

平滑影像 Gaussian filter

Gaussian
noise

Kernel size = 3×3



Kernel size = 7×7



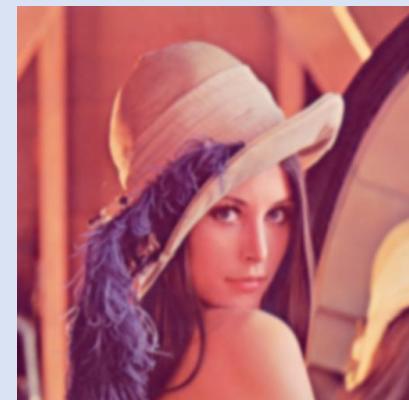
Kernel size = 15×15



Salt and
pepper noise



STD



平滑影像 Mean filter

Gaussian
noise

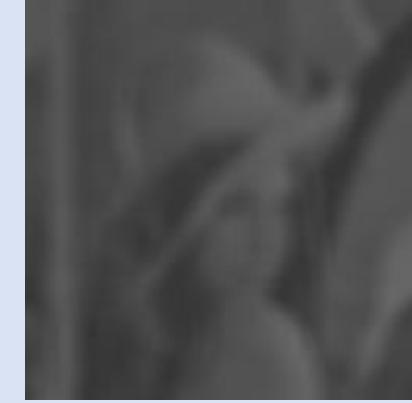
Kernel size = 3×3



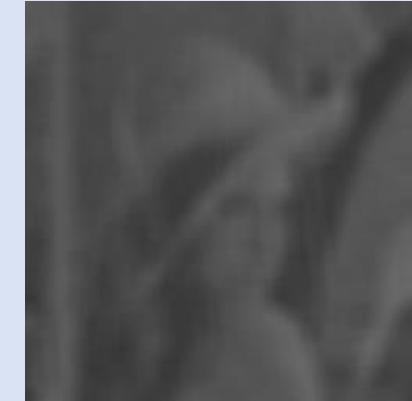
Kernel size = 7×7



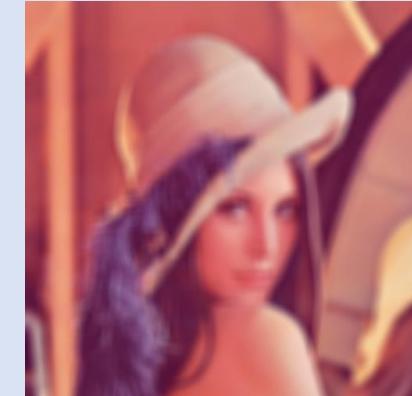
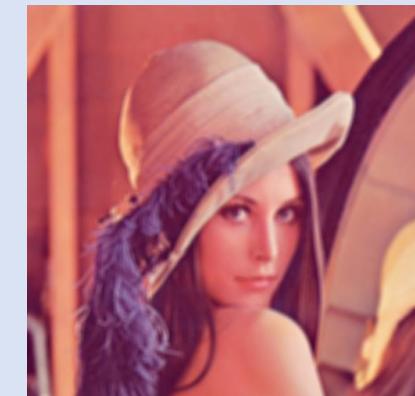
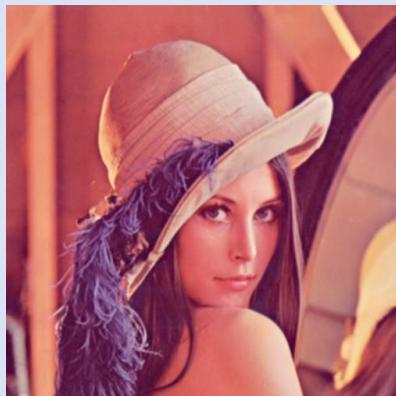
Kernel size = 15×15



Salt and
pepper noise



STD



平滑影像 Median filter

Gaussian
noise

Kernel size = 3×3



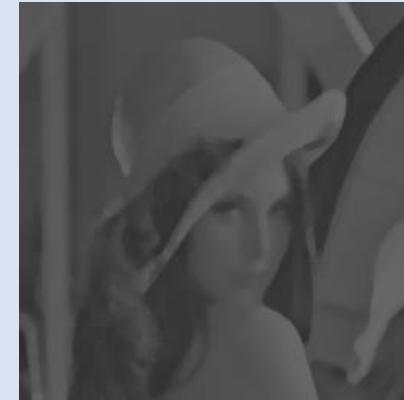
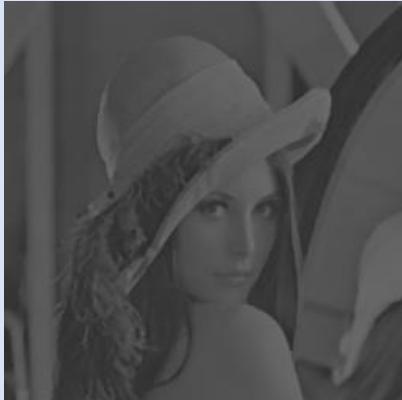
Kernel size = 7×7



