Image formation
Lecture 1.1 - Light, camera, optics and colour

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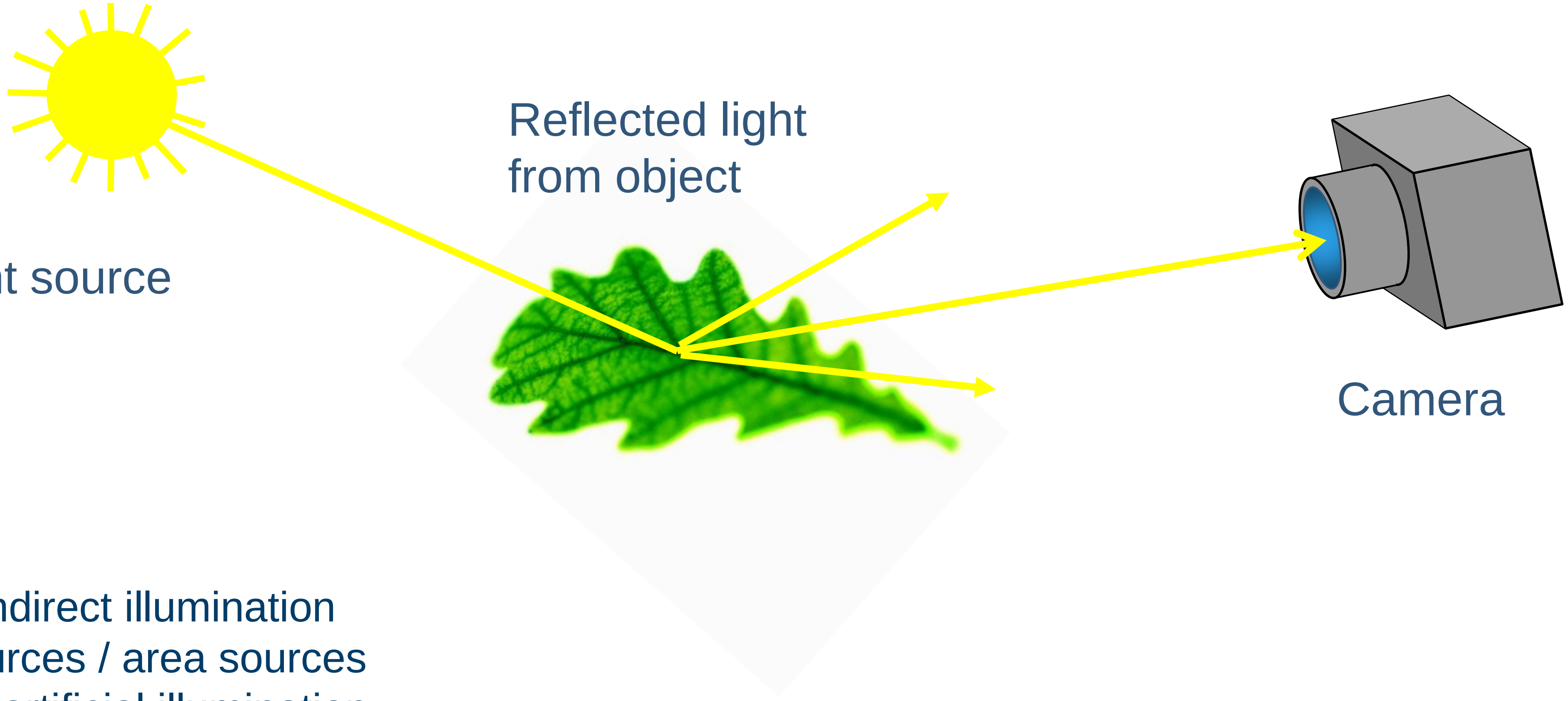
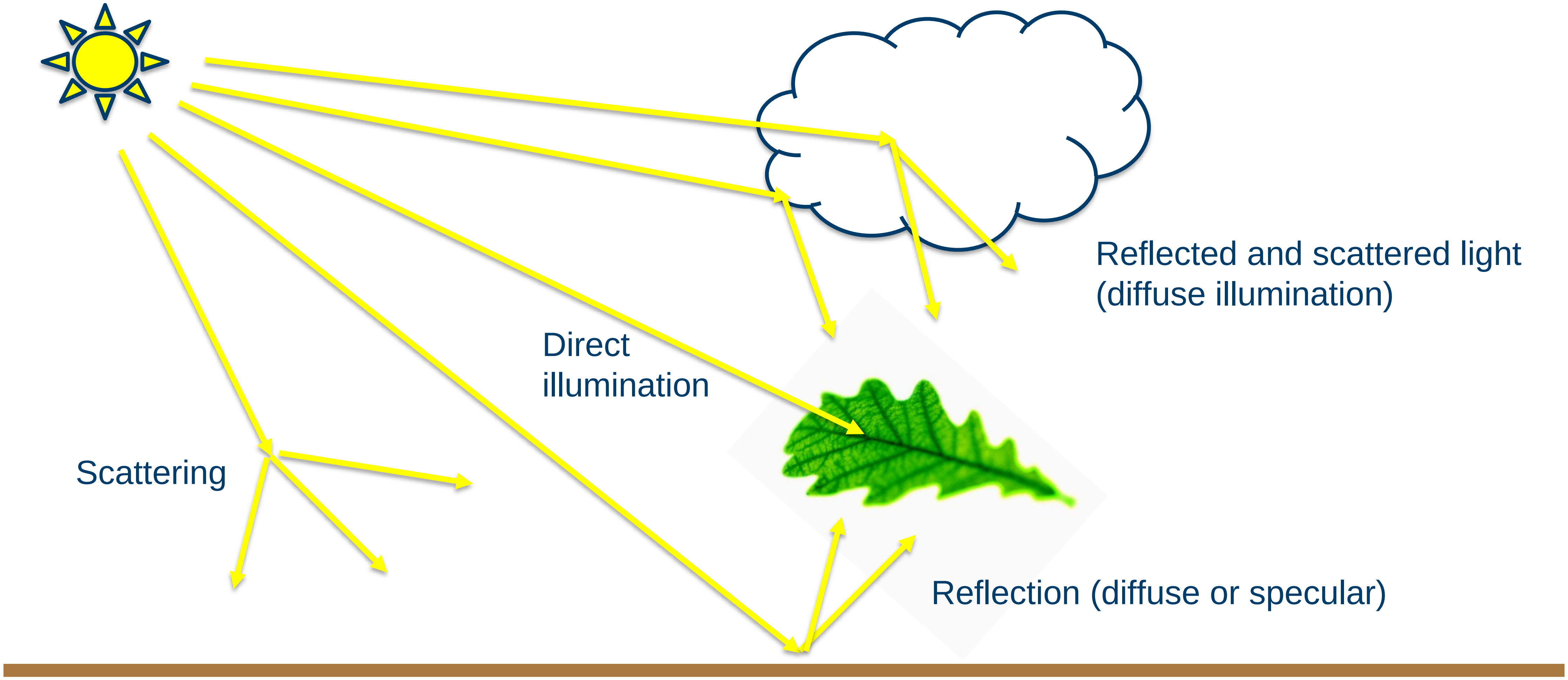
Imaging with visible light

