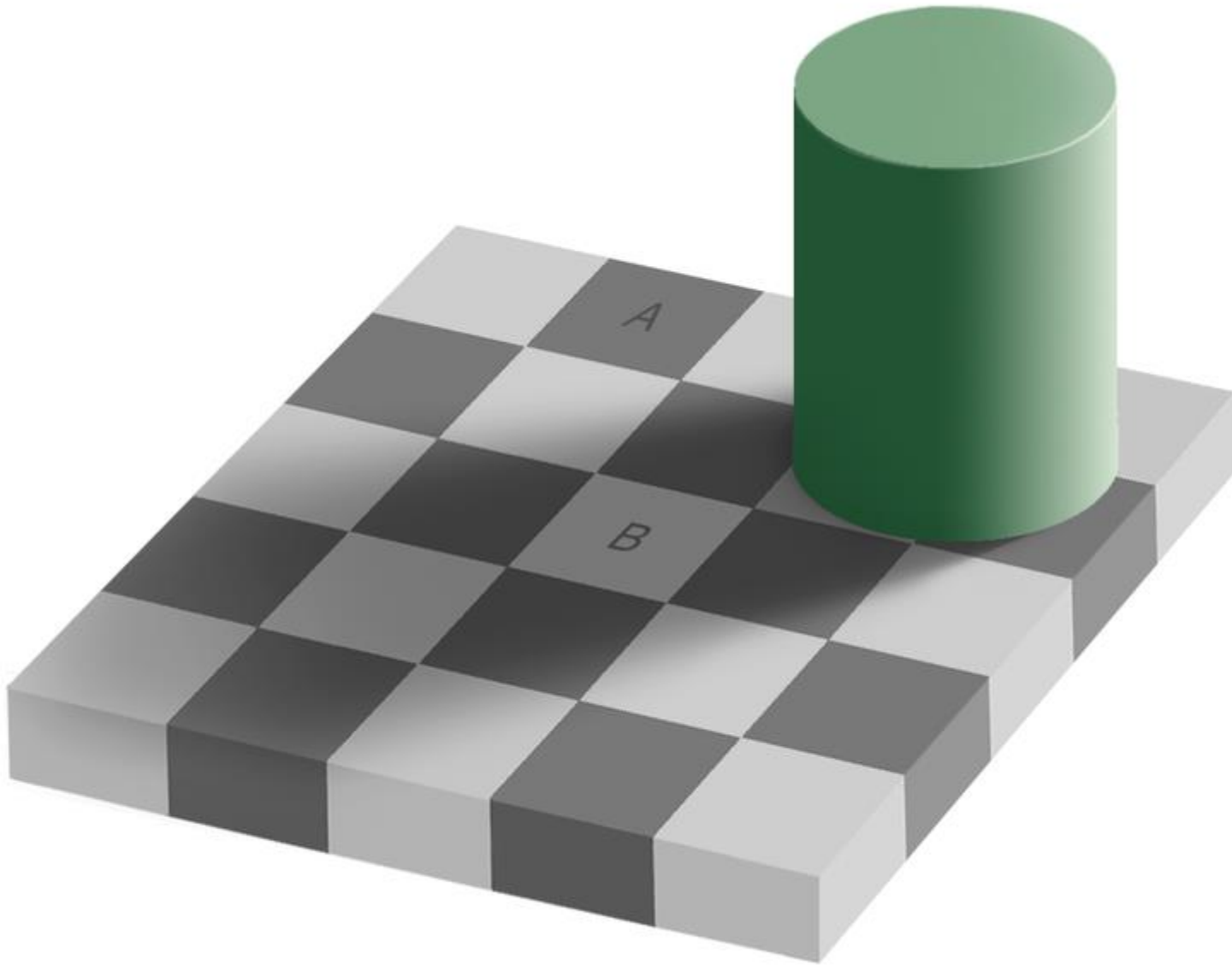
مصطفی کمالی تبریزی

۵ مهر ۱۳۹۹

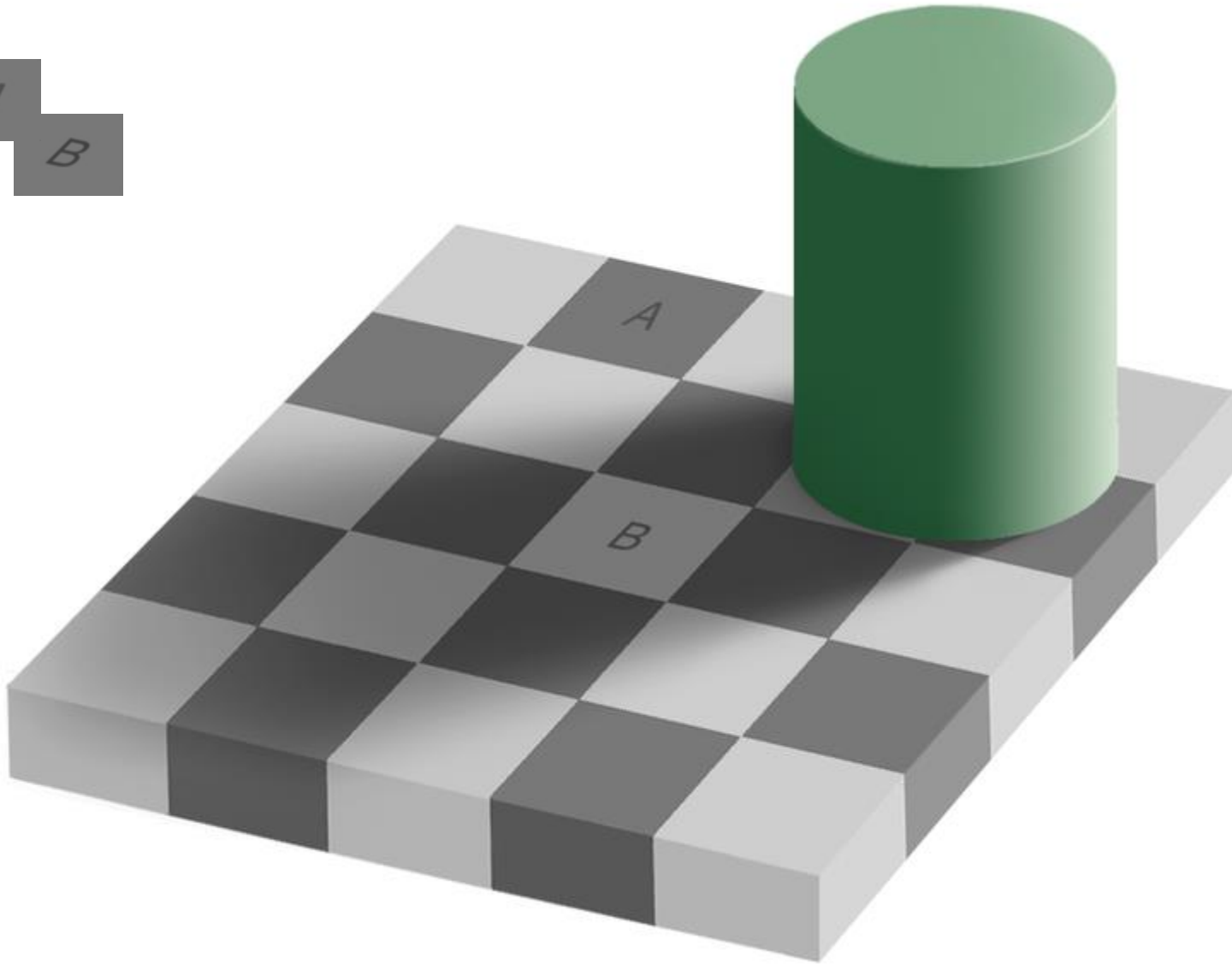
جلسه سوم

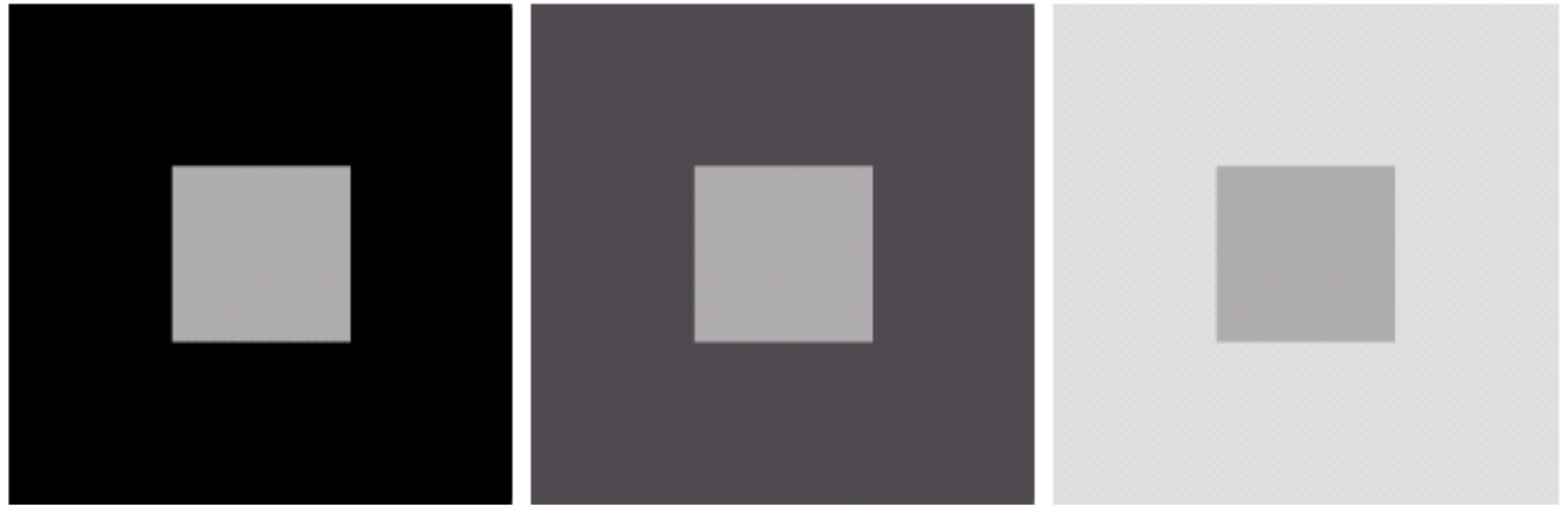
# *Visual Perception*

# *Perception of Intensity*



# *Perception of Intensity*

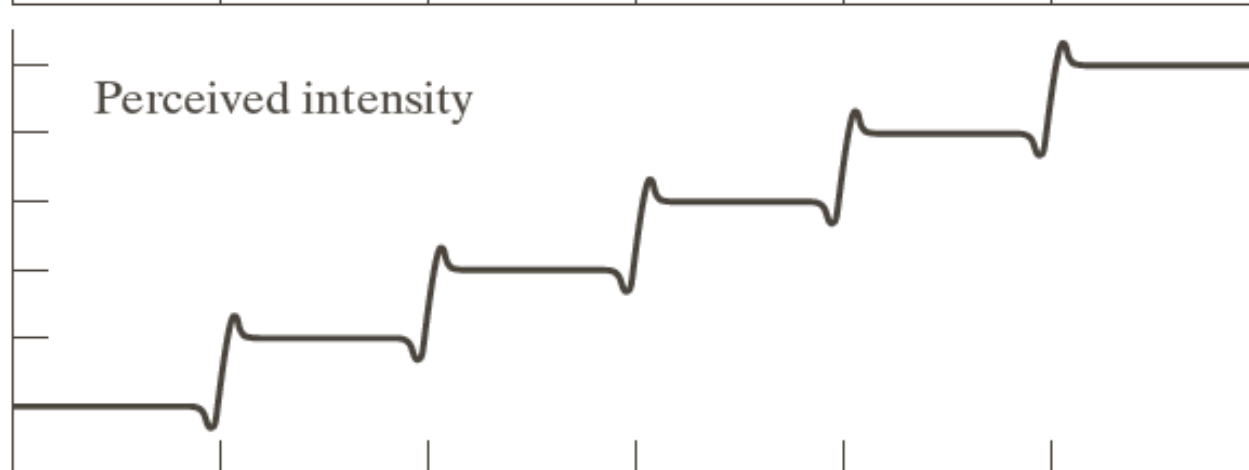
