

Index

- Abnormal scans, 312
- Actual measurement vector, 163
- AdaBoost method, 313
- Adaptive histogram equalization, 76–79
 - applied to sample image, 79, 80
 - multi-region calculation approach, 78
- Adaptive thresholding, 66
 - applied to sample image, 66
 - in Matlab, 66
- Additive noise, 46
- Affine transformation, 179
 - in homogeneous coordinates, 174–175
 - property, 175
- Analogue-to-digital (A/D) converter, 41
- Anatomical landmarks, 236
- Approximate shape
 - single-parameter measures of, 237
- Automated classification, 293
 - purpose of, 291–292
 - class labelling, 292
 - task specification, 291–292
- Basic bitmap format (BMP), 6
- Basic local texture operators, 245
- Bayes decision rule, 304–305, 307
- Bayesian approach, 303, 304
- Bayesian classifiers, 303, 305
 - classification, 310
 - comparison of, 310
- Bayesian estimators, 165
- Bayesian-related reconstruction
 - techniques, 158
- Bayes' law, 286, 287
- Best linear unbiased estimator (BLUE), 167
- Bilinear transform, 190
- Binary images, 6, 197, 198
 - after thresholding, 238
 - erosion and dilation of, 200
 - effects and uses of, 204–205
 - to identify features, 206
- Bit-plane slicing, 5, 7
- Bit-plane splicing, 4–5
- Blind deconvolution, 156–158
 - maximum likelihood, 158
- Blurring effect, 85
- Boost filtering. *See* Unsharp mask filter
- Boundary extraction, 212–213
- Camera, 38–43, 47, 48, 53, 131, 142, 180, 207
 - projection models, 38, 39
- Canny edge detectors, 102, 271–274
 - basic procedure, 272
 - edge direction, 272
 - hysteresis, 273
 - nonmaximum suppression, 273
 - use of Gaussian kernel for image, 272
 - zero-crossing method, 274
 - practical application of, 273
 - use of LoG and, 273
- Capture-card-based system, schematic, 42
- Capture noise, 44
- Catchment basins, 279
- Class-conditional density function, 305, 307
- Classification systems
 - binary classifier, 294
 - design of, 294–296
 - class definition, 294
 - classifier performance, 295

- Classification systems (*Continued*)
 - data exploration, 294–295
 - descriptions, 296
 - feature selection and extraction, 295
 - flow diagram, 294
 - minimum distance criteria, 296–297
 - pattern, 296
 - prototypes, 296–297
 - supervised and unsupervised, 292
 - terms, with summary descriptions, 296
- Class prototype, 296
- Colour slicing, 14
- Complex function, 121, 132
- Compression artefacts, 8, 45
- Computed tomography (CT), 49
- Computer peripheral interfaces, 43
- Computer system, 42, 43, 50
- Connectivity concept, 86
- Constrained least-squares deconvolution, 151, 153
- Constrained least-squares restoration, 163–164
- Continuous function, parameters, 95
- Continuous spatial signal, 1
- Contrast stretching, 67–69, 83
 - applied to sample image, 68
- Convolution, 30
 - blind, 157
 - constrained, 163
 - of 1-D functions, 29
 - digital, 34–37
 - discrete, 35
 - with Gaussian blur, 24
 - importance and meaning, 30–34
 - integral, 29
 - between kernel and image, 88
 - kernels, 200
 - linear filtering, 88, 95
 - multiple, 34
 - operator, 21
 - with PSF, 22
 - standard, 161
 - theorem, 30, 129–131, 143
- Correspondence, 235, 236, 274
- Cost function, 152
 - least-squares, 177, 178
 - risk and, 311–312
 - scalar, 163, 164
- Covariance matrix, 251, 303, 306, 307, 310
 - diagonalization of, 256
 - minimize error, 166
 - for two variables, 248
- Cumulative distribution function (CDF), 70, 74, 75, 207
- 2-D affine transformation, 173–174
- Dark–light boundary, 277
- 2-D arrays, 6, 7, 9
- 3-D arrays, 7, 10
- 2-D cartesian coordinate space
 - of MxN digital image, 2
- 1-D convolution integral, 31
- Decision boundaries, 298
- Delta like detector, 32
- Descriptors, rotation-invariant set, 242
- Desktop-level multi-processor systems, 44
- 2-D feature space, 292, 293
 - summary statistics for data, 248
 - weight/height values, distribution of, 247
- 2-D feature vectors, 247, 292
- Difference of Gaussians (DoG), 271
- Digital imaging systems, 34, 40, 161, 247
 - noise effects in, 45
- Digital video camera, CCD sensor, 43
- Digitization process
 - digitization hardware, 42–43
 - quantization, 40–42
 - resolution vs. performance, 43–44
- 3-D imaging, 50
- Dimensionality reduction, 246, 255
- Dirac delta function, 25, 26
- Discrete Fourier transform (DFT), 135–137, 139.
