

Chapter 10

Basic Video Compression Techniques

[10.1 Introduction to Video Compression](#)

[10.2 Video Compression with Motion Compensation](#)

[10.3 Search for Motion Vectors](#)

[10.4 H.261](#)

[10.5 H.263](#)

10.1 Introduction to Video Compression

- A video consists of a time-ordered sequence of frames, i.e., images.
- An obvious solution to video compression would be predictive coding based on previous frames.
- Compression proceeds by subtracting images: subtract in time order and code the residual error.
- It can be done even better by searching for just the right parts of the image to subtract from the previous frame.

10.2 Video Compression with Motion Compensation

- Consecutive frames in a video are similar — temporal redundancy exists.
- Temporal redundancy is exploited so that not every frame of the video needs to be coded independently as a new image.
The difference between the current frame and other frame(s) in the sequence will be coded — small values and low entropy, good for compression.
- Steps of Video compression based on *Motion Compensation (MC)*:
 1. Motion Estimation (motion vector search).
 2. MC-based Prediction.
 3. Derivation of the prediction error, i.e., the difference.

Motion Compensation

- Each image is divided into *macroblocks* of size $N \times N$.
 - By default, $N = 16$ for luminance images. For chrominance images, $N = 8$ if 4:2:0 chroma subsampling is adopted.
- Motion compensation is performed at the macroblock level.
 - The current image frame is referred to as *Target Frame*.
 - A match is sought between the macroblock in the Target Frame and the most similar macroblock in previous and/or future frame(s) (referred to as *Reference frame(s)*).
 - The displacement of the reference macroblock to the target macroblock is called a *motion vector* **MV**.
 - Figure 10.1 shows the case of *forward prediction* in which the Reference frame is taken to be a previous frame.

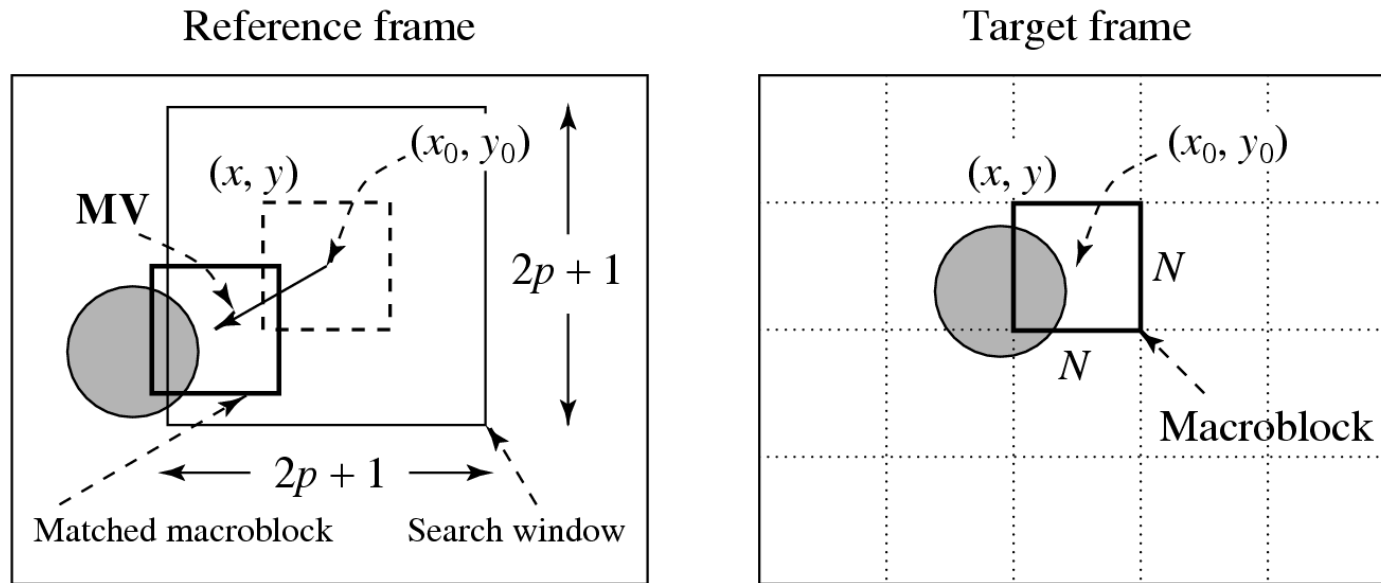


Fig. 10.1: Macroblocks and Motion Vector in Video Compression.

- MV search is usually limited to a small immediate neighborhood — both horizontal and vertical displacements in the range $[-p, p]$.

This makes a search window of size $(2p + 1) \times (2p + 1)$.

10.3 Search for Motion Vectors

- The difference between two macroblocks can then be measured by their *Mean Absolute Difference (MAD)*:

$$MAD(i, j) = \frac{1}{N^2} \sum_{k=0}^{N-1} \sum_{l=0}^{N-1} |C(x+k, y+l) - R(x+i+k, y+j+l)| \quad (10.1)$$

N – size of the macroblock,

k and l – indices for pixels in the macroblock,

i and j – horizontal and vertical displacements,

$C(x+k, y+l)$ – pixels in macroblock in Target frame,

$R(x+i+k, y+j+l)$ – pixels in macroblock in Reference frame.

- The goal of the search is to find a vector (i, j) as the motion vector $\mathbf{MV} = (\mathbf{u}, \mathbf{v})$, such that $MAD(i, j)$ is minimum:

$$(u, v) = \left[(i, j) \mid MAD(i, j) \text{ is minimum}, i \in [-p, p], j \in [-p, p] \right] \quad (10.2)$$

Sequential Search

- **Sequential search:** sequentially search the whole $(2p + 1) \times (2p + 1)$ window in the Reference frame (also referred to as Full search).
 - a macroblock centered at each of the positions within the window is compared to the macroblock in the Target frame pixel by pixel and their respective *MAD* is then derived using Eq. (10.1).
 - The vector (i, j) that offers the least *MAD* is designated as the **MV** (u, v) for the macroblock in the Target frame.
 - Sequential search method is very costly — assuming each pixel comparison requires three operations (subtraction, absolute value, addition), the cost for obtaining a motion vector for a single macroblock is $(2p + 1) \cdot (2p + 1) \cdot N^2 \cdot 3 \Rightarrow O(p^2 N^2)$.

PROCEDURE 10.1 Motion-vector:sequential-search

BEGIN

```
    min_MAD = LARGE_NUMBER;      /* Initialization */
    for i = -p to p
    {
        for j = -p to p
        {
            cur_MAD = MAD(i, j);
            if cur_MAD < min_MAD
            {
                min_MAD = cur_MAD;
                u = i; /* Get the coordinates for MV.
            }
        }
    }
    */
    v = j;
```

END

2D Logarithmic Search

- **Logarithmic search:** a more efficient version, that is suboptimal but still usually effective.
- The procedure for 2D Logarithmic Search of motion vectors takes several iterations and is akin to a binary search:
 - As illustrated in Fig. 10.2, initially only nine locations in the search window are used as seeds for a MAD-based search; they are marked as '1'.
 - After the one that yields the minimum *MAD* is located, the center of the new search region is moved to it and the step-size ("offset") is reduced to half.
 - In the next iteration, the nine new locations are marked as '2' and so on.