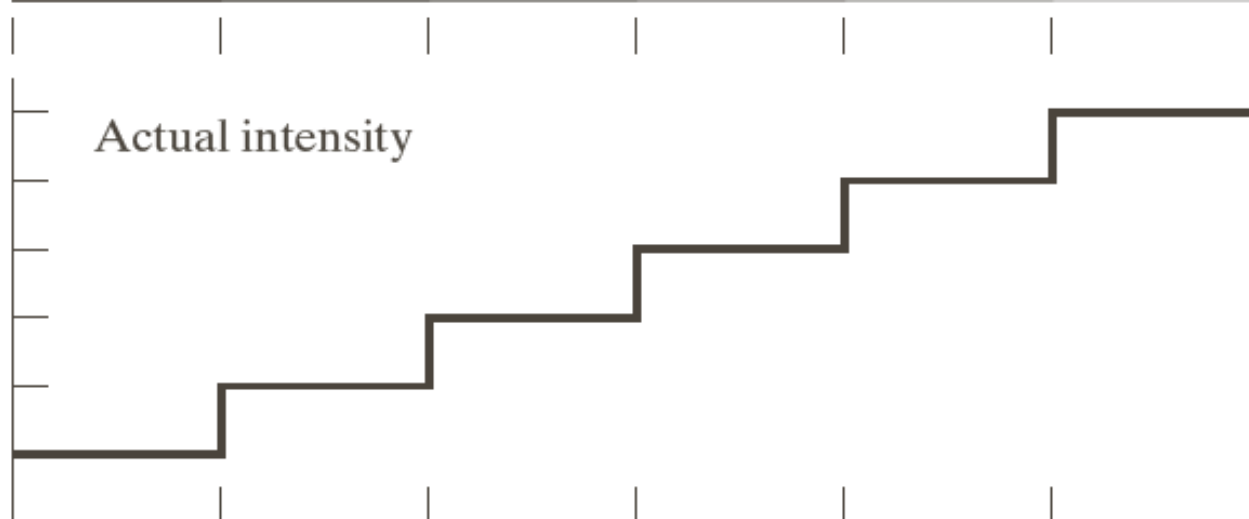




a b c

**FIGURE 2.8** Examples of simultaneous contrast. All the inner squares have the same intensity, but they appear progressively darker as the background becomes lighter.

