High dynamic range imaging

Digital Visual Effects, Spring 2007

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with slides by Fedro Durand, Brian Curless, Steve Seitz and Alexei Efros

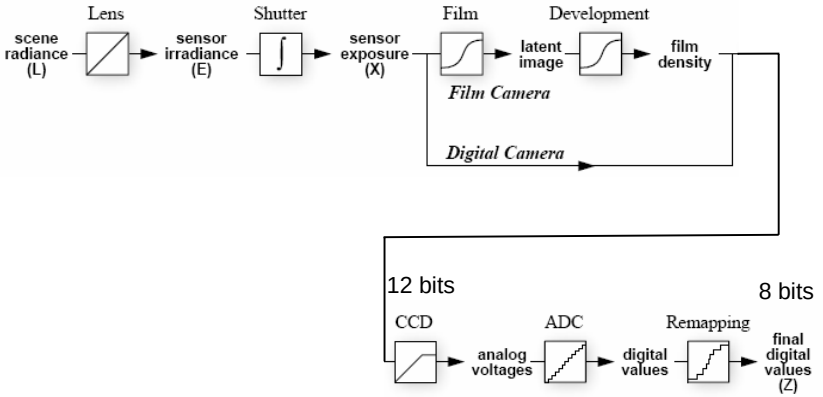
Announcements

- Assignment #1 announced on 3/7 (due on 3/27 noon)
- TA/signup sheet/gil/tone mapping
- Considered easy; it is suggested that you implement at least one bonus (MTB/tone mapping/other HDR construction)
- You have a total of 10 days of delay without penalty for assignments; after that, -1 point per day applies in your final grade until reaching zero for each project.

Camera is an imperfect device

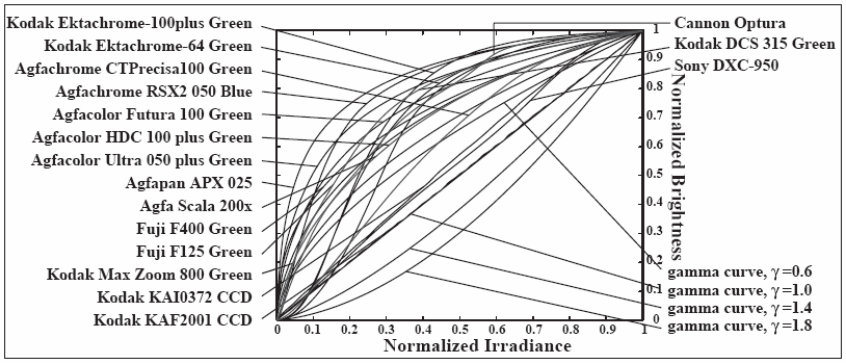
- Camera is an imperfect device for measuring the radiance distribution of a scene because it cannot capture the full spectral content and dynamic range.
- Limitations in sensor design prevent cameras from capturing all information passed by lens.

Camera pipeline



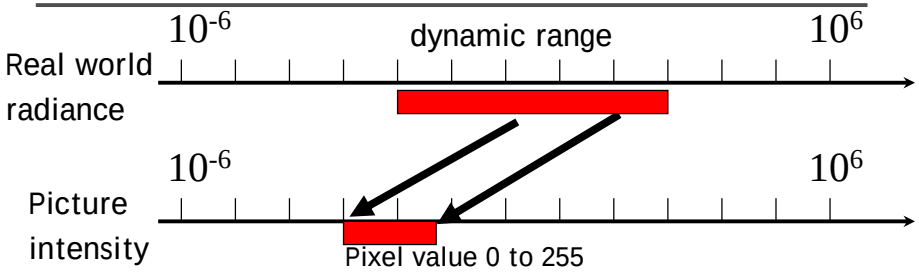
Real-world response functions

In general, the response function is not provided by camera makers who consider it part of their proprietary product differentiation. In addition, they are beyond the standard gamma curves.