 - See also* Fourier transform
 - centring of, 135
 - definition of, 136
 - inverse, 136
 - quadrants in, 137
- Discrete images, mathematical analysis, 2
- Discriminant functions, 298, 307
 - linear, 297–299, 308
 - in N dimensions, 301
- Distortion, 38–40, 44, 169, 184, 185, 190
- 2-D object, 169
 - principal axes of
 - calculation of, 255
- Domain-specific format, 7
- 2-D projective transformation matrix, 181
- 1-D rectangle signal, repeated convolution, 37

- 2-D rotation matrix, 156
- 2-D signal, 49
- 3-D space, 180
- Edge detection
 - challenges, 270
 - filtering for (*See* Image enhancement process)
 - using the zero-crossing method, 274
- Edge-detector kernel, 98
- Edge direction. *See also* Canny edge detector
 - calculation, 272
 - digitization, 272
 - nonmaximum suppression, application, 273
- Edge-spread function (ESF), 155
- EFIT-V, 260
- Eigenfaces
 - and human face, 258–261
 - linear combination, 260
- Eigenvalue spectrum, 259, 260
- Eigenvector/eigenvalue decomposition, 251
- Eigenvectors R, 253, 254
 - diagonalizing matrix of, 253
- Ensemble classifiers, 312
 - automated, 311
 - combining weak classifiers, 313
- Entropy, 246
- Error covariance matrix, 166, 167
- Error function, 156
- Euclidean definition, 302
- Euclidean distance, 177, 282, 297, 302
 - classifier, 298, 302, 303
- Exponential function, 60, 119
- Exponential transform, 59, 60, 82
- Extracting connected components, 213–215
- Facial prototypes, 297
- Facial recognition, automated, 246
- Facial synthesis, 247
- Fast Fourier transform (FFT), 125, 134, 138.
 - See also* Fourier transform
- Feature extraction, 97, 169, 263, 292, 295
- Feature space, 296, 298, 306
 - decision boundaries which partition, 298
 - distinct clusters, 293
 - FLD define direction within, 311
- Field programmable gate arrays (FPGA), 44
- Filter kernels, 35, 87, 98. *See also* Filter mask
- Filter mask, 95, 100
- Finite detector, 33
- Finite pinhole aperture, 33
- Fisher linear discriminant (FLD)
 - calculation of, 310
 - defining direction within feature space, 311
 - reducing N -dimensional feature space to, 311
- Floating-point images, 7
- Fourier coefficients, 241, 242
 - expansion coefficients, 119, 239
- Fourier descriptors, 241
- Fourier domain, 35, 114, 115, 148
- Fourier hypothesis, 119
- Fourier transforms, 113, 126–129, 143
 - centred discrete, 136–139
 - complex Fourier series, 118–119
 - convolution theorem, 129–131
 - 1-D Fourier transform, 119–121
 - 2-D Fourier transform, 123
 - central meaning, 125
 - properties, 124
 - digital Fourier transforms, 134
 - Fourier spectrum calculation, 118
 - frequency space, 113–118
 - functions, 123
 - inverse Fourier transform/reciprocity, 122–126
 - linear systems, 129
 - optical transfer function, 131–134
 - properties, 124
 - sampled data, 135–136
- Frequency cut-off, 118
- Frequency domain, 23, 85, 154. *See also* Fourier
 - domain
 - analysis, 115
 - central feature of, 122
 - convolution, 143
 - filtering, 127, 128, 130
 - Fourier transform spreading out in, 122
 - image processing, 126
 - linear system in, 129
 - multiplication of OTFs in, 131
 - restoration, 154
 - sampling intervals in, 135
 - ‘standard’ deconvolution problem, 154, 156
- Frequency-domain processing, 113
 - centred discrete Fourier transform, 136–139
 - complex Fourier series, 118–119
 - convolution theorem, 129–131