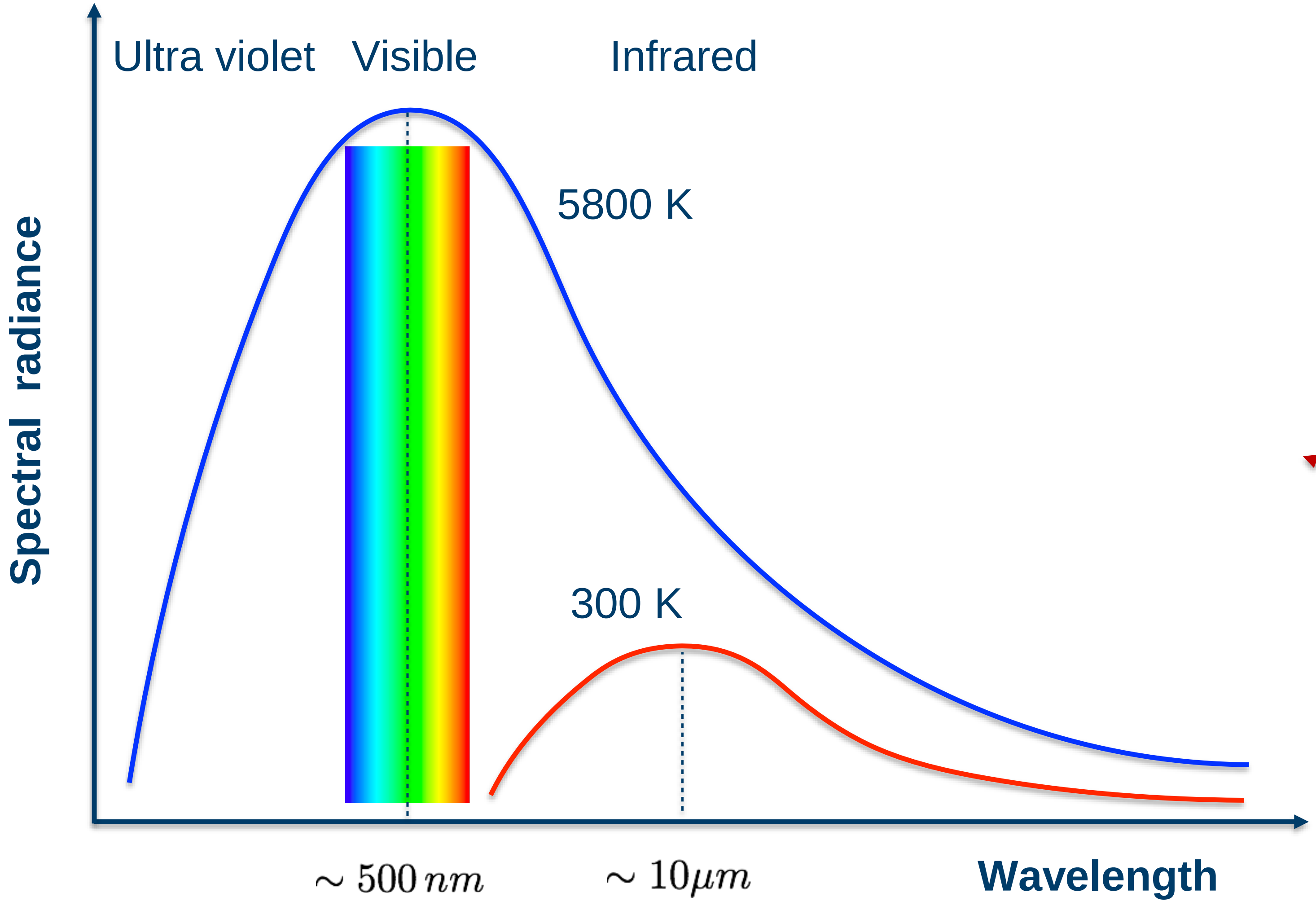


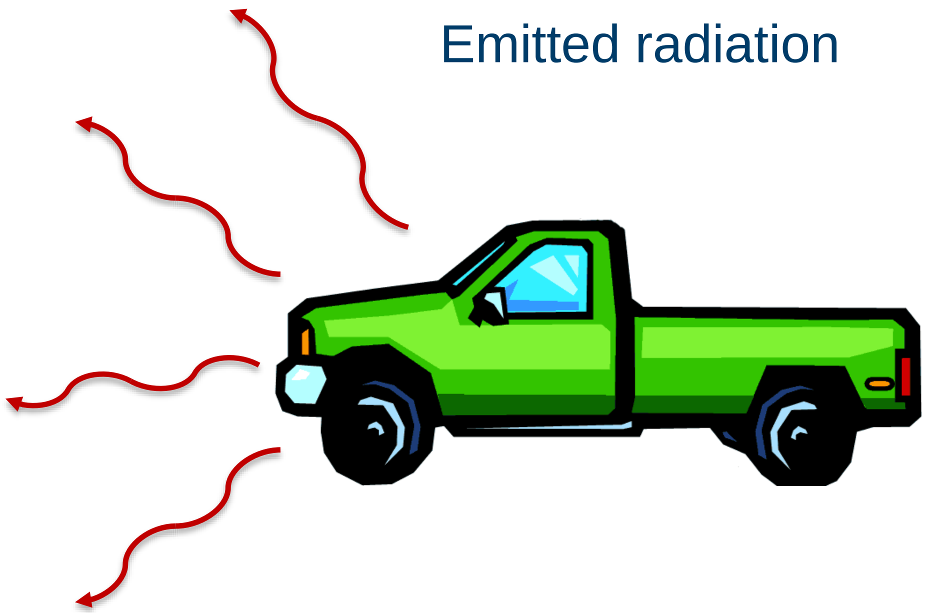
- Direct / indirect illumination
- Point sources / area sources
- Natural / artificial illumination

Direct and indirect illumination



Thermal radiation - Planck distribution

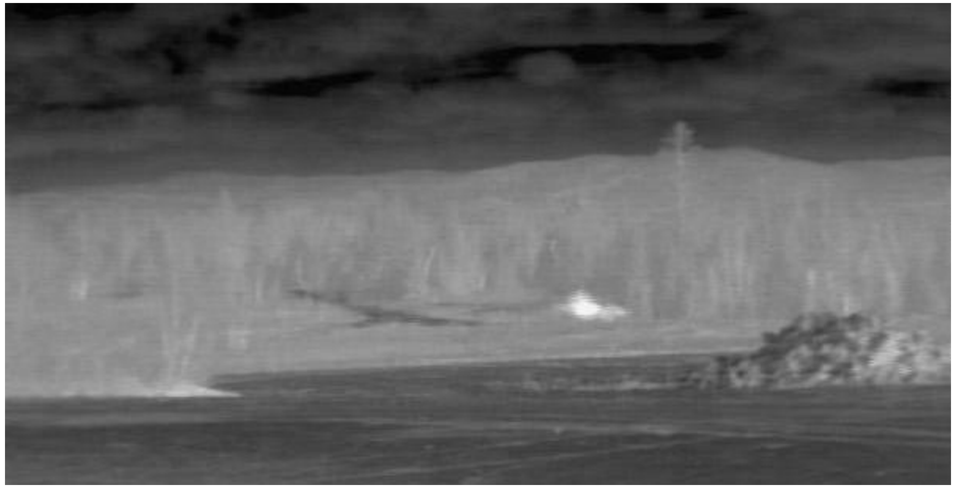




Reflected and emitted radiation

Image in visible light:

- Imaging with **reflected** (and scattered) radiation from the sun or other natural or artificial sources.



Infrared (thermal) image:

- Imaging with (mainly) the **emitted** thermal radiation from the scene.

Other frequency domains and wave types used for imaging:

- Millimeter waves, x-rays, … (electromagnetic waves)
- Acoustic (sonar), seismic, … (mechanical waves)

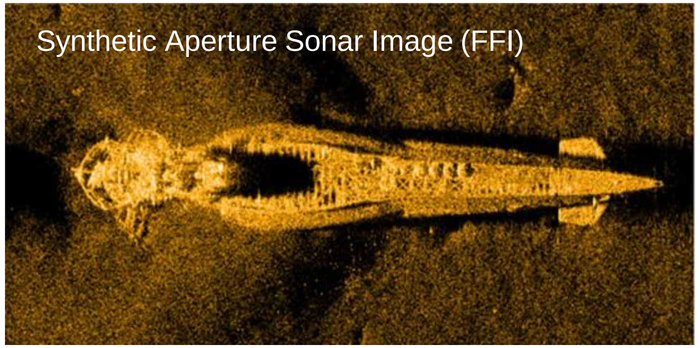
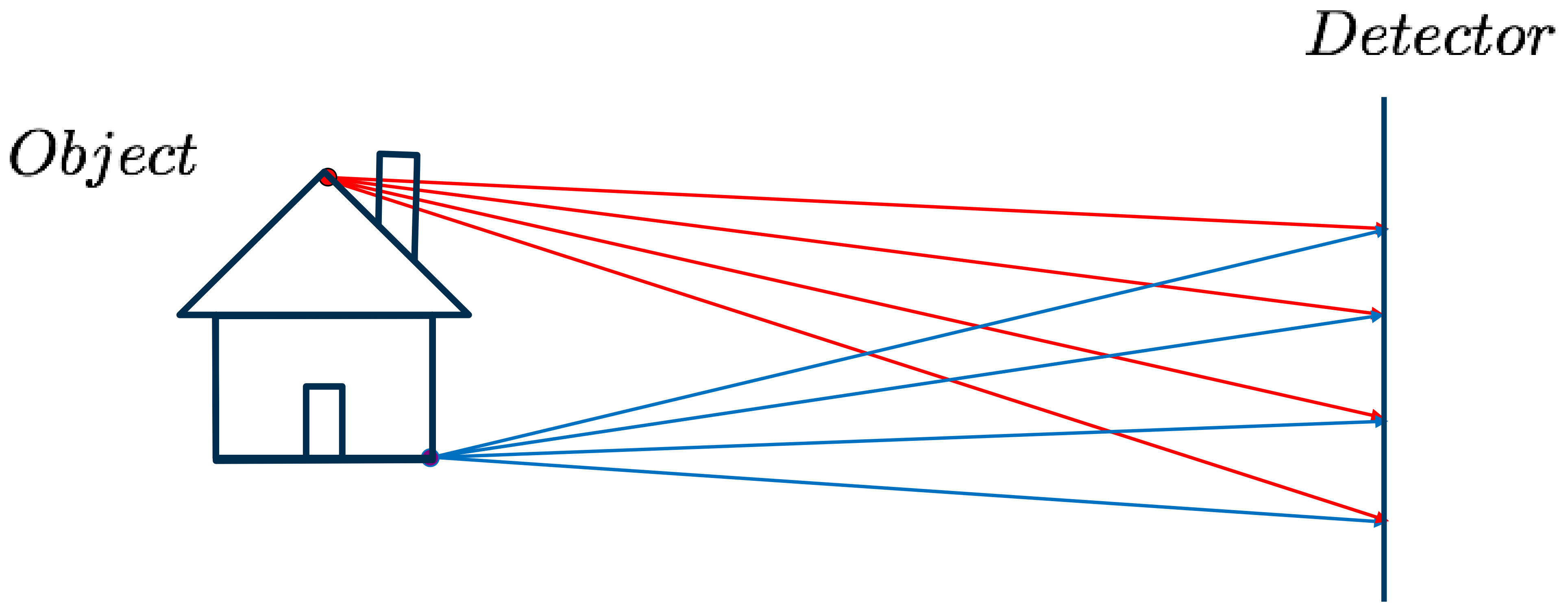
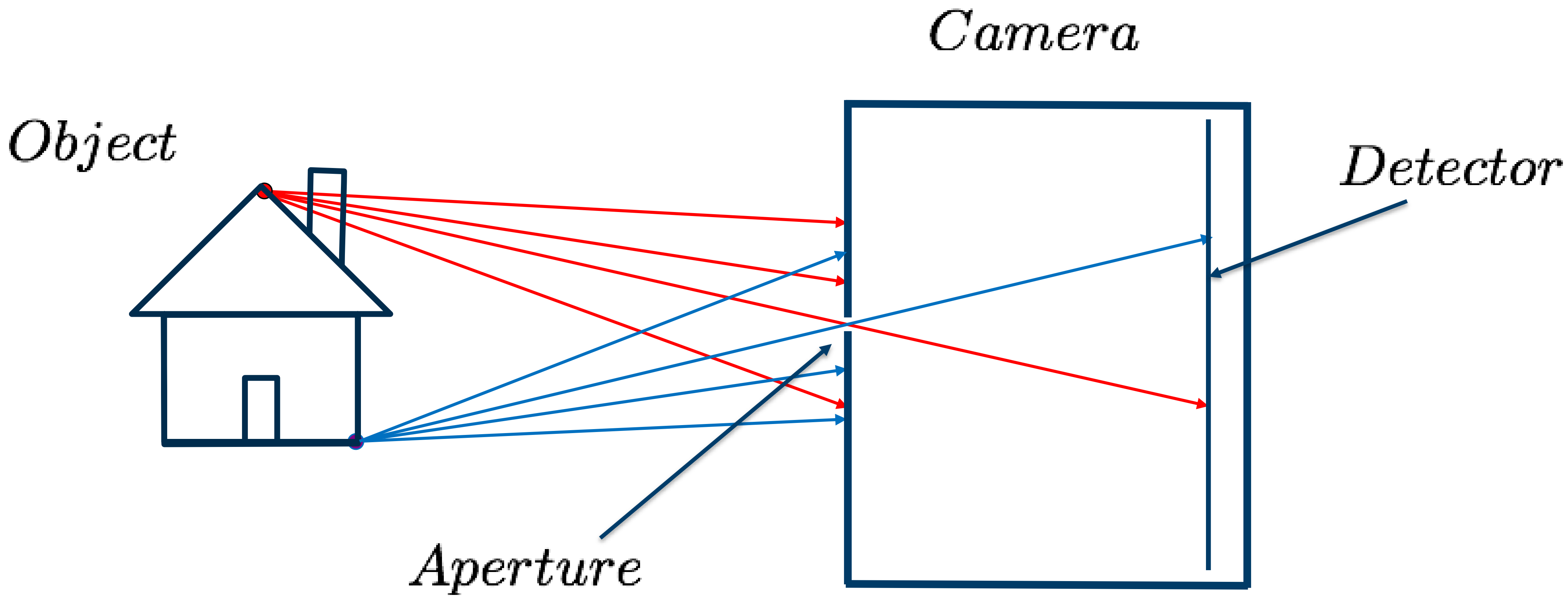