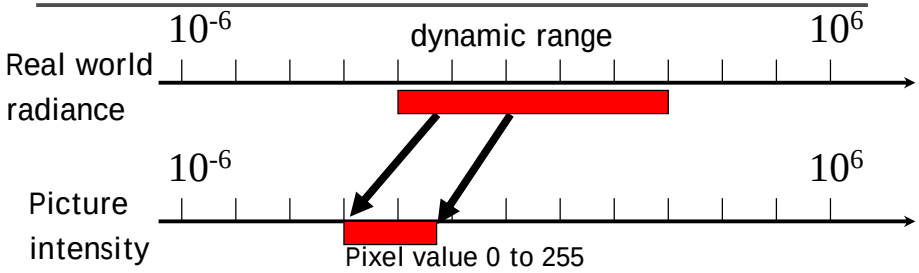


High dynamic range image

Short exposure



Long exposure

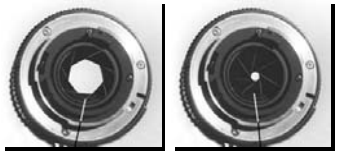


Camera is not a photometer

- Limited dynamic range
  - ⇒ Perhaps use multiple exposures?
- Unknown, nonlinear response
  - ⇒ Not possible to convert pixel values to radiance
- Solution:
  - Recover response curve from multiple exposures, then reconstruct the *radiance map*

Varying exposure

- Ways to change exposure
  - Shutter speed
  - Aperture
  - Neutral density filters



Shutter speed

- Note: shutter times usually obey a power series – each "stop" is a factor of 2
- ¼, 1/8, 1/15, 1/30, 1/60, 1/125, 1/250, 1/500, 1/1000 sec

Usually really is:

¼, 1/8, 1/16, 1/32, 1/64, 1/128, 1/256, 1/512, 1/1024 sec

Varying shutter speeds

HDRI capturing from multiple exposures

- Capture images with multiple exposures
- Image alignment (even if you use tripod, it is suggested to run alignment)
- Ghost/flare removal
- Response curve recovery

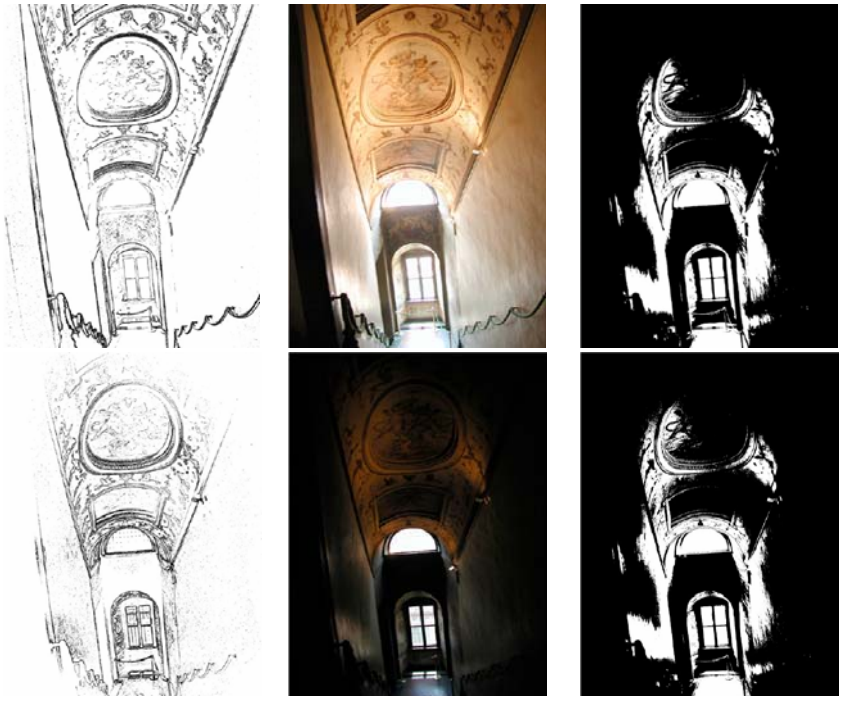


Image alignment

- We will introduce a fast and easy-to-implement method for this task, called Median Threshold Bitmap (MTB) alignment technique.
- Consider only integral translations. It is enough empirically.
- The inputs are N grayscale images. (You can either use the green channel or convert into grayscale by Y=(54R+183G+19B)/256)
- MTB is a binary image formed by thresholding the input image using the median of intensities.

Why is MTB better than gradient?

- Edge-detection filters are dependent on image exposures
- Taking the difference of two edge bitmaps would not give a good indication of where the edges are misaligned.