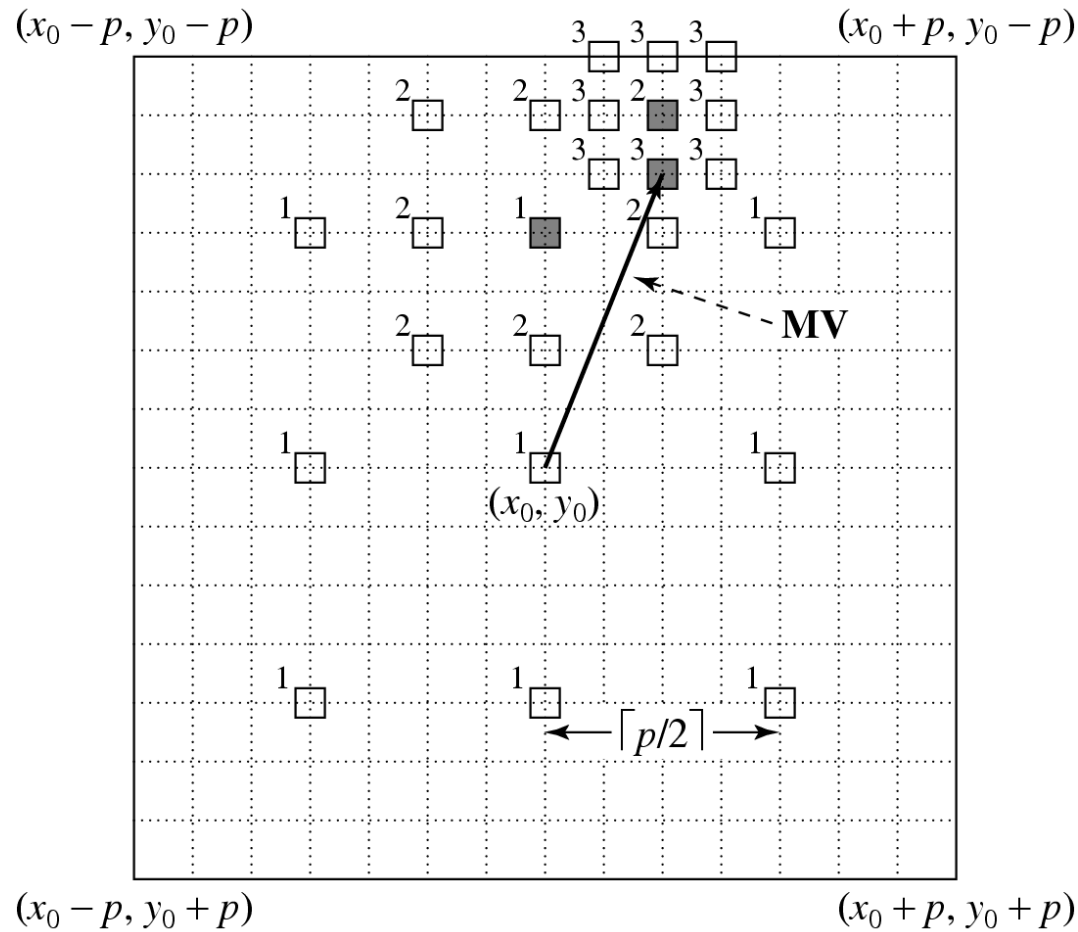


Fig. 10.2: 2D Logarithmic Search for Motion Vectors.

PROCEDURE 10.2 Motion-vector:2D-logarithmic-search

BEGIN

offset = $\lceil \frac{p}{2} \rceil$

Specify nine macroblocks within the search window in the Reference frame, they are centered at (x_0, y_0) and separated by offset horizontally and/or vertically;

WHILE last \neq TRUE

{

Find one of the nine specified macroblocks that yields minimum *MAD*;

IF offset = 1 THEN last = TRUE;

offset = $\lceil \text{offset}/2 \rceil$;

Form a search region with the new offset and new center found;

}

END

- Using the same example as in the previous subsection, the total operations per second is dropped to:

$$\begin{aligned} OPS_per_second &= (8 \cdot (\log_2 p + 1) + 1) \cdot N^2 \cdot 3 \cdot \frac{720 \times 480}{N \cdot N} \cdot 30 \\ &= (8 \cdot \log_2 15 + 9) \times 16^2 \times 3 \times \frac{720 \times 480}{16 \times 16} \times 30 \\ &\approx 1.25 \times 10^9 \end{aligned}$$

Hierarchical Search

- The search can benefit from a hierarchical (multiresolution) approach in which initial estimation of the motion vector can be obtained from images with a significantly reduced resolution.
- Figure 10.3: a three-level hierarchical search in which the original image is at Level 0, images at Levels 1 and 2 are obtained by down-sampling from the previous levels by a factor of 2, and the initial search is conducted at Level 2.
- Since the size of the macroblock is smaller and p can also be proportionally reduced, the number of operations required is greatly reduced.

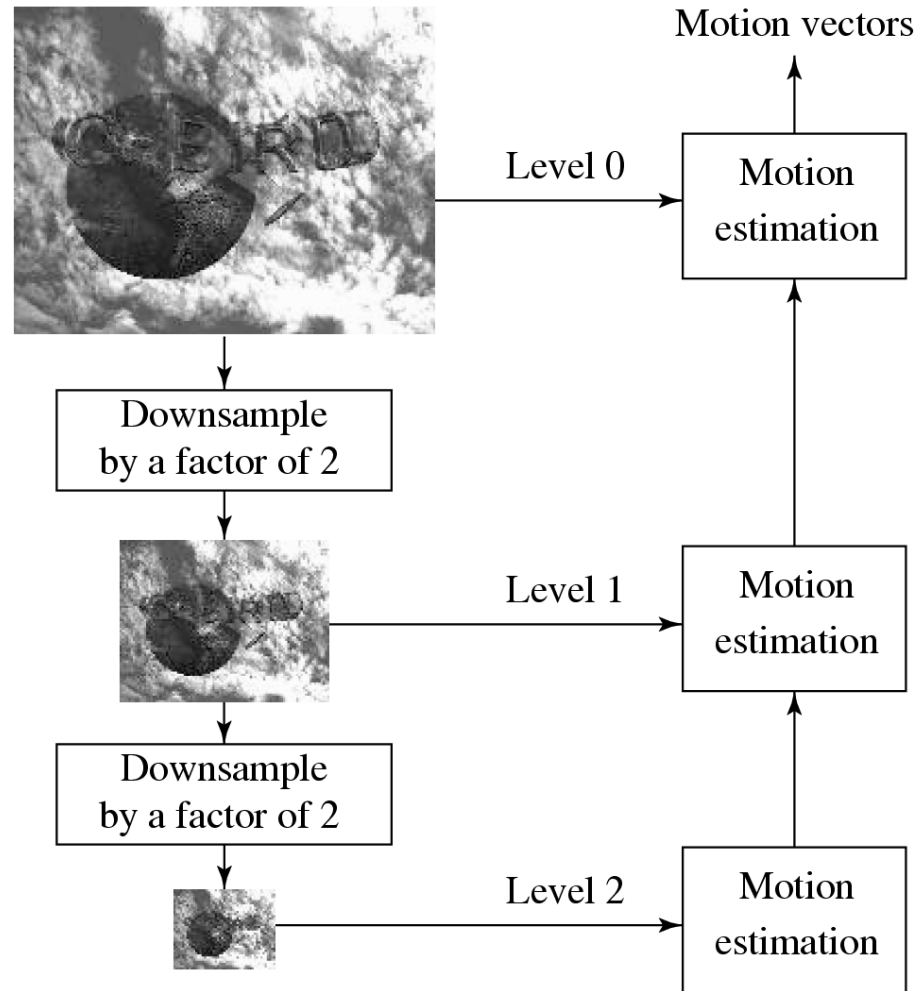


Fig. 10.3: A Three-level Hierarchical Search for Motion Vectors.

