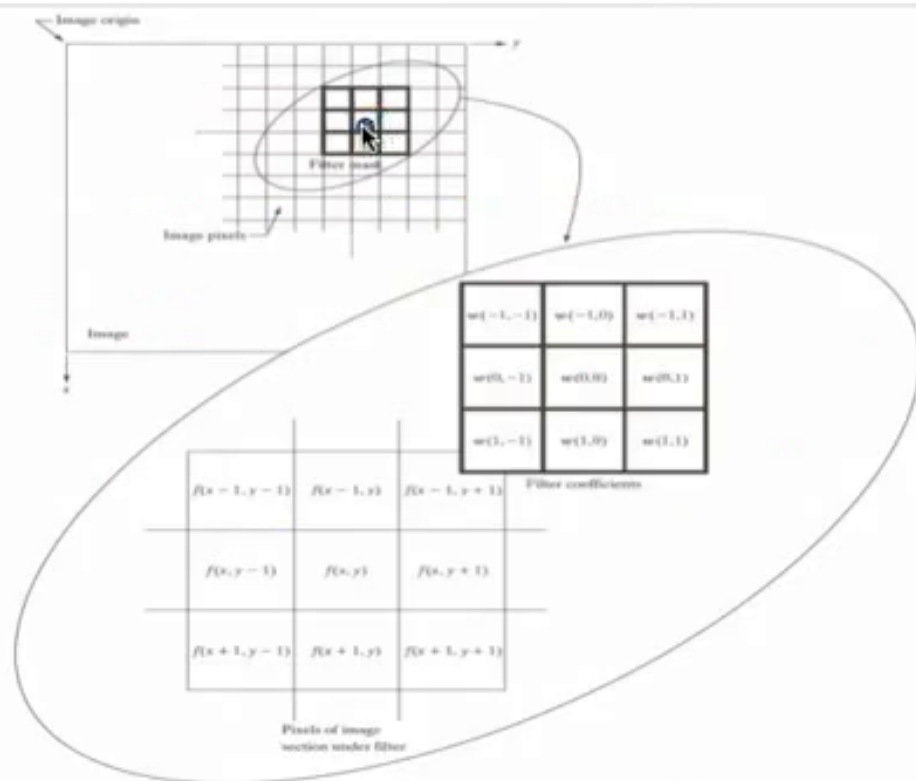
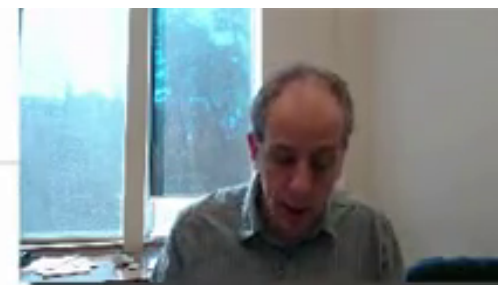




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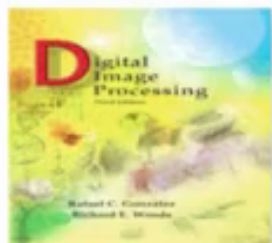
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Chapter 3 Intensity Transformations & Spatial Filtering



w_1	w_2	w_3
w_4	w_5	w_6
w_7	w_8	w_9

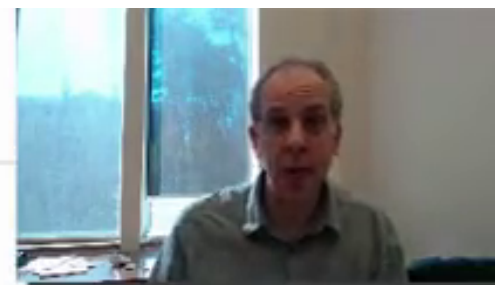
FIGURE 3.28 The mechanics of linear spatial filtering using a 3×3 filter mask. The form chosen to denote the coordinates of the filter mask coefficients simplifies writing expressions for linear filtering.