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a

b

c

**FIGURE 2.7**

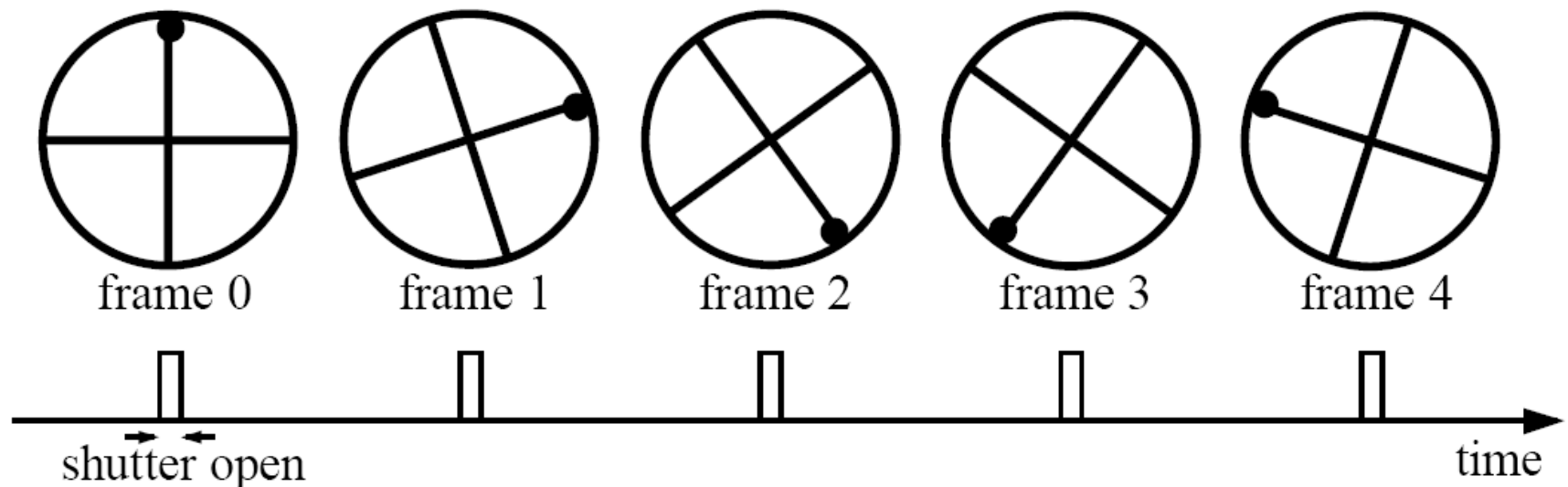
Illustration of the Mach band effect. Perceived intensity is not a simple function of actual intensity.

# *Aliasing in Video*

Imagine a spoked wheel moving to the right (rotating clockwise).

Mark wheel with dot so we can see what's happening.

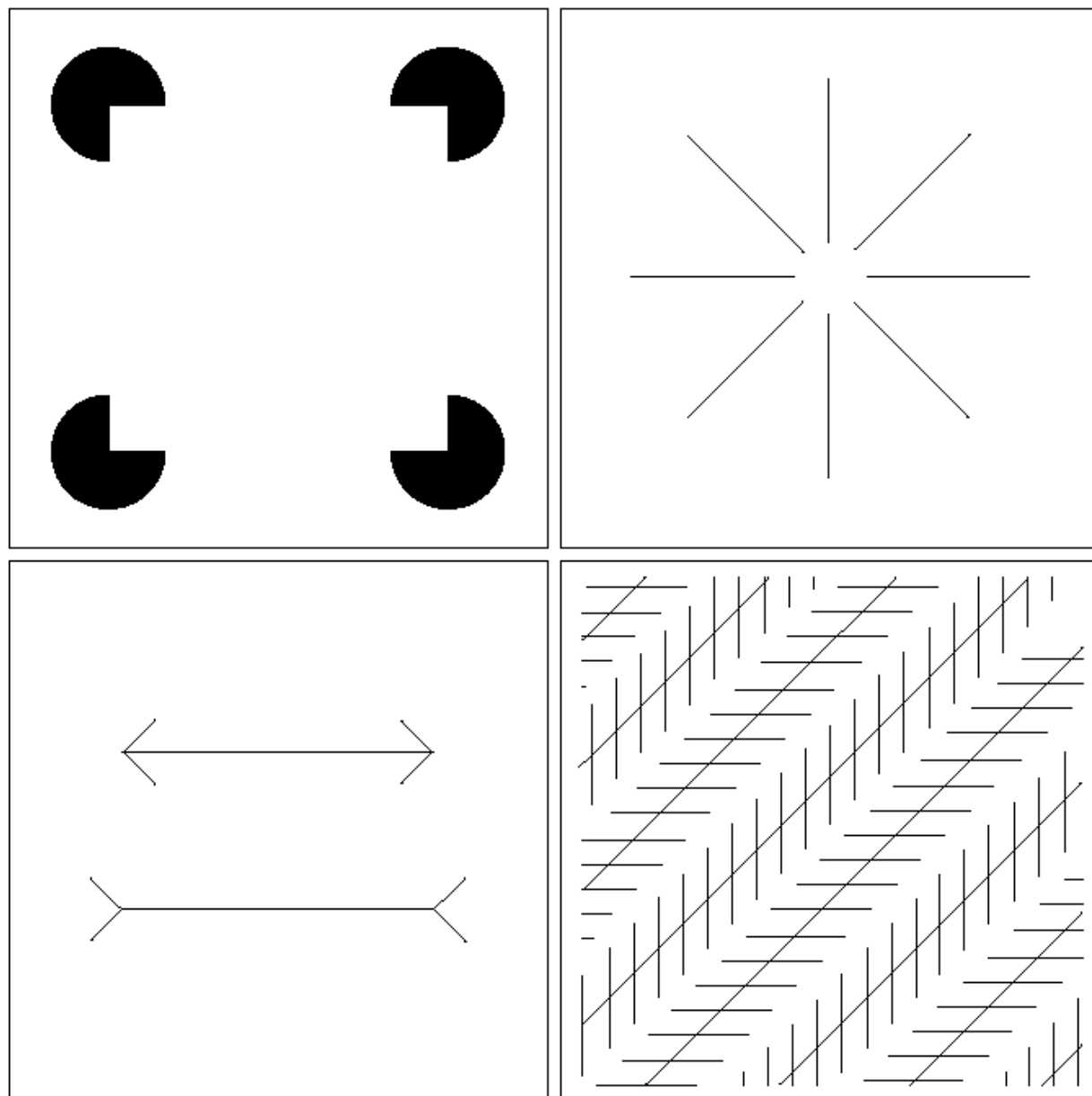
If camera shutter is only open for a fraction of a frame time (frame time =  $1/30$  sec. for video,  $1/24$  sec. for film):