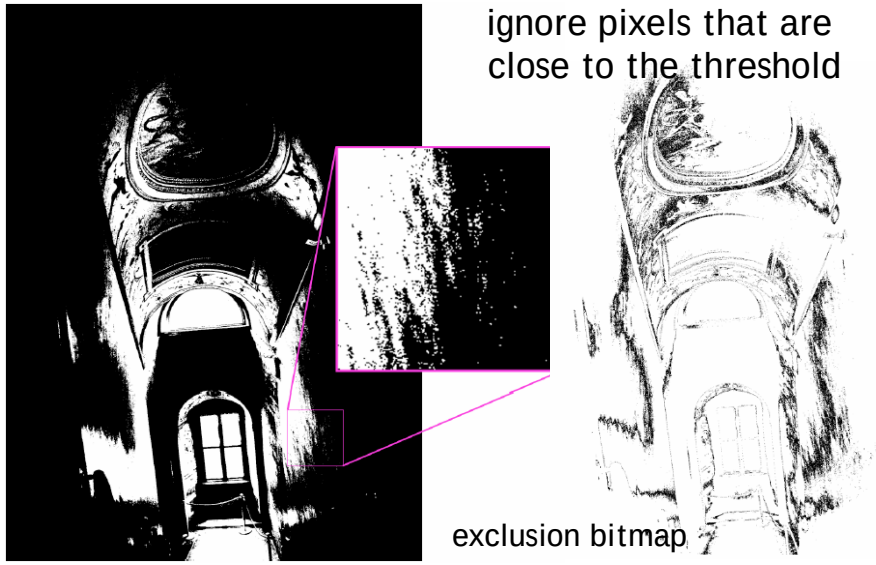
Search for the optimal offset

- Try all possible offsets.
- Gradient descent
- Multiscale technique

- log(max_offset) levels
- Try 9 possibilities for the top level
- Scale by 2 when passing down; try its 9 neighbors

Threshold noise

ignore pixels that are close to the threshold



exclusion bitmap

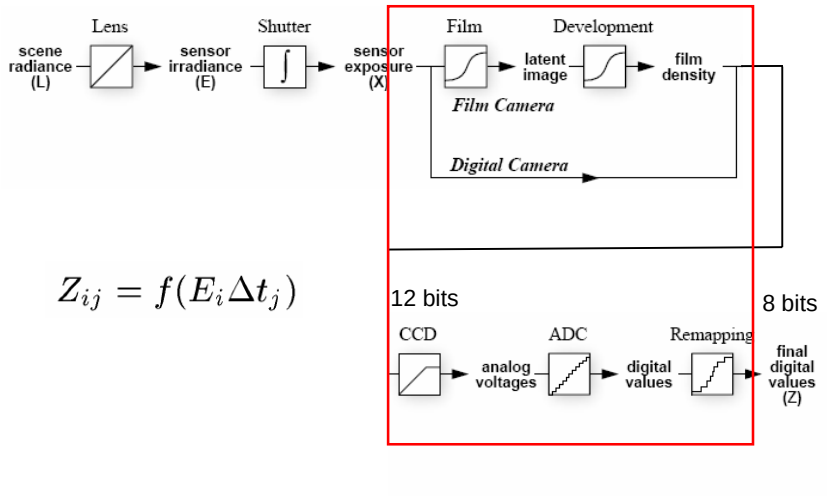
Efficiency considerations

- XOR for taking difference
- AND with exclusion maps
- Bit counting by table lookup

Results

Success rate = 84%. 10% failure due to rotation. 3% for excessive motion and 3% for too much high-frequency content.