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Chapter 3 Intensity Transformations & Spatial Filtering

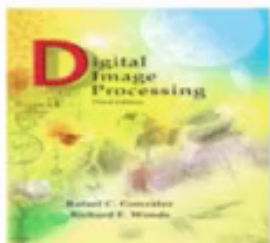


$$\frac{1}{9} \times \begin{bmatrix} 1 & 1 & 1 \\ 1 & 1 & 1 \\ 1 & 1 & 1 \end{bmatrix}$$

$$\frac{1}{16} \times \begin{bmatrix} 1 & 2 & 1 \\ 2 & 4 & 2 \\ 1 & 2 & 1 \end{bmatrix}$$

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.



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Chapter 3

Intensity Transformations & Spatial Filtering

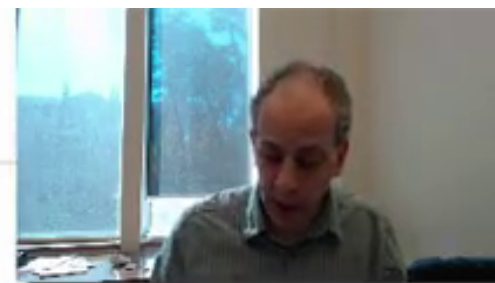
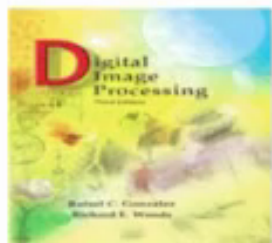


FIGURE 3.33 (a) Original image, of size 500×500 pixels. (b)–(f) Results of smoothing with square averaging filter masks of sizes $m = 3, 5, 9, 15$, and 35 , respectively. The black squares at the top are of sizes $3, 5, 9, 15, 25, 35, 45$, and 55 pixels, respectively; their borders are 25 pixels apart. 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.

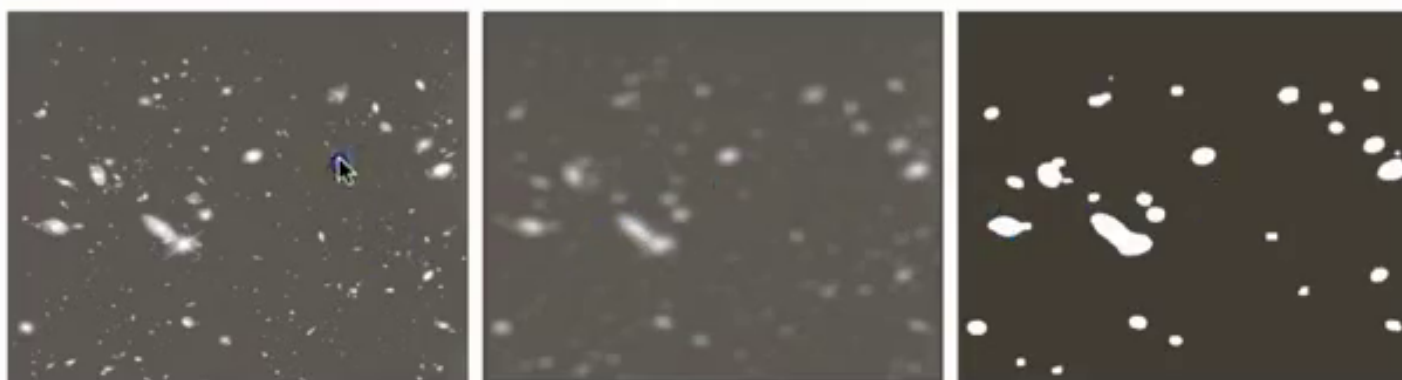
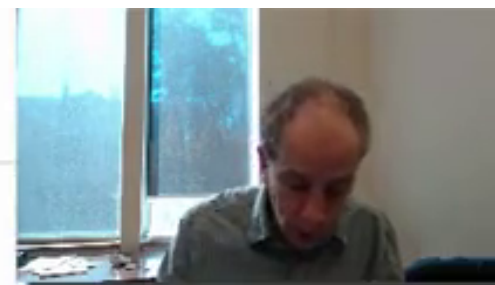




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Chapter 3 Intensity Transformations & Spatial Filtering



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.)