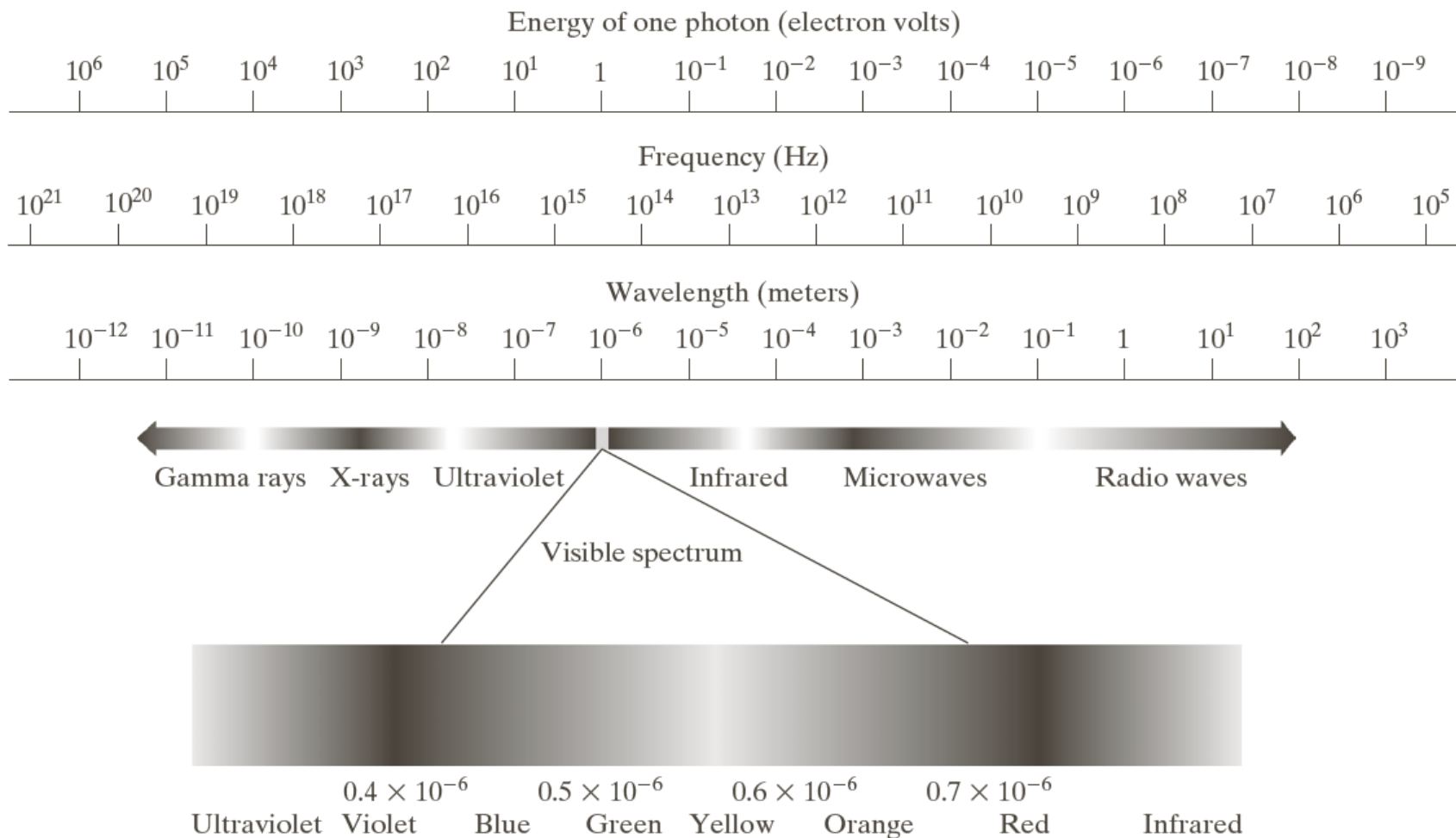
Without dot, wheel appears to be rotating slowly backwards!  
(counterclockwise)

a	b
c	d

**FIGURE 2.9** Some well-known optical illusions.







**FIGURE 2.10** The electromagnetic spectrum. The visible spectrum is shown zoomed to facilitate explanation, but note that the visible spectrum is a rather narrow portion of the EM spectrum.

# *References*

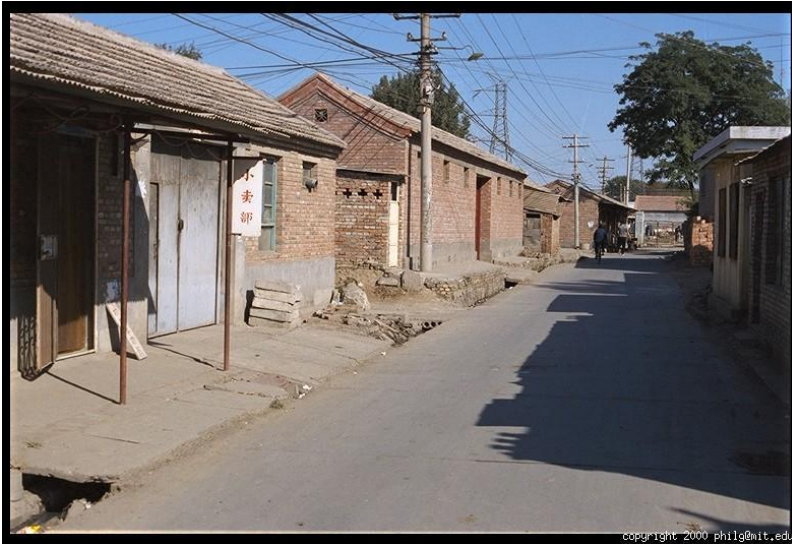
- Gonzalez, 4<sup>th</sup> Edition  
Chapter 1 and Chapter 2
- Szeliski  
Chapter 1 and Chapter 2

# *Color Image*

R

G

B



Color Image



Red (R)



Green (G)



Blue (B)





