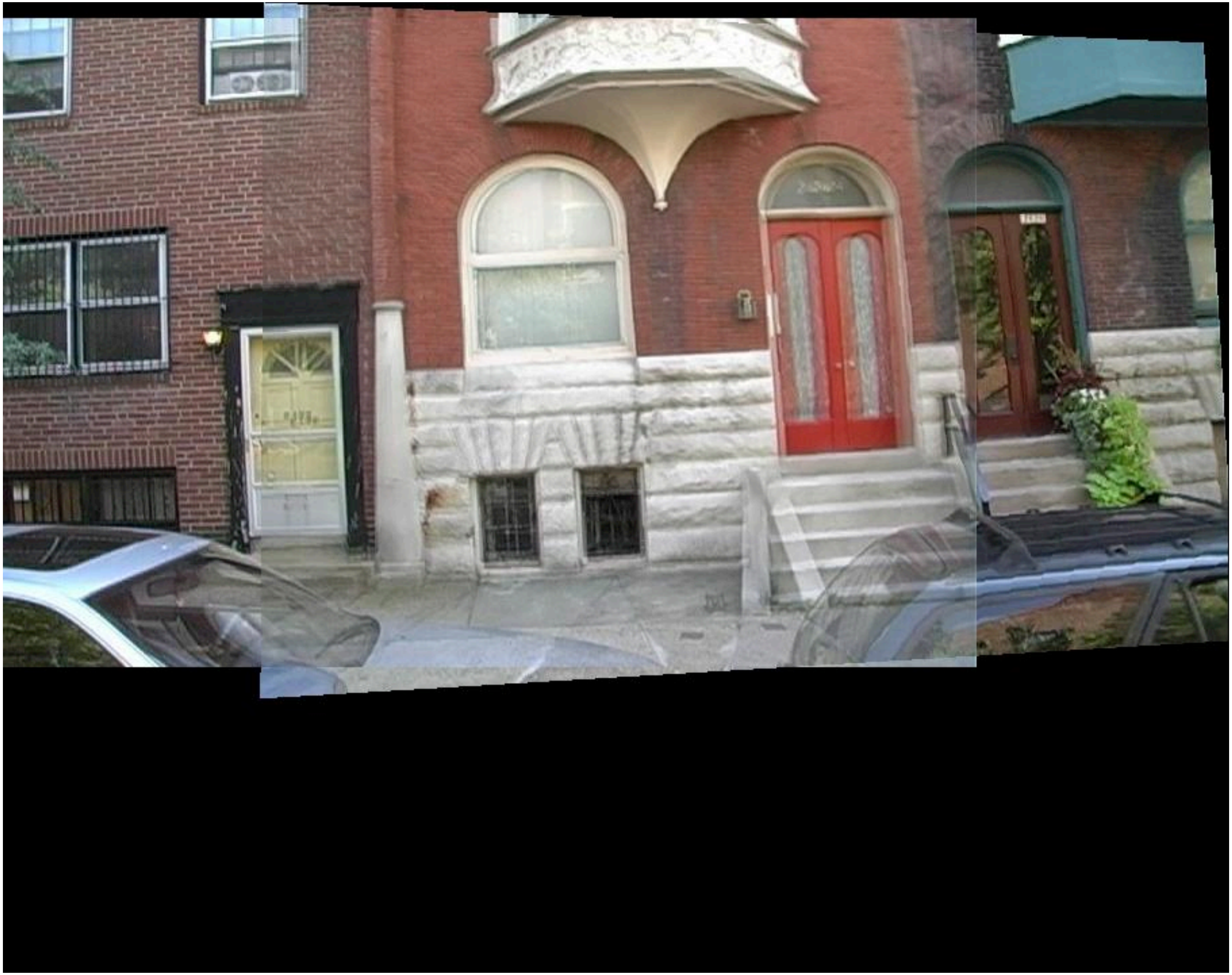
Image Warping

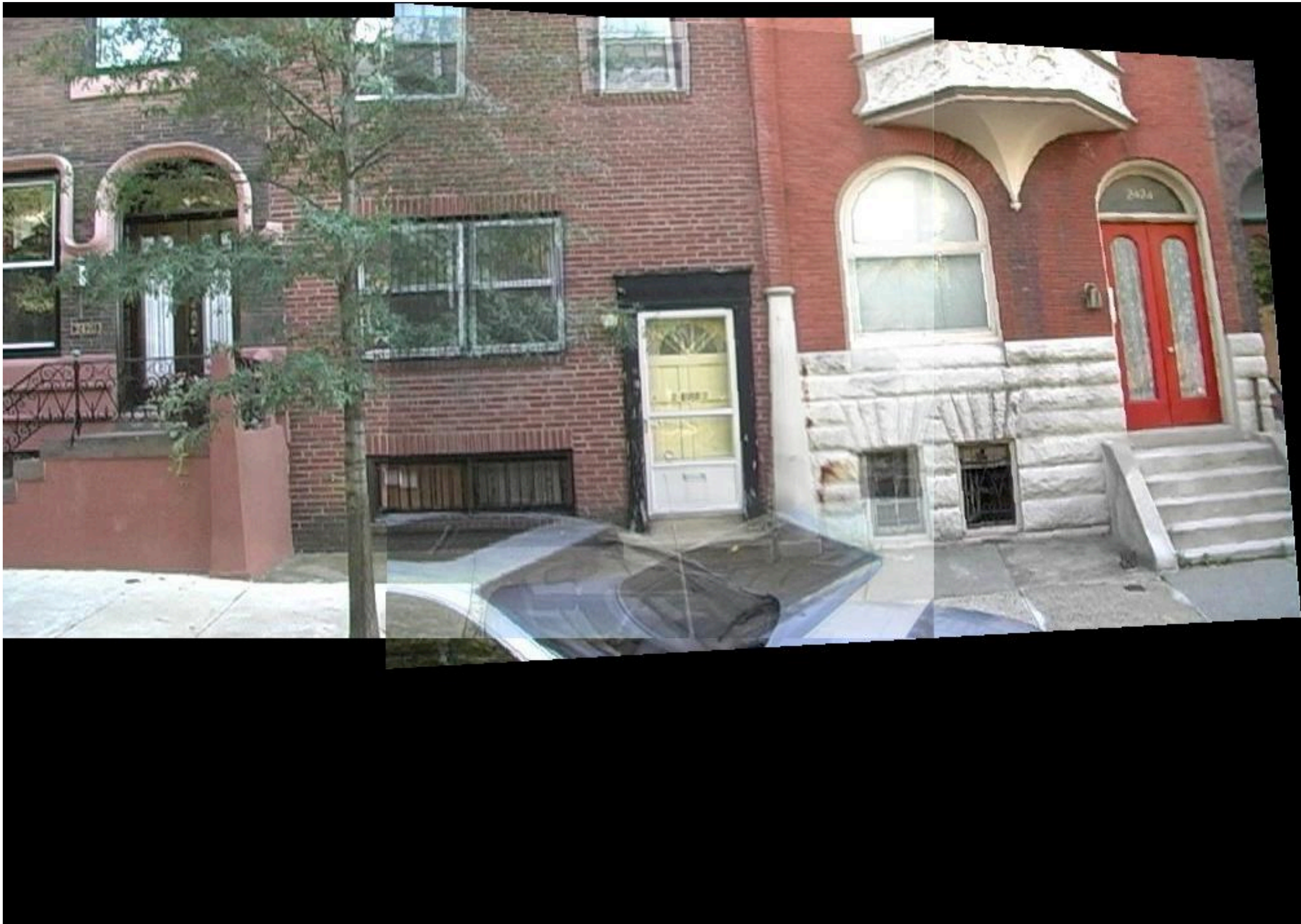
http://maps.a9.com

http://www.cs.ubc.ca/~mbrown/autostitch/autostitch.html

Autostiching on A9.com images,

Spruce street, Philadelphia





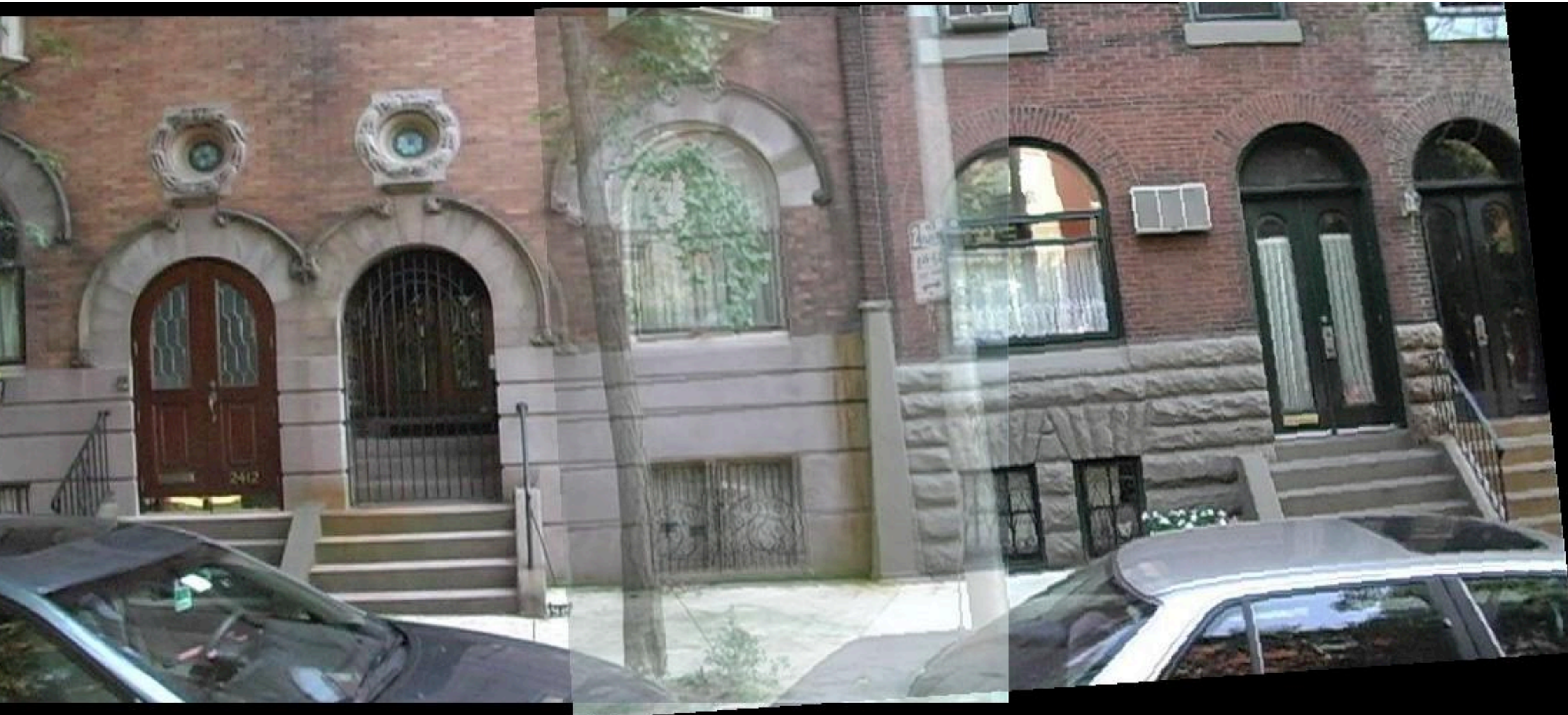

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Image Warping

Slides from 15-463: Computational Photography
Alexei Efros, CMU, Fall 2005