- Frequency-domain processing (*Continued*)
 - 1-D Fourier transform, 119–121
 - digital Fourier transforms, 134
 - Fourier spectrum calculation, 118
 - Fourier transform, understanding, 126–129
 - frequency space, 113–118
 - inverse Fourier transform/reciprocity, 122–126
 - linear systems, 129
 - optical transfer function, 131–134
 - sampled data, 135–136
- Frequency plot, 63
- Frequency-space methods, 113, 114
- Gamma correction
 - application, 62
 - based on grey-scale, 83
 - power-law transform, 62
 - on sample image, 63
- Gaussian blur, 24, 145
- Gaussian curves, 288
- Gaussian distribution, 288
- Gaussian filter, 47, 95–97, 109, 110, 158, 270, 277
- Gaussian function, 95, 134, 271, 288
- Gaussian kernel, 37, 103, 104, 107, 108, 272, 273
- Gaussian noise, 21, 46, 90–95, 97, 109
- Gaussian smoothing operator, 104
- Gauss–Markov estimator, 165–167
- Geometric construction, for producing skeleton, 223
- Geometric manipulation of images, 171
- Gibbs distribution, 287
- GIF images, 6
- Gradient images
 - preprocessing step in, 280
 - watershed, direct calculation of, 282
- Graphics processing unit (GPU) processing, 44
- Grayscale/false colour image, 3
- Grey-scale closing, 229
- Grey-scale dilation, 227
 - with flat structuring elements, 228–229
- Grey-scale erosion, 227
 - with flat structuring elements, 228–229
- Grey-scale image, 11, 12, 63, 69
- Grey-scale intensity, 49
- Grey-scale opening, 229
 - correction of nonuniform illumination, 230
- Grey-scale pixel, 258
- Grey-scale sensor, 41
- Grey-scale structuring elements, 227–228
- Grey-scale values, 72
- Haralick's criterion, 275
- Harmonic functions, 23, 114–116, 118, 120, 124, 129
- Harmonic signals, 114
- Harris function, 276, 277
- Harris response function, 278
- Histogram equalization theory, 69–70
 - applied to sample image, 73
 - discrete case, 70–71
 - in practice, 71–73
- Histogram-matching theory, 73–74
 - applied to sample image, 76
 - discrete case, 74–75
 - in practice, 75–76
- Histograms, 63–73
 - pixel distributions, 63–64
 - adaptive thresholding, 66–67
 - contrast stretching, 67–69
 - for threshold selection, 65
 - using Otsu's method, 265
- Hit-or-miss transformation, 216–219
 - application to detect target shape, 219
 - fully constrained, 220
 - general form of, 219
 - generalization, 219–220
 - to identify locations, 216, 217
 - relaxing constraints in, 220–222
 - steps, to identify points in image, 217, 218
- Homogeneous coordinates, 171–173
- Hue, Saturation and Value (HSV) colour space, 11–13, 78, 80, 111
- Human faces
 - components of sample of, 257
 - scaled and registered, 259
 - thumbnail images of, 300
 - use of PCA modelling of, 262
- Human visual system, 3, 41, 42, 97
- Image
 - colour, 2–3
 - colour spaces, 9–14
 - perceptual colour space, 12–14
 - RGB, 10–12

- compression method, 5, 7
- 3-D imaging, 50, 180
- encoding noise, 45
- formation (*See* Image formation process)
- formats, 5–9
 - image compression, 7–9
 - image data types, 6–7
 - properties, 6
- grey-scale images, 49
- infrared (IR), 49
- layout, 1–2
- in Matlab, 14–19
 - accessing pixel values, 16–17
 - basic display of images, 15–16
 - reading, writing and querying images, 14
- medical imaging, 49
- neighbourhood connectivity, 86
- processing operation, 44, 50 (*See also* Image processing)
- radar/sonar imaging, 50
- registration, 179