Hierarchical Search (Cont'd)

- Given the estimated motion vector (u^k, v^k) at Level k , a 3×3 neighborhood centered at $(2 \cdot u^k, 2 \cdot v^k)$ at Level $k - 1$ is searched for the refined motion vector.
- The refinement is such that at Level $k - 1$ the motion vector (u^{k-1}, v^{k-1}) satisfies:

$$(2u^k - 1 \leq u^{k-1} \leq 2u^k + 1, 2v^k - 1 \leq v^{k-1} \leq 2v^k + 1)$$

- Let (x_0^k, y_0^k) denote the center of the macroblock at Level k in the target frame. The procedure for hierarchical motion vector search for the macroblock centered at (x_0^0, y_0^0) in the Target frame can be outlined as follows:

PROCEDURE 10.3 Motion-vector:hierarchical-search

BEGIN

// Get macroblock center position at the lowest resolution Level k

$x_0^k = x_0^0 / 2^k$; $y_0^k = y_0^0 / 2^k$;

Use Sequential (or 2D Logarithmic) search method to get initial estimated **MV**(u^k, v^k) at Level k ;

WHILE last \neq TRUE

{

Find one of the nine macroblocks that yields minimum MAD at Level $k - 1$ centered at

$(2(x_0^k + u^k) - 1 \leq x \leq 2(x_0^k + u^k) + 1; 2(y_0^k + v^k) - 1 \leq y \leq 2(y_0^k + v^k) + 1)$;

IF $k = 1$ THEN last = TRUE;

$k = k - 1$;

Assign $(x_0^k; y_0^k)$ and (u^k, v^k) with the new center location and **MV**;

}

END

Table 10.1: Comparison of Computational Cost of Motion Vector Search Methods

Search Method	<i>OPS_per_second</i> for 720×480 at 30 fps	
	$p = 15$	$p = 7$
Sequential search	29.89×10^9	7.00×10^9
2D Logarithmic search	1.25×10^9	0.78×10^9
3-level Hierarchical search	0.51×10^9	0.40×10^9

10.4 H.261

- H.261: An earlier digital video compression standard, its principle of MC-based compression is retained in all later video compression standards.
 - The standard was designed for videophone, video conferencing and other audiovisual services over ISDN.
 - The video codec supports bit-rates of $p \times 64$ kbps, where p ranges from 1 to 30 (Hence also known as $p * 64$).
 - Require that the delay of the video encoder be less than 150 msec so that the video can be used for real-time bidirectional video conferencing.

ITU Recommendations & H.261 Video Formats

- H.261 belongs to the following set of ITU recommendations for visual telephony systems:
 1. H.221 — Frame structure for an audiovisual channel supporting 64 to 1,920 kbps.
 2. H.230 — Frame control signals for audiovisual systems.
 3. H.242 — Audiovisual communication protocols.
 4. H.261 — Video encoder/decoder for audiovisual services at $p \times 64$ kbps.
 5. H.320 — Narrow-band audiovisual terminal equipment for $p \times 64$ kbps transmission.

Table 10.2 Video Formats Supported by H.261

Video format	Luminance image resolution	Chrominance image resolution	Bit-rate (Mbps) (if 30 fps and uncompressed)	H.261 support
QCIF	176 × 144	88 × 72	9.1	required
CIF	352 × 288	176 × 144	36.5	optional

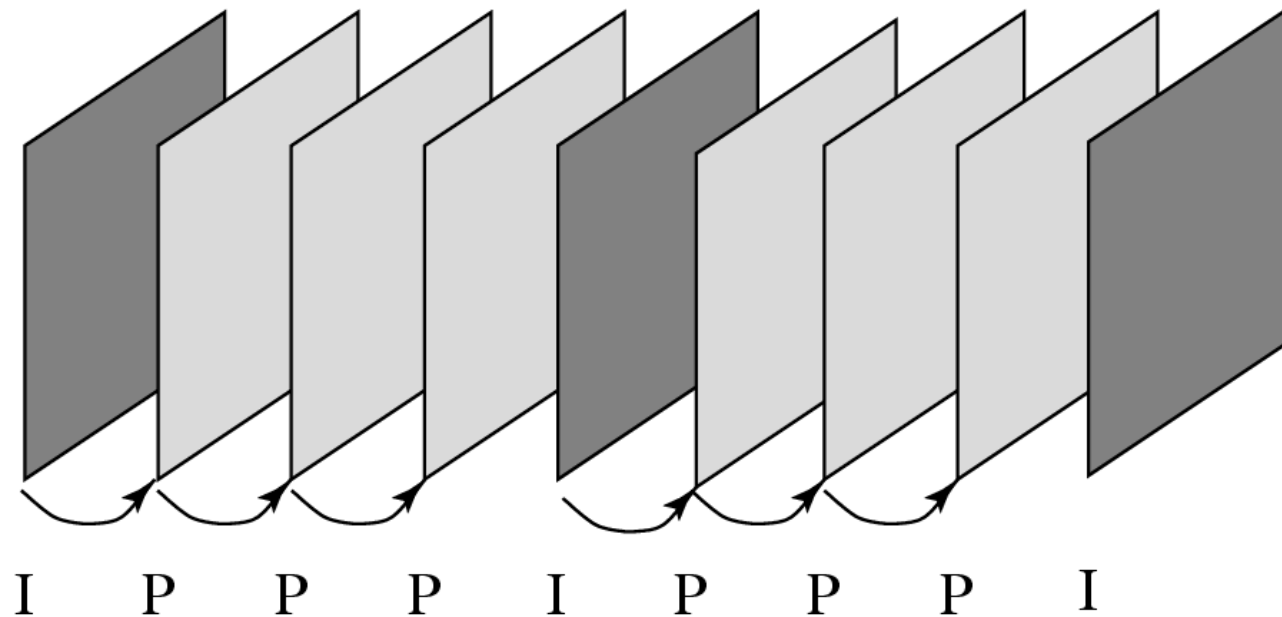


Fig. 10.4: H.261 Frame Sequence.

H.261 Frame Sequence

- Two types of image frames are defined: Intra-frames (I-frames) and Inter-frames (P-frames):
 - I-frames are treated as independent images. Transform coding method similar to JPEG is applied within each I-frame, hence “Intra”.
 - P-frames are not independent: coded by a forward predictive coding method (prediction from a previous P-frame is allowed — not just from a previous I-frame).
 - **Temporal redundancy removal** is included in P-frame coding, whereas I-frame coding performs only **spatial redundancy removal**.
 - To avoid propagation of coding errors, an I-frame is usually sent a couple of times in each second of the video.
- Motion vectors in H.261 are always measured in units of full pixel and they have a limited range of ± 15 pixels, i.e., $p = 15$.

