

Contributions		Non-local Kalman		Experiments																																																																																																													
<div>We suggest a video denoising pipeline with the following advantages:</div> <ul style="list-style-type: none"><li>Particularly suited for real-time processing</li><li>Produces temporally consistent videos, which are much better visually</li><li>Competitive with current state-of-the-art denoising methods</li></ul>		<div><i>Patch trajectories</i></div> <div><i>Spatial denoising</i></div> <div><i>Temporal filtering</i></div> <div><math display="block">\mathbf{p}_{t+1,i} = \mathbf{p}_{t,i} + \mathbf{w}_{t,i} \text{ with } \mathbf{w}_{t,i} \sim \mathcal{N}(\mathbf{0}, \mathbf{C}_t)</math><math display="block">\mathbf{q}_{t,i} = \mathbf{p}_{t,i} + \mathbf{n}_{t,i} \text{ with } \mathbf{n}_{t,i} \sim \mathcal{N}(\mathbf{0}, \sigma^2 \mathbf{I}).</math></div>		<div><i>Quantitative evaluation</i></div> <div>Our algorithm is compared against VBM3D and VBM4D, two current state-of-the-art methods</div> <table><tr><th><math>\sigma</math></th><th>Method</th><th>Bus</th><th>Foreman</th><th>Pedestrian_area</th><th>Crowd_run</th><th>Touchdown_pass</th><th>Station2</th><th>Average</th></tr><tr><td rowspan="4">10</td><td>VBM3D</td><td>33.32/.7824</td><td>37.40/.6681</td><td>40.78/.6577</td><td>35.62/.8017</td><td>39.08/.6103</td><td>38.92/.7266</td><td>37.52/.7078</td></tr><tr><td>VBM4D</td><td>33.39/.8237</td><td>37.39/.6871</td><td>40.56/.7463</td><td>35.69/.8457</td><td>39.60/.6752</td><td>39.93/.7746</td><td>37.76/.7588</td></tr><tr><td>NL-Kalman</td><td>33.34/.8502</td><td>36.16/.6782</td><td>38.67/.7420</td><td>34.29/.8383</td><td>38.82/.6940</td><td>39.91/.7916</td><td>36.86/.7657</td></tr><tr><td><i>NL-Kalman (oracle)</i></td><td><i>33.87/.8713</i></td><td><i>36.93/.7230</i></td><td><i>39.23/.7592</i></td><td><i>34.64/.8514</i></td><td><i>39.58/.7433</i></td><td><i>40.50/.8059</i></td><td><i>37.46/.7923</i></td></tr><tr><td rowspan="4">20</td><td>VBM3D</td><td>29.57/.6064</td><td>34.60/.5763</td><td>36.93/.5579</td><td>32.22/.7122</td><td>36.09/.4703</td><td>35.45/.5689</td><td>34.14/.5820</td></tr><tr><td>VBM4D</td><td>29.55/.6856</td><td>34.61/.6073</td><td>36.75/.6468</td><td>32.07/.7439</td><td>36.41/.4795</td><td>36.23/.6395</td><td>34.27/.6338</td></tr><tr><td>NL-Kalman</td><td>29.58/.7291</td><td>33.19/.5844</td><td>35.61/.6444</td><td>30.89/.7478</td><td>35.91/.5181</td><td>36.81/.6868</td><td>33.66/.6518</td></tr><tr><td><i>NL-Kalman (oracle)</i></td><td><i>30.43/.7752</i></td><td><i>34.18/.6301</i></td><td><i>36.45/.6738</i></td><td><i>31.44/.7746</i></td><td><i>36.99/.6135</i></td><td><i>37.46/.7116</i></td><td><i>34.49/.6965</i></td></tr><tr><td