Image formation

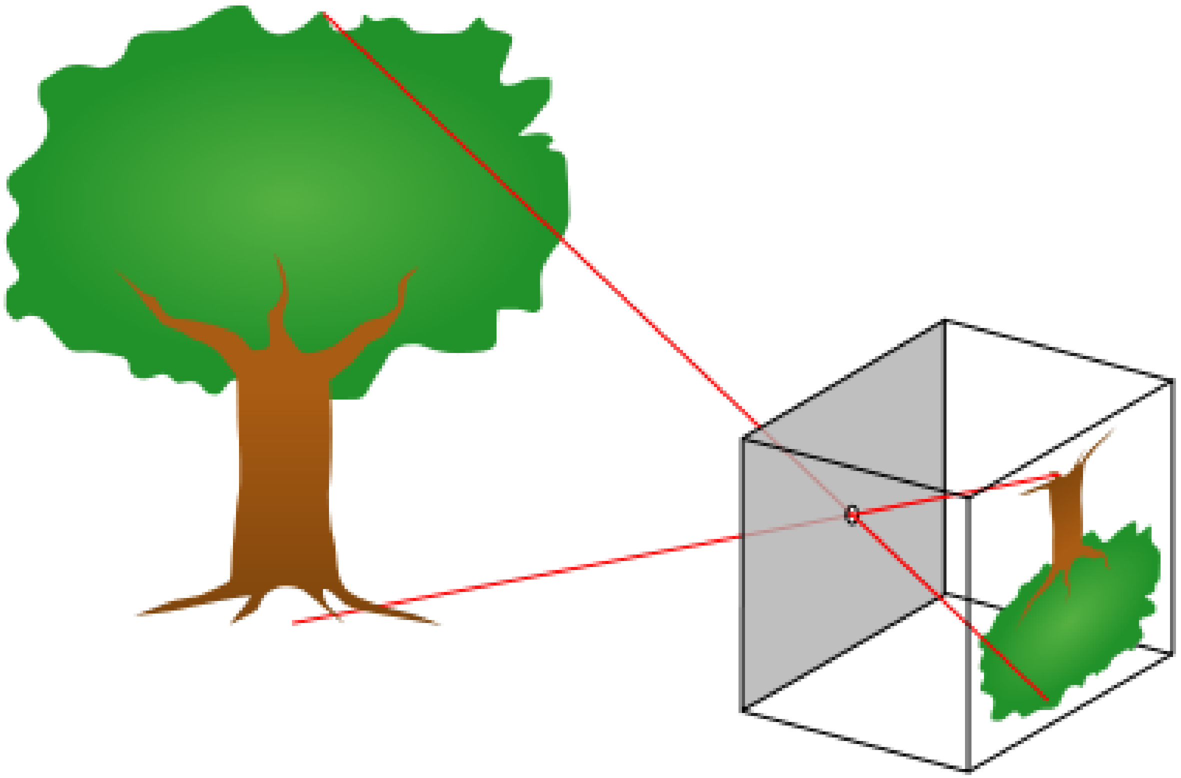


No image is formed!

