Lecture 3 Image Sampling

COMP3204 & COMP6223 Computer Vision

How is an image sampled and what does it imply?

Book
pp
49-71

Department of Electronics and Computer Science

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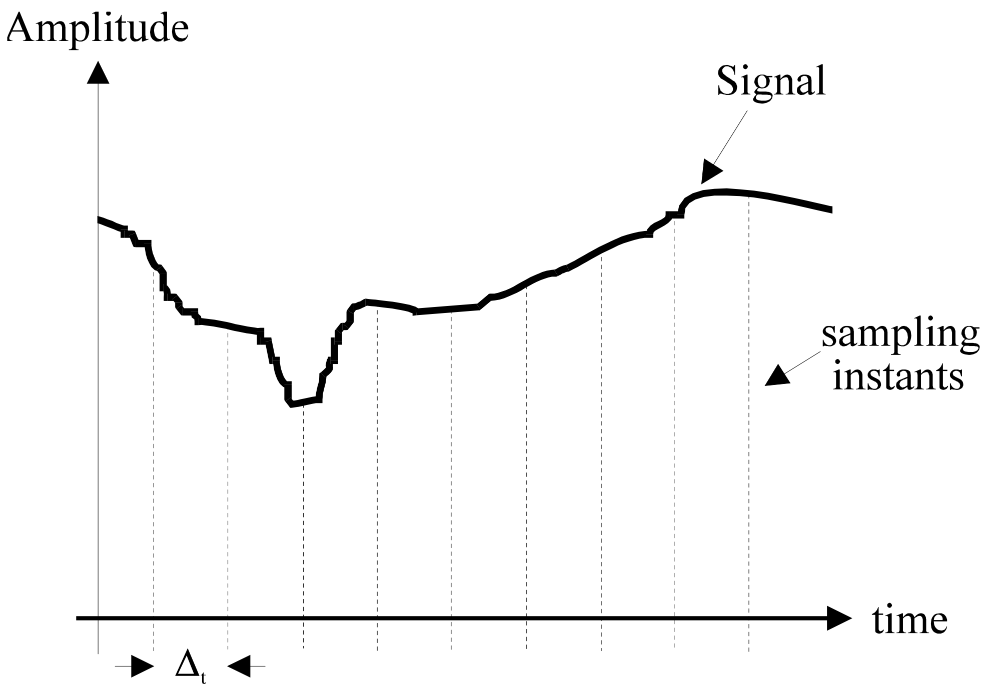
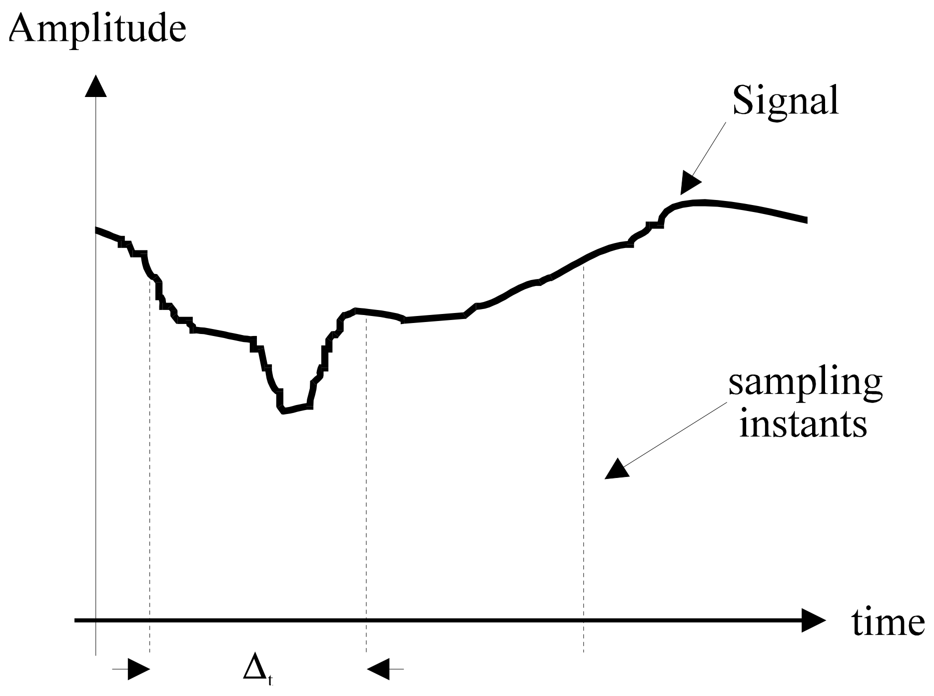