Recovering response curve



$$Z_{ij} = f(E_i \Delta t_j)$$

Recovering response curve

Image series

Δt = 2 sec | Δt = 1 sec | Δt = 1/2 sec | Δt = 1/4 sec | Δt = 1/8 sec

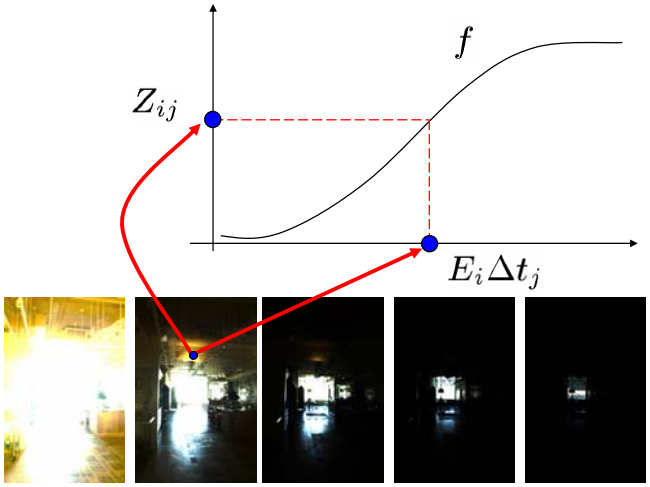
$$Z_{ij} = f(E_i \Delta t_j)$$

$$X_{ij} = E_i \Delta t_j$$

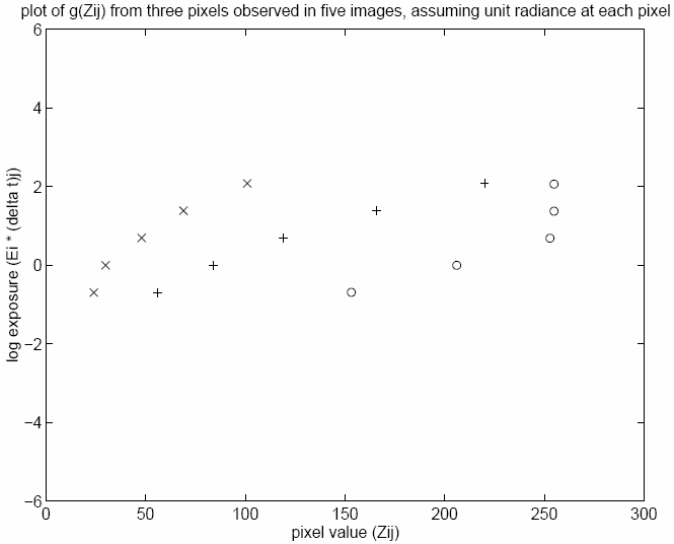
$$\ln X_{ij} = \ln E_i + \ln \Delta t_j$$

Recovering response curve

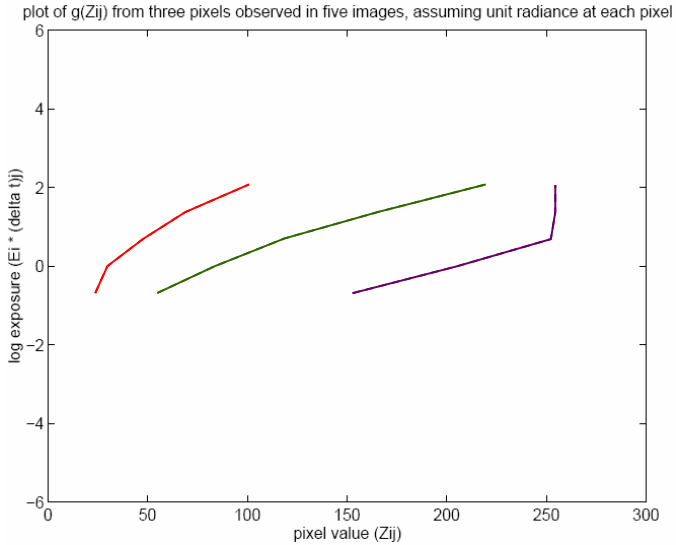
- We want to obtain the inverse of the response curve



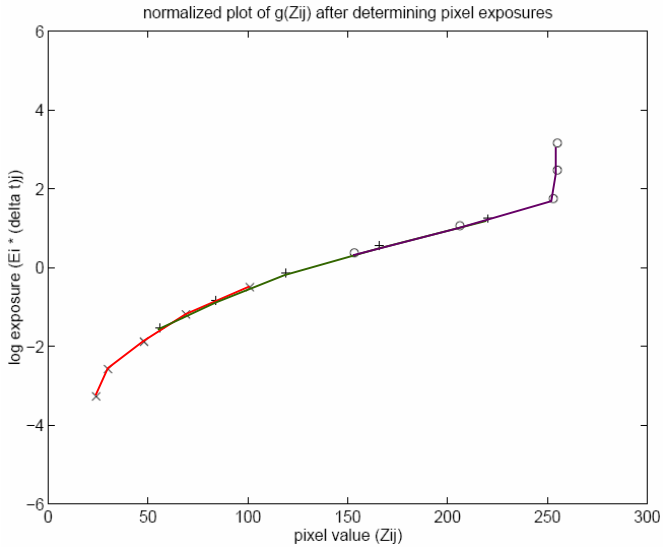
Idea behind the math



Idea behind the math



Idea behind the math



Math for recovering response curve

$$Z_{ij} = f(E_i \Delta t_j)$$

f is monotonic, it is invertible

$$\ln f^{-1}(Z_{ij}) = \ln E_i + \ln \Delta t_j$$

let us define function $g = \ln f^{-1}$

$$g(Z_{ij}) = \ln E_i + \ln \Delta t_j$$

minimize the following

$$\mathcal{O} = \sum_{i=1}^{N} \sum_{j=1}^{P} [g(Z_{ij}) - \ln E_i - \ln \Delta t_j]^2 + \lambda \sum_{z=Z_{min}+1}^{Z_{max}-1} g''(z)^2$$