Intra-frame (I-frame) Coding

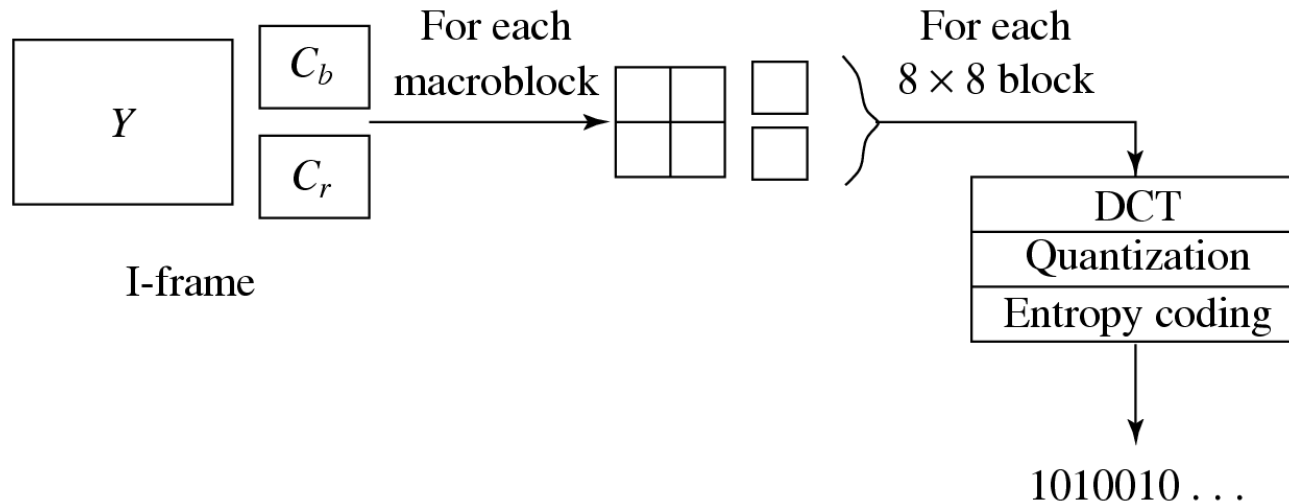


Fig. 10.5: I-frame Coding.

- **Macroblocks** are of size 16 x 16 pixels for the Y frame, and 8 x 8 for C_b and C_r frames, since 4:2:0 chroma subsampling is employed. A macroblock consists of four Y, one C_b, and one C_r 8 x 8 blocks.
- For each 8 x 8 block a DCT transform is applied, the DCT coefficients then go through quantization zigzag scan and entropy coding.

Inter-frame (P-frame) Predictive Coding

- Figure 10.6 shows the H.261 P-frame coding scheme based on motion compensation:
 - For each macroblock in the Target frame, a motion vector is allocated by one of the search methods discussed earlier.
 - After the prediction, a *difference macroblock* is derived to measure the *prediction error*.
 - Each of these 8 x 8 blocks go through DCT, quantization, zigzag scan and entropy coding procedures.

- The P-frame coding encodes the difference macroblock (not the Target macroblock itself).
- Sometimes, a good match cannot be found, i.e., the prediction error exceeds a certain acceptable level.
 - The MB itself is then encoded (treated as an Intra MB) and in this case it is termed a *non-motion compensated MB*.
- For a motion vector, the difference **MVD** is sent for entropy coding:

$$\mathbf{MVD} = \mathbf{MV}_{\text{Preceding}} - \mathbf{MV}_{\text{Current}} \quad (10.3)$$

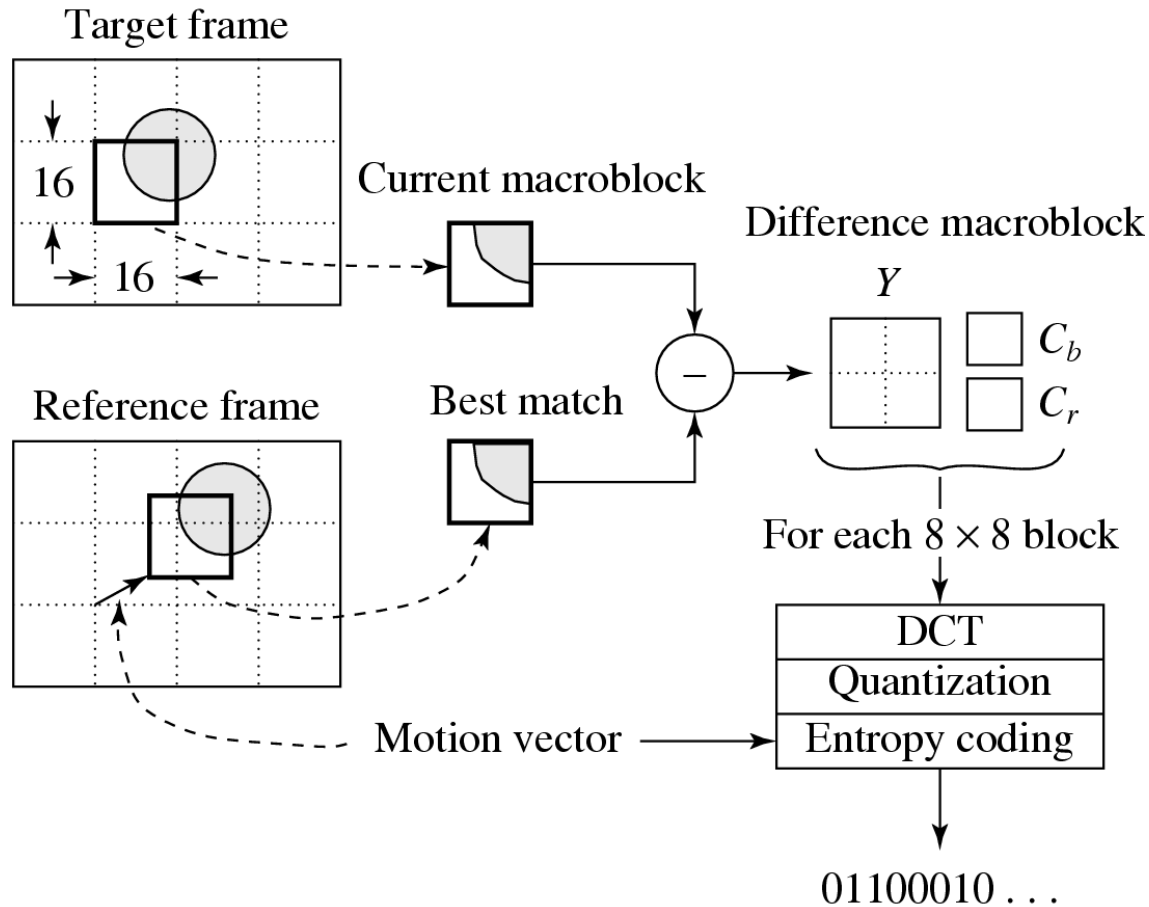


Fig. 10.6: H.261 P-frame Coding Based on Motion Compensation

Quantization in H.261

- The quantization in H.261 uses a constant *step_size*, for all DCT coefficients within a macroblock.
- If we use *DCT* and *QDCT* to denote the DCT coefficients before and after the quantization, then for DC coefficients in Intra mode:

$$QDCT = \text{round}\left(\frac{DCT}{\text{step_size}}\right) = \text{round}\left(\frac{DCT}{8}\right) \quad (10.4)$$

for all other coefficients:

$$QDCT = \left\lfloor \frac{DCT}{\text{step_size}} \right\rfloor = \left\lfloor \frac{DCT}{2 * \text{scale}} \right\rfloor \quad (10.5)$$

scale — an integer in the range of [1, 31].