# Color Images

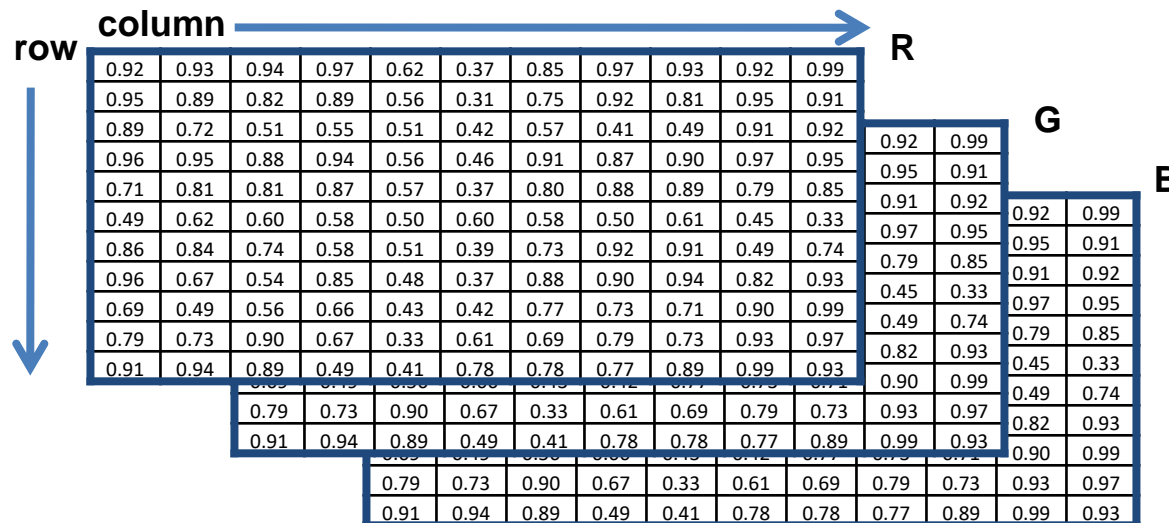


عکس محمد عالم خان، امیر بخارا، سال ۱۲۸۱ شمسی

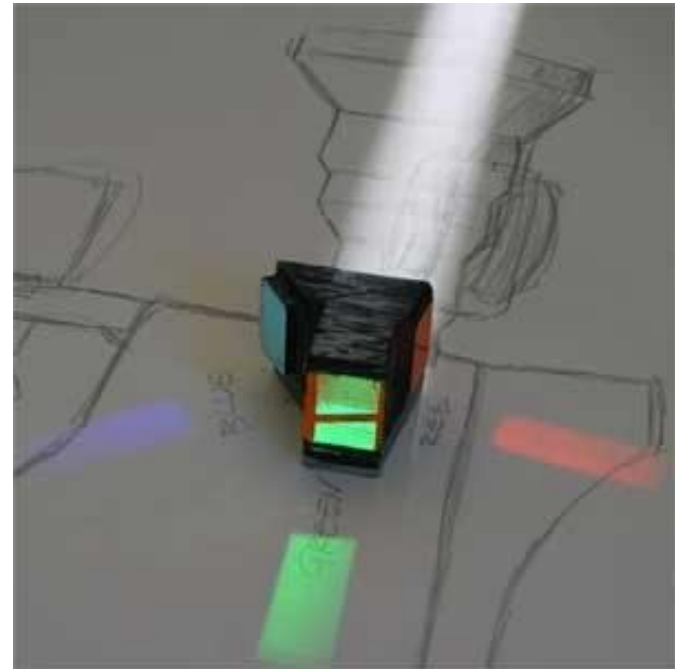
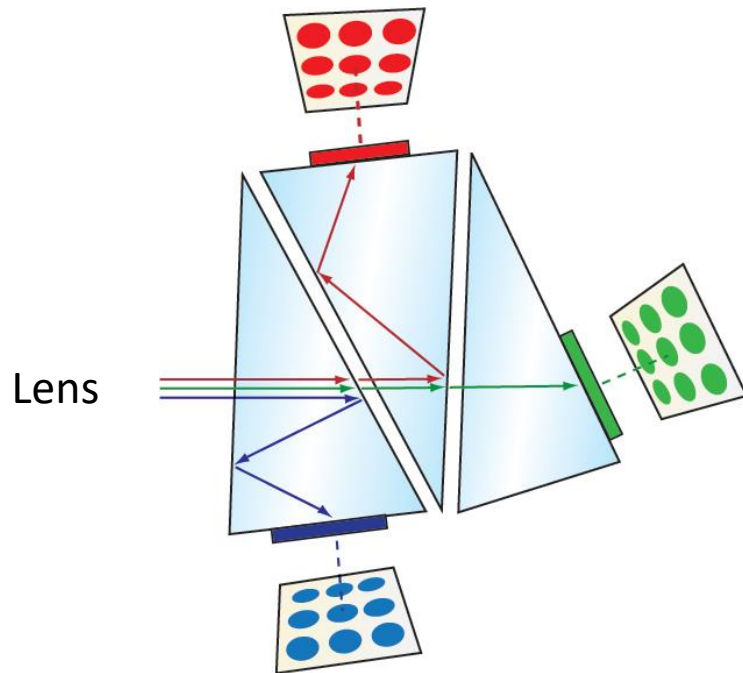
# Images in Python

```
im = cv2.imread(filename)           # read image
im = cv2.cvtColor(im, cv2.COLOR_BGR2RGB) # order channels as RGB
im = im / 255                       # values range from 0 to 1
```

- RGB image `im` is a `H x W x 3` matrix (numpy.ndarray)
- `im[0, 0, 0]` = top-left pixel value in R-channel
- `im[x, y, c]` = `x+1` pixels down, `y+1` pixels to right in the `cth` channel
- `im[H-1, W-1, 2]` = bottom-right pixel in B-channel

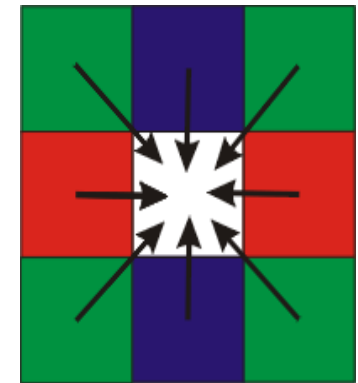
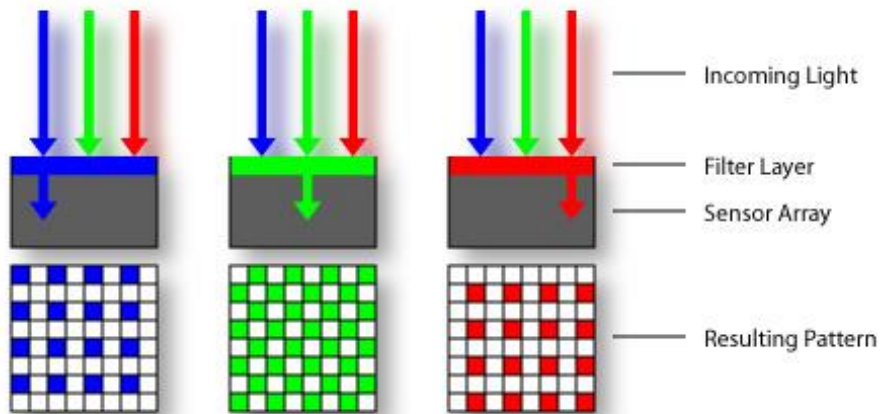
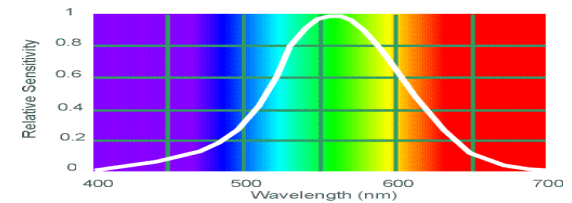
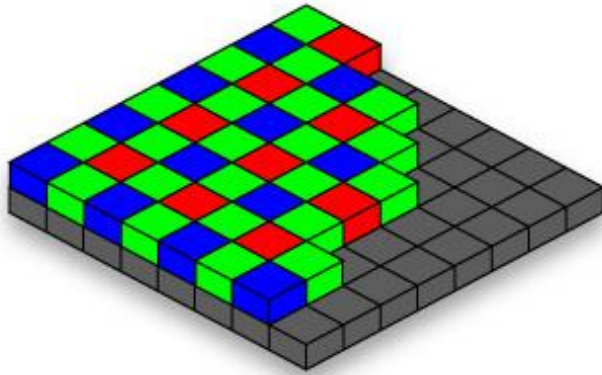