$$g''(z) = g(z-1) - 2g(z) + g(z+1)$$

Recovering response curve

- The solution can be only up to a scale, add a constraint

$$g(Z_{mid}) = 0, \text{ where } Z_{mid} = \tfrac{1}{2}(Z_{min} + Z_{max})$$

- Add a hat weighting function

$$w(z) = \begin{cases} z - Z_{min} & \text{for } z \leq \tfrac{1}{2}(Z_{min} + Z_{max}) \\ Z_{max} - z & \text{for } z > \tfrac{1}{2}(Z_{min} + Z_{max}) \end{cases}$$

$$\mathcal{O} = \sum_{i=1}^{N} \sum_{j=1}^{P} \{w(Z_{ij}) [g(Z_{ij}) - \ln E_i - \ln \Delta t_j]\}^2 +$$

$$\lambda \sum_{z=Z_{min}+1}^{Z_{max}-1} [w(z) g''(z)]^2$$

Recovering response curve

- We want $N(P-1) > (Z_{max} - Z_{min})$
  If P=11, N~25 (typically 50 is used)
- We prefer that selected pixels are well distributed and sampled from constant regions. They picked points by hand.
- It is an overdetermined system of linear equations and can be solved using SVD

How to optimize?

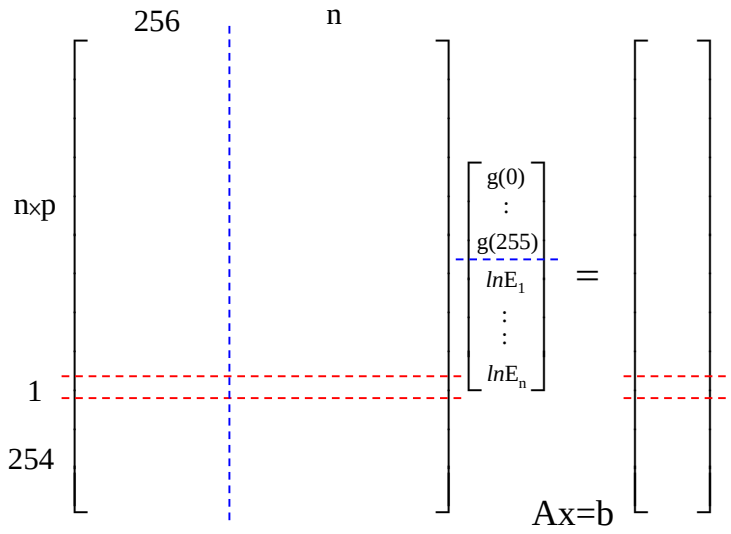
$$\mathcal{O} = \sum_{i=1}^{N}\sum_{j=1}^{P}\{w(Z_{ij})\,[g(Z_{ij}) - \ln E_i - \ln \Delta t_j]\}^2 +$$

$$\lambda \sum_{z=Z_{min}+1}^{Z_{max}-1} [w(z)g''(z)]^2$$

1. Set partial derivatives zero
2.

$$\min \sum_{i=1}^{N} (\mathbf{a}_i \mathbf{x} - \mathbf{b}_i)^2 \rightarrow \text{least-square solution of } \begin{bmatrix} \mathbf{a}_1 \\ \mathbf{a}_2 \\ \vdots \\ \mathbf{a}_N \end{bmatrix} \mathbf{x} = \begin{bmatrix} \mathbf{b}_1 \\ \mathbf{b}_2 \\ \vdots \\ \mathbf{b}_N \end{bmatrix}$$

Sparse linear system



Questions

- Will g(127)=0 always be satisfied? Why and why not?
- How to find the least-square solution for an over-determined system?

Least-square solution for a linear system

$$\underset{m\times n}{\mathbf{A}}\ \underset{n}{\mathbf{x}} = \underset{m}{\mathbf{b}}$$
$$m > n$$

The are often mutually incompatible. We instead find $\mathbf{x}$ to minimize the norm $\|\mathbf{Ax}-\mathbf{b}\|$ of the residual vector $\mathbf{Ax}-\mathbf{b}$. If there are multiple solutions, we prefer the one with the minimal length $\|\mathbf{x}\|$.