rowspan="4">30</td><td>VBM3D</td><td>27.59/.4995</td><td>32.77/.5224</td><td>34.44/.4869</td><td>30.14/.6394</td><td>34.55/.3906</td><td>33.36/.4536</td><td>32.14/.4987</td></tr><tr><td>VBM4D</td><td>27.53/.5988</td><td>32.91/.5612</td><td>34.45/.5745</td><td>29.95/.6704</td><td>34.76/.3801</td><td>34.14/.5420</td><td>32.29/.5545</td></tr><tr><td>NL-Kalman</td><td>27.30/.6327</td><td>31.27/.5335</td><td>33.27/.5680</td><td>28.64/.6708</td><td>33.91/.4034</td><td>34.73/.5986</td><td>31.52/.5678</td></tr><tr><td><i>NL-Kalman (oracle)</i></td><td><i>28.48/.6993</i></td><td><i>32.50/.5802</i></td><td><i>34.43/.6102</i></td><td><i>29.44/.7078</i></td><td><i>35.20/.5186</i></td><td><i>35.46/.6338</i></td><td><i>32.59/.6250</i></td></tr></table> <div><i>Qualitative evaluation</i></div> <div>Remarks</div> <div>References</div> <div><div>[1] Barnes et al. "PatchMatch: a randomized correspondence algorithm for structural image editing". <i>ACM Transactions on Graphics-TOG</i>, 2009.</div><div>[2] Korman and Avidan "Coherency sensitive hashing". <i>IEEE ICCV</i>, 2011.</div><div>[3] Arias et al. "Analysis of a variational framework for exemplar-based image inpainting". <i>SIAM</i>, 2012.</div><div>[4] Kaiming and Sun "Computing Nearest-Neighbor Fields via Propagation-Assisted KD-trees". <i>IEEE CVPR</i>, 2012.</div></div>		$\sigma$	Method	Bus	Foreman	Pedestrian_area	Crowd_run	Touchdown_pass	Station2	Average	10	VBM3D	33.32/.7824	37.40/.6681	40.78/.6577	35.62/.8017	39.08/.6103	38.92/.7266	37.52/.7078	VBM4D	33.39/.8237	37.39/.6871	40.56/.7463	35.69/.8457	39.60/.6752	39.93/.7746	37.76/.7588	NL-Kalman	33.34/.8502	36.16/.6782	38.67/.7420	34.29/.8383	38.82/.6940	39.91/.7916	36.86/.7657	<i>NL-Kalman (oracle)</i>	<i>33.87/.8713</i>	<i>36.93/.7230</i>	<i>39.23/.7592</i>	<i>34.64/.8514</i>	<i>39.58/.7433</i>	<i>40.50/.8059</i>	<i>37.46/.7923</i>	20	VBM3D	29.57/.6064	34.60/.5763	36.93/.5579	32.22/.7122	36.09/.4703	35.45/.5689	34.14/.5820	VBM4D	29.55/.6856	34.61/.6073	36.75/.6468	32.07/.7439	36.41/.4795	36.23/.6395	34.27/.6338	NL-Kalman	29.58/.7291	33.19/.5844	35.61/.6444	30.89/.7478	35.91/.5181	36.81/.6868	33.66/.6518	<i>NL-Kalman (oracle)</i>	<i>30.43/.7752</i>	<i>34.18/.6301</i>	<i>36.45/.6738</i>	<i>31.44/.7746</i>	<i>36.99/.6135</i>	<i>37.46/.7116</i>	<i>34.49/.6965</i>	30	VBM3D	27.59/.4995	32.77/.5224	34.44/.4869	30.14/.6394	34.55/.3906	33.36/.4536	32.14/.4987	VBM4D	27.53/.5988	32.91/.5612	34.45/.5745	29.95/.6704	34.76/.3801	34.14/.5420	32.29/.5545	NL-Kalman	27.30/.6327	31.27/.5335	33.27/.5680	28.64/.6708	33.91/.4034	34.73/.5986	31.52/.5678	<i>NL-Kalman (oracle)</i>	<i>28.48/.6993</i>	<i>32.50/.5802</i>	<i>34.43/.6102</i>	<i>29.44/.7078</i>	<i>35.20/.5186</i>	<i>35.46/.6338</i>	<i>32.59/.6250</i>
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