(a) sampling at high frequency



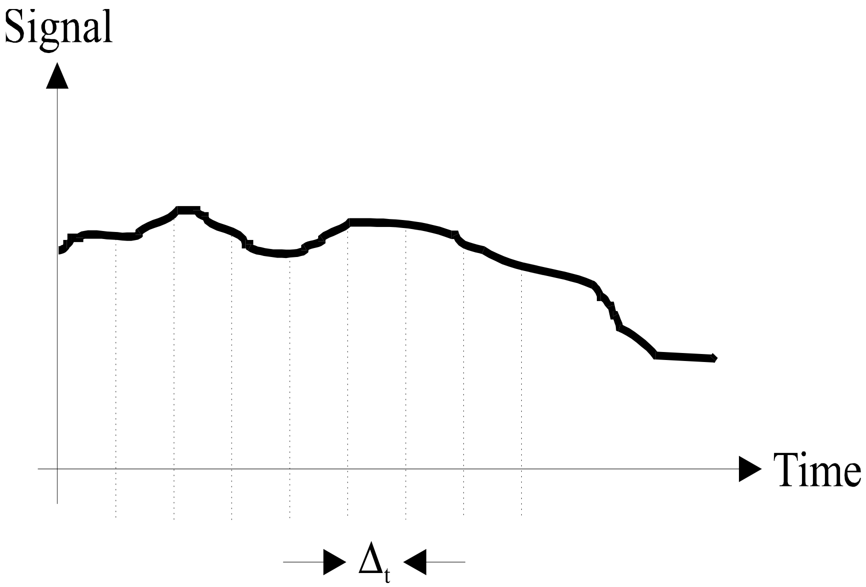
(b) sampling at low frequency

Sampling at Different Frequencies

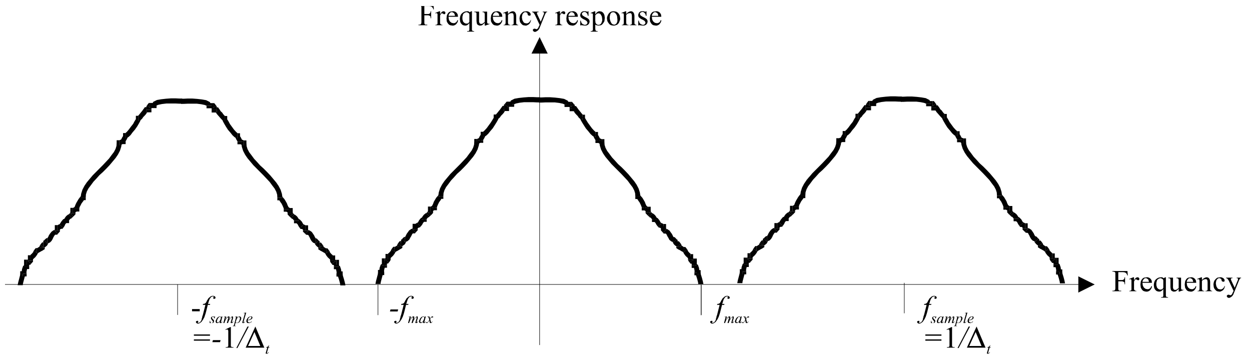
(a) high resolution

(c) low resolution - aliased

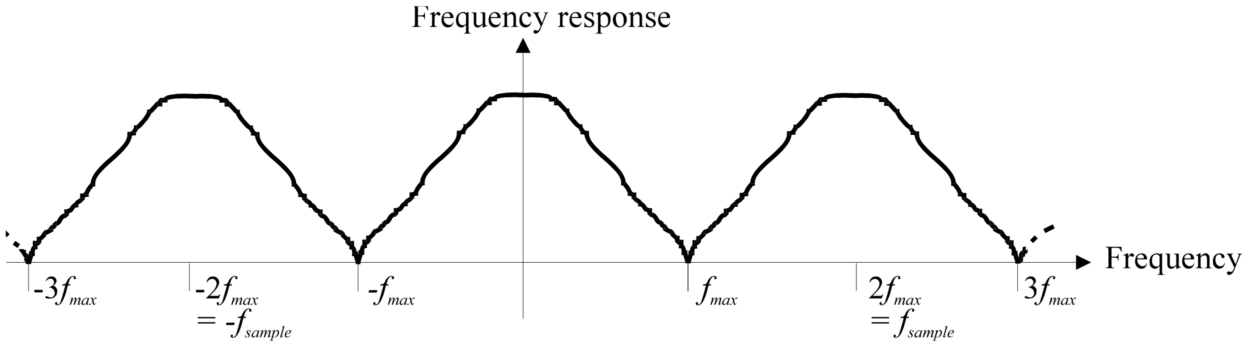
Aliasing in Sampled Imagery



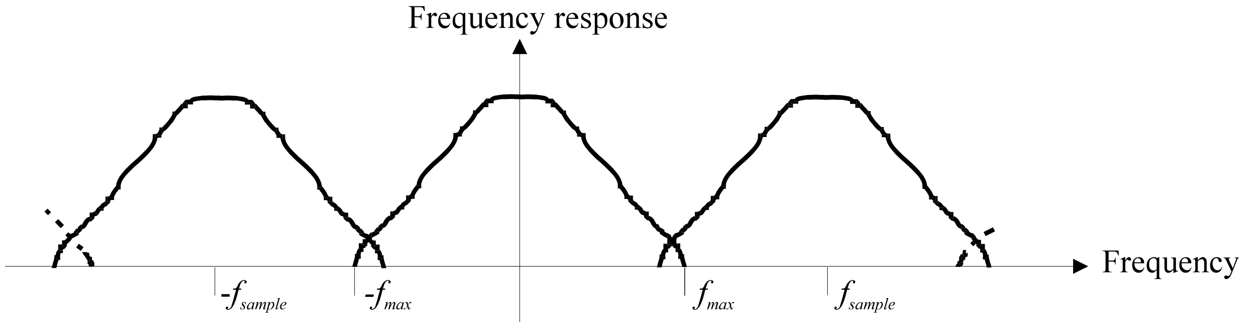
(a) sampled signal



(b) oversampled spectra

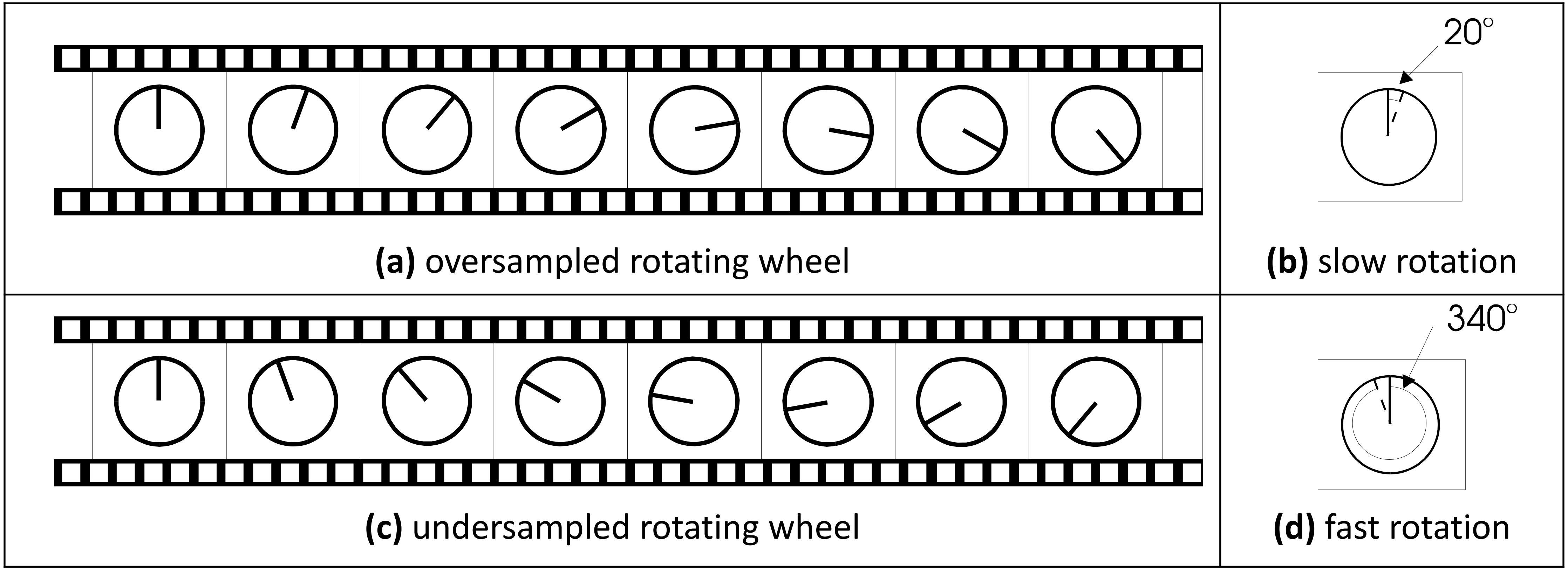


(c) sampling at the Nyquist rate



(d) undersampled, aliased, spectra

Sampled Spectra