Some slides from Steve Seitz

Image Warping

image filtering: change ***range*** of image

$$g(x) = T(f(x))$$

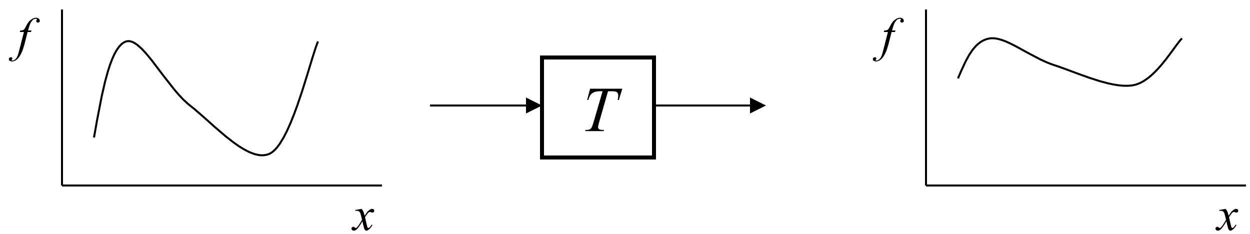


image warping: change ***domain*** of image

$$g(x) = f(T(x))$$

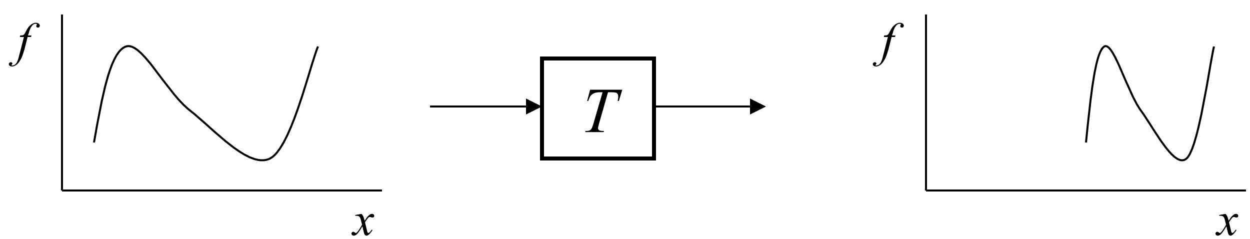


Image Warping

image filtering: change ***range*** of image

$$g(x) = T(f(x))$$

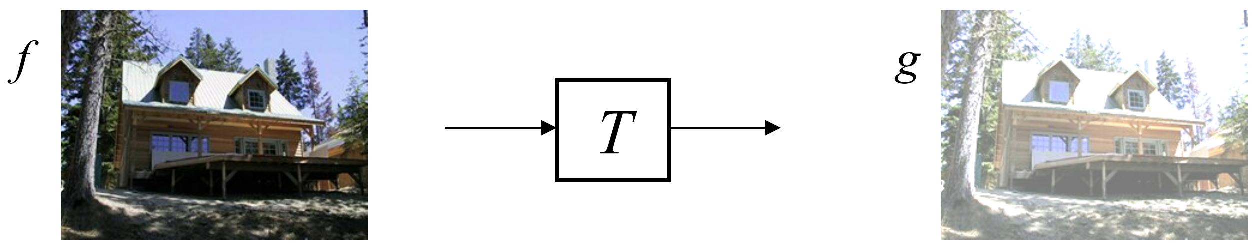
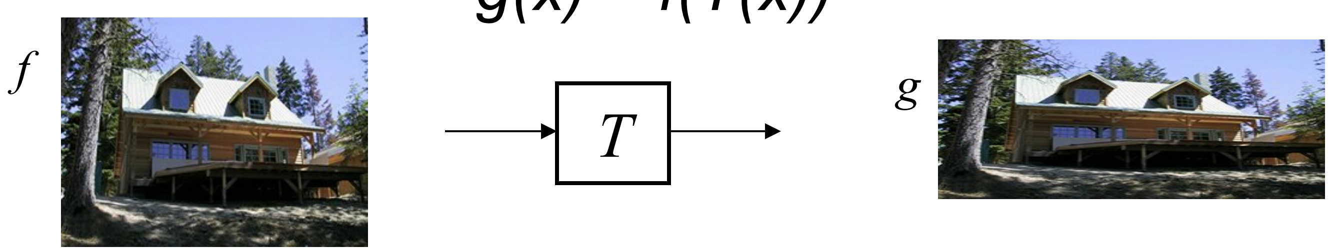