Kernel size = 15×15



Salt and
pepper noise



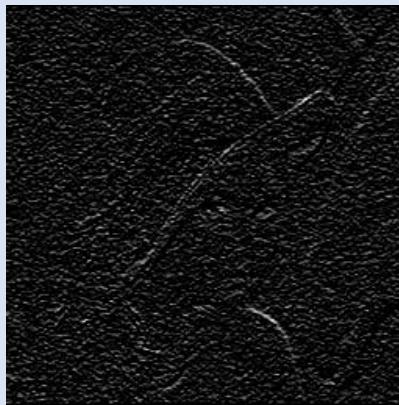
STD



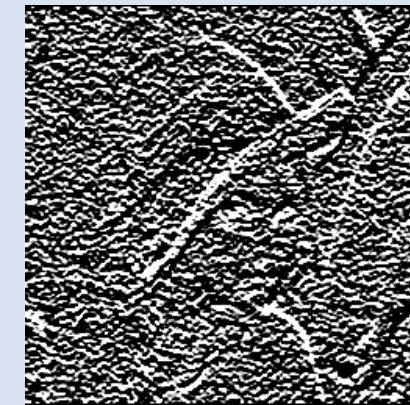
影像邊緣Sobel filter

Gaussian
Noise-X-8U

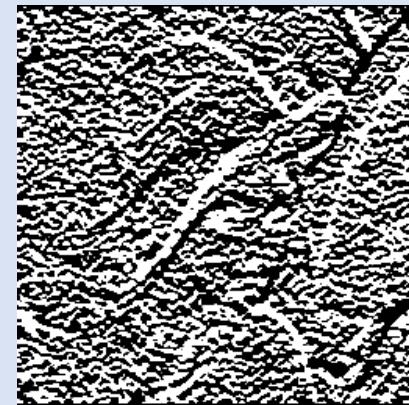
Kernel size = 3x3



Kernel size = 5x5



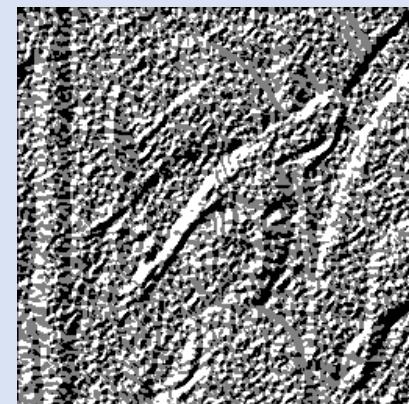
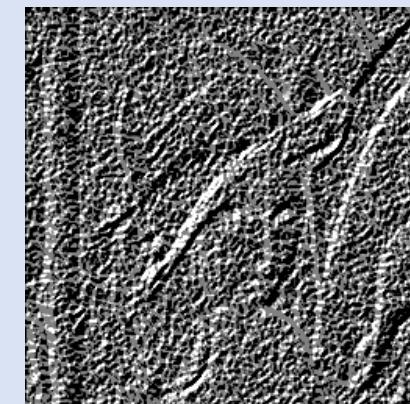
Kernel size = 7x7



Gaussian
Noise-Y-8U

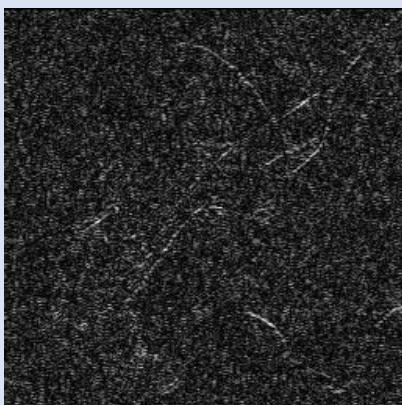


Gaussian
Noise-X+Y-8U

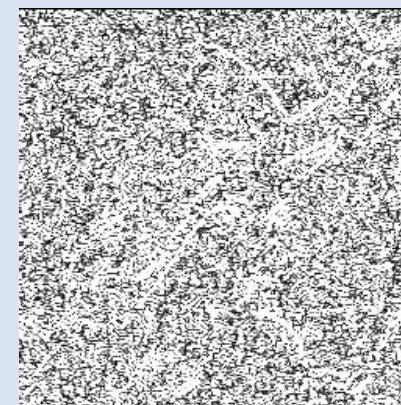


影像邊緣Sobel filter

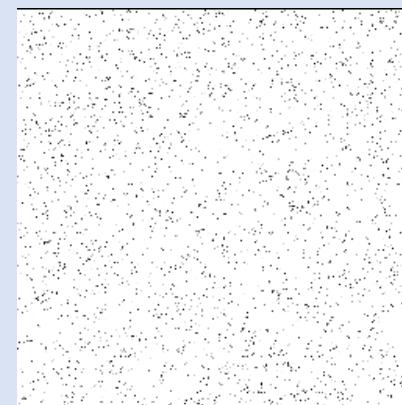
Gaussian
Noise-X-16S



Kernel size = 3x3

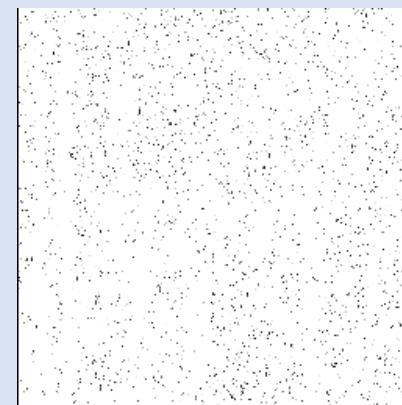
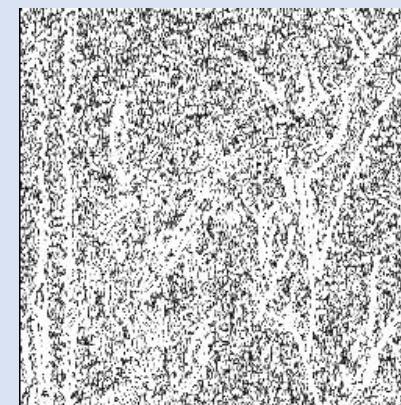
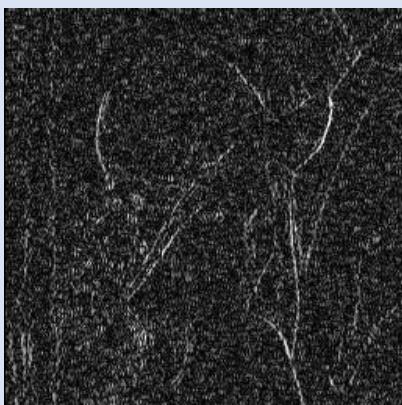