(a) oversampled rotating wheel

(b) slow rotation

(c) undersampled rotating wheel

(d) fast rotation

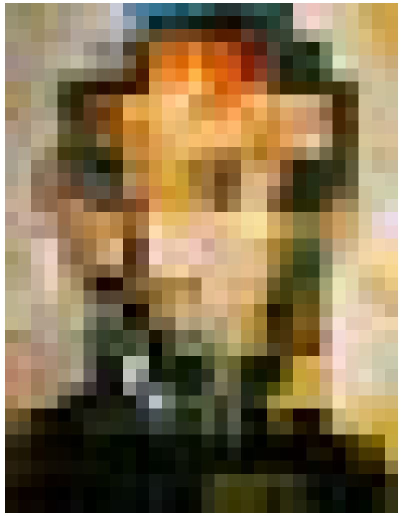
Correct and Incorrect Apparent Wheel Motion

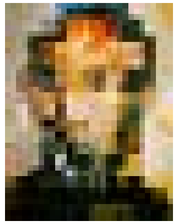
https://www.youtube.com/watch?v=e1EqXE06xr8

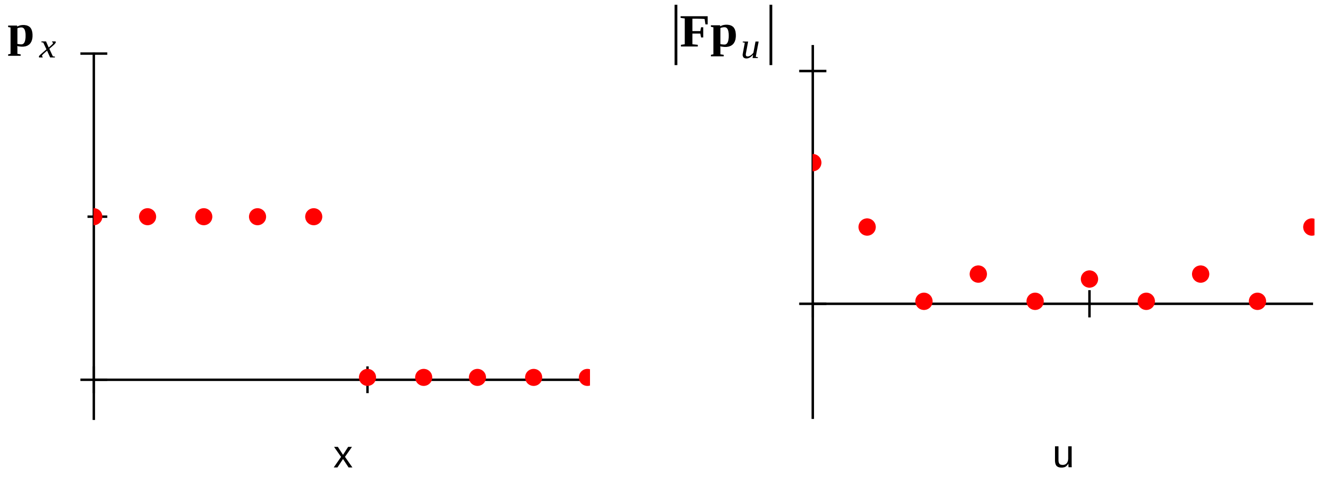
Sampling theory

- Nyquist’s sampling theorem is 1D
- E.g. speech 6kHz, sample at 12 kHz
- Video bandwidth (CCIR) is 5MHz
- Sampling at 10MHz gave 576×576 images
- Guideline: “two pixels for every pixel of interest”