image warping: change ***domain*** of image

$$g(x) = f(T(x))$$



Parametric (global) warping

Examples of parametric warps:

translation

rotation

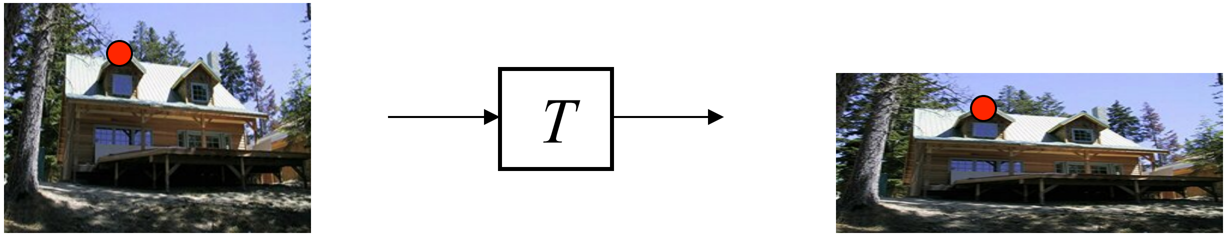
aspect

affine

perspective

cylindrical

Parametric (global) warping



$\mathbf{p} = (x,y)$ $\mathbf{p'} = (x',y')$

Transformation T is a coordinate-changing machine:

$$p' = T(p)$$

What does it mean that *T* is global?

- Is the same for any point p
- can be described by just a few numbers (parameters)

Let's represent *T* as a matrix:

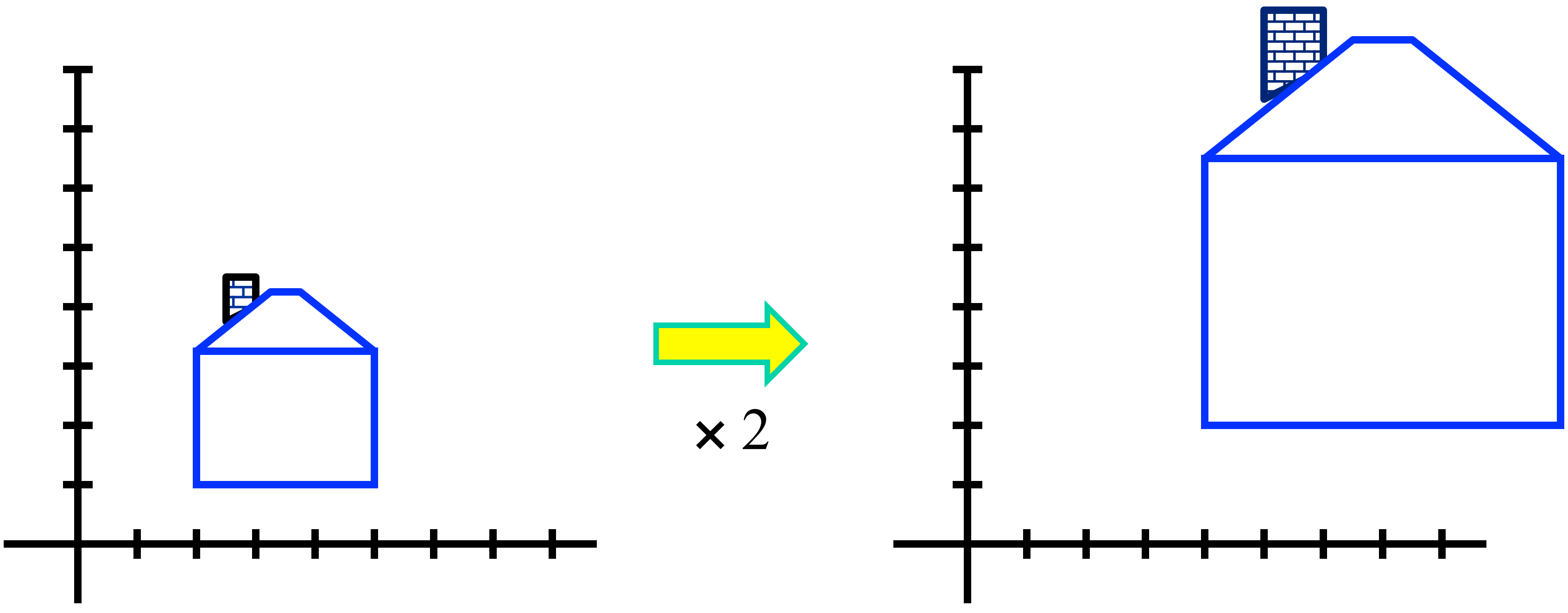
$$p' = \mathbf{M}^*p$$

$$\begin{bmatrix} x' \\ y' \end{bmatrix} = \mathbf{M} \begin{bmatrix} x \\ y \end{bmatrix}$$

Scaling

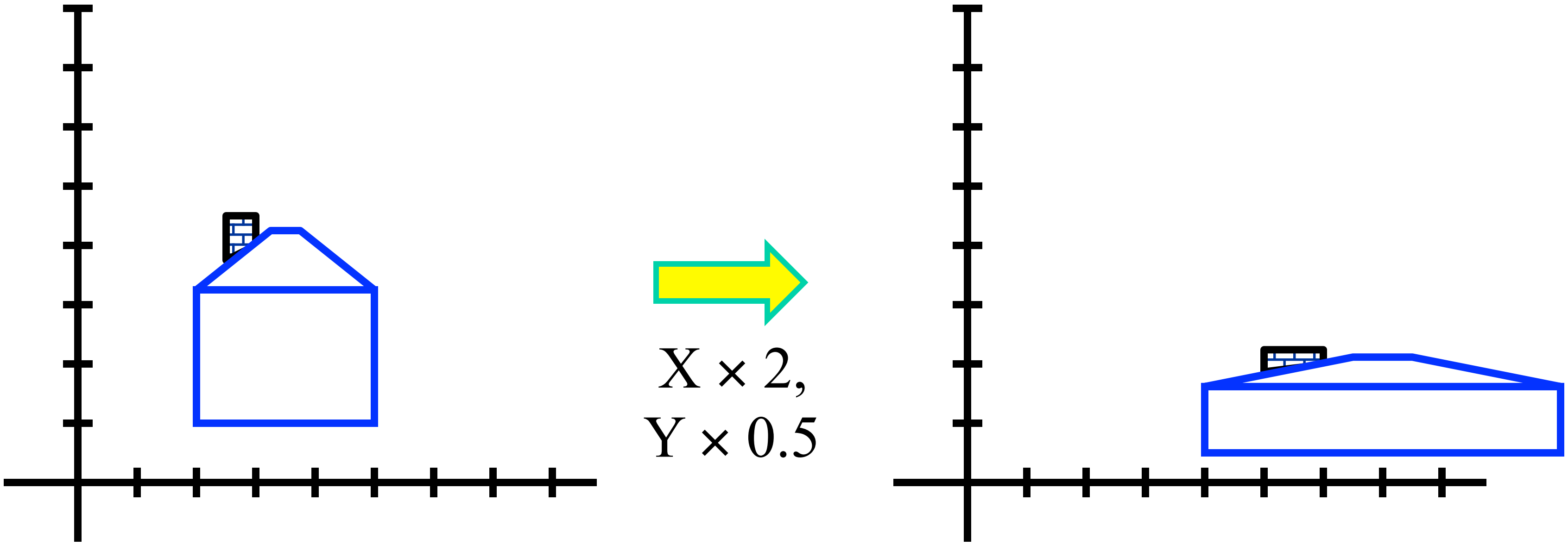
Scaling a coordinate means multiplying each of its components by a scalar