H.261 Encoder and Decoder

- Fig. 10.7 shows a relatively complete picture of how the H.261 encoder and decoder work.

A scenario is used where frames I , P_1 , and P_2 are encoded and then decoded.

- Note: decoded frames (not the original frames) are used as reference frames in motion estimation.
- The data that goes through the observation points indicated by the circled numbers are summarized in Tables 10.3 and 10.4.

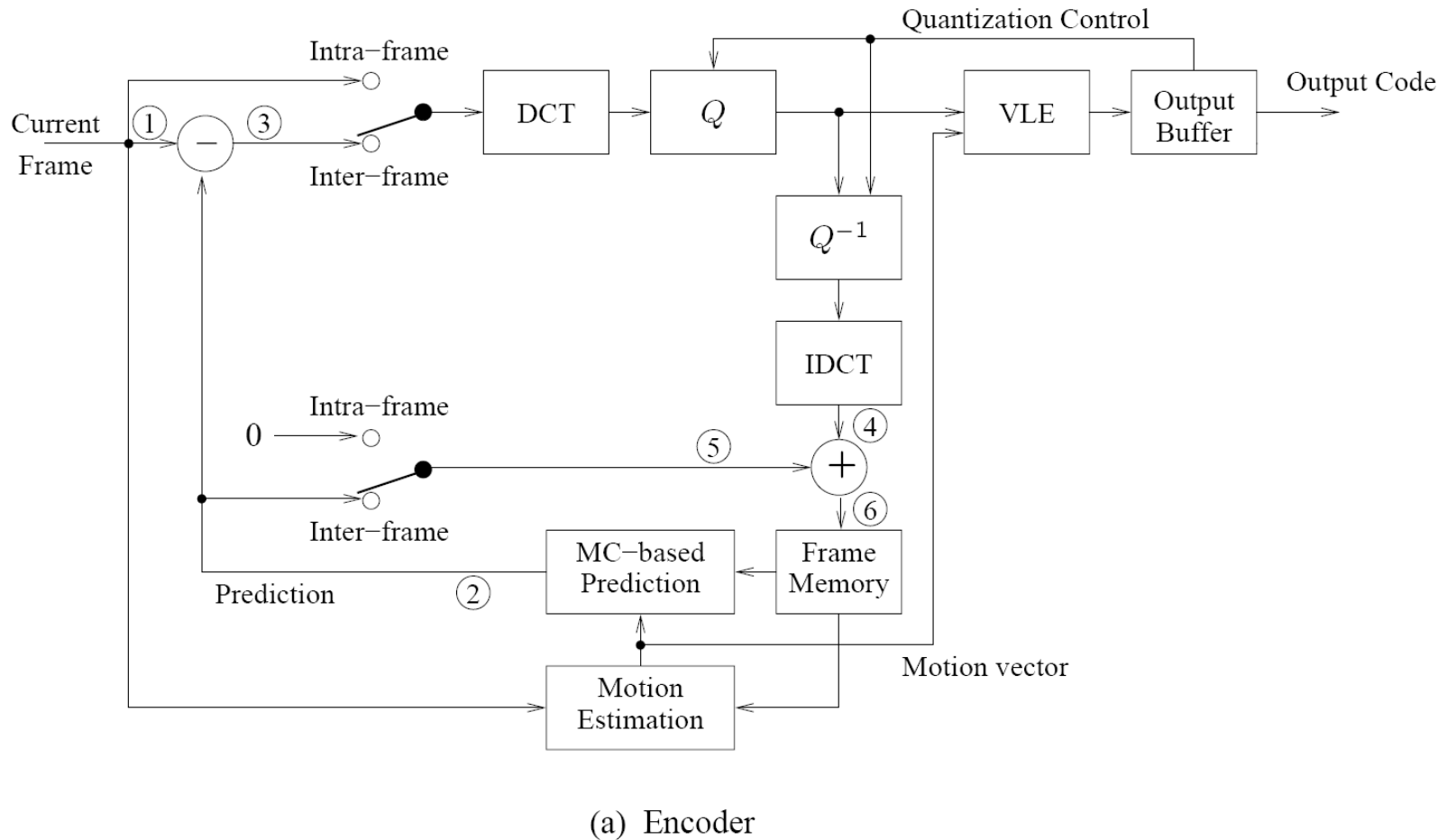
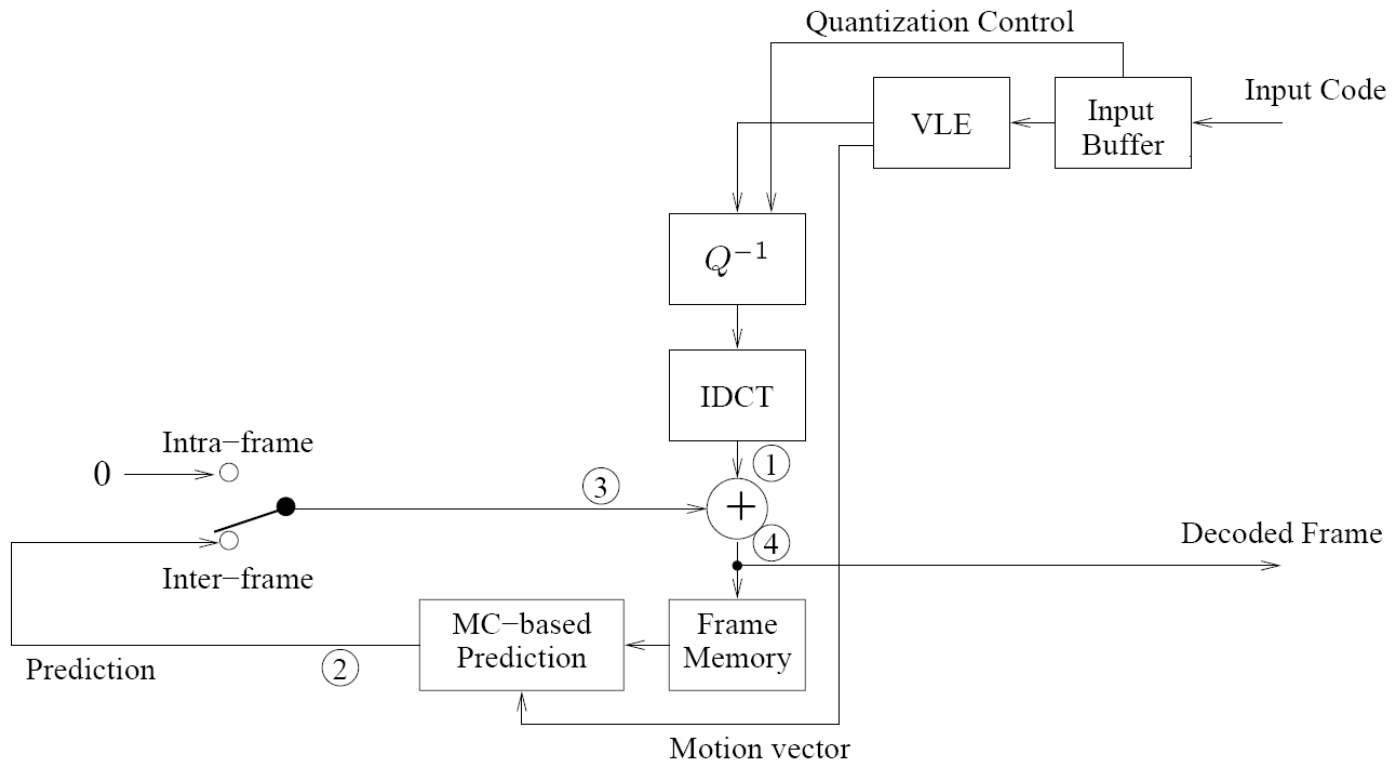