Kernel size = 5x5

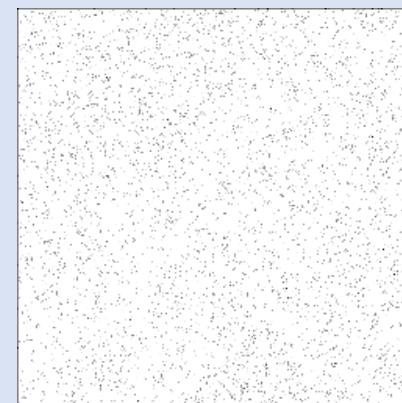
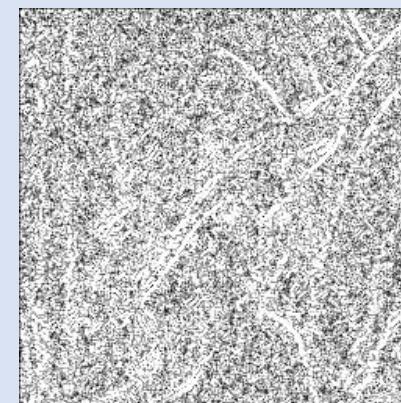
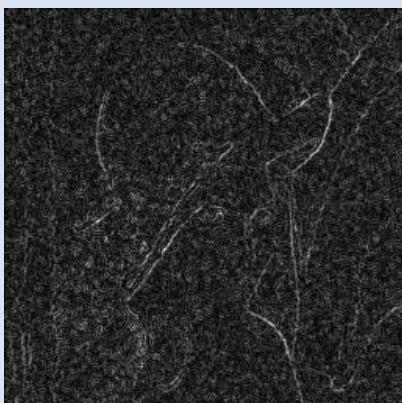


Kernel size = 7x7

Gaussian
Noise-Y-16S

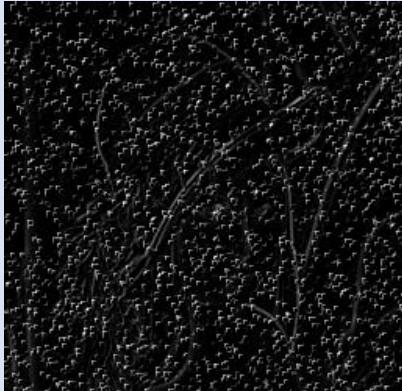
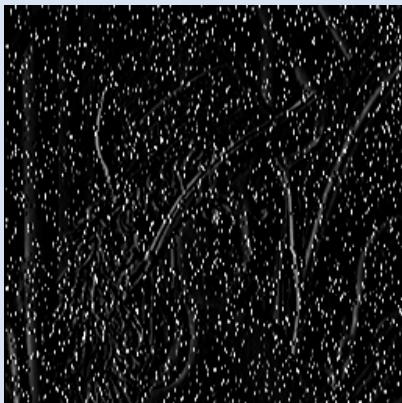
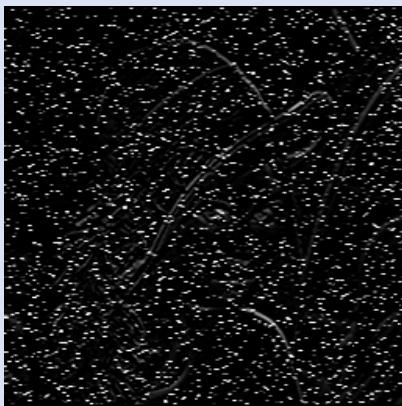