https://www.pinterest.com/pin/275423333431517864/

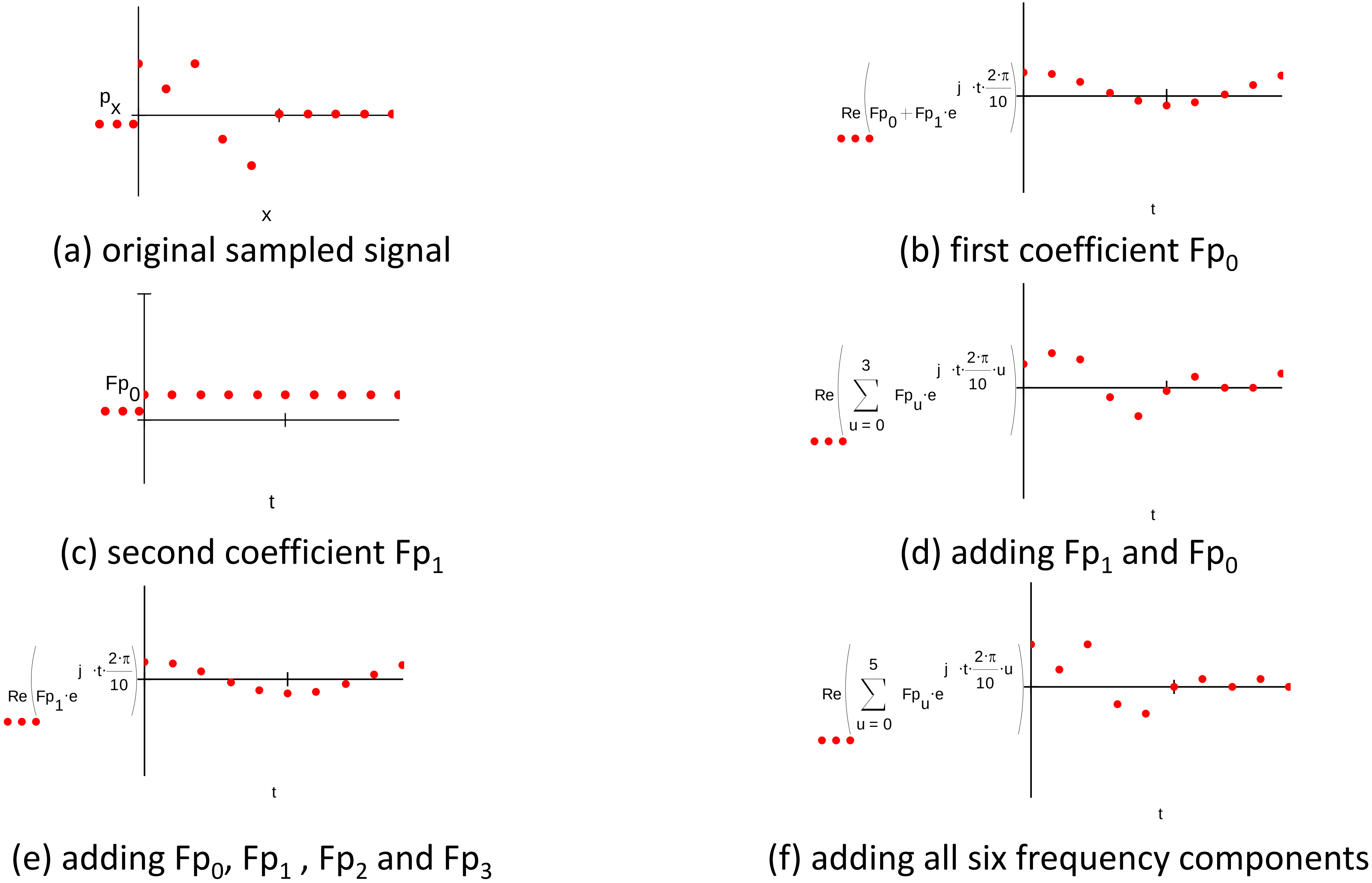






(a) sampled pulse (b) DFT of sampled pulse

Transform Pair for Sampled Pulse



(a) original sampled signal

(b) first coefficient Fp_0

(c) second coefficient Fp_1

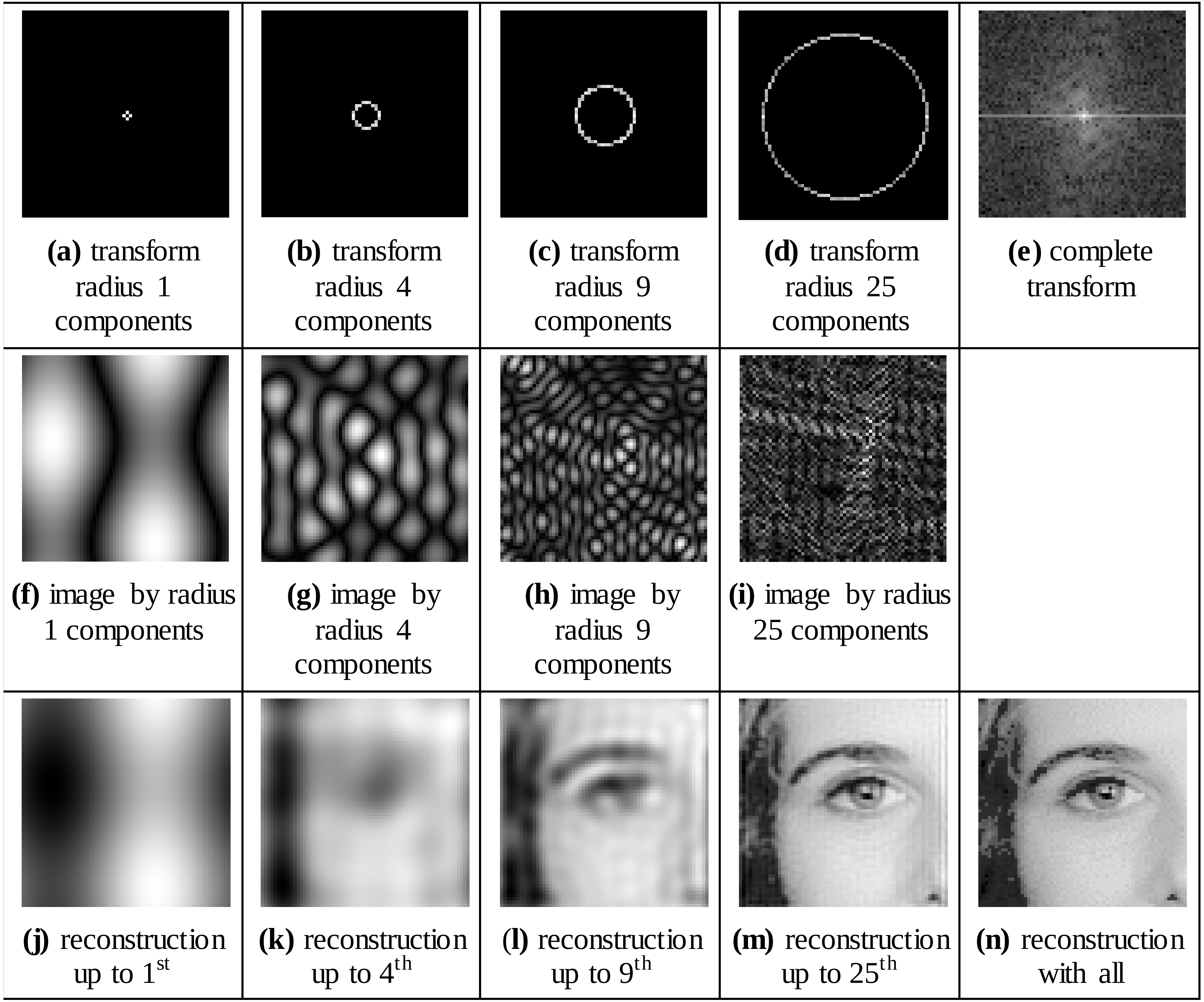
(d) adding Fp_1 and Fp_0

(e) adding Fp_0, Fp_1 , Fp_2 and Fp_3

(f) adding all six frequency components

Signal Reconstruction from Transform Components

Reconstruction



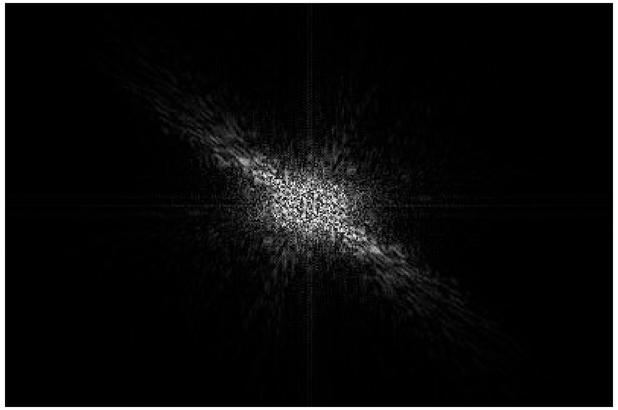