Simple camera - Pinhole camera



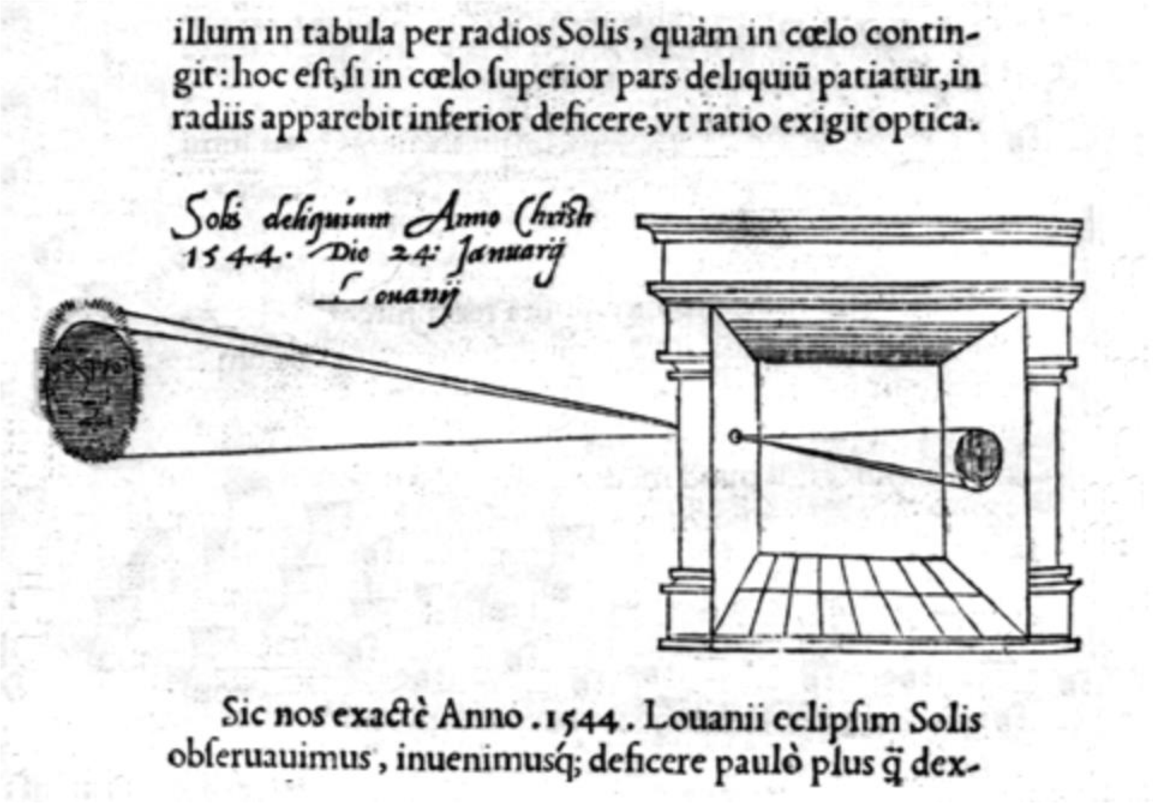
Pinhole camera



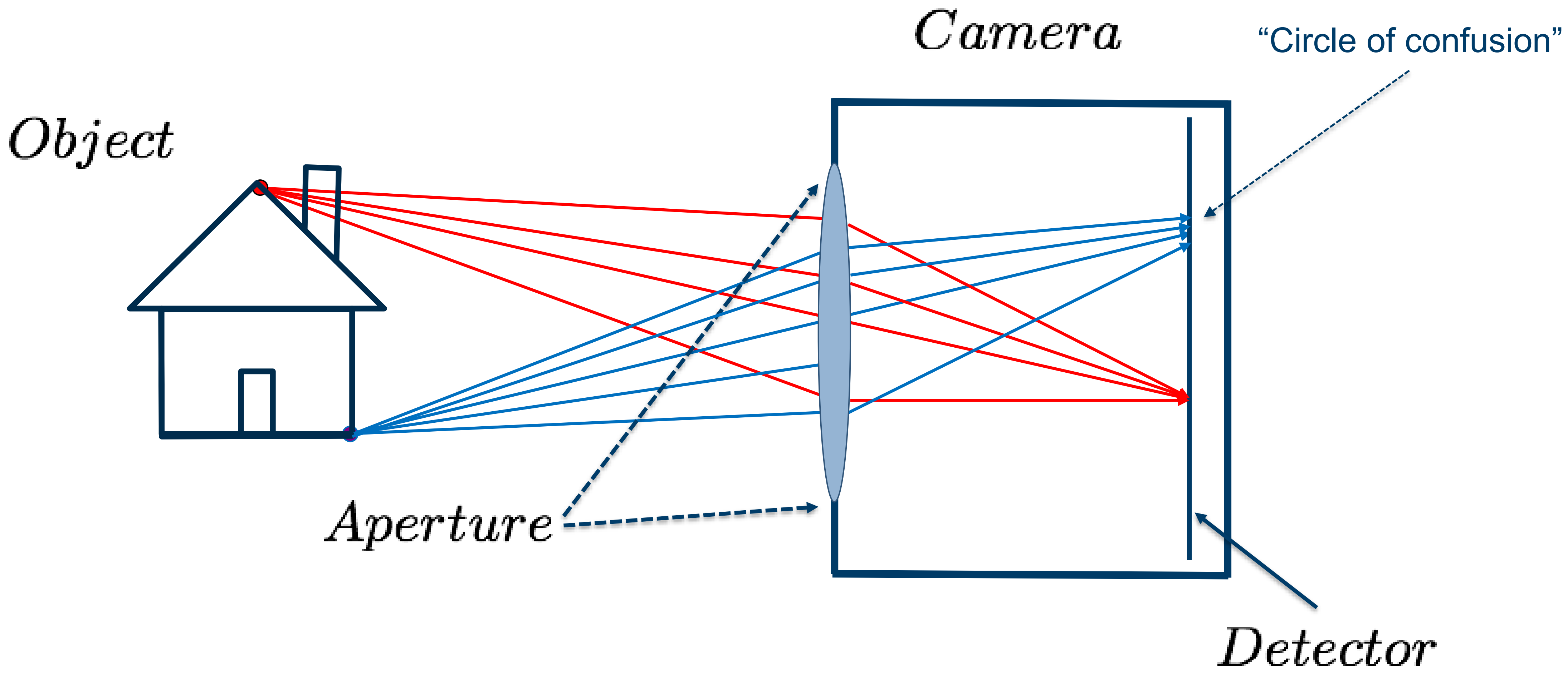
Small aperture → Dark image

Large aperture → Image out of focus

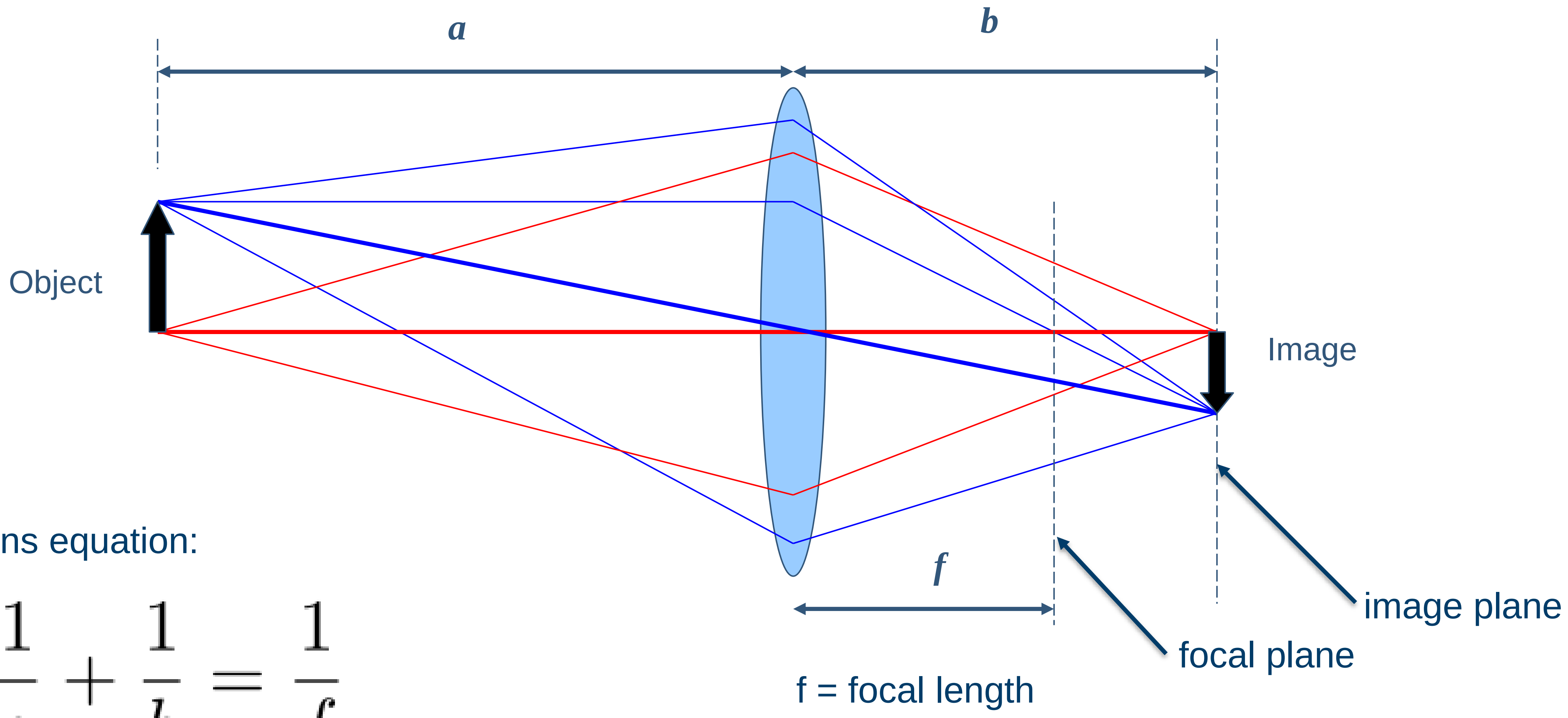
Camera obscura



Camera with a lens



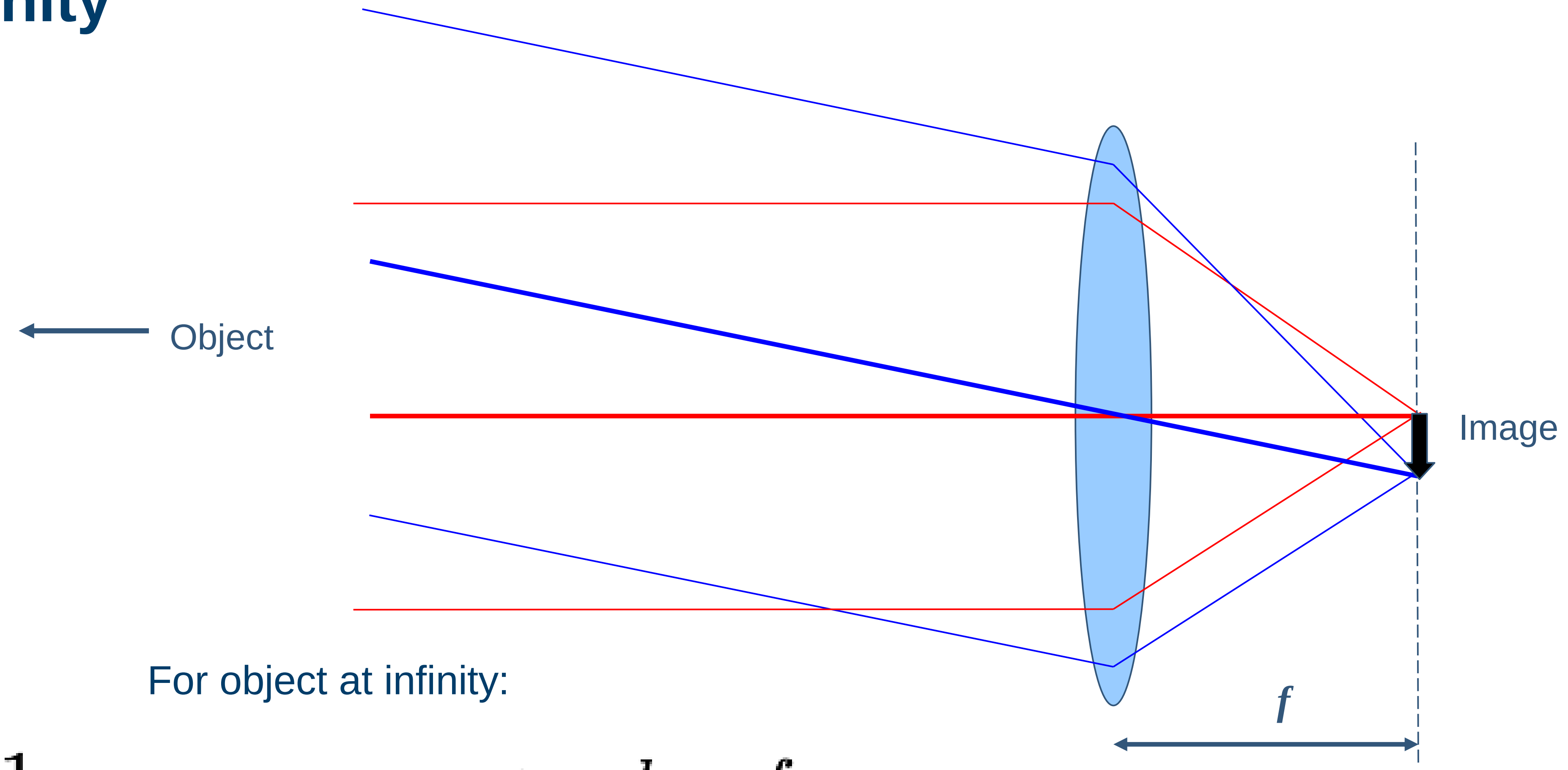
Imaging with a lens



Lens equation:

$$\frac{1}{a} + \frac{1}{b} = \frac{1}{f}$$

Object at infinity



Lens equation:

$$\frac{1}{a} + \frac{1}{b} = \frac{1}{f}$$

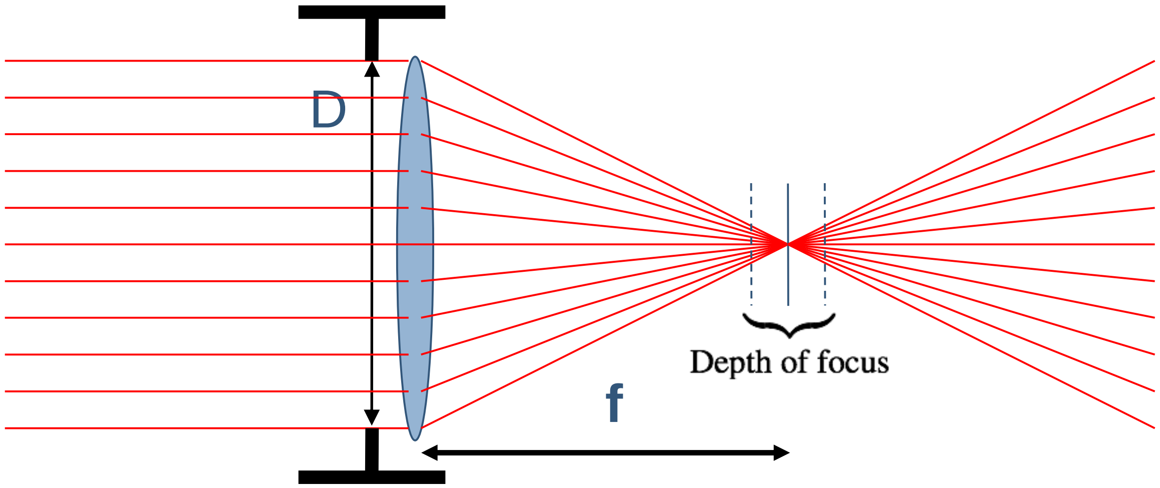
For object at infinity:

$$a = \infty \quad \Rightarrow \quad b = f$$

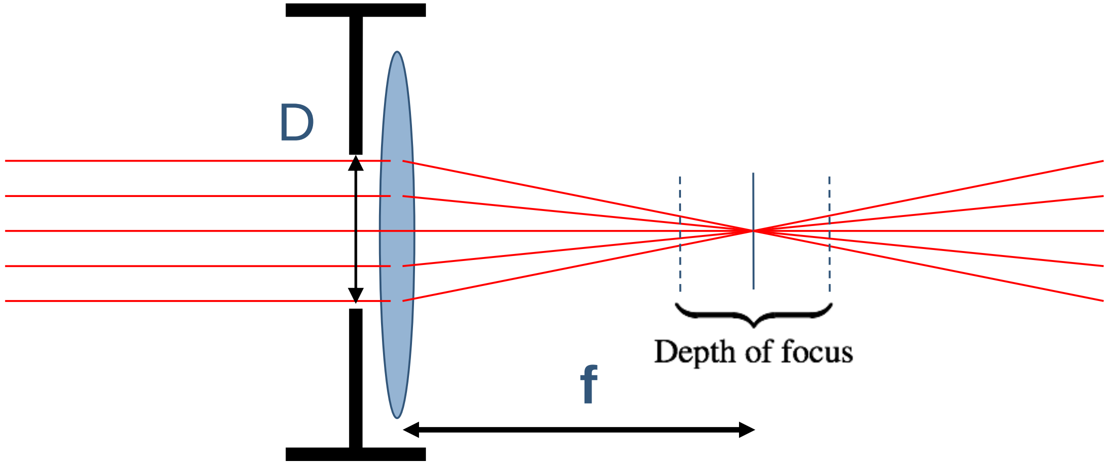
i.e. image is formed in focal plane.

Depth of focus

Large aperture



Small aperture

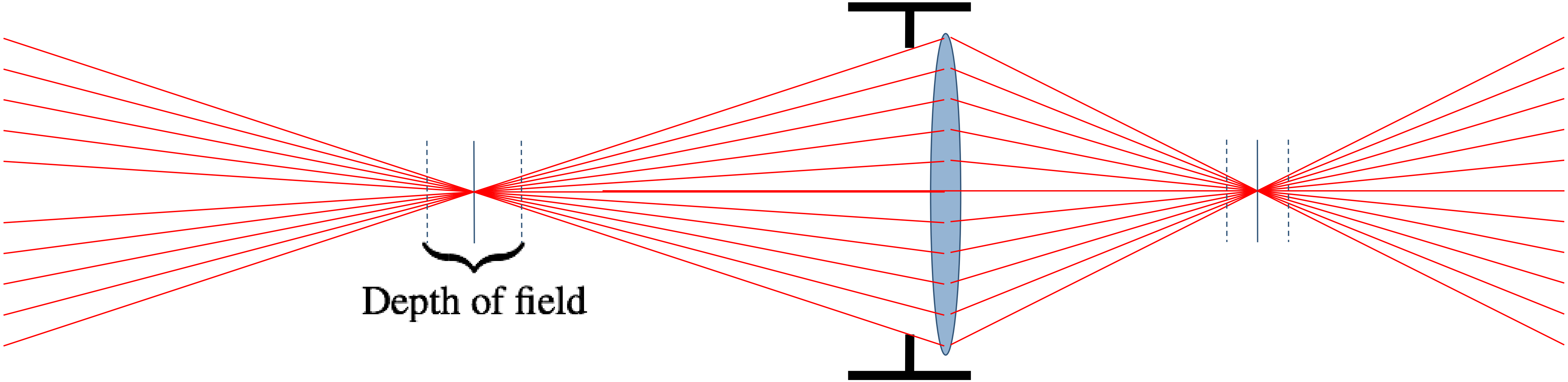


F-number: f/D (examples: f/2.8, f/4, f/5.6, f/8, f/11, f/22)