- resolution and quantization, 3–5
 - bit-plane splicing, 4–5
- scientific imaging, 50
- transformations, 184
- warping, 186
- Image enhancement process
 - edge detection, filtering for, 97–105
 - derivative filters, for discontinuities, 97–99
 - first-order edge detection, 99–101
 - second-order edge detection, 101–105
 - edge enhancement, 105–109
 - Laplacian edge sharpening, 105–107
 - unsharp mask filter, 107–109
 - filter kernels, 87–90
 - goal of, 85
 - linear filtering mechanics, 87–90
 - nonlinear spatial filtering, 90
 - noise removal, filtering for, 90–97
 - Gaussian filtering, 95–97
 - mean filtering, 91–92
 - median filtering, 93–94
 - rank filtering, 94–95
 - pixel neighbourhoods, 86–87
 - via image filtering, 85–86
- Image formation process, 21
 - engineering of, 37–46
 - camera, 38–44
 - noise, 44–46
 - key elements, 21
 - mathematics of, 22–37
 - convolution, 30–34
 - digital convolution, 34–37
 - dirac delta/impulse function, 25–27
 - linear imaging systems, 23–24
 - linear shift-invariant systems/convolution integral, 29–30
 - linear superposition integral, 24–25
 - multiple convolution, 34
 - point-spread function, 28
- Image histogram, 266. *See also* Histograms
- Image processing, 264, 265
 - techniques, 87
- Image recognition
 - colour, 264
 - motion, 264
 - texture, 264
- Image restoration process, 141
 - blind deconvolution, 156–158
 - constrained deconvolution, 151–154
 - constrained least-squares restoration, 163–164
 - generalized Gauss–Markov estimator, 165–167
 - imaging equation, solutions to, 151
 - imaging models, 141–142
 - inverse Fourier filter, restoration by, 143–146
 - iterative deconvolution, 158–161
 - Lucy–Richardson algorithm, 158–161
 - matrix formulation, 161–162
 - point-spread function and noise, nature of, 142–143
 - standard least-squares solution, 162–163
 - stochastic input distributions/Bayesian estimators, 165
 - unknown point-spread function/optical transfer function, 154–156
 - Wiener–Helstrom filter, 146–147
 - origin of, 147–151
- Image segmentation, 170, 263
 - automated methods, 170
 - Canny edge detector, 271–274
 - edge/boundary methods, 263
 - edge detection, challenge of, 270
 - features, 263–265
 - image properties, use of, 263–265
 - intensity thresholding
 - global thresholding, problems, 266–267
 - using, 265

- Image segmentation (*Continued*)
 interest operators, 274–279
 Laplacian of a Gaussian (LoG), 270–271
 manual segmentation, 170
 with Markov random fields
 Bayes' theorem, 287
 Gibbs distribution, 287
 iterated conditional modes (ICM)
 algorithm, 290
 neighbourhood weighting parameter, 289–290
 parameter estimation, 288–289
 pixel, 286
 noisy, under water image, 289
 purpose of, 264
 region-based methods, 263
 region growing, 267
 region splitting, 267
 segmentation function, 280–286
 split-and-merge algorithm, 267–269
 watershed segmentation, 279–280
- Imaging systems. *See* Digital imaging systems;
 Linear imaging system
- Impulse function, 25–27
- Incident intensity, 33, 34
- Intensity quantization effects, 41, 42
- Intensity thresholding, 207, 208, 238, 263, 265–267, 286
- Inverse filter. *See* Optical transfer function (OTF)
- Isoplanatism. *See* Shift invariance
- Iterated conditional modes (ICM) algorithm, 290
 Markov random field segmentation, 290
- Jet colour map, 3
- JPEG format, 6