(a) transform radius 1 components
(b) transform radius 4 components
(c) transform radius 9 components
(d) transform radius 25 components
(e) complete transform

(f) image by radius 1 components
(g) image by radius 4 components
(h) image by radius 9 components
(i) image by radius 25 components

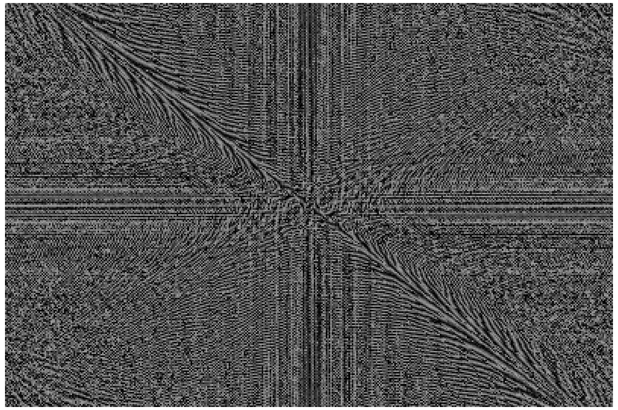
(j) reconstruction up to 1st
(k) reconstruction up to 4th
(l) reconstruction up to 9th
(m) reconstruction up to 25th
(n) reconstruction with all