Uniform scaling means this scalar is the same for all components:



Scaling

Non-uniform scaling: different scalars per component:



Scaling

Scaling operation:

$$x' = ax$$

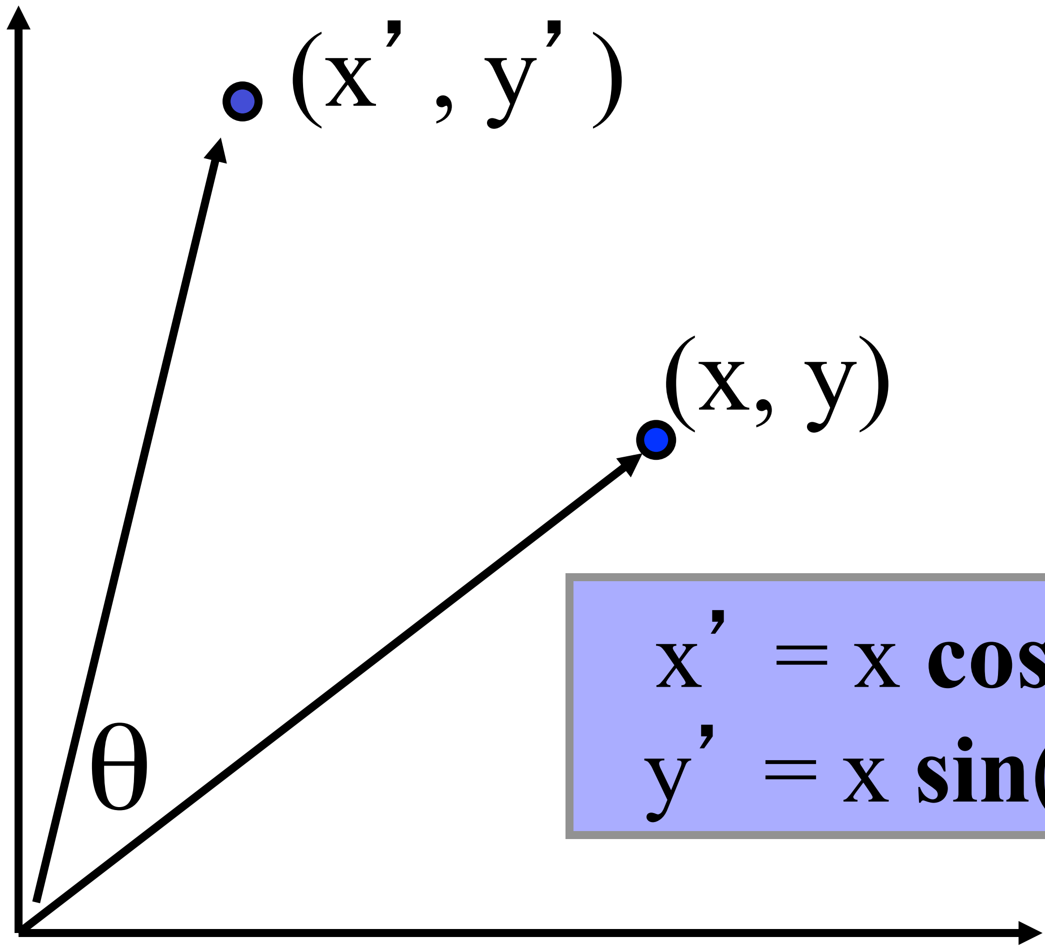
$$y' = by$$

Or, in matrix form:

$$\begin{bmatrix} x' \\ y' \end{bmatrix} = \underbrace{\begin{bmatrix} a & 0 \\ 0 & b \end{bmatrix}}_{\textit{scaling matrix S}} \begin{bmatrix} x \\ y \end{bmatrix}$$

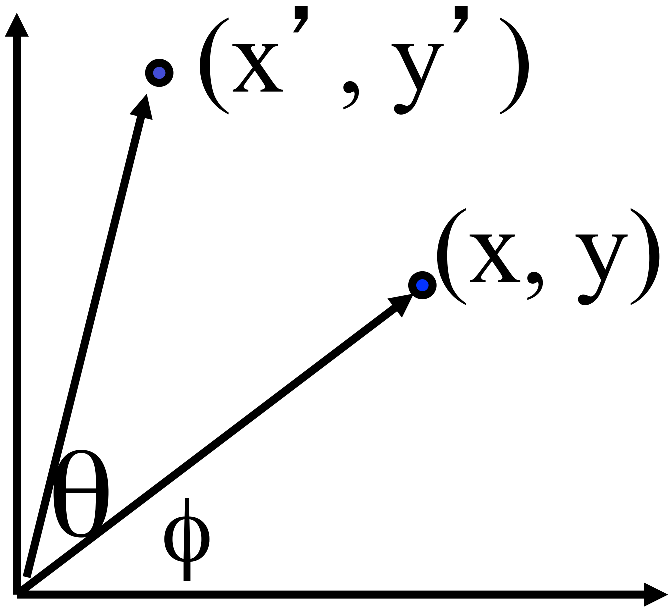
What's inverse of S?

2-D Rotation



$$x' = x\ \mathbf{cos}(\theta) - y\ \mathbf{sin}(\theta)$$
$$y' = x\ \mathbf{sin}(\theta) + y\ \mathbf{cos}(\theta)$$

2-D Rotation



$x = r \cos(\phi)$
$y = r \sin(\phi)$
$x' = r \cos(\phi + \theta)$
$y' = r \sin(\phi + \theta)$

Trig Identity…

$x' = r \cos(\phi) \cos(\theta) - r \sin(\phi) \sin(\theta)$
$y' = r \sin(\phi) \sin(\theta) + r \cos(\phi) \cos(\theta)$

Substitute…

$x' = x\,\mathbf{cos}(\theta) - y\,\mathbf{sin}(\theta)$
$y' = x\,\mathbf{sin}(\theta) + y\,\mathbf{cos}(\theta)$

2-D Rotation

This is easy to capture in matrix form:

$$\begin{bmatrix} x' \\ y' \end{bmatrix} = \underbrace{\begin{bmatrix} \cos(\theta) & -\sin(\theta) \\ \sin(\theta) & \cos(\theta) \end{bmatrix}}_{\mathbf{R}} \begin{bmatrix} x \\ y \end{bmatrix}$$

Even though sin(θ) and cos(θ) are nonlinear functions of θ,

- ***x' is a linear combination of x and y***
- ***y' is a linear combination of x and y***

What is the inverse transformation?

- Rotation by –θ
- For rotation matrices, det(R) = 1 so $\mathbf{R}^{-1} = \mathbf{R}^{T}$

2x2 Matrices

What types of transformations can be represented with a 2x2 matrix?