Least-square solution for a linear system

If we perform SVD on $\mathbf{A}$ and rewrite it as

$$\mathbf{A} = \mathbf{U}\mathbf{\Sigma}V^{\mathrm{T}}$$

then $\hat{\mathbf{x}} = \mathbf{V}\mathbf{\Sigma}^{+}\mathbf{U}^{\mathrm{T}}\mathbf{b}$ is the least-square solution.

pseudo inverse

$$\mathbf{\Sigma}^{+} = \begin{bmatrix} 1/\sigma_1 & & & & & 0 & \cdots & 0 \\ & \ddots & & & & \vdots & & \vdots \\ & & 1/\sigma_r & & & & & \\ & & & 0 & & & & \\ & & & & \ddots & & & \\ & & & & & 0 & 0 & \cdots & 0 \end{bmatrix}$$

Proof

find x 使 $\|Ax-b\|$ 最小、

$\|Ax-b\| = \|U\Sigma V^T x - b\|$

$= \|U(\Sigma V^T x - U^T b)\|$ U是rotation 不改變長度

$= \|\Sigma V^T x - U^T b\|$

令 $y = V^T x$ $\quad c = U^T b$

則相當於找 y 使 $\|\Sigma y - c\|$ 最小、

$$\begin{pmatrix} \sigma_1 & & & 0 \\ & \ddots & & \\ & & \sigma_r & \\ 0 & & & 0 \end{pmatrix} \begin{pmatrix} y_1 \\ \vdots \\ y_n \end{pmatrix} - \begin{pmatrix} c_1 \\ \vdots \\ c_n \end{pmatrix}$$

Proof

$\Rightarrow y_i = \frac{c_i}{\sigma_i}$ $\quad i=1\cdots r$ $\quad y_i = 0$ $\quad i=r+1\cdots n$

$$\Rightarrow \tilde{y} = \begin{pmatrix} 1/\sigma_1 & & & 0 \\ & \ddots & & \\ & & 1/\sigma_r & \\ 0 & & & 0 \end{pmatrix} \begin{pmatrix} c_1 \\ \vdots \\ c_r \\ \vdots \\ c_n \end{pmatrix} = \Sigma^{+} c$$

$\Rightarrow \tilde{y} = V^T \tilde{x} = \Sigma^{+} c = \Sigma^{+} U^T b$

$\Rightarrow \tilde{x} = V \Sigma^{+} U^T b$ ※

Libraries for SVD

- Matlab
- GSL
- Boost
- LAPACK
- ATLAS

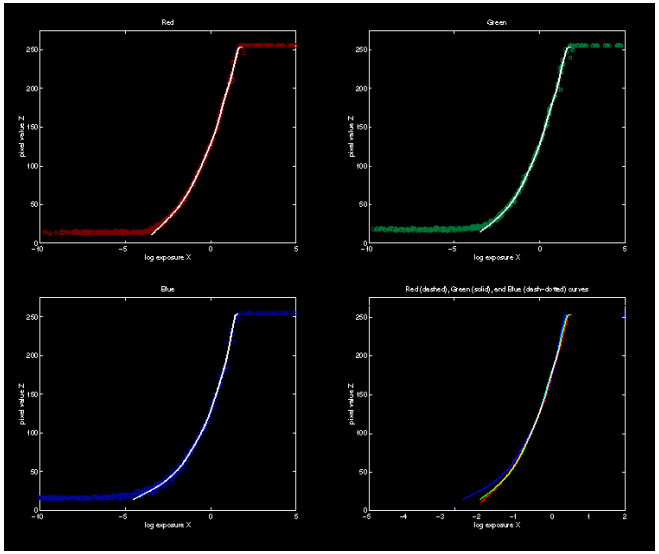
Matlab code

```
%
% gsolve.m - Solve for imaging system response function
%
% Given a set of pixel values observed for several pixels in several
% images with different exposure times, this function returns the
% imaging system's response function g as well as the log film irradiance
% values for the observed pixels.
%
% Assumes:
%
%  Zmin = 0
%  Zmax = 255
%
% Arguments:
%
%  Z(i,j) is the pixel values of pixel location number i in image j
%  B(j)   is the log delta t, or log shutter speed, for image j
%  l      is lamdba, the constant that determines the amount of smoothness
%  w(z)   is the weighting function value for pixel value z
%
% Returns:
%
%  g(z)   is the log exposure corresponding to pixel value z
%  lE(i)  is the log film irradiance at pixel location i
%
```