Shift invariance

(a) original image

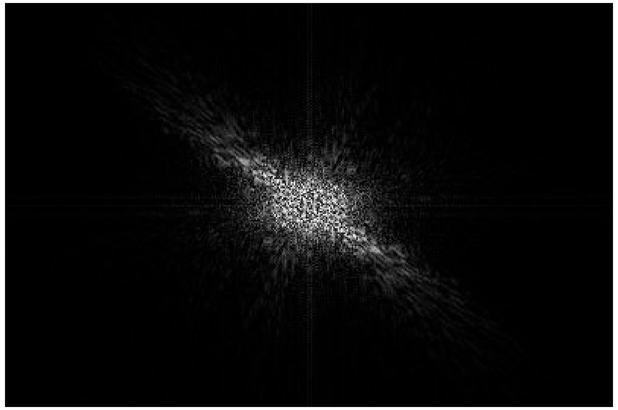


(b) magnitude of Fourier transform of original image

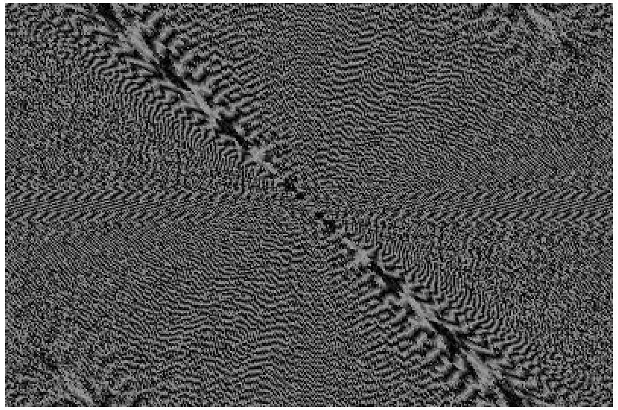


(c) phase of Fourier transform of original image

(d) shifted image



(e) magnitude of Fourier transform of shifted image

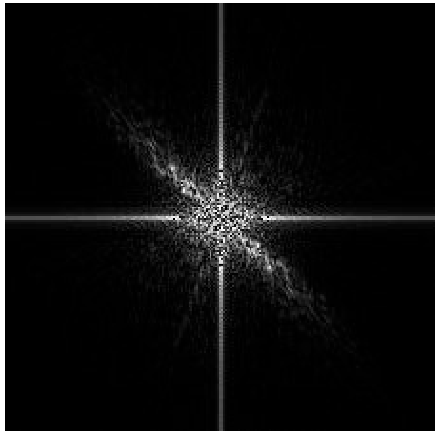


(f) phase of Fourier transform of shifted image

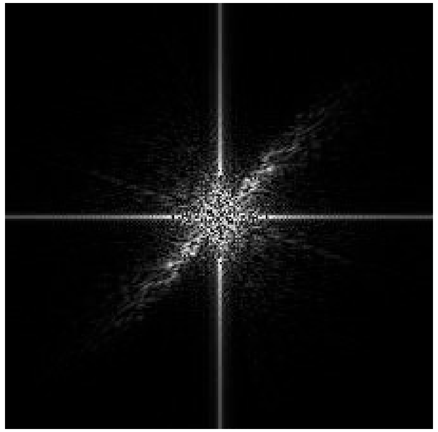
Rotation

(a) original image

(b) rotated image



(c) transform of original image

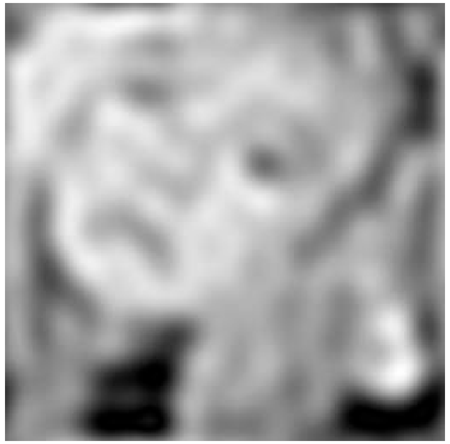


(d) transform of rotated image

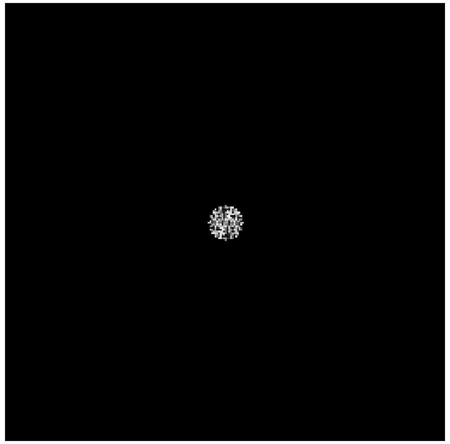
$$\mathbf{FP}_{u,v} = \frac{1}{N}\sum_{y=0}^{N-1}\sum_{x=0}^{N-1}\mathbf{P}_{x,y}\,e^{-j\left(\frac{2\pi}{N}\right)(uy+vx)}$$