Fig. 10.7: H.261 Encoder and Decoder.



(b) Decoder

Fig. 10.7 (Cont'd): H.261 Encoder and Decoder.

Table 10.3: Data Flow at the Observation Points in H.261 Encoder

Current Frame	Observation Point					
	1	2	3	4	5	6
I	I			\tilde{I}	0	\tilde{I}
P_1	P_1	P'_1	D_1	\tilde{D}_1	P'_1	\tilde{P}_1
P_2	P_2	P'_2	D_2	\tilde{D}_2	P'_2	\tilde{P}_2

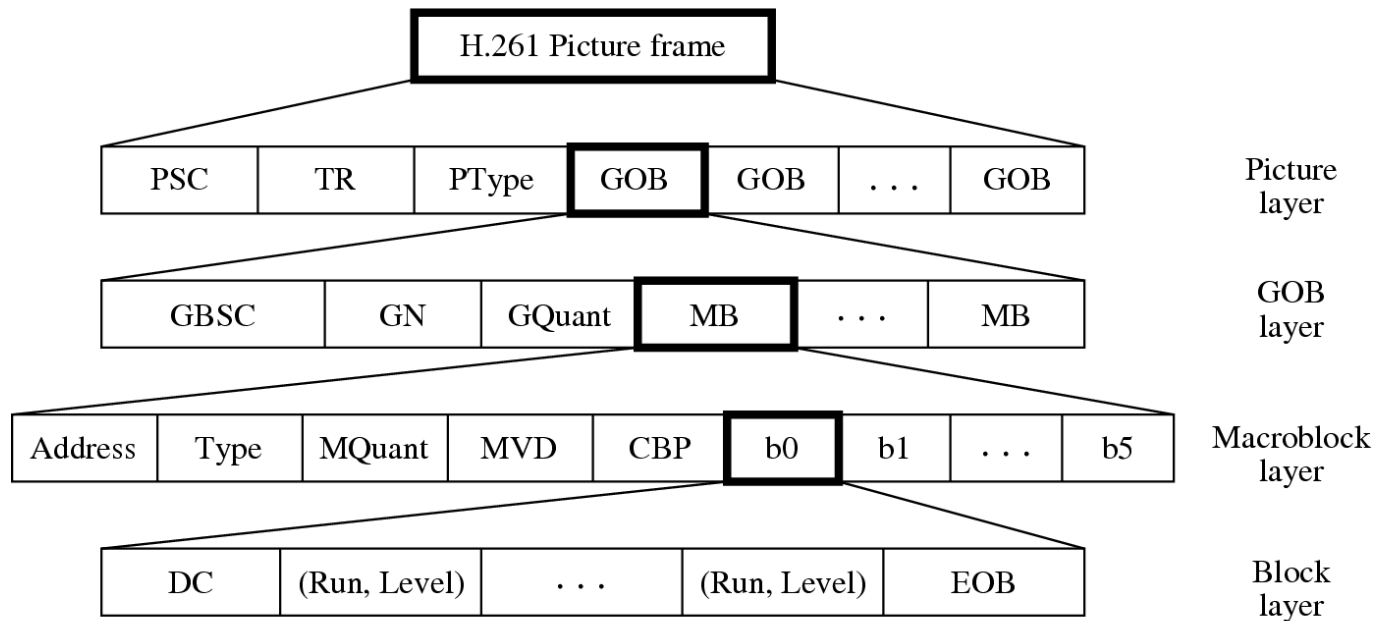
Table 10.4: Data Flow at the Observation Points in H.261 Decoder

Current Frame	Observation Point			
	1	2	3	4
I	\tilde{I}		0	\tilde{I}
P_1	\tilde{D}_1	P'_1	P'_1	\tilde{P}_1
P_2	\tilde{D}_2	P'_2	P'_2	\tilde{P}_2

A Glance at Syntax of H.261 Video Bitstream

- Fig. 10.8 shows the syntax of H.261 video bitstream: a hierarchy of four layers: Picture, Group of Blocks (GOB), Macroblock, and Block.
 1. **The Picture layer:** PSC (Picture Start Code) delineates boundaries between pictures. TR (Temporal Reference) provides a time-stamp for the picture.
 2. **The GOB layer:** H.261 pictures are divided into regions of 11 x 3 macroblocks, each of which is called a Group of Blocks (GOB).
 - Fig. 10.9 depicts the arrangement of GOBs in a CIF or QCIF luminance image.
 - For instance, the CIF image has 2 x 6 GOBs, corresponding to its image resolution of 352 x 288 pixels. Each GOB has its Start Code (GBSC) and Group number (GN).

- In case a network error causes a bit error or the loss of some bits, H.261 video can be recovered and resynchronized at the next identifiable GOB.
 - GQuant indicates the Quantizer to be used in the GOB unless it is overridden by any subsequent MQuant (Quantizer for Macroblock). GQuant and MQuant are referred to as *scale* in Eq. (10.5).
3. **The Macroblock layer:** Each Macroblock (MB) has its own Address indicating its position within the GOB, Quantizer (MQuant), and six 8 x 8 image blocks (4 Y, 1 Cb, 1 Cr).
 4. **The Block layer:** For each 8 x 8 block, the bitstream starts with DC value, followed by pairs of length of zerorun (Run) and the subsequent non-zero value (Level) for ACs, and finally the End of Block (EOB) code. The range of Run is [0; 63]. Level reflects quantized values — its range is [-127, 127] and Level \neq 0.



PSC Picture Start Code

PType Picture Type

GBSC GOB Start Code

GQuant GOB Quantizer

MQuant MB Quantizer

CBP Coded Block Pattern

TR Temporal Reference

GOB Group of Blocks

GN Group Number

MB Macroblock

MVD Motion Vector Data

EOB End of Block

Fig. 10.8: Syntax of H.261 Video Bitstream.