Matlab code

```
function [g,lE]=gsolve(Z,B,l,w)

n = 256;
A = zeros(size(Z,1)*size(Z,2)+n+1,n+size(Z,1));
b = zeros(size(A,1),1);

k = 1;              %% Include the data-fitting equations
for i=1:size(Z,1)
  for j=1:size(Z,2)
    wij = w(Z(i,j)+1);
    A(k,Z(i,j)+1) = wij; A(k,n+i) = -wij; b(k,1) = wij * B(i,j);
    k=k+1;
  end
end

A(k,129) = 1;       %% Fix the curve by setting its middle value to 0
k=k+1;

for i=1:n-2         %% Include the smoothness equations
  A(k,i)=l*w(i+1); A(k,i+1)=-2*l*w(i+1); A(k,i+2)=l*w(i+1);
  k=k+1;
end

x = A\b;            %% Solve the system using SVD

g = x(1:n);
lE = x(n+1:size(x,1));
```

Recovered response function



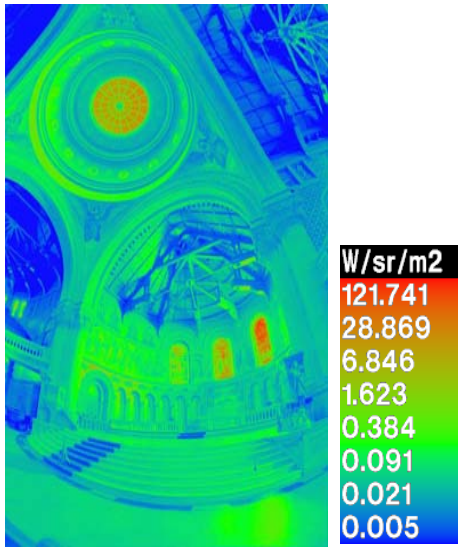
Constructing HDR radiance map

$$\ln E_i = g(Z_{ij}) - \ln \Delta t_j$$

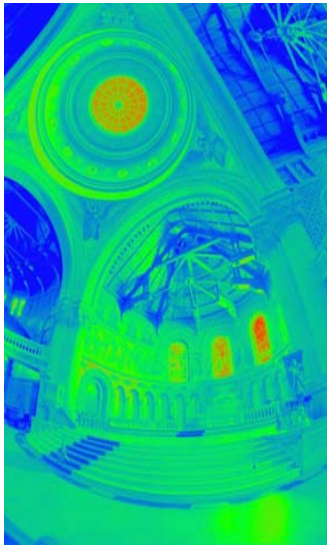
combine pixels to reduce noise and obtain a more reliable estimation

$$\ln E_i = \frac{\sum_{j=1}^{P} w(Z_{ij})(g(Z_{ij}) - \ln \Delta t_j)}{\sum_{j=1}^{P} w(Z_{ij})}$$

Reconstructed radiance map



What is this for?



- Human perception
- Vision/graphics applications

Automatic ghost removal

before

after

Weighted variance

Moving objects and high-contrast edges render high variance.

Region masking

Thresholding; dilation; identify regions;