2D Identity?

$$x' = x$$
$$y' = y$$

$$\begin{bmatrix} x' \\ y' \end{bmatrix} = \begin{bmatrix} 1 & 0 \\ 0 & 1 \end{bmatrix} \begin{bmatrix} x \\ y \end{bmatrix}$$

2D Scale around (0,0)?

$$\boldsymbol{x}' = \boldsymbol{s}_x * \boldsymbol{x}$$
$$\boldsymbol{y}' = \boldsymbol{s}_y * \boldsymbol{y}$$

$$\begin{bmatrix} \boldsymbol{x}' \\ \boldsymbol{y}' \end{bmatrix} = \begin{bmatrix} \boldsymbol{s}_x & 0 \\ 0 & \boldsymbol{s}_y \end{bmatrix} \begin{bmatrix} \boldsymbol{x} \\ \boldsymbol{y} \end{bmatrix}$$

2x2 Matrices

What types of transformations can be represented with a 2x2 matrix?

2D Rotate around (0,0)?

$$x' = \cos\Theta * x - \sin\Theta * y$$
$$y' = \sin\Theta * x + \cos\Theta * y$$

$$\begin{bmatrix} x' \\ y' \end{bmatrix} = \begin{bmatrix} \cos\Theta & -\sin\Theta \\ \sin\Theta & \cos\Theta \end{bmatrix} \begin{bmatrix} x \\ y \end{bmatrix}$$

2D Shear?

$$\boldsymbol{x' = x + sh_x * y}$$
$$\boldsymbol{y' = sh_y * x + y}$$

$$\begin{bmatrix} \boldsymbol{x'} \\ \boldsymbol{y'} \end{bmatrix} = \begin{bmatrix} 1 & \boldsymbol{sh_x} \\ \boldsymbol{sh_y} & 1 \end{bmatrix} \begin{bmatrix} \boldsymbol{x} \\ \boldsymbol{y} \end{bmatrix}$$

2x2 Matrices

What types of transformations can be represented with a 2x2 matrix?

2D Mirror about Y axis?

$$x' = -x$$
$$y' = y$$

$$\begin{bmatrix} x' \\ y' \end{bmatrix} = \begin{bmatrix} -1 & 0 \\ 0 & 1 \end{bmatrix} \begin{bmatrix} x \\ y \end{bmatrix}$$

2D Mirror over (0,0)?

$$x' = -x$$
$$y' = -y$$

$$\begin{bmatrix} x' \\ y' \end{bmatrix} = \begin{bmatrix} -1 & 0 \\ 0 & -1 \end{bmatrix} \begin{bmatrix} x \\ y \end{bmatrix}$$

2x2 Matrices

What types of transformations can be represented with a 2x2 matrix?

2D Translation?

$$x' = x + t_x$$

$$y' = y + t_y$$

NO!

Only linear 2D transformations can be represented with a 2x2 matrix

All 2D Linear Transformations

Linear transformations are combinations of …

- Scale,
- Rotation,
- Shear, and
- Mirror

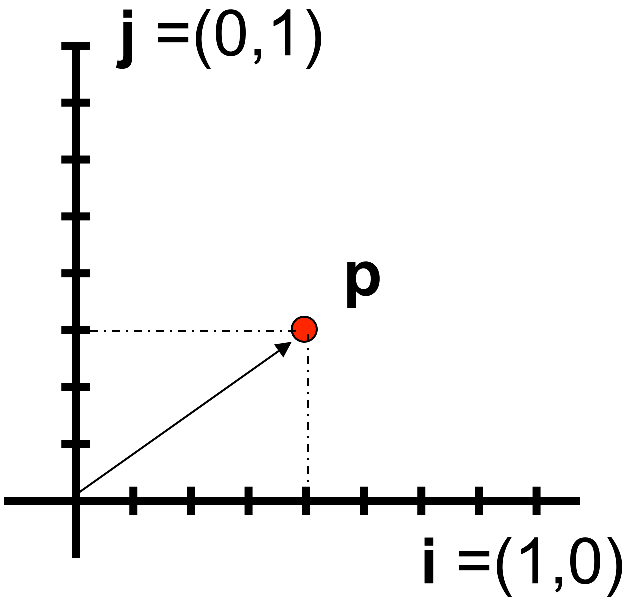
$$\begin{bmatrix} x' \\ y' \end{bmatrix} = \begin{bmatrix} a & b \\ c & d \end{bmatrix} \begin{bmatrix} x \\ y \end{bmatrix}$$

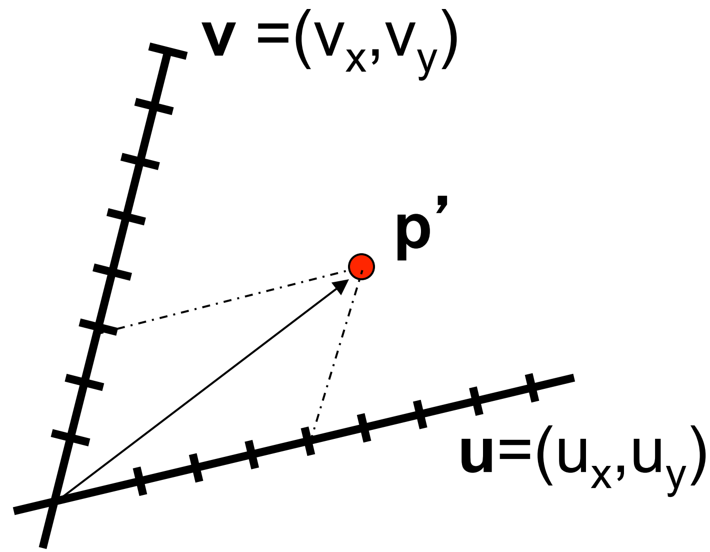
Properties of linear transformations:

- Origin maps to origin
- Lines map to lines
- Parallel lines remain parallel
- Ratios are preserved
- Closed under composition

$$\begin{bmatrix} x' \\ y' \end{bmatrix} = \begin{bmatrix} a & b \\ c & d \end{bmatrix} \begin{bmatrix} e & f \\ g & h \end{bmatrix} \begin{bmatrix} i & j \\ k & l \end{bmatrix} \begin{bmatrix} x \\ y \end{bmatrix}$$

Linear Transformations as Change of Basis





$\mathbf{p}=4\mathbf{i}+3\mathbf{j} = (4,3)$

$\mathbf{p}' = 4\mathbf{u}+3\mathbf{v}$

$p_x' = 4u_x+3v_x$
$p_y' = 4u_y+3v_y$

$$\mathbf{p}' = \begin{bmatrix} u_x & v_x \\ u_y & v_y \end{bmatrix}\begin{bmatrix} 4 \\ 3 \end{bmatrix} = \begin{bmatrix} u_x & v_x \\ u_y & v_y \end{bmatrix}\mathbf{p}$$

Any linear transformation is a basis!!!

- What's the inverse transform?
- How can we change from any basis to any basis?
- What if the basis are orthogonal?