- k means algorithm, 313, 314
- k-means clustering, 313–315
- Lagrange multipliers method, 164
- Landmarks, 235
 anatomical/true landmarks, 236
 mathematical landmarks, 236
 pseudo-landmarks, 236
- Laplacian edge detection, 101–102
- Laplacian filter, 102
 construction of, 102
- Laplacian kernels, 103
- Laplacian of Gaussian (LoG) filter, 103–104, 270, 274
 basic shape of, 272
 edge sharpening, 106, 107
- Law of total probability, 305
- Linear discriminant, 307
 functions, 297–301
 in N dimensions, 301
- Linear functions, 298
- Linear imaging system, 23, 28
 action of, 130
 2-D systems, 141
 equation, 158
 frequency-domain perspective, 129
 main elements, 143
- Linearly separable filtering, 101
- Linear machine, 308
- Linear model, 162
- Linear operator, 152
 demonstration, 24
- Linear shift-invariant systems, 29
- Linear superposition integral, 24
 principle, 25
- Linear transformations
 and effects, 175
 coefficient values, 174
- Line-fit error, 293
- Logarithmic function
 parameter, 58
- Logarithmic transform effect, 58
- Lossy compression technique, 8, 9
- LR deconvolution, 161
- LSI imaging equation, 143, 146
- LSI system, 30
 output of, 34
- Lucy–Richardson algorithm, 158–161
- Magnetic resonance imaging (MRI), 49
- Mahalanobis distance, 302, 303, 306
 extension of, 302–303
- Mapping function, 59
- Marker-controlled segmentation, 282, 283
 watershed segmentation, 284
- Markov random fields, 286, 287

- Matlab, 1, 3, 14–17, 19, 35, 52, 56, 59, 61, 62, 64, 182, 189, 190, 238–240, 244, 253–255, 266, 268, 269, 273–274, 277–279, 281–286, 315
 - adaptive histogram equalization, 78
 - contrast stretching in, 68
 - convention, 1
 - filtering effect, 108
 - functions, 150
 - Gaussian filter in, 96
 - histogram matching, 75
 - histogram operations, 80
 - HSV implementation, 13
 - image multiplication and division, 54
 - image processing toolbox, 158
 - image subtraction, 53
 - imfilter()* function, 103
 - imnoise()* function, 47, 91, 109
 - linear convolution filtering, 89
 - LoG operator in, 104
 - in lossy compression format, 9
 - LR deconvolution algorithm, 160
 - mean filter, 91
 - median filtering, 93
 - zero-crossing detector with LoG filter, 104–105
- Matrix formulation, 161
- Matrix operator, 166
- Mean filtering, 91
 - drawbacks of, 92
- Median filtering, 92
- Medical imaging, 49–50
- Mexican hat function, 271
- Minimum distance classifier
 - extension of, 302–303
- Minimum mean-square error (MMSE), 148
- Misclassifications, 300
 - relative importance of, 312
- Misclassified test, 310
- Modulation transfer function (MTF), 132, 134
- Moore's law, 44
- Morphological opening
 - and closing, 209–210
 - rolling-ball analogy, 210–212
 - effects of, 224
- Morphological operations, 197
 - corresponding Matlab® functions, 232
 - to grey-scale and colour images, 198
- Morphological operators, 200
 - dilation, 200–201
 - to join small breaks in defining contour, 205
 - erosion, 200–201
 - application in particle sizing, 207–209
- Morphological processing, 237, 238
- Morphological skeletons, 223
- Morphological structuring elements, 199
- Multivariate normal density, 306
- Multivariate normal (MVN) distribution, 305, 307
 - Bayesian classifiers for, 307–310
 - risk and cost functions, 311–312
- Multivariate normal distributions
 - Bayesian classifiers for
 - Fisher linear discriminant (FLD), 310–311