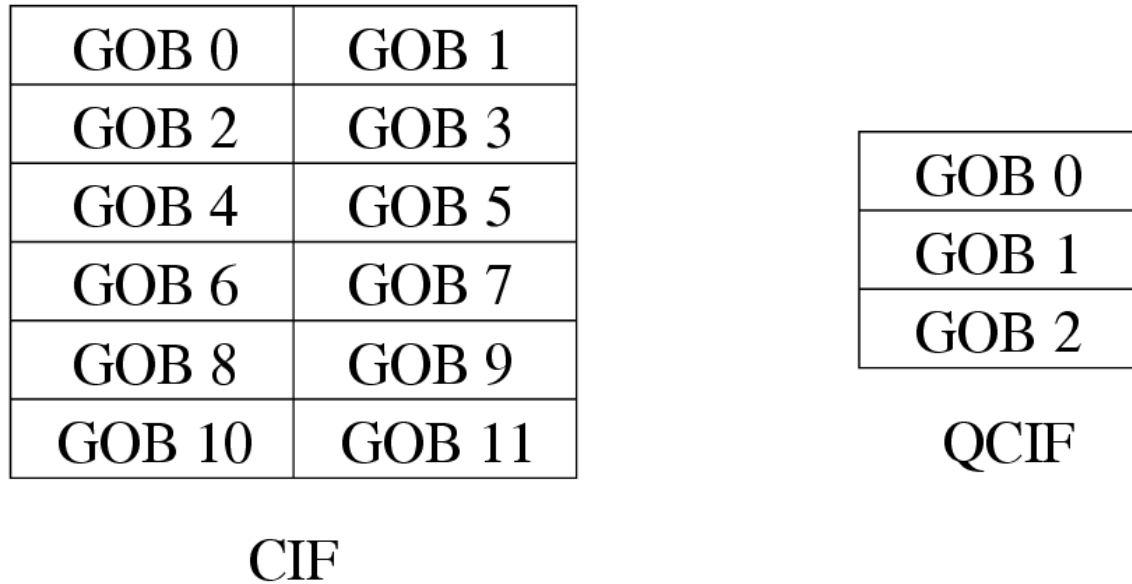


Fig. 10.9: Arrangement of GOBs in H.261 Luminance Images.

10.5 H.263

- H.263 is an improved video coding standard for video conferencing and other audiovisual services transmitted on Public Switched Telephone Networks (PSTN).
 - Aims at low bit-rate communications at bit-rates of less than 64 kbps.
 - Uses predictive coding for inter-frames to reduce temporal redundancy and transform coding for the remaining signal to reduce spatial redundancy (for both Intra-frames and inter-frame prediction).

Table 10.5: Video Formats Supported by H.263

Video format	Luminance image resolution	Chrominance image resolution	Bit-rate (Mbps) (if 30 fps and uncompressed)	Bit-rate (kbps) BPPmaxKb (compressed)
sub-QCIF	128×96	64×48	4.4	64
QCIF	176×144	88×72	9.1	64
CIF	352×288	176×144	36.5	256
4CIF	704×576	352×288	146.0	512
16CIF	$1,408 \times 1,152$	704×576	583.9	1024

H.263 & Group of Blocks (GOB)

- As in H.261, H.263 standard also supports the notion of Group of Blocks (GOB).
- The difference is that GOBs in H.263 do not have a fixed size, and they always start and end at the left and right borders of the picture.
- As shown in Fig. 10.10, each QCIF luminance image consists of 9 GOBs and each GOB has 11 x 1 MBs (176 x 16 pixels), whereas each 4CIF luminance image consists of 18 GOBs and each GOB has 44 x 2 MBs (704 x 32 pixels).

GOB 0
GOB 1
GOB 2
GOB 3
GOB 4
GOB 5

Sub-QCIF

GOB 0
GOB 1
GOB 2
GOB 3
GOB 4
GOB 5
GOB 6
GOB 7
GOB 8

QCIF

GOB 0
GOB 1
GOB 2
GOB 3
GOB 4
GOB 5
•
•
•
GOB 15
GOB 16
GOB 17

CIF, 4CIF, and 16CIF

Fig. 10.10: Arrangement of GOBs in H.263 Luminance Images.

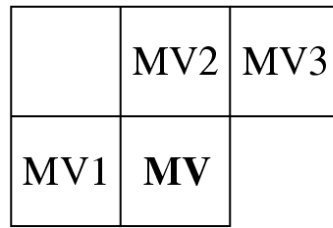
Motion Compensation in H.263

- The horizontal and vertical components of the **MV** are predicted from the median values of the horizontal and vertical components, respectively, of **MV1**, **MV2**, **MV3** from the “previous”, “above” and “above and right” MBs (see Fig. 10.11 (a)).
- For the Macroblock with **MV**(u , v):

$$u_p = \text{median}(u_1, u_2, u_3),$$

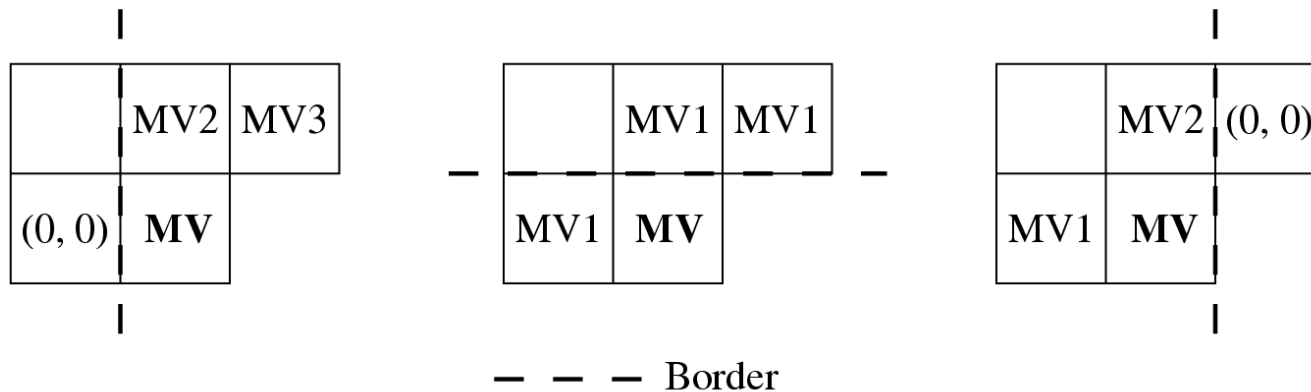
$$v_p = \text{median}(v_1, v_2, v_3). \quad (10.6)$$

Instead of coding the **MV**(u , v) itself, the error vector (δu , δv) is coded, where $\delta u = u - u_p$ and $\delta v = v - v_p$.



MV Current motion vector
MV1 Previous motion vector
MV2 Above motion vector
MV3 Above and right motion vector

(a)



(b)

Fig. 10.11: Prediction of Motion Vector in H.263.

Half-Pixel Precision

- In order to reduce the prediction error, **half-pixel precision** is supported in H.263 vs. full-pixel precision only in H.261.
 - The default range for both the horizontal and vertical components u and v of $\mathbf{MV}(u, v)$ are now $[-16, 15.5]$.
 - The pixel values needed at half-pixel positions are generated by a simple **bilinear interpolation** method, as shown in Fig. 10.12.