Gaussian
Noise-X+Y-16S



影像邊緣Sobel filter

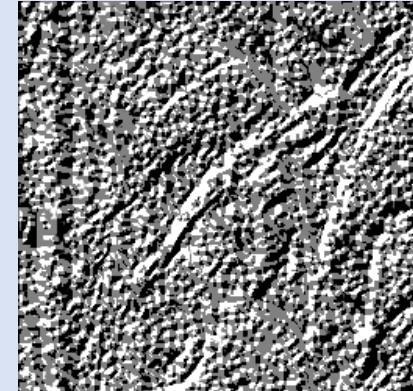
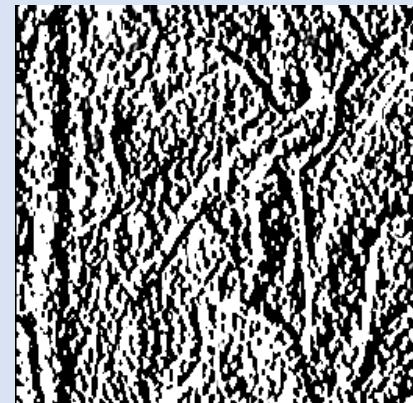
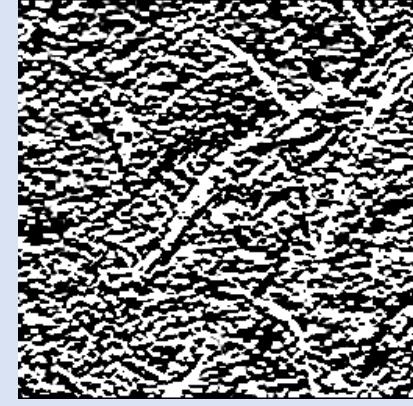
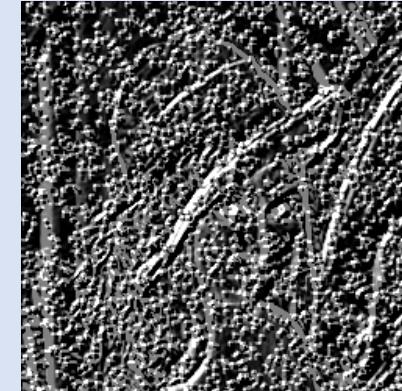
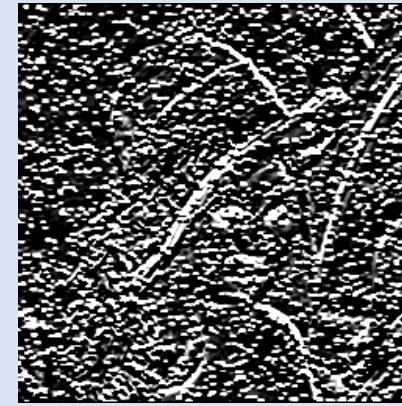
Salt and pepper
Noise-X-8U



Kernel size = 3x3

Kernel size = 5x5

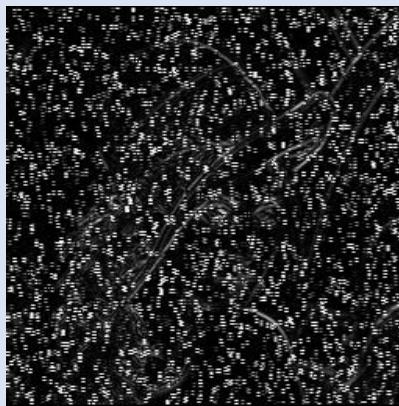
Kernel size = 7x7



Salt and pepper
Noise-X+Y-8U

影像邊緣Sobel filter

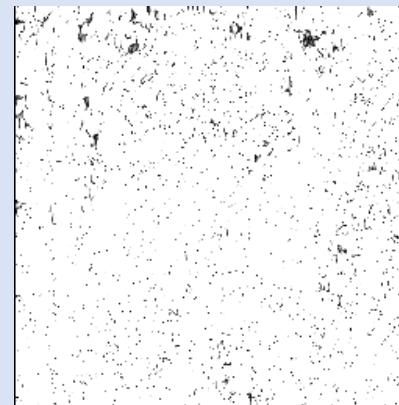
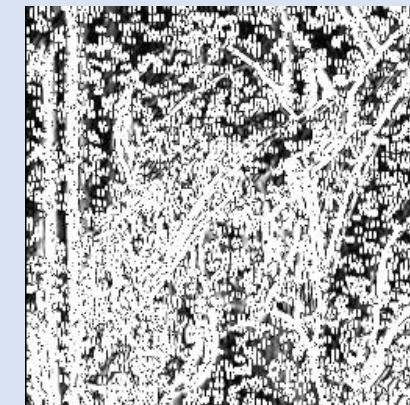
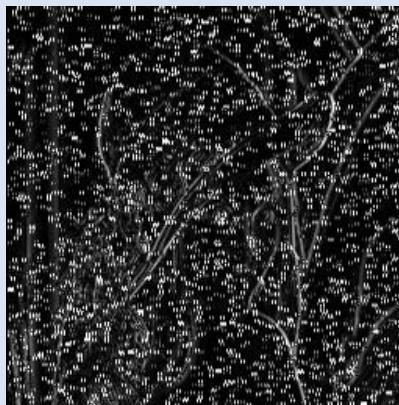
Salt and pepper
Noise-X-16S



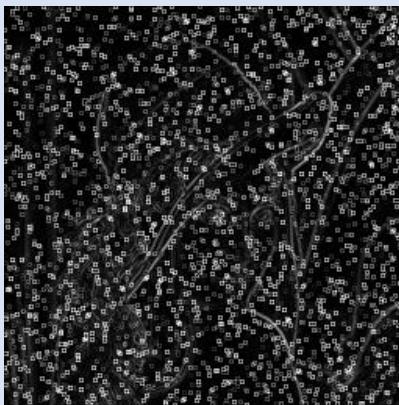
Kernel size = 3x3

Kernel size = 5x5

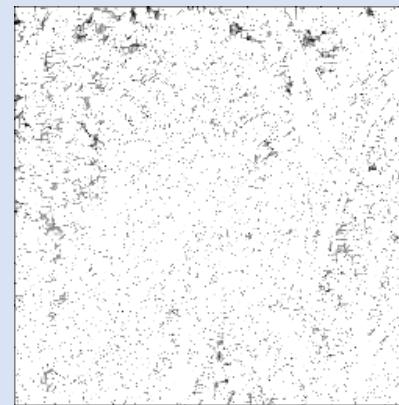
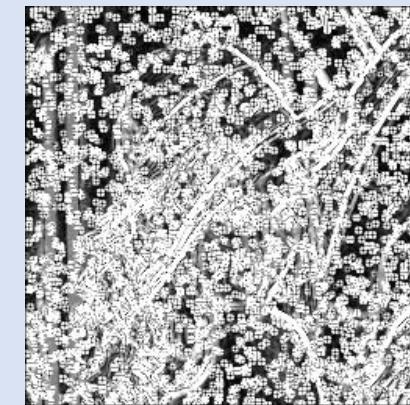
Kernel size = 7x7