Filtering

- Fourier gives access to frequency components

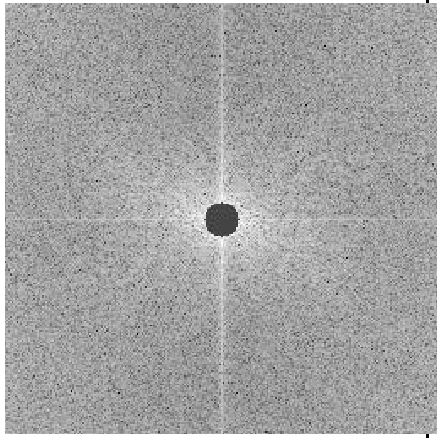


(a) low-pass filtered image



(b) low-pass filtered transform

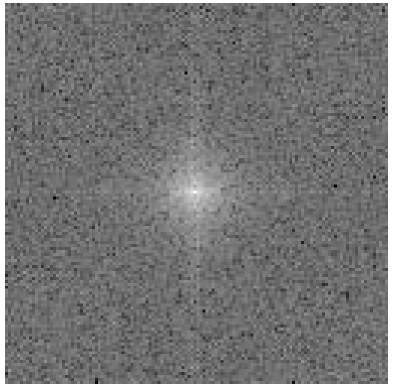
(c) high-pass filtered image



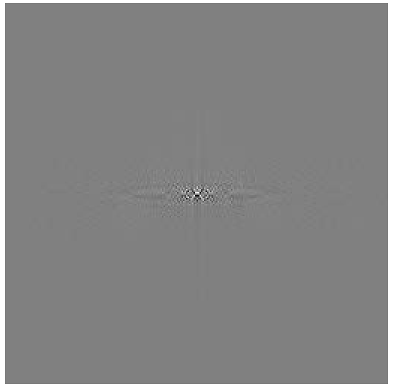
(d) high-pass filtered transform

Other transforms

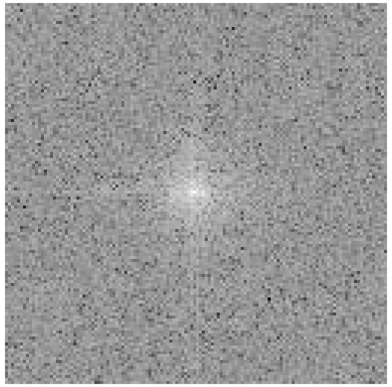
- For Lena



(a) Fourier transform



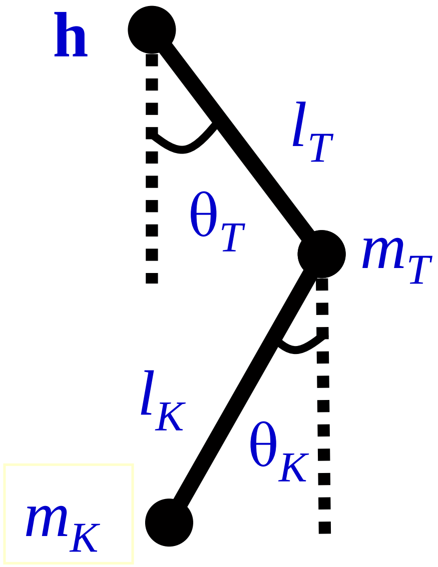
(b) discrete cosine transform

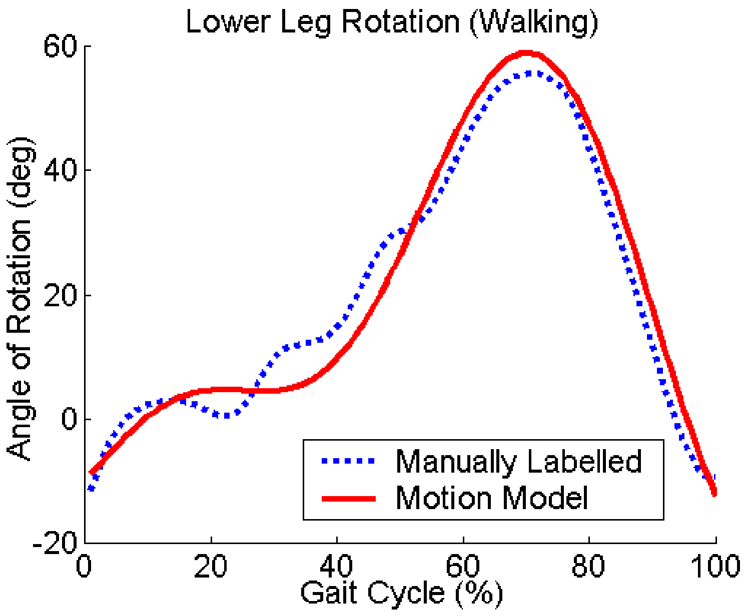


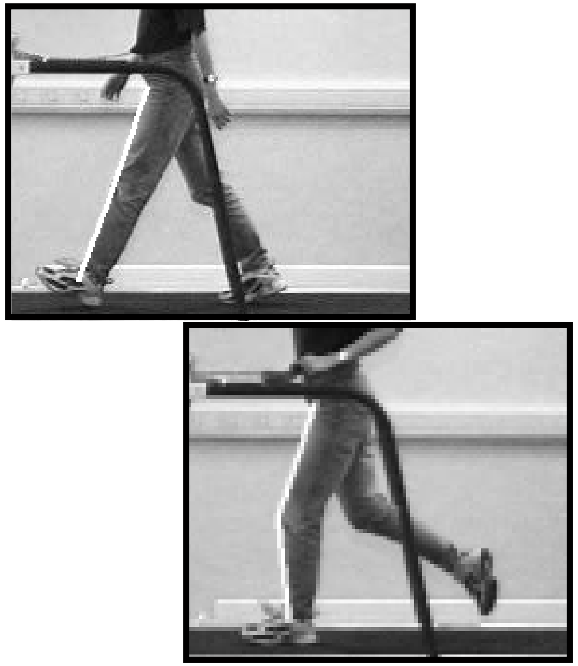
(c) Hartley transform

Modelling Gait(s)

- Extended pendular thigh-model, based on angles
- Uses forced oscillator/ bilateral symmetry/ phase coupling