Homogeneous Coordinates

Q: How can we represent translation as a 3x3 matrix?

$$x' = x + t_x$$

$$y' = y + t_y$$

Homogeneous Coordinates

Homogeneous coordinates

- represent coordinates in 2 dimensions with a 3-vector

$$\begin{bmatrix} x \\ y \end{bmatrix} \xrightarrow{\text{homogeneous coords}} \begin{bmatrix} x \\ y \\ 1 \end{bmatrix}$$

Homogeneous Coordinates

Q: How can we represent translation as a 3x3 matrix?

$$x' = x + t_x$$

$$y' = y + t_y$$

A: Using the rightmost column:

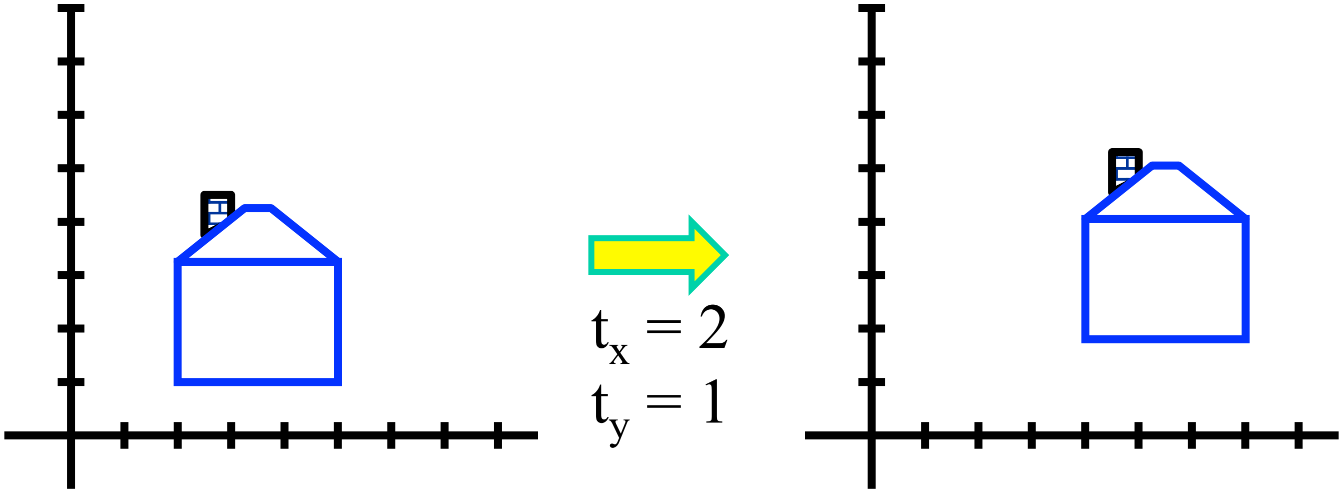
$$\mathbf{T}ranslation = \begin{bmatrix} 1 & 0 & t_x \\ 0 & 1 & t_y \\ 0 & 0 & 1 \end{bmatrix}$$

Translation

Example of translation

Homogeneous Coordinates

$$\begin{bmatrix} x' \\ y' \\ 1 \end{bmatrix} = \begin{bmatrix} 1 & 0 & t_x \\ 0 & 1 & t_y \\ 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} x \\ y \\ 1 \end{bmatrix} = \begin{bmatrix} x + t_x \\ y + t_y \\ 1 \end{bmatrix}$$



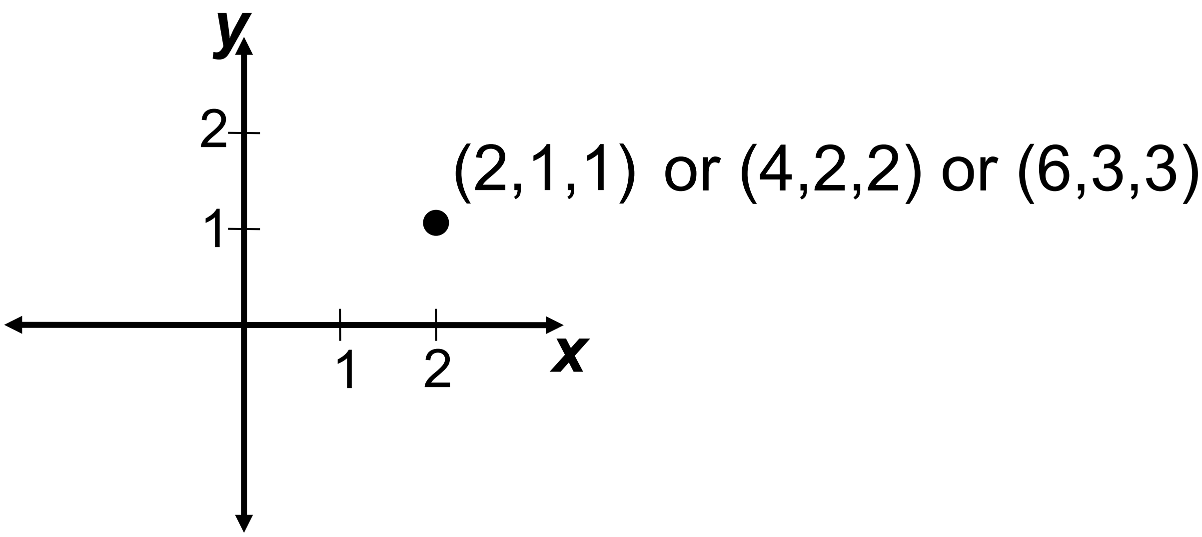
$t_x = 2$

$t_y = 1$

Homogeneous Coordinates

Add a 3rd coordinate to every 2D point

- (x, y, w) represents a point at location (x/w, y/w)
- (x, y, 0) represents a point at infinity
- (0, 0, 0) is not allowed



Convenient coordinate system to represent many useful transformations

Basic 2D Transformations

Basic 2D transformations as 3x3 matrices

$$\begin{bmatrix} x' \\ y' \\ 1 \end{bmatrix} = \begin{bmatrix} 1 & 0 & t_x \\ 0 & 1 & t_y \\ 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} x \\ y \\ 1 \end{bmatrix}$$

Translate

$$\begin{bmatrix} \boldsymbol{x}' \\ \boldsymbol{y}' \\ 1 \end{bmatrix} = \begin{bmatrix} \boldsymbol{s_x} & 0 & 0 \\ 0 & \boldsymbol{s_y} & 0 \\ 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} \boldsymbol{x} \\ \boldsymbol{y} \\ 1 \end{bmatrix}$$

Scale

$$\begin{bmatrix} x' \\ y' \\ 1 \end{bmatrix} = \begin{bmatrix} \cos\Theta & -\sin\Theta & 0 \\ \sin\Theta & \cos\Theta & 0 \\ 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} x \\ y \\ 1 \end{bmatrix}$$

Rotate

$$\begin{bmatrix} \boldsymbol{x}' \\ \boldsymbol{y}' \\ 1 \end{bmatrix} = \begin{bmatrix} 1 & \boldsymbol{sh_x} & 0 \\ \boldsymbol{sh_y} & 1 & 0 \\ 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} \boldsymbol{x} \\ \boldsymbol{y} \\ 1 \end{bmatrix}$$

Shear

Affine Transformations

$$\begin{bmatrix} x' \\ y' \\ w \end{bmatrix} = \begin{bmatrix} a & b & c \\ d & e & f \\ 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} x \\ y \\ w \end{bmatrix}$$

Affine transformations are combinations of …

- Linear transformations, and
- Translations

Properties of affine transformations:

- Origin does not necessarily map to origin
- Lines map to lines
- Parallel lines remain parallel
- Ratios are preserved
- Closed under composition
- Models change of basis

Projective Transformations

$$\begin{bmatrix} x' \\ y' \\ w' \end{bmatrix} = \begin{bmatrix} a & b & c \\ d & e & f \\ g & h & i \end{bmatrix} \begin{bmatrix} x \\ y \\ w \end{bmatrix}$$

Projective transformations …

- Affine transformations, and
- Projective warps

Properties of projective transformations:

- Origin does not necessarily map to origin
- Lines map to lines
- Parallel lines do not necessarily remain parallel
- Ratios are not preserved
- Closed under composition
- Models change of basis