Salt and pepper
Noise-Y-16S



Salt and pepper
Noise-X+Y-16S



影像邊緣Sobel filter

STD-X-8U

Kernel size = 3x3



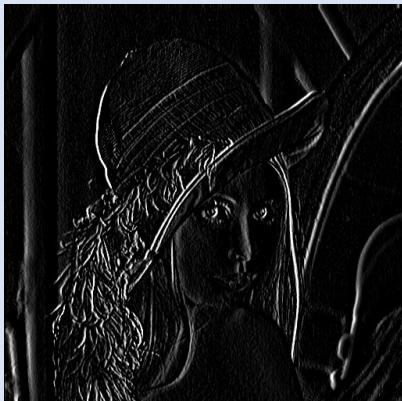
Kernel size = 5x5



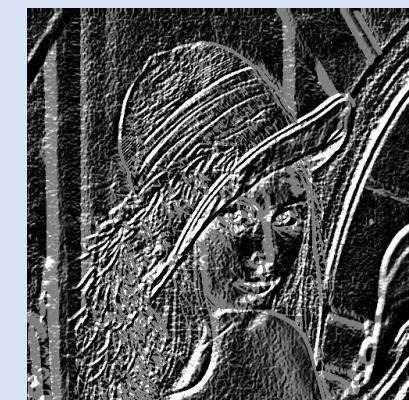
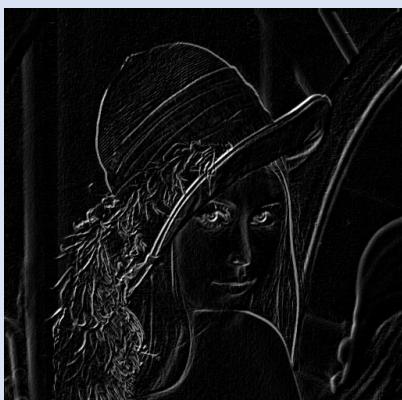
Kernel size = 7x7



STD-Y-8U



STD-X+Y-8U



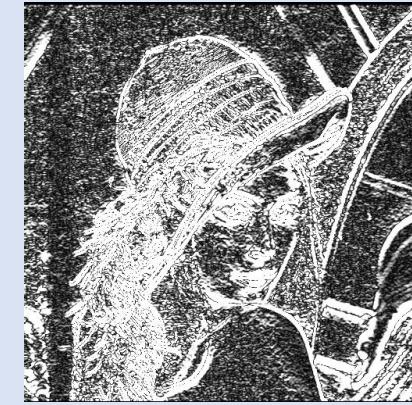
影像邊緣Sobel filter

STD-X-16S

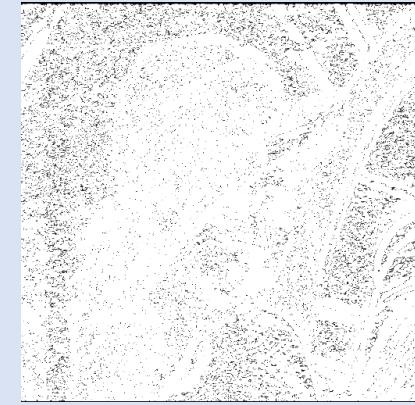
Kernel size = 3x3



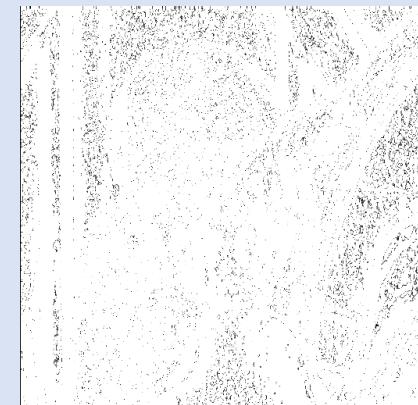
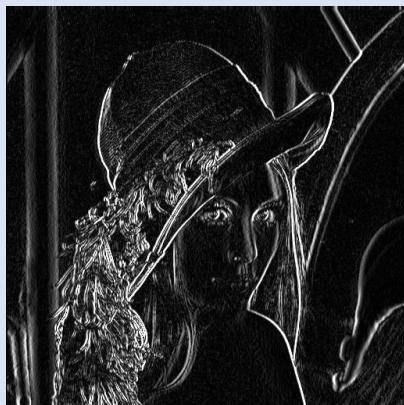
Kernel size = 5x5