Small f-number → Narrow depth of focus

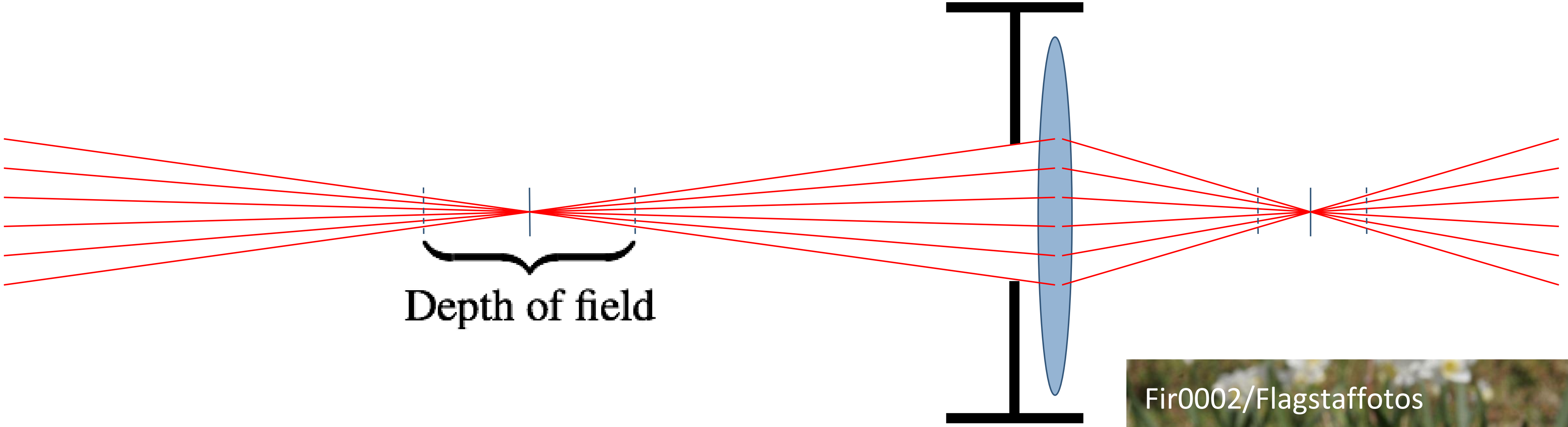
Large f-number → Large depth of focus

Depth of field – large aperture



Large aperture → Narrow depth of field

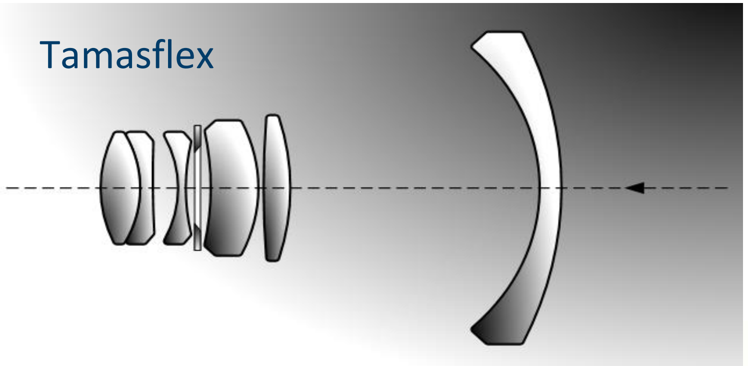
Depth of field – small aperture



Small aperture → Large depth of field

Too small aperture will lead to *diffraction* and loss of sharpness

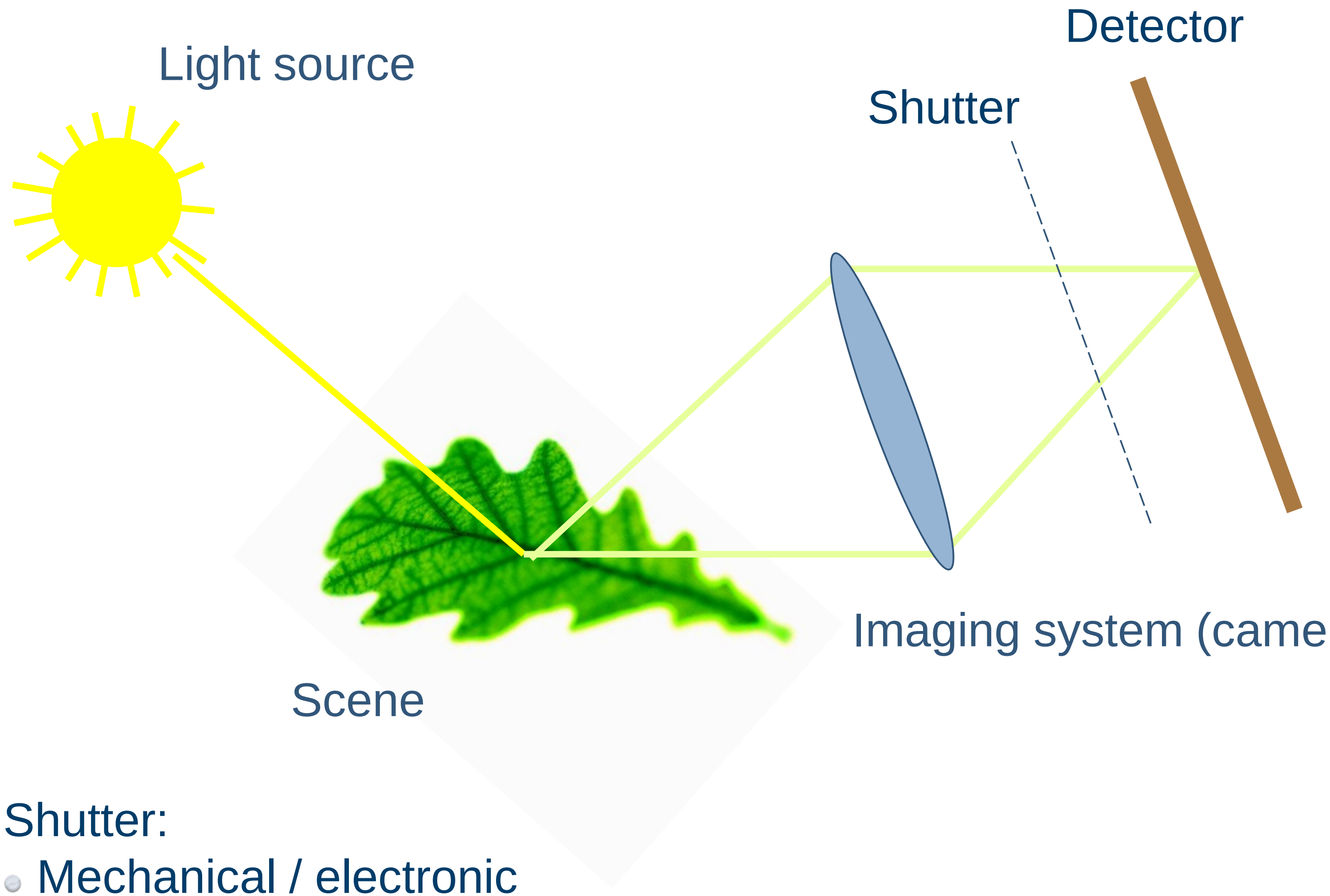
Practical lenses

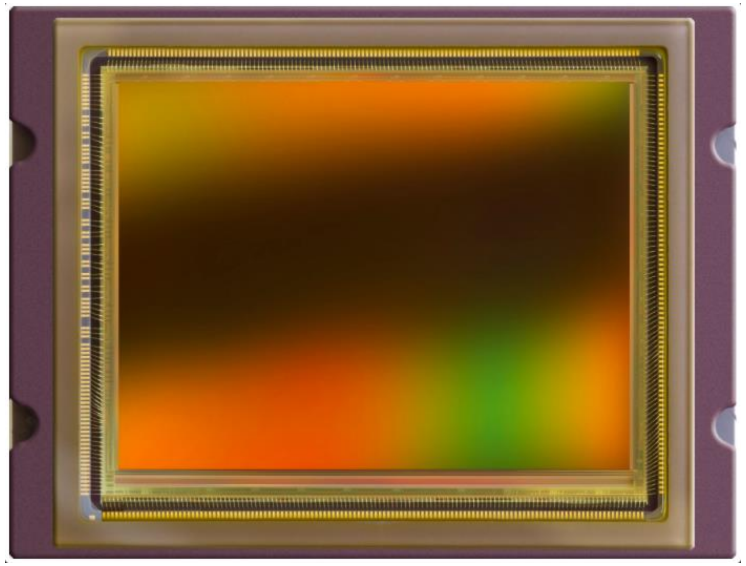


Fixed focal length lens

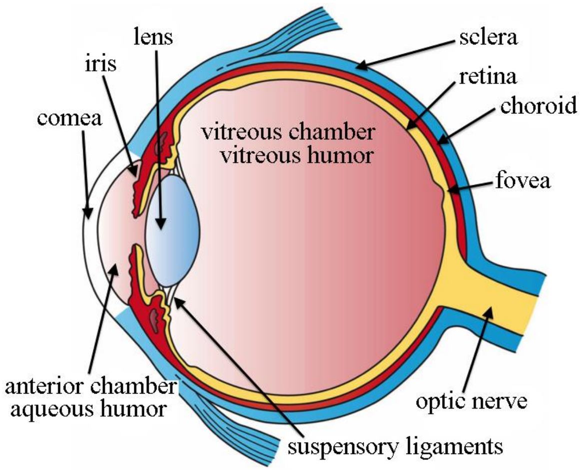
Zoom lens (variable focal length)

Image capture





CMOS image sensor (CMOSIS 48Mp)



Shutter:

- Mechanical / electronic
- Global / rolling

Digital image

$j \rightarrow$

$i \downarrow$

255	255	255	255	255	255	255	255	255	255
255	255	255	255	255	255	255	255	255	255
255	255	255	0	0	255	255	255	255	255
255	255	255	0	0	85	255	255	255	255
255	255	0	85	85	0	255	255	255	255
255	255	0	85	85	170	170	255	255	255
255	85	85	0	170	170	85	85	255	255
255	255	170	170	85	85	85	255	255	255
255	255	255	255	255	255	255	255	255	255
255	255	255	255	255	255	255	255	255	255

$$image(i, j)$$

Colour images

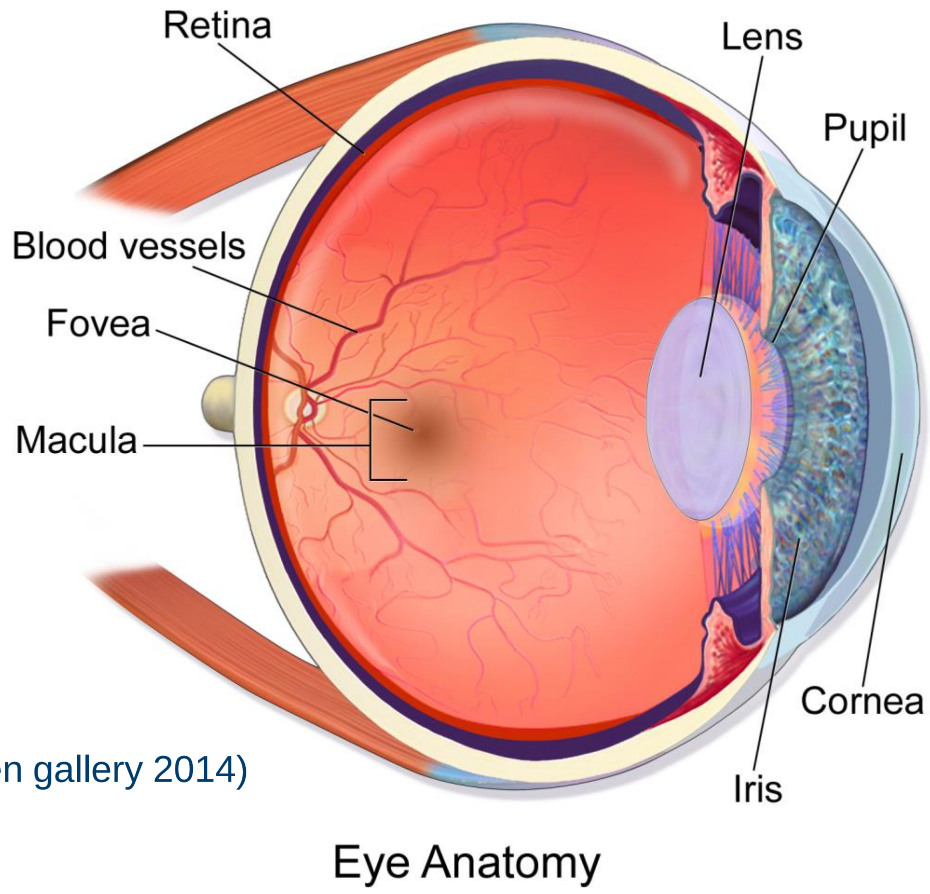
Red

Green

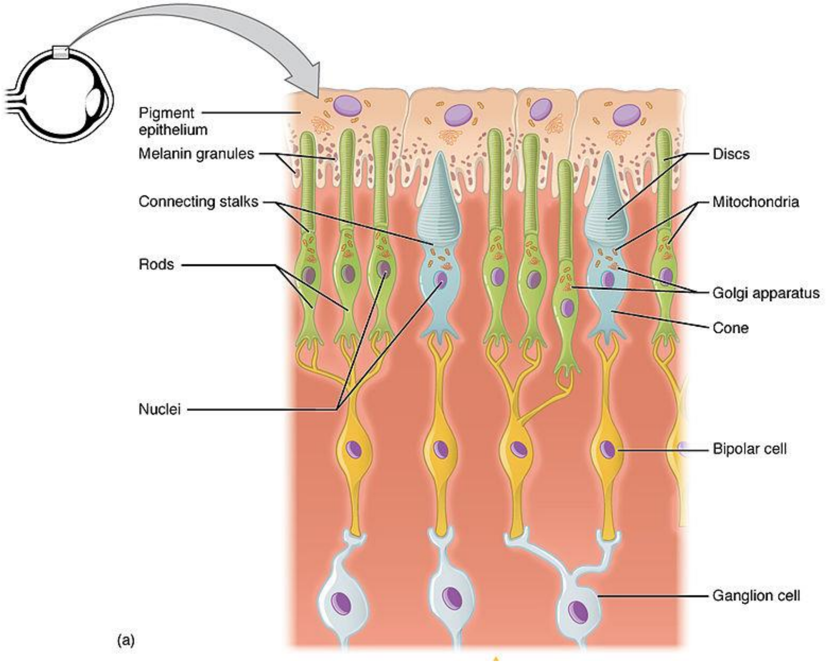
Blue

RGB colour image

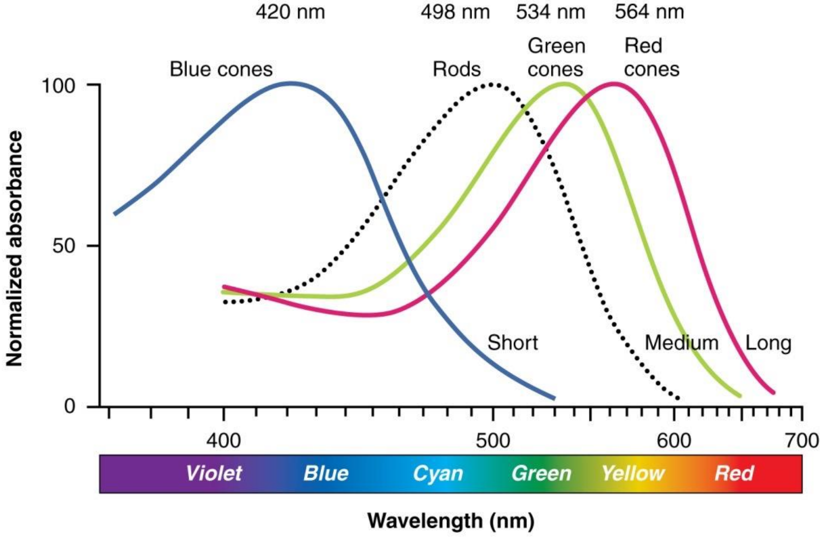
Human Vision



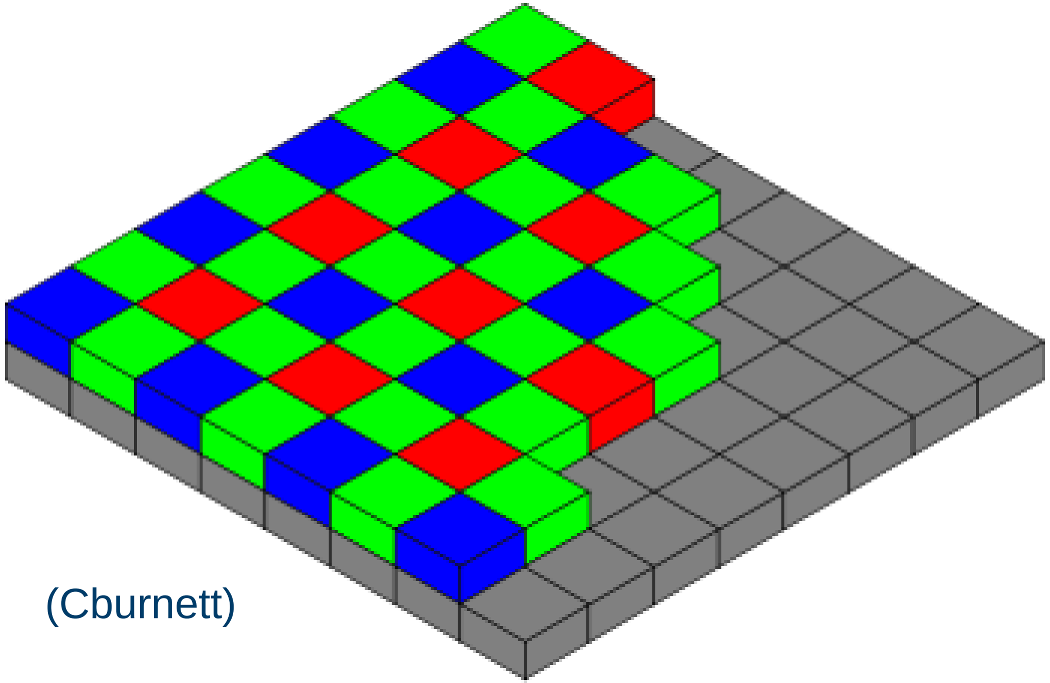
(Blausen gallery 2014)



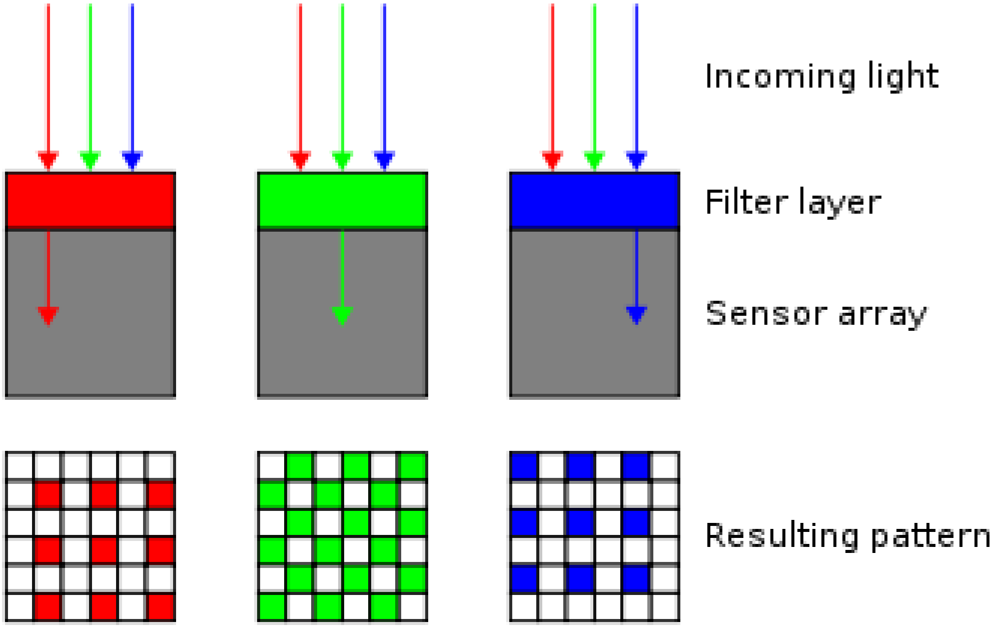
(OpenStax College - Anatomy & Physiology)



Colour Sensing in digital cameras - Bayer filter



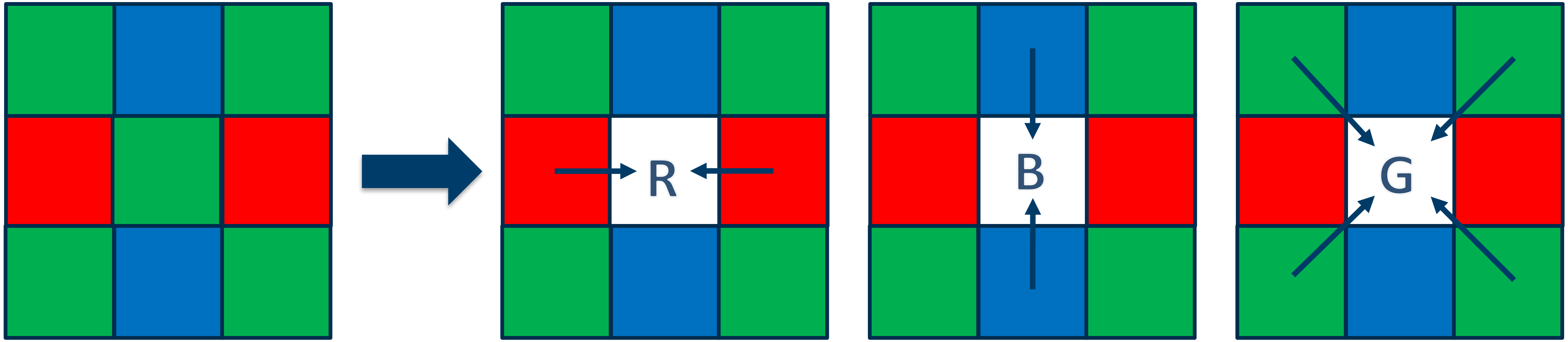
(Cburnett)