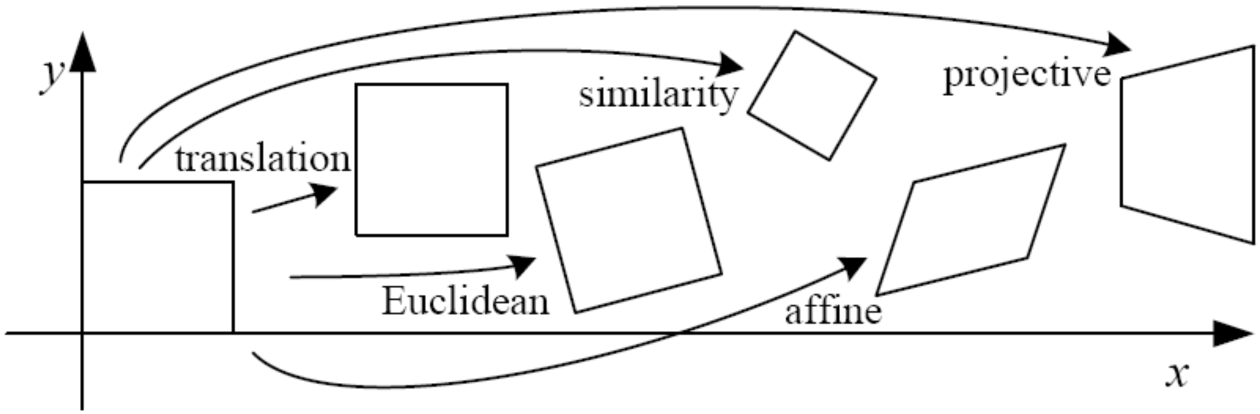
Matrix Composition

Transformations can be combined by matrix multiplication

$$\begin{bmatrix} x' \\ y' \\ w' \end{bmatrix} = \left(\begin{bmatrix} 1 & 0 & tx \\ 0 & 1 & ty \\ 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} \cos\Theta & -\sin\Theta & 0 \\ \sin\Theta & \cos\Theta & 0 \\ 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} sx & 0 & 0 \\ 0 & sy & 0 \\ 0 & 0 & 1 \end{bmatrix} \right) \begin{bmatrix} x \\ y \\ w \end{bmatrix}$$

$$\mathbf{p'} \quad = \quad T(t_x,t_y) \qquad R(\Theta) \qquad S(s_x,s_y) \qquad \mathbf{p}$$

2D image transformations

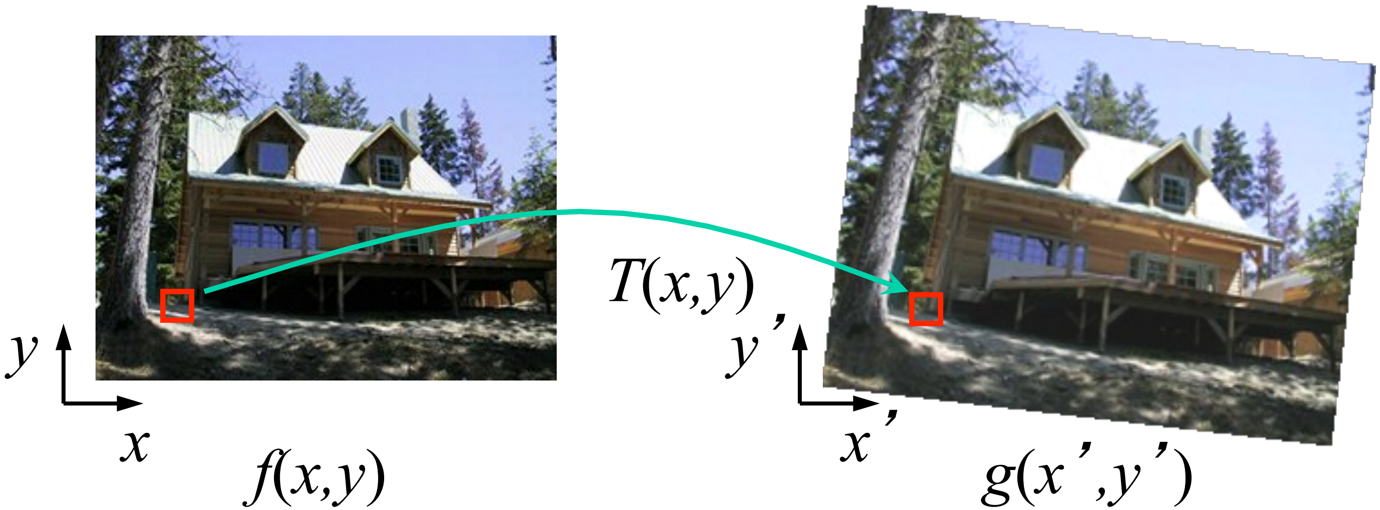


Name	Matrix	# D.O.F.	Preserves:	Icon
translation	$\left[\, \boldsymbol{I} \mid \boldsymbol{t} \,\right]_{2\times 3}$			
rigid (Euclidean)	$\left[\, \boldsymbol{R} \mid \boldsymbol{t} \,\right]_{2\times 3}$			
similarity	$\left[\, s\boldsymbol{R} \mid \boldsymbol{t} \,\right]_{2\times 3}$			
affine	$\left[\, \boldsymbol{A} \,\right]_{2\times 3}$			
projective	$\left[\, \tilde{\boldsymbol{H}} \,\right]_{3\times 3}$			

These transformations are a nested set of groups

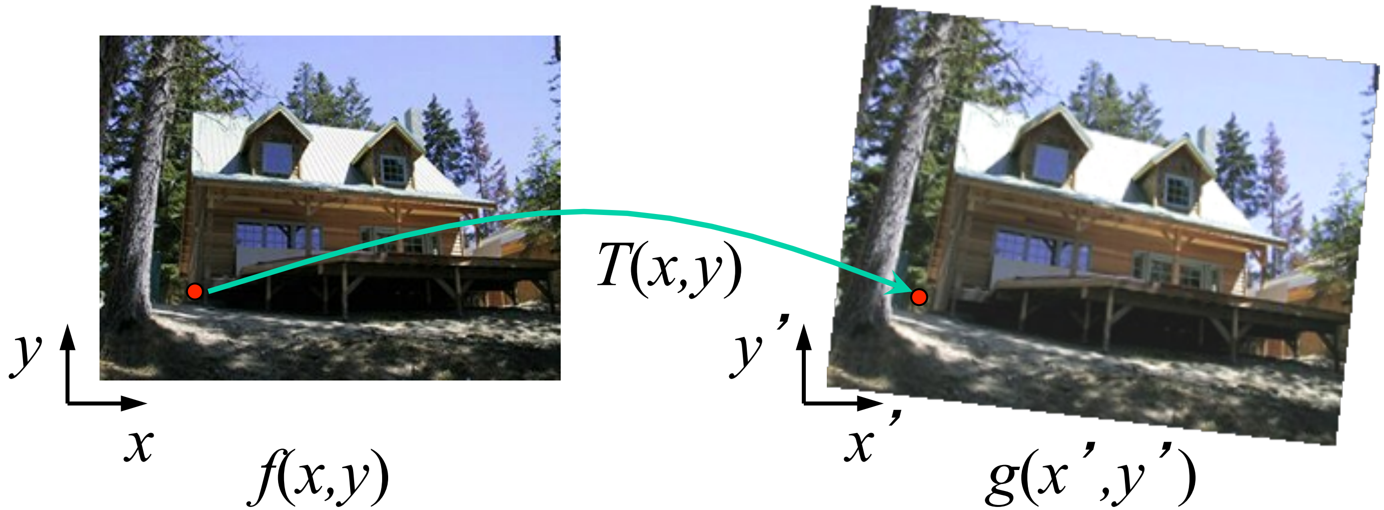
- Closed under composition and inverse is a member

Image warping



Given a coordinate transform $(x', y') = h(x,y)$ and a source image $f(x,y)$, how do we compute a transformed image $g(x', y') = f(T(x,y))$?