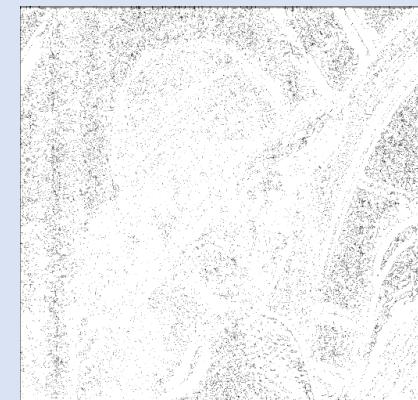
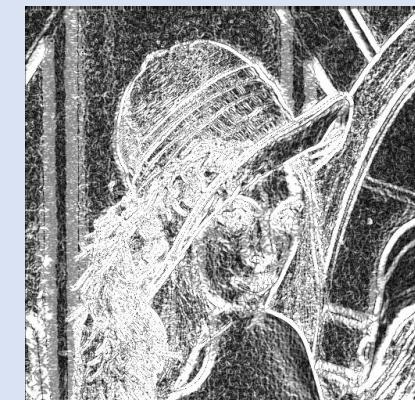
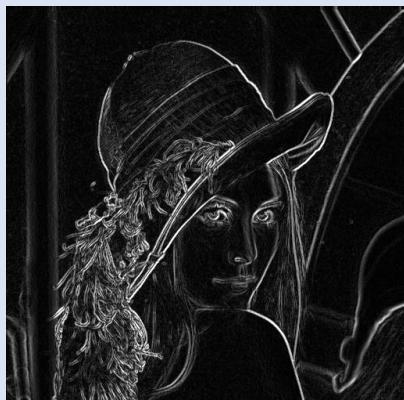
Kernel size = 7x7



STD-Y-16S



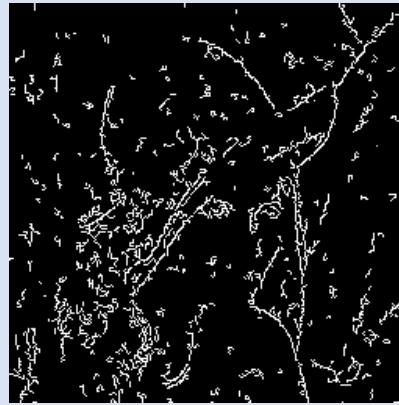
STD-X+Y-16S



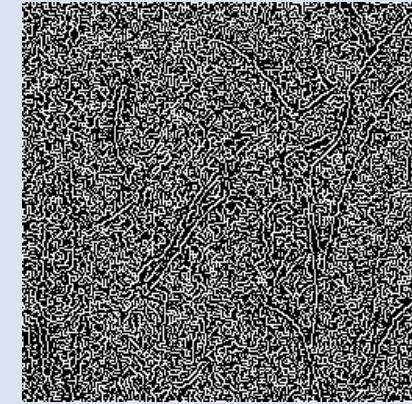
影像邊緣Canny filter

Gaussian
noise

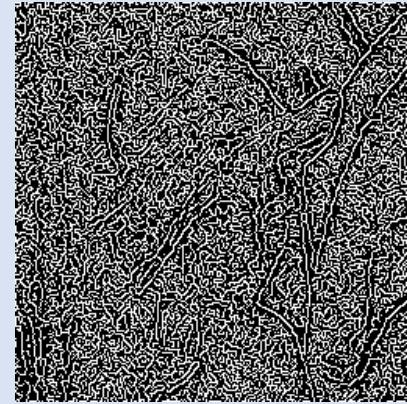
Kernel size = 3×3



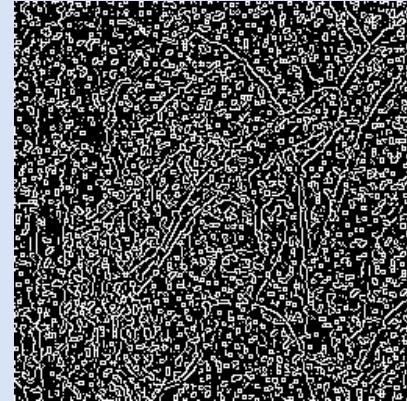
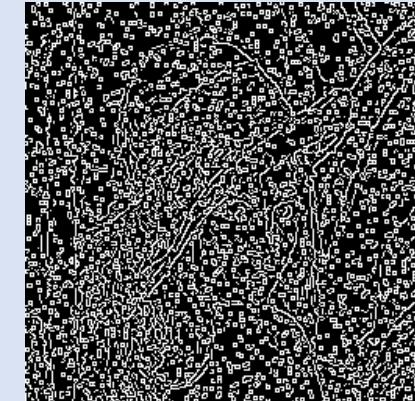
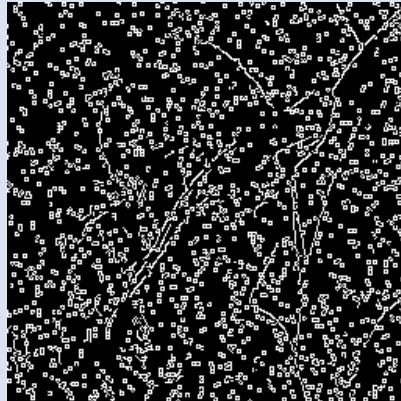
Kernel size = 5×5