- N -dimensional space, 251
- N -dimensional vectors, 297
- Neighbourhood weighting parameter θ_n , 289–290
- Neighbouring pixels, 289
- Noise, 21, 271
 - differential filters
 - effect of, 270
 - effects of, 270
 - power, 152
 - power spectra, 147
- Noise models, 151
 - nature of, 142–143
- Noisy, segmentation of, 289
- Nonlinear distortion, 184
- Nonlinear transformations, 184–186
 - degrees of freedom, 184
- Normalization. *See* Contrast stretching
- Normalized central moments possess, 243
- Nyquist sampling theorem, 40
- Object function, 21
- Off-diagonal element, 306
- Opening, by reconstruction, 224–226
- Optical transfer function (OTF), 129, 131–134, 144, 153
 - effect of, 133
- Optimal linear restoration filter, 147
- Optimization criterion, 148
- Orthogonal eigenvectors, 250. *See also* Eigenvectors R

- Orthographic projection, 39
- Otsu's method, for threshold selection, 265, 266
- Periodic square wave synthesis, 117
- Perspective distortion, 38. *See also* Distortion
- Perspective projection model, effects, 39
- Photon-limited system, 29
- Picture element, 49
- Piecewise warp, 191. *See also* Warping
 - first stage in, 192
- Pin-hole perspective projection model, 39
- Pixels, 1, 40, 43, 49
 - distributions, histograms, 63–73
 - adaptive histogram equalization, 76–79
 - adaptive thresholding, 66–67
 - contrast stretching, 67–69
 - histogram equalization in practice, 71–73
 - histogram equalization theory, 69–71
 - histogram matching, 73–76
 - histogram operations on colour images, 79–80
 - for threshold selection, 65
 - 2-D pixel, 3
 - information, type, 51
 - intensity, 72
 - labelling, analytical approach, 289
 - neighbourhoods, 86–87
 - operations upon pixels, 50–57
 - arithmetic operations, 51–54
 - logical operations, 54–55
 - thresholding, 55–57
 - point-based operations on images, 57–63
 - exponential transform, 59–61
 - logarithmic transform, 57–59
 - power-law (gamma) transform, 61–63
 - value, types, 86
- PNG format, 6
 - images, 7
- Point-spread function (PSF), 21, 22, 131
 - 1-D version, 155
 - effect of, 28
 - nature of, 142–143
- Poisson density function, 159
- Poisson noise, 159
- Power-law transform, 61, 62
 - imadjust* function, 62
- Prairie-fire analogy, 222
- Prewitt/Sobel kernels, 100
- Principal component analysis (PCA), 235, 246–249
 - basic aim of, 247
 - compact encoding, 260
 - of digital images, 256
 - dimensionality reduction, 255–256
 - for face encoding and recognition, 259
 - modelling of human faces, 261
 - out-of-sample data vector, 257
 - out-of-sample examples, representation of, 256–258
 - pixel-to-pixel basis, 256
 - principal axes, 252
 - properties of, 252–255
 - real power of, 255
 - theory of, 249–252
- Prior probabilities, 305
- Probability density function (PDF), 63, 74, 165, 207, 243, 305
- Probability theory, 70, 207, 243
- Processing noise, 45
- Procrustes alignment, 170, 176–180
- Procrustes transformation, 175–176
- Projective transformation, 180–184
 - coordinate mappings, 183
 - defined by mapping, 181
 - preserved quantities and, 184
- Pruning, 224
- Quadtree decomposition, 268, 269
- Quantization, 3–5
- Radar/sonar imaging, 50
- Radial Fourier expansion, 239–242
- Rank filtering, 94–95
- Radial Fourier expansions, 241
- Rectangle function, 26, 134
 - Fourier transform of, 122
- Red, green and blue (RGB) image, 7, 10, 12.