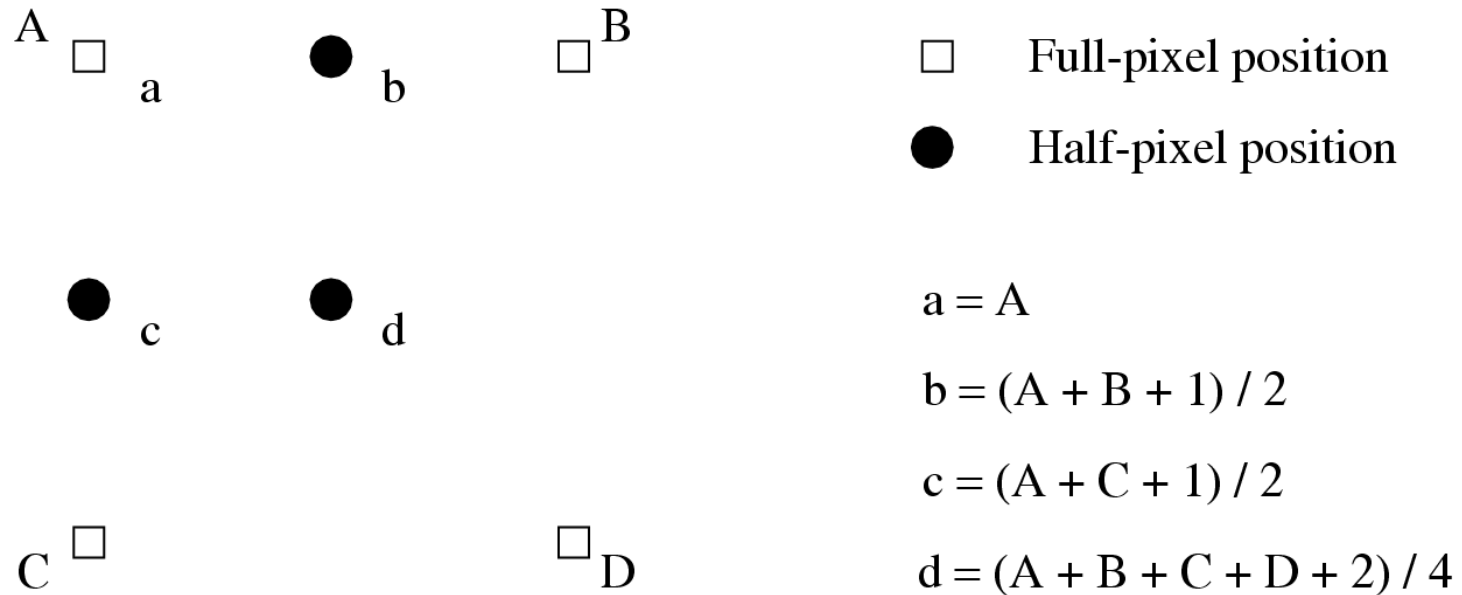


Fig. 10.12: Half-pixel Prediction by Bilinear Interpolation in H.263.

Optional H.263 Coding Modes

- H.263 specifies many negotiable coding options in its various Annexes. Four of the common options are as follows:

1. Unrestricted motion vector mode:

- The pixels referenced are no longer restricted to be within the boundary of the image.
- When the motion vector points outside the image boundary, the value of the boundary pixel that is geometrically closest to the referenced pixel is used.
- The maximum range of motion vectors is $[-31.5, 31.5]$.

2. Syntax-based arithmetic coding mode:

- As in H.261, variable length coding (VLC) is used in H.263 as a default coding method for the DCT coefficients.
- Similar to H.261, the syntax of H.263 is also structured as a hierarchy of four layers. Each layer is coded using a combination of fixed length code and variable length code.

3. Advanced prediction mode:

- In this mode, the macroblock size for MC is reduced from 16 to 8.
- Four motion vectors (from each of the 8 x 8 blocks) are generated for each macroblock in the luminance image.

4. PB-frames mode:

- In H.263, a PB-frame consists of two pictures being coded as one unit, as shown Fig. 10.13.
- The use of the PB-frames mode is indicated in PTYPE.
- The PB-frames mode yields satisfactory results for videos with moderate motions.
- Under large motions, PB-frames do not compress as well as B-frames and an improved new mode has been developed in Version 2 of H.263.

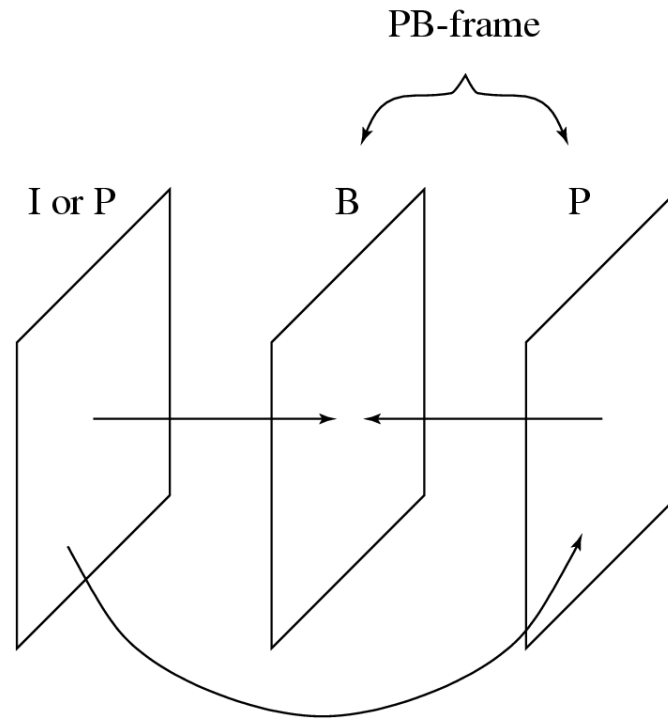


Fig. 10.13: A PB-frame in H.263.

H.263+ and H.263++

- The aim of H.263+: broaden the potential applications and offer additional flexibility in terms of custom source formats, different pixel aspect ratio and clock frequencies.
- H.263+ provides 12 new negotiable modes in addition to the four optional modes in H.263.
 - It uses Reversible Variable Length Coding (RVLC) to encode the difference motion vectors.
 - A *slice* structure is used to replace GOB to offer additional flexibility.

- H.263+ implements *Temporal*, *SNR*, and *Spatial scalabilities*.
- Support of Improved PB-frames mode in which the two motion vectors of the B-frame do not have to be derived from the forward motion vector of the P-frame as in Version 1.
- H.263+ includes deblocking filters in the coding loop to reduce blocking effects.

- H.263++ includes the baseline coding methods of H.263 and additional recommendations for Enhanced Reference Picture Selection (ERPS), Data Partition Slice (DPS), and Additional Supplemental Enhancement Information.
 - The ERPS mode operates by managing a multi-frame buffer for stored frames – enhances coding efficiency and error resilience capabilities.
 - The DPS mode provides additional enhancement to error resilience by separating header and motion vector data from DCT coefficient data in the bitstream and protects the motion vector data by using a reversible code.