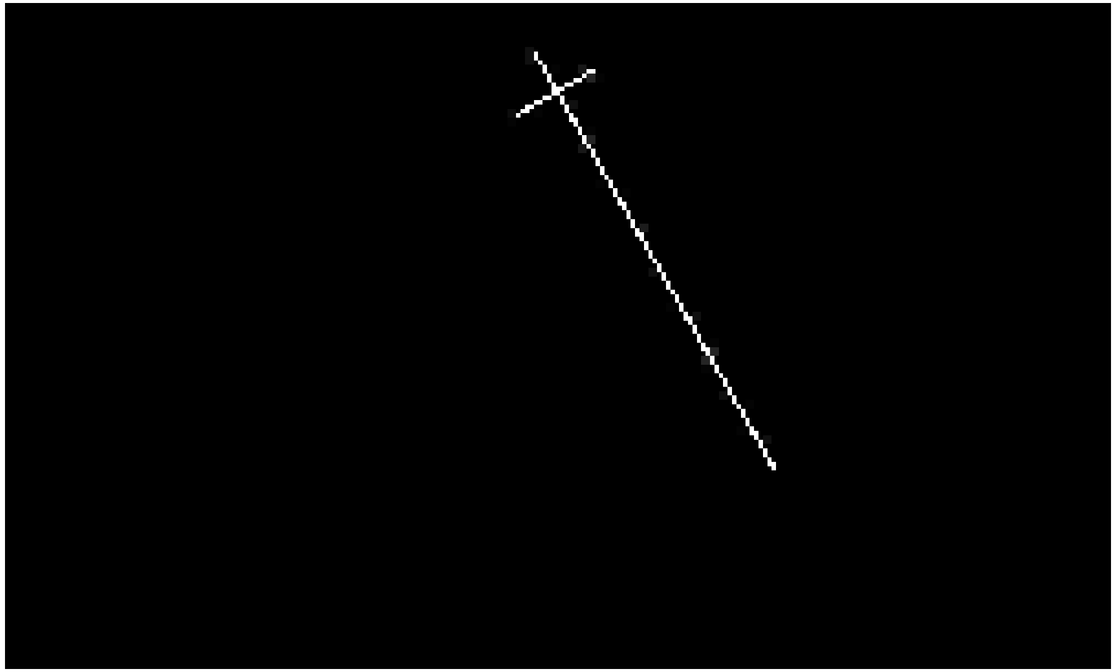






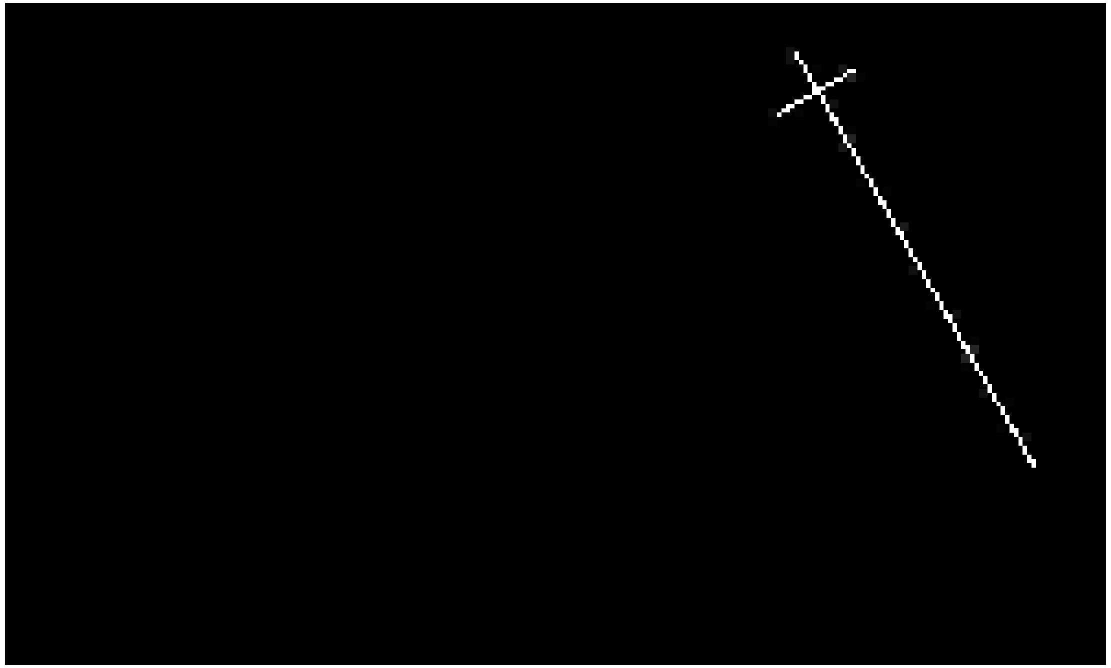
Yam, Nixon and Carter, *AVBPA* 2001, *Patt. Recog.* 2004

Modeling the Thigh’s Motion 1



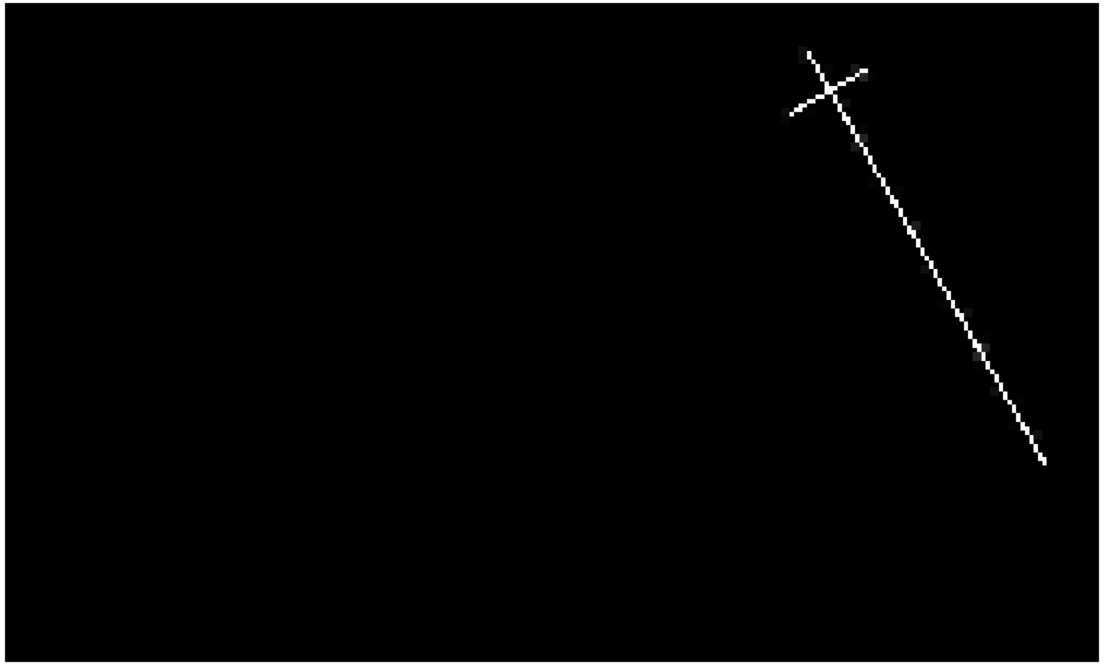
$$vs_x(t) = A\cos(\omega t + \phi)$$

Modeling the Thigh's Motion 2



$$vh_x(t) = Vx + A\cos(\omega t + \phi)$$

Modeling the Thigh's Motion 3



$$\phi(t) = a_0 + \sum_{k=1}^{N} \left[b_k \cos\left(k\omega_0 t + \psi \right) \right]$$

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Validity?

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Applications of 2D FT

- Understanding and analysis
- Speeding up algorithms
- Representation (invariance)
- Coding
- Recognition/ understanding (e.g. texture)