 - See also* True-colour images
 - colour channels, 17
 - colour space, 11
 - to grey-scale image conversion, 11–12
 - values, 79
- Region filling, 215–216

- Resolution, 3–5
 - bit resolution, 4
 - spatial resolution, 4
 - temporal resolution, 4
- Roberts, Prewitt and Sobel filters, 100, 101
- Roberts cross, 99, 100
- Rolling-ball analogy, 210–212
- Salt and pepper noise, 46, 90, 91, 93
- Sample covariance matrix, 247
- Sampling noise, 44
- Sampling theorem, 40
- Scaling, 178
- Scaling constant, 58
- Scaling factor, 39, 57, 108
- Scene occlusion, 45
- Scientific imaging, 50
- Segmentation function, 280–286
- Segmentation techniques. *See* Image segmentation
- Shannon's sampling theorem, 40
- Shape, description, 169–170
 - treatment of boundaries and shape, 170
- Shape descriptors, 169
- Shape-preserving transformations, 170
 - under linear operations of, 171
- Shape transformation, 171–173
- Shape vector, 169
- Shift invariance, 29
- Sifting theorem, 27
- Signatures, 239–242
 - arbitrary scale factor, multiplication of, 241
 - of closed boundary, 239
 - distance from, 242
- Simple square-root transform, 59
- Single-parameter measure, 169
- Singularity, properties of, 27
- Singular value decomposition (SVD), 178, 179
- Size density function, 208, 209
- Skeletonization, 222–224
- Sliding window approach, 77
- Sobel and Prewitt operators, 100
- Sobel operators, 272
- Soft focus effect. *See* Blurring effect
- Spatial domain filtering, 85, 86
- Spatial-domain image processing, 126
- Spatial frequency regime, 145
- Spatial functions synthesis, 121
- Spatial quantization effects, 41
- Spatial transformation
 - of image, 186–189
 - overdetermined, 189–190
- Split-and-merge algorithm, 267, 268
- Spurs, in skeleton, 224
- Standard least-squares solution, 162–163
- Statistical moments
 - over neighbourhood/spatial scale in image, 264
 - as region descriptors, 243–245
- Statistical noise distribution, 21
- Structuring element, 198
 - decomposition and Matlab, 202–204
 - function *getsequence*, 203
 - functions *imdilate* and *imopen*, 204
 - strel* object, 202–203
 - local neighbourhood defined by, 199
 - within Matlab, 201–202
- Sum of squared errors
 - principal axis minimizes, 248
- Supervised classifiers, 292
- System matrix, 164, 165
- Texture features, 246
- Three-channel RGB images, 54
- Thresholding, 55–57
 - of complex image, 56
 - for object identification, 56
 - variations on, 57
- TIFF image format, 7
- Tile-based approach. *See* Sliding window approach
- Top-hat transformation, 230–231
- Translation, 170, 171, 173, 176, 177, 179, 189
 - invariant, 241, 243
 - parameters, 174
 - vector, 174
- True-colour images, 7
 - components, 10
- Unsharp mask filter, 107–109
 - edge sharpening, 109
- Unsupervised classifiers
 - k-means clustering, 313–315
- Unsupervised learning algorithms, 313

- Video frame, 4
- Voxels, 2
- Warping, 186
 - applications, 186
 - central concept, 187
 - forward and reverse mapping, 194–195
 - piecewise affine, 191–194
 - piecewise wrap, 191
 - transformation, basic steps, 188
 - using global polynomial transformation, 190
- Watershed. *See also* Image segmentation
 - calculation, 282
 - methods, 280
 - segmentation, 279–280
 - marker-controlled, 284
 - yields, 279, 280
- Weak classifier, 313
- Weighting factor, 159
- Wiener–Helstrom filter, 146–147
 - historical importance, 149
 - origin of, 147–151
- Zero-crossing detector, 104
- Zero-crossing method, 271
 - edge detection, 274