# *Cameras with Three Sensors*



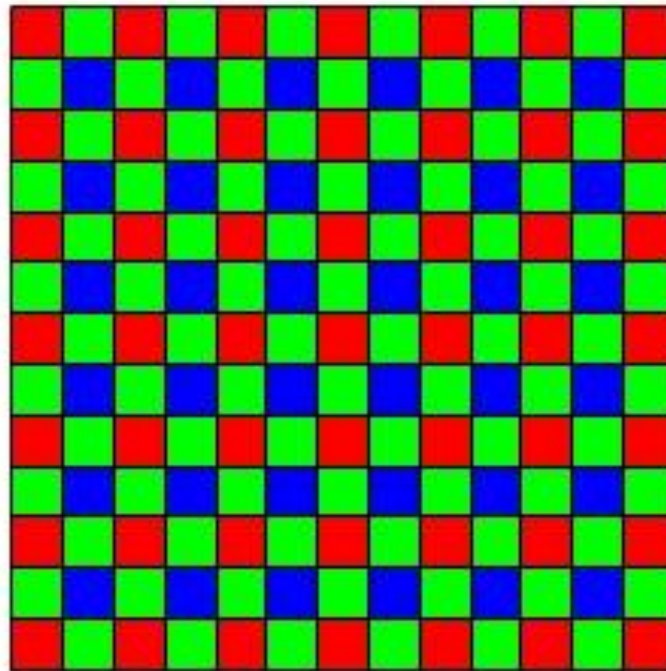
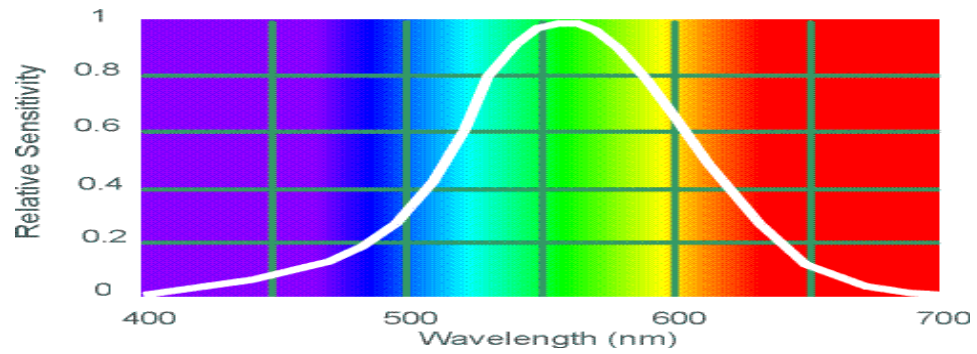
[Edmund Optics; Adam Wilt]

# Cheaper / More Compact Color Sensing: Bayer Filter



- Estimate RGB at 'G' cells from neighboring values



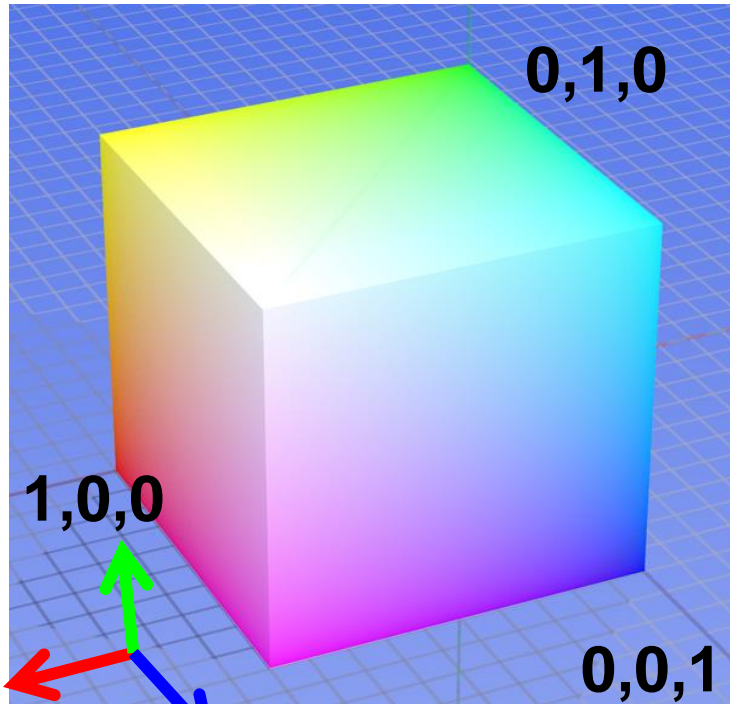


**Bayer filter**

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# *Color Spaces: RGB*

Default color space



RGB cube

- Easy for devices
- But not perceptual
- Where do the grays live?
- Where is hue and saturation?



**R**

(G=0,B=0)



**G**

(R=0,B=0)