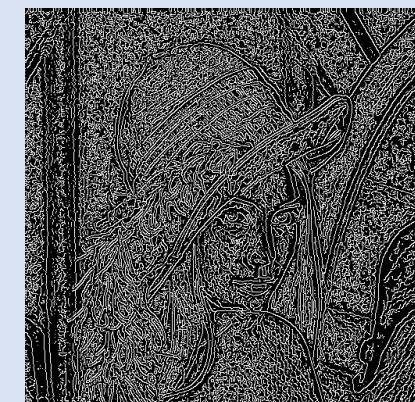
Kernel size = 7×7



Salt and
pepper noise



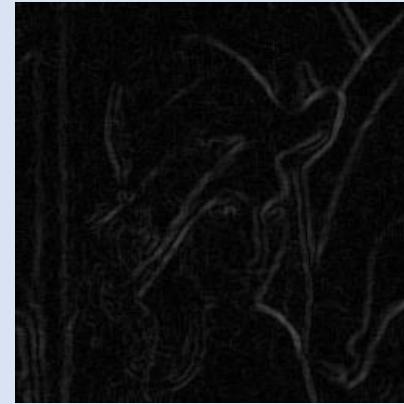
STD



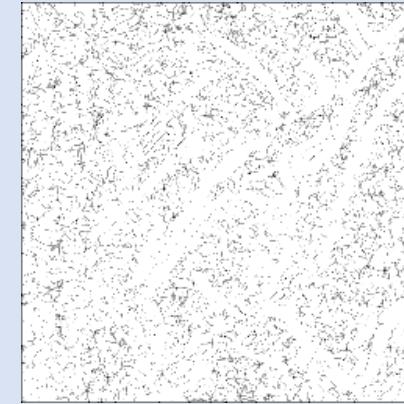
影像邊緣mean+Sobel

Gaussian
noise

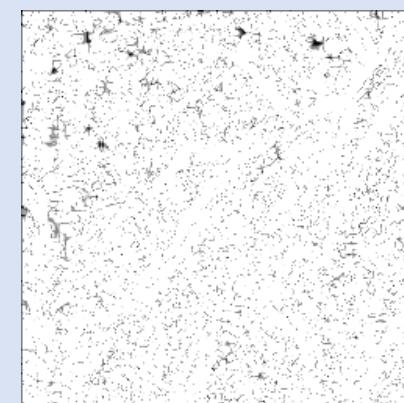
Kernel size = 3×3



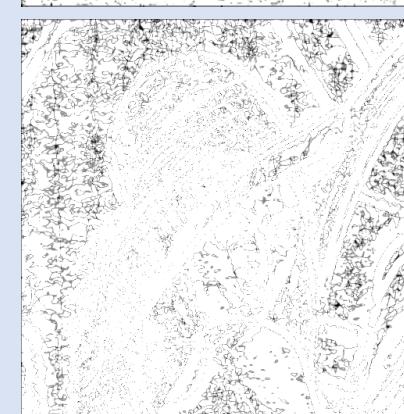
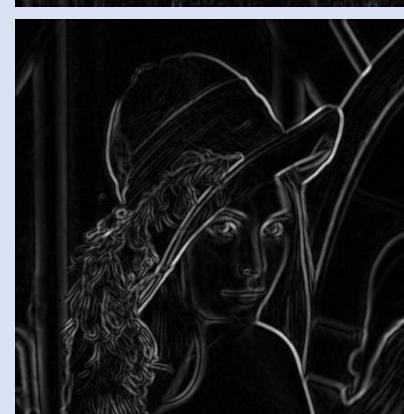
Kernel size = 5×5



Salt and
pepper noise



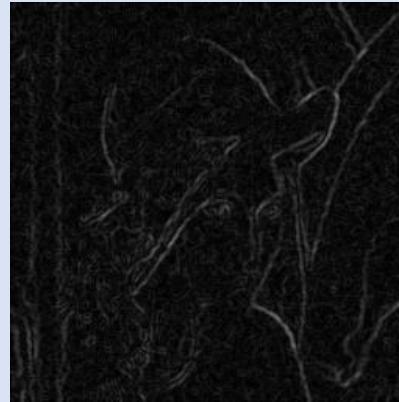
STD



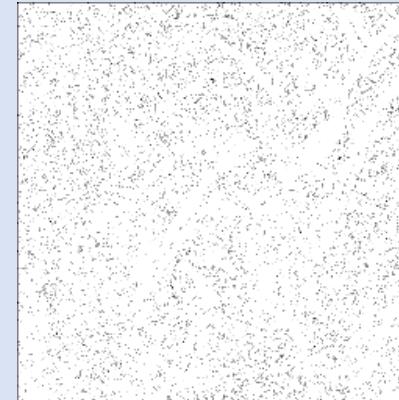
影像邊緣Gaussian+Sobel

Gaussian
noise

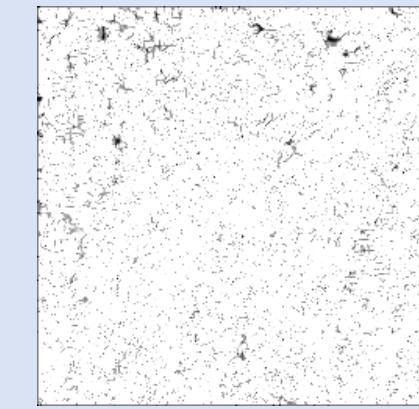
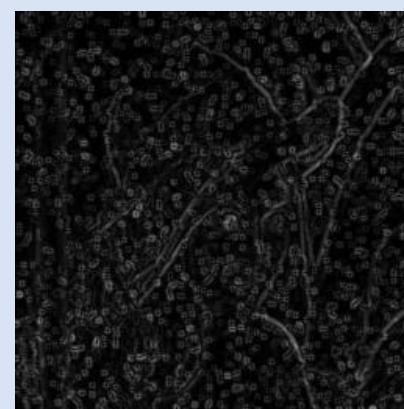
Kernel size = 3×3