Undersampled (incomplete) colour information

Demosaicing (debayering)

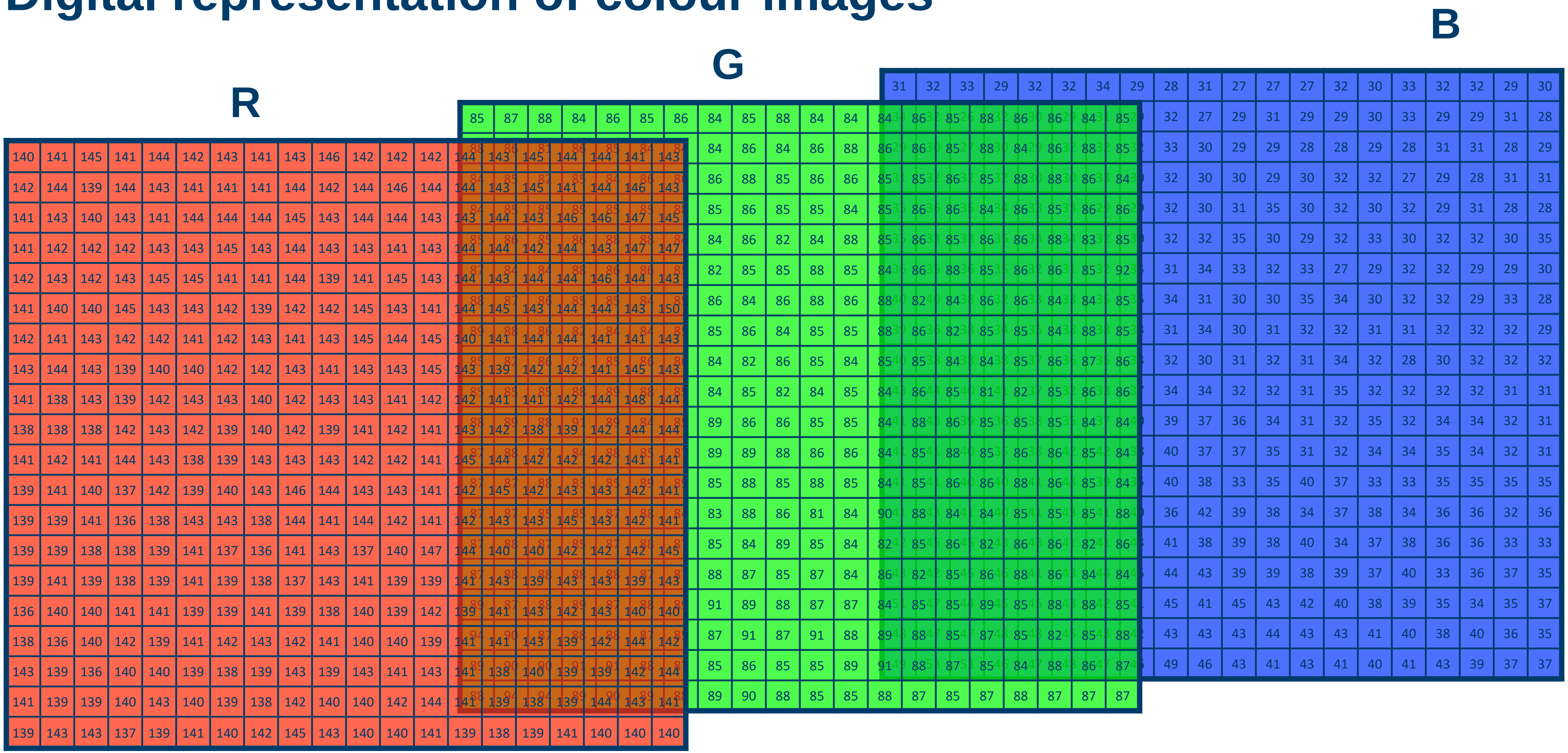
Reconstruction of full colour image from incomplete colour information from the image sensor.



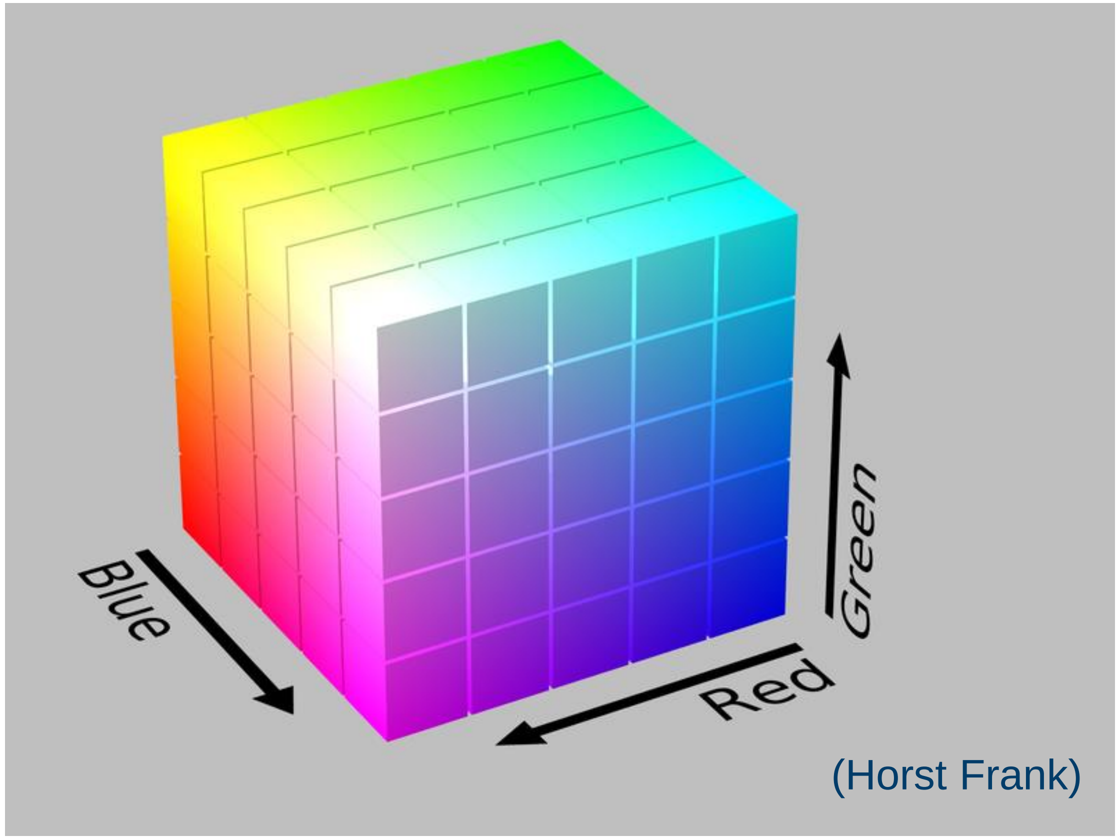
Algorithms:
- Nearest-neighbor interpolation
- Bilinear interpolation
- Bicubic interpolation

Other methods:
- Splines
- Lanczos resampling
- Methods utilizing pixel values

Digital representation of colour images



RGB colour space



Normalized RGB values:

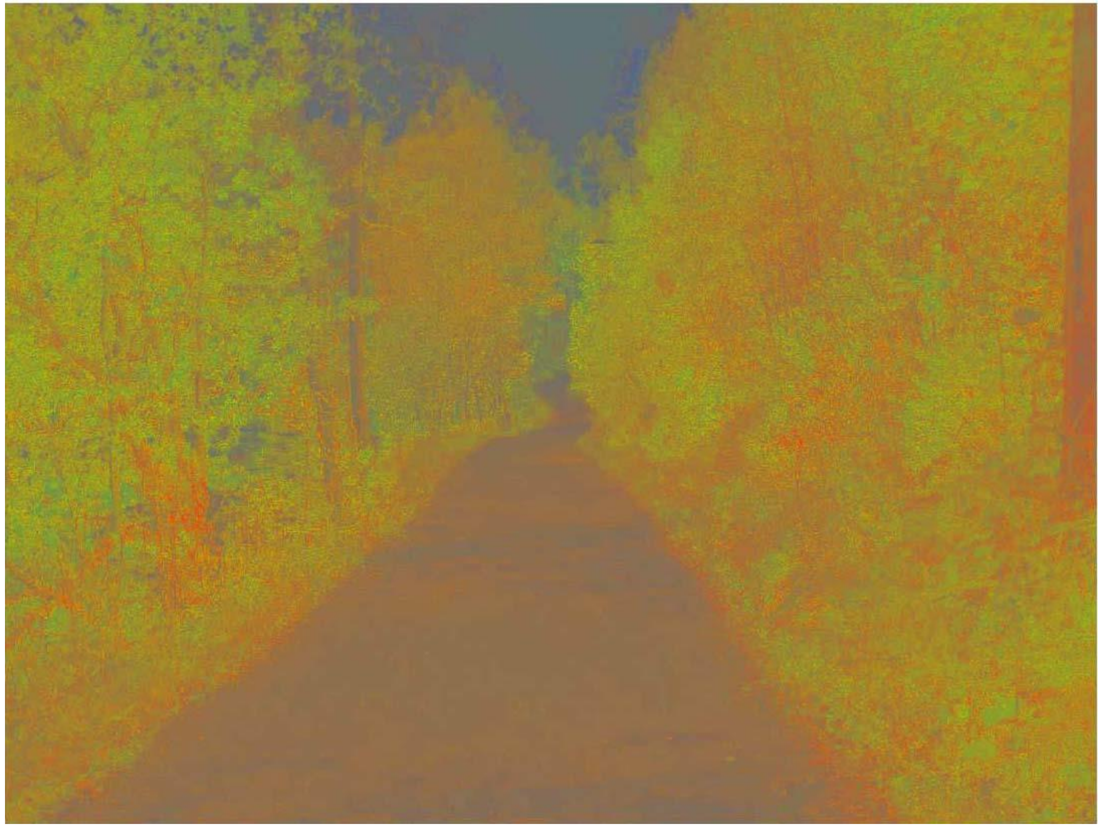
$$r = \frac{R}{R+G+B}$$
$$g = \frac{G}{R+G+B}$$
$$b = \frac{B}{R+G+B}$$

(Illumination invariance)