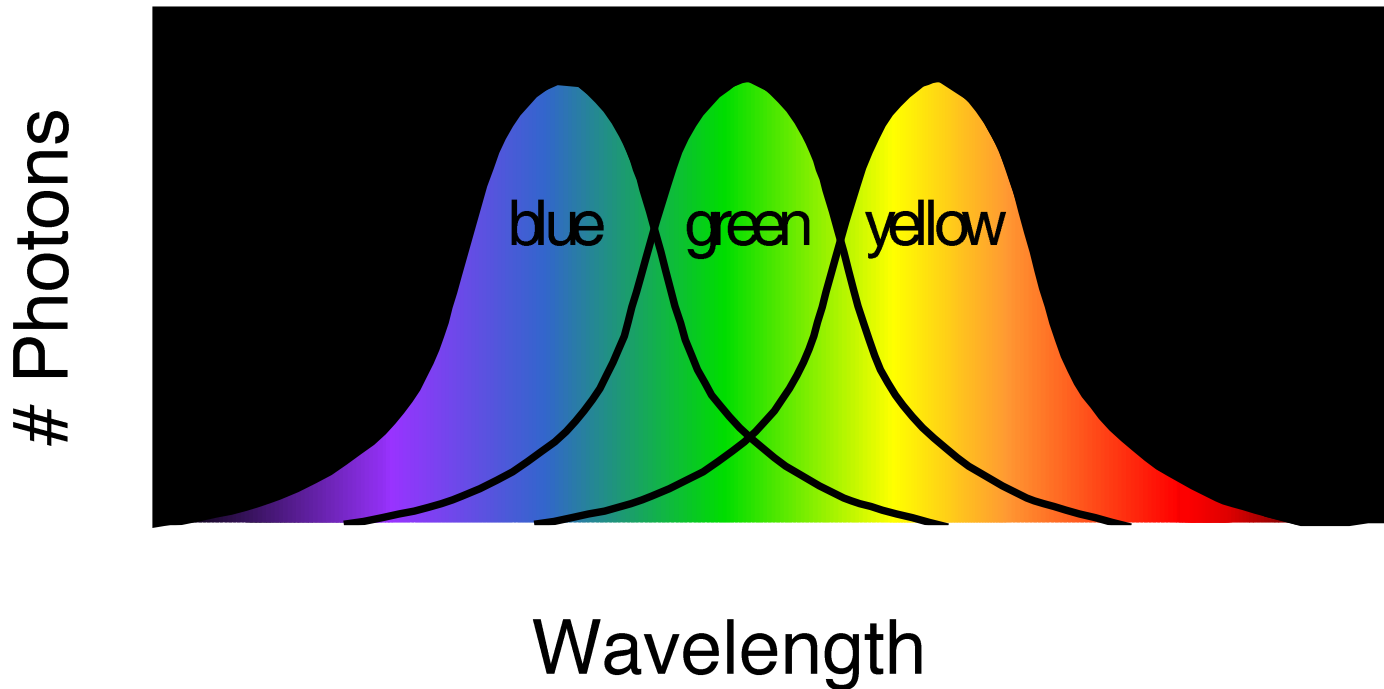


**B**

(R=0,G=0)