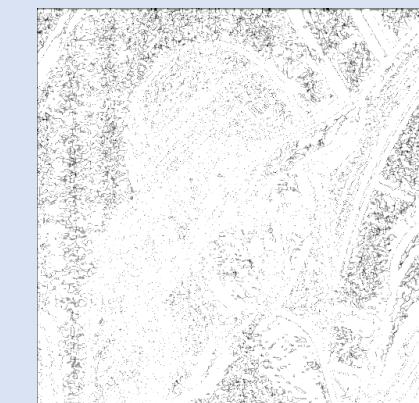
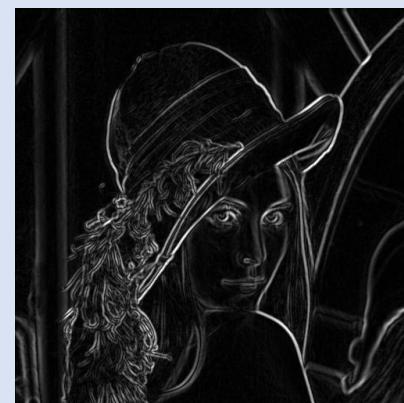
Kernel size = 5×5



Salt and
pepper noise



STD



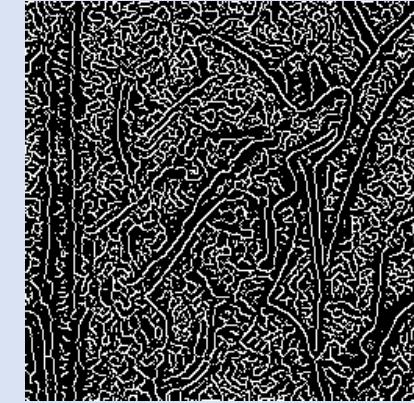
影像邊緣mean+Canny

Gaussian
noise

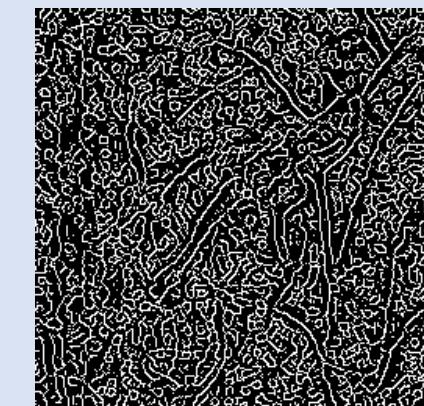
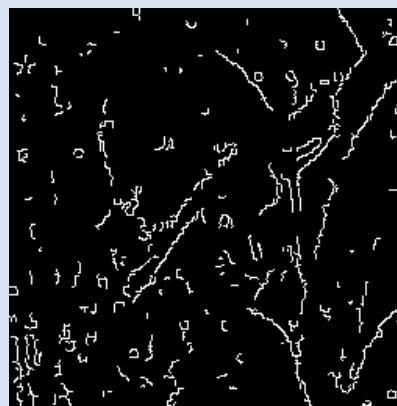
Kernel size = 3×3



Kernel size = 5×5



Salt and
pepper noise



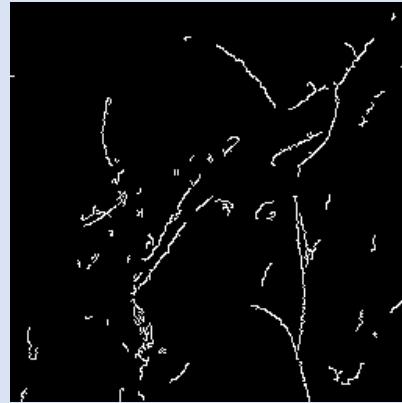
STD



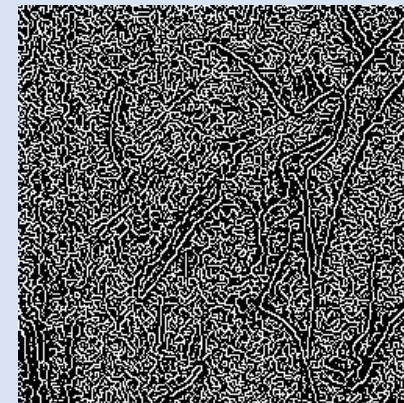
影像邊緣Gaussian+Canny

Gaussian
noise

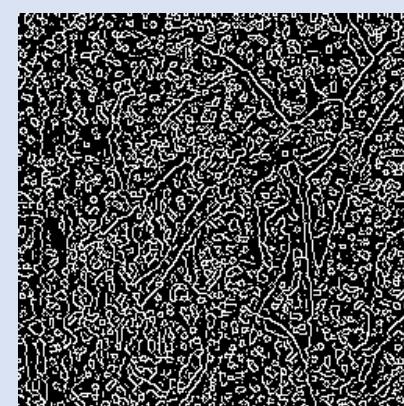
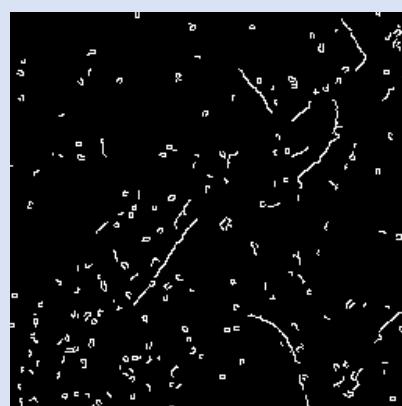
Kernel size = 3×3



Kernel size = 5×5



Salt and
pepper noise



STD