Forward warping

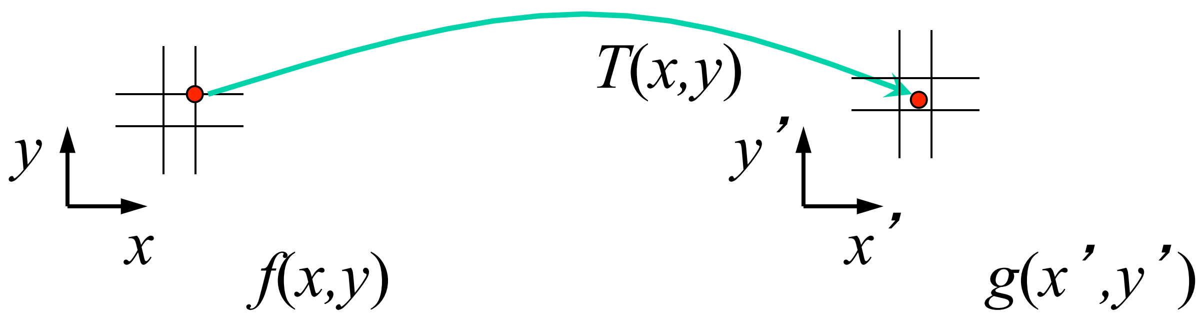


Send each pixel $f(x,y)$ to its corresponding location

$(x',y') = T(x,y)$ in the second image

Q: what if pixel lands “between” two pixels?

Forward warping



Send each pixel $f(x,y)$ to its corresponding location

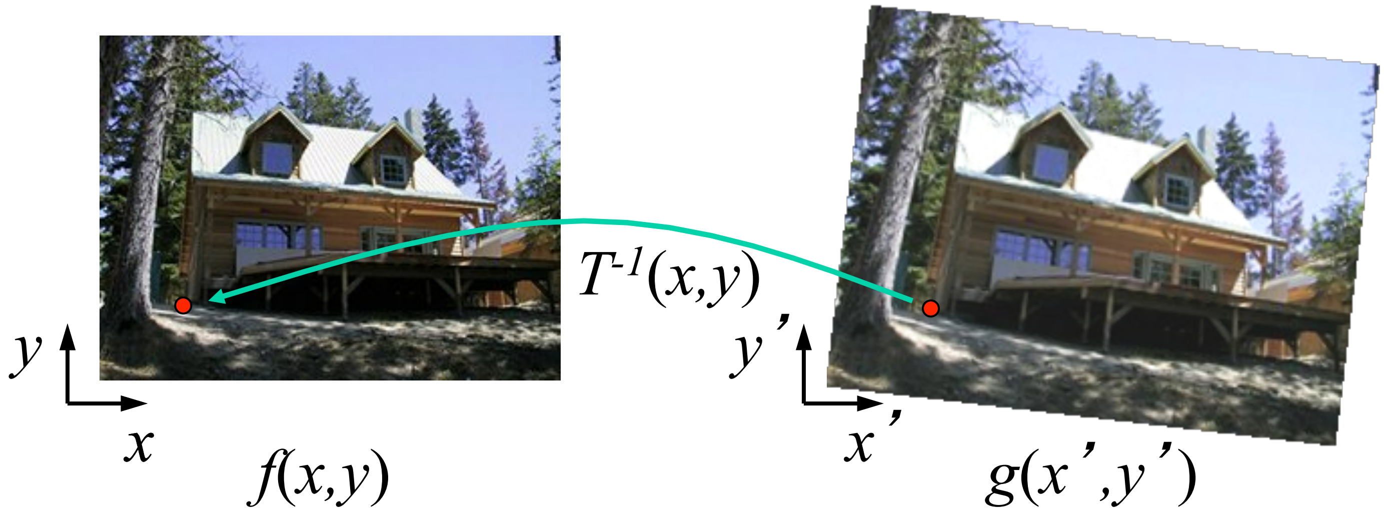
$(x',y') = T(x,y)$ in the second image

Q: what if pixel lands "between" two pixels?

A: distribute color among neighboring pixels (x',y')

- Known as "splatting"

Inverse warping

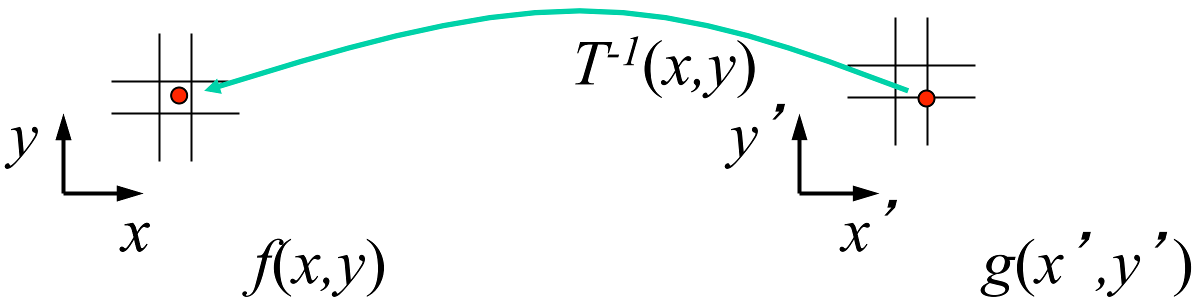


Get each pixel $g(x',y')$ from its corresponding location

$(x,y) = T^{-1}(x',y')$ in the first image

Q: what if pixel comes from "between" two pixels?

Inverse warping



Get each pixel $g(x',y')$ from its corresponding location

$(x,y) = T^{-1}(x',y')$ in the first image

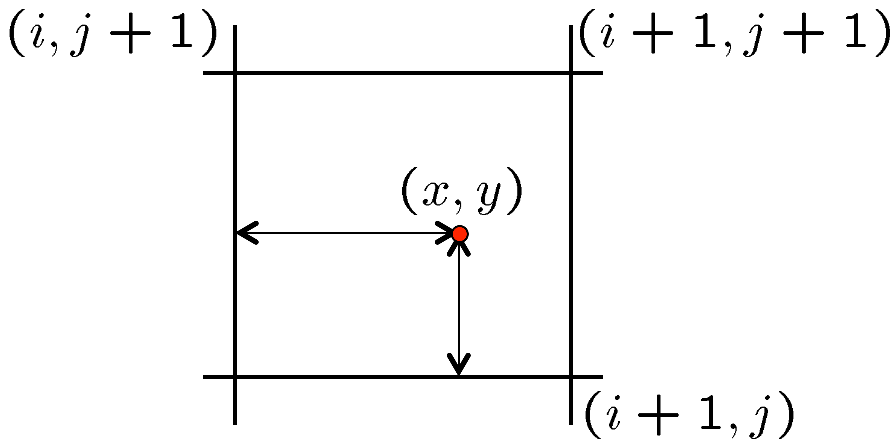
Q: what if pixel comes from "between" two pixels?

A: *Interpolate* color value from neighbors

– nearest neighbor, bilinear, Gaussian, bicubic

Bilinear interpolation

Sampling at *f(x,y):*



$$
\begin{aligned}
f(x,y) = \quad & (1-a)(1-b) && f[i,j] \\
& +a(1-b) && f[i+1,j] \\
& +ab && f[i+1,j+1] \\
& +(1-a)b && f[i,j+1]
\end{aligned}
$$

Forward vs. inverse warping

Q: which is better?

A: usually inverse—eliminates holes

- however, it requires an invertible warp function—not always possible...