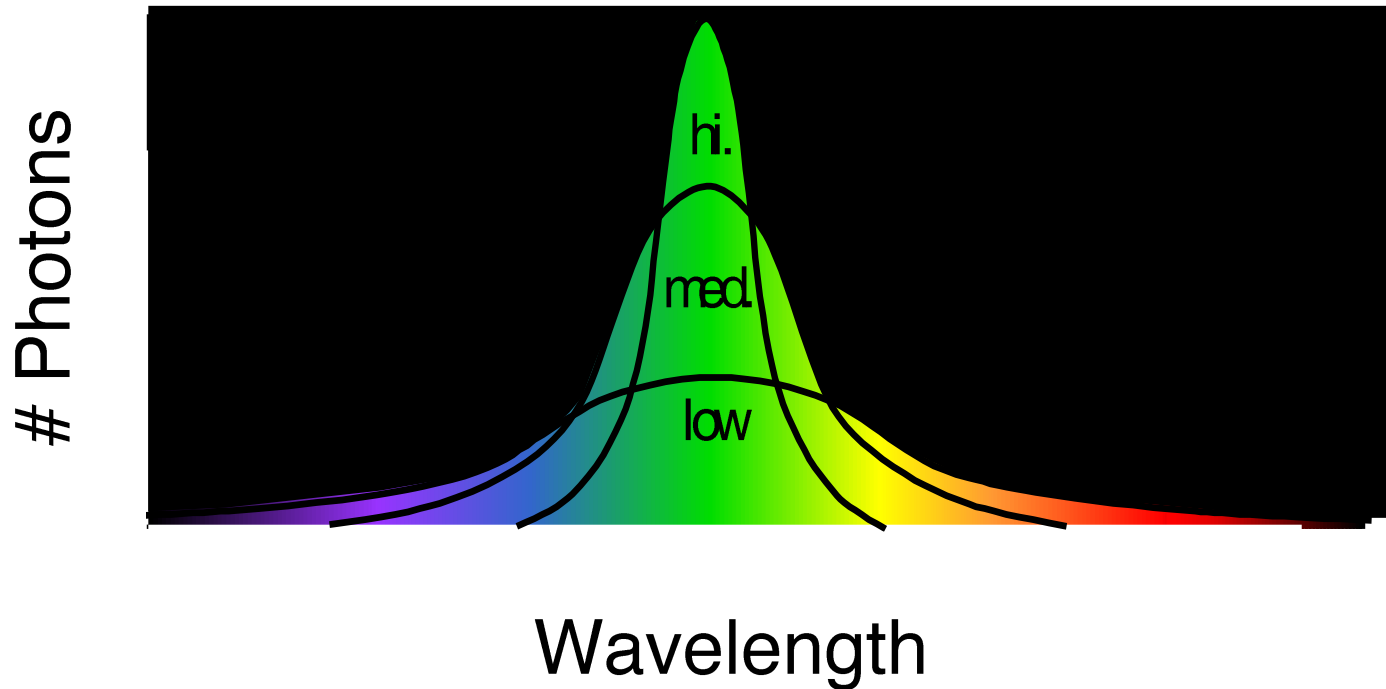
# The Psychophysical Correspondence

Mean  $\longleftrightarrow$  Hue



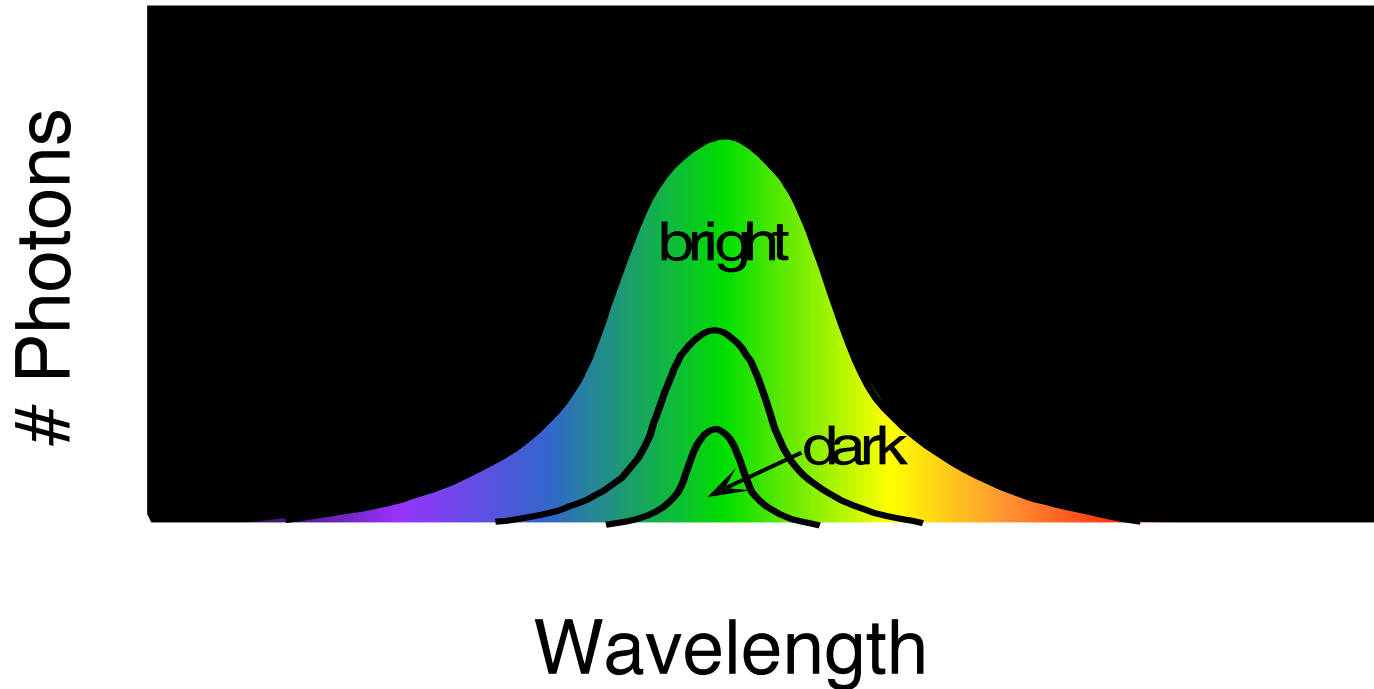
# The Psychophysical Correspondence

Variance  $\longleftrightarrow$  Saturation



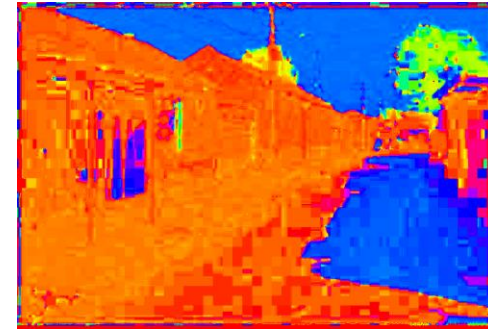
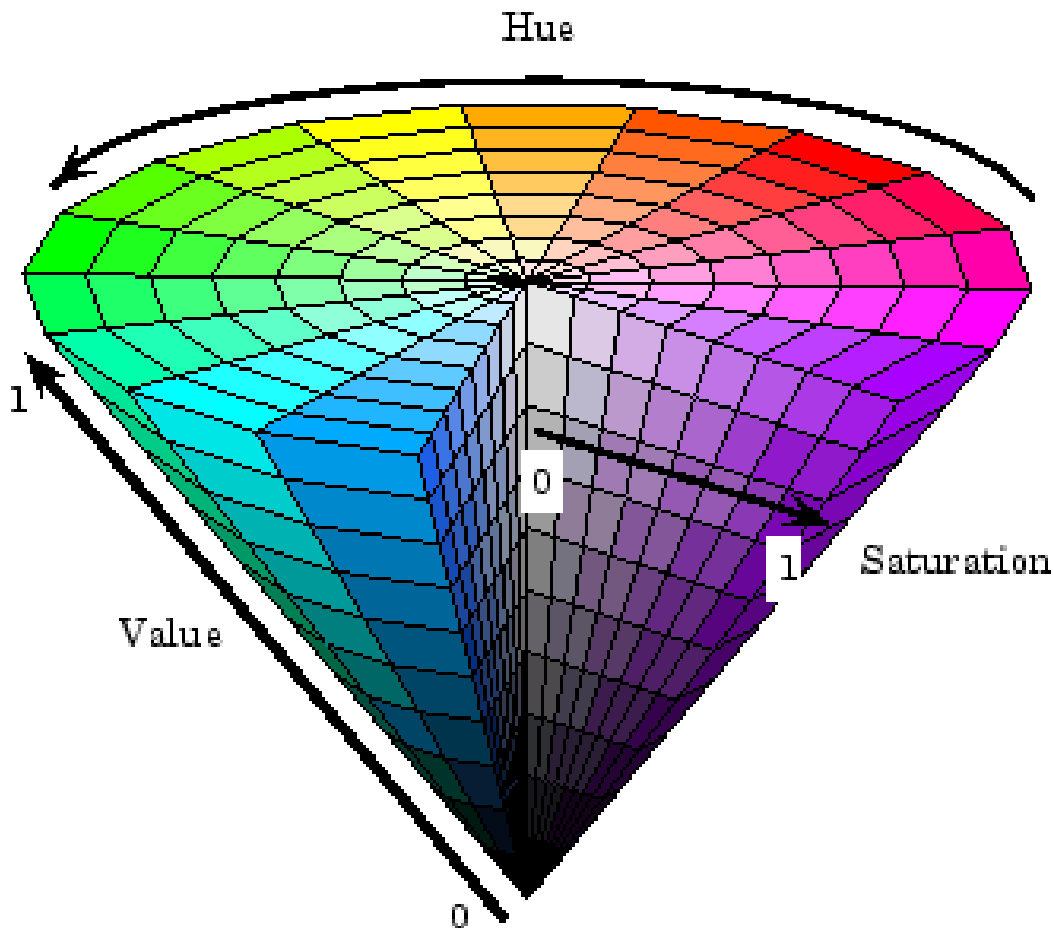
# The Psychophysical Correspondence

Area  $\longleftrightarrow$  Brightness



# *Color spaces: HSV*

Intuitive color space



**H**  
(S=1,V=1)



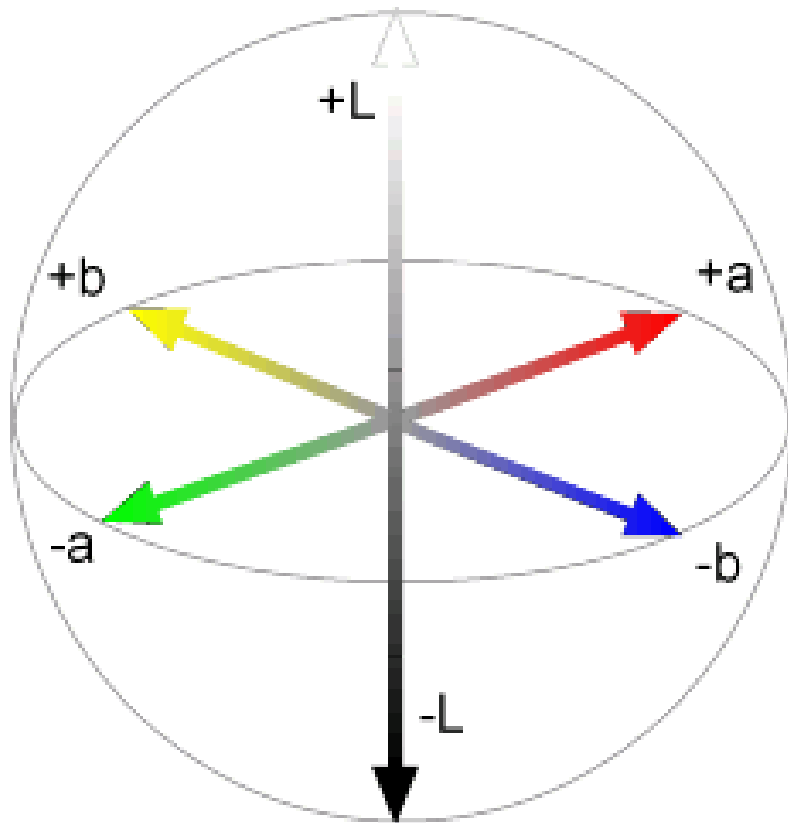
**S**  
(H=1,V=1)



**V**  
(H=1,S=0)

# *Color spaces: $L^*a^*b^*$*

“Perceptually uniform”\* color space



**L**  
(a=0,b=0)



**a**  
(L=65,b=0)



**b**  
(L=65,a=0)

# *References*

- Color Image Processing  
Gonzalez, chapter 7  
Szeliski, section 2.3.2 (and 2.2)