Colour coordinate systems: $RGB \Rightarrow XYZ \Rightarrow LAB$

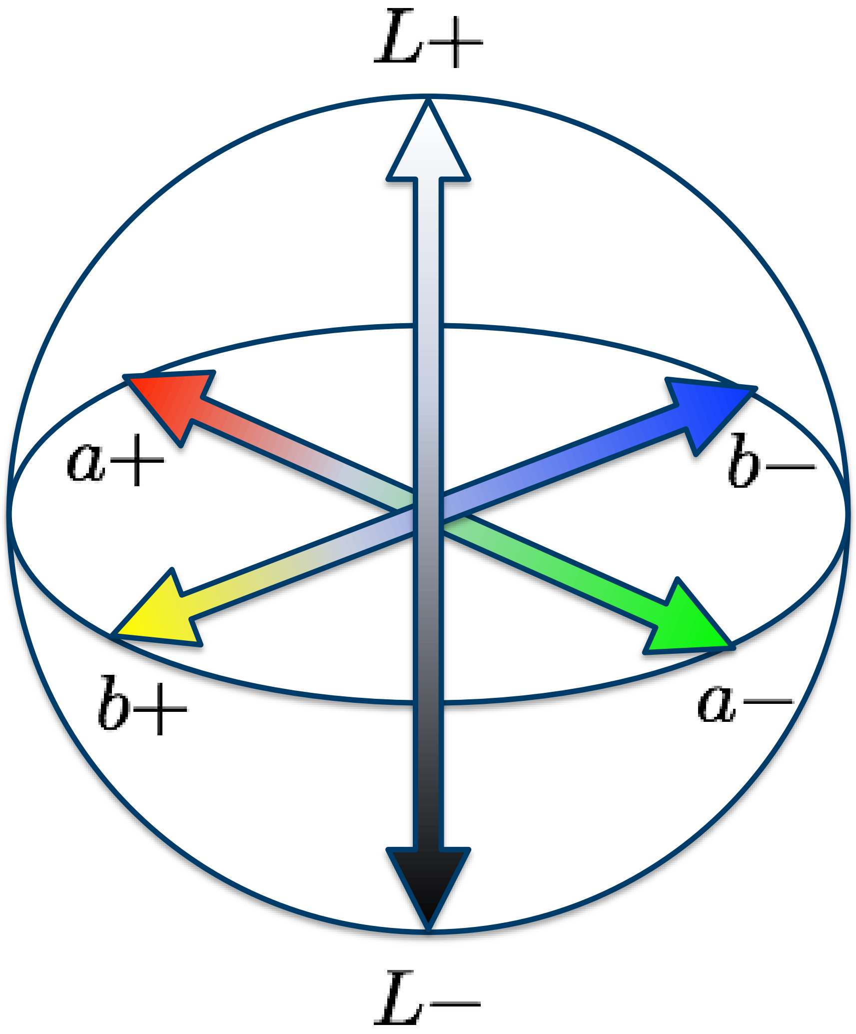
RGB normalization (example)

RGB original



Normalized RGB

Lab colour space (CIE 1976 L* a* b*)



«Perceptually uniform» colour space:

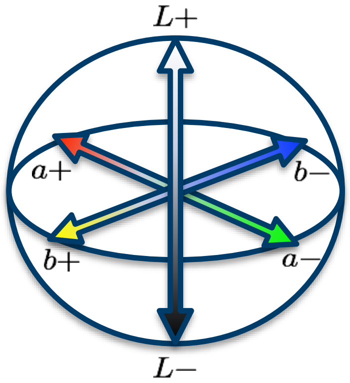
- Approximation to human vision
- L* = Lightness
- a*, b* = Colour opponent dimensions

- L* = darkest black to brightest white (0 - 100)
- a* = green to red (-100 to +100)
- b* = blue to yellow (-100 to +100)

Lab - example

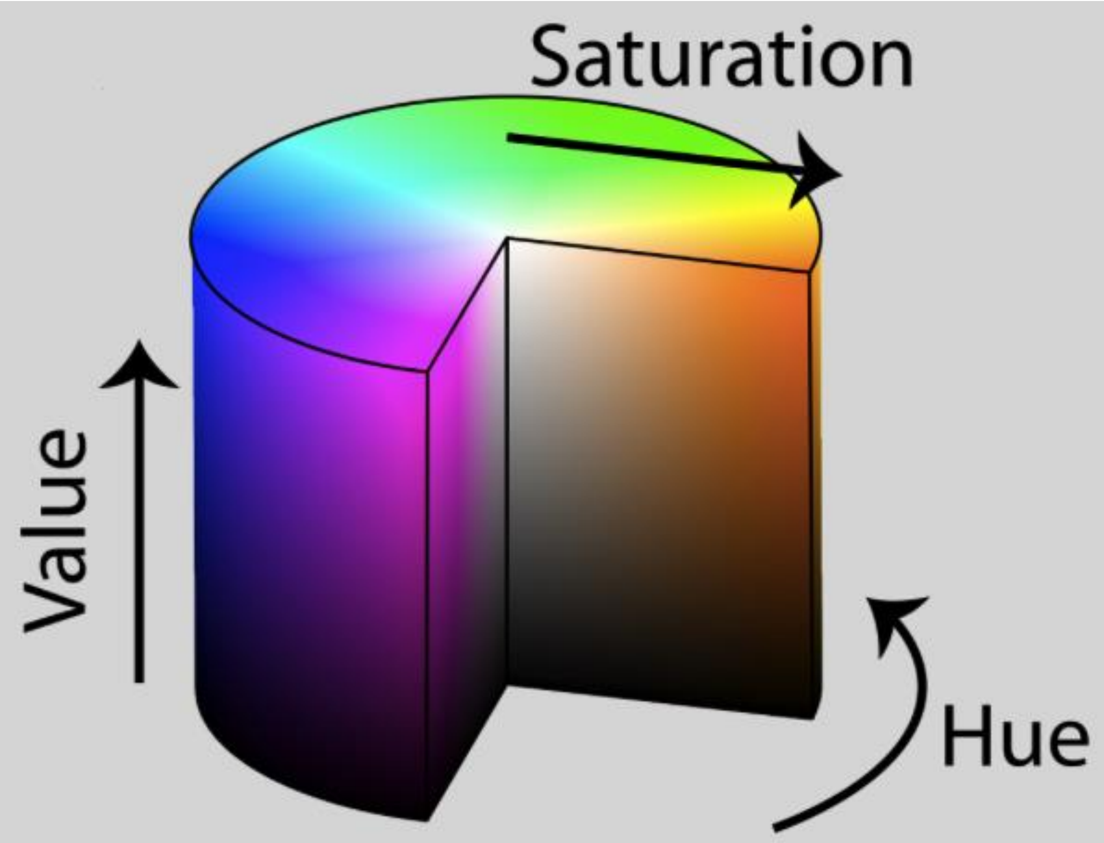
L

a



b

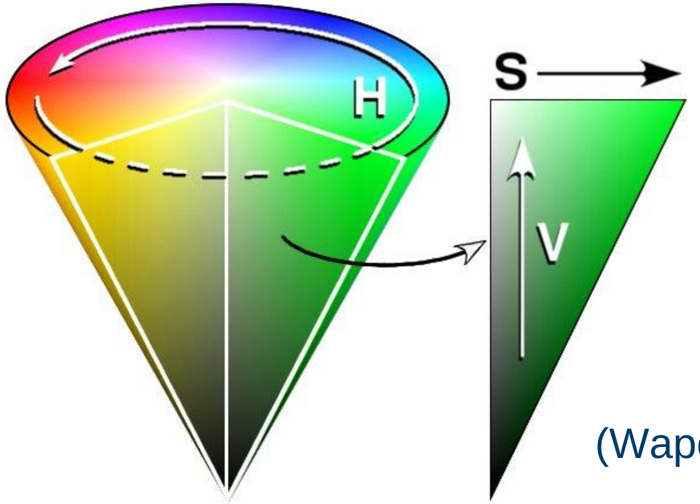
HSV colour space (Hue, Saturation, Value)



(Jacob Rus, 2010)

Intuitive colour space:

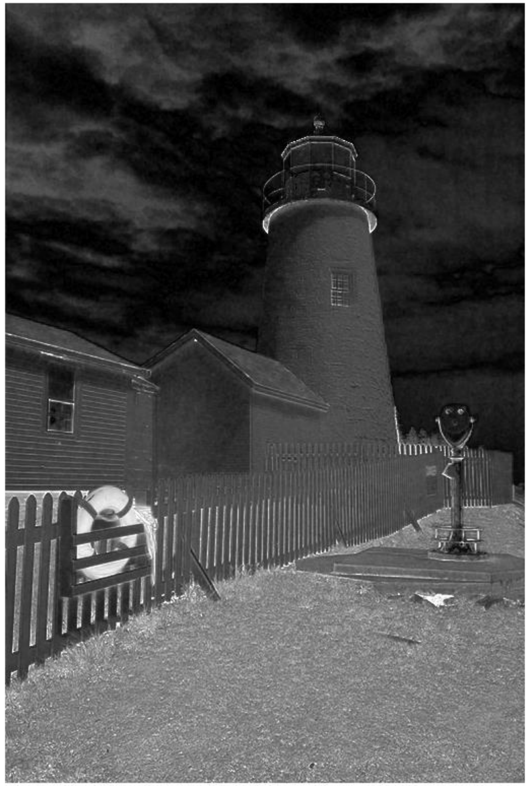
- Cylindrical representation of RGB values
- Hue = angle from 0º to 360º
- Saturation = 0 - 100% (gray to primary colour)
- Value = 0 - 100% (totally black to bright colours)



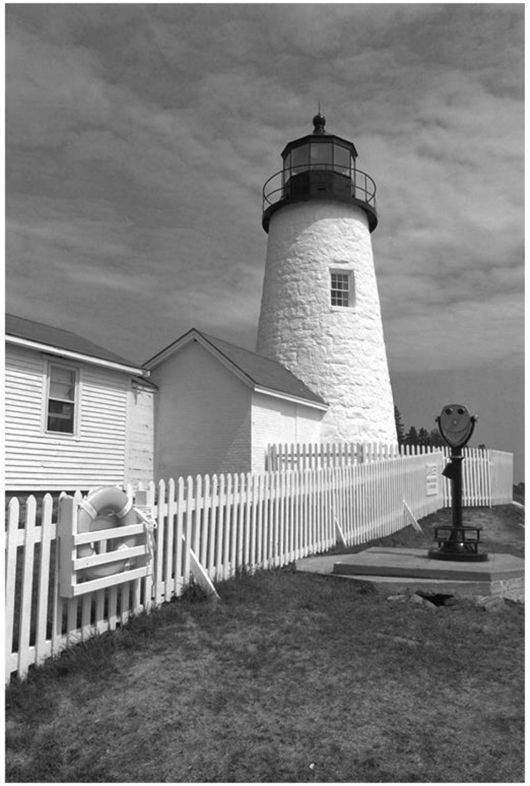
(Wapcaplet)

HSV

Hue



Saturation



Value

Summary

Image formation:

- Illumination
- Cameras
- Optics
- Image Capture
- Colour Sensing.

More information: Szeliski 2.2 and 2.3