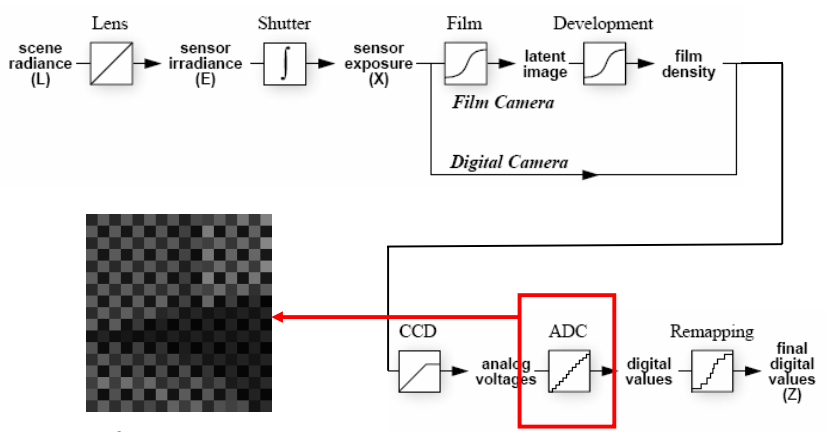
Best exposure in each region

Lens flare removal

before

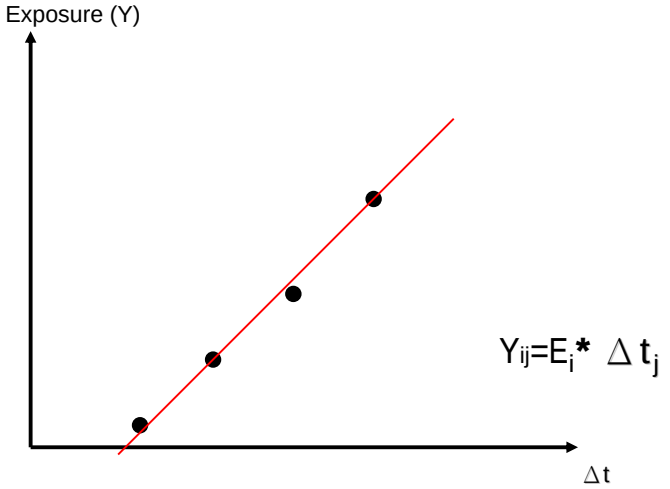
after

Easier HDR reconstruction



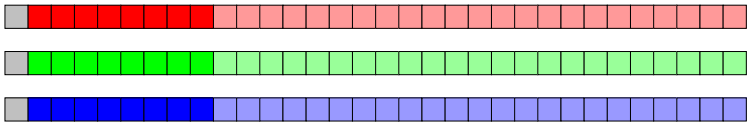
raw image =
12-bit CCD snapshot

Easier HDR reconstruction



Portable floatMap (.pfm)

- 12 bytes per pixel, 4 for each channel



sign exponent mantissa

Text header similar to Jeff Poskanzer's .ppm image format:

```
PF
768 512
1
<binary image data>
```

Floating Point TIFF similar

Radiance format (.pic, .hdr, .rad)

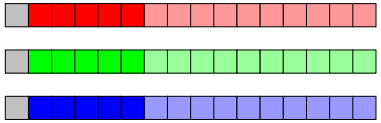
(145, 215, 87, 149) =
(145, 215, 87) * 2^(149-128) =
1190000 1760000 713000

(145, 215, 87, 103) =
(145, 215, 87) * 2^(103-128) =
0.00000432 0.00000641 0.00000259

Ward, Greg. "Real Pixels," in Graphics Gems IV, edited by James Arvo, Academic Press, 1994

ILM's OpenEXR (.exr)

- 6 bytes per pixel, 2 for each channel, compressed



sign exponent mantissa

- Several lossless compression options, 2:1 typical
- Compatible with the "half" datatype in NVidia's Cg
- Supported natively on GeForce FX and Quadro FX

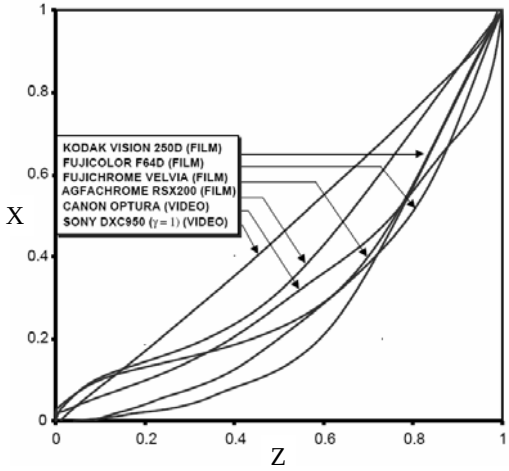
- Available at http://www.openexr.net/

Radiometric self calibration

- Assume that any response function can be modeled as a high-order polynomial

$$X = g(Z) = \sum_{m=0}^{M} c_m Z^m$$

- No need to know exposure time in advance



Mitsunaga and Nayar

- To find the coefficients c_m to minimize the following

$$\varepsilon = \sum_{i=1}^{N}\sum_{j=1}^{P}\left[\sum_{m=0}^{M} c_m Z_{ij}^m - R_{j,j+1}\sum_{m=0}^{M} c_m Z_{i,j+1}^m\right]^2$$

A guess for the ratio of

$$\frac{X_{ij}}{X_{i,j+1}} = \frac{E_i \Delta t_j}{E_i \Delta t_{j+1}} = \frac{\Delta t_j}{\Delta t_{j+1}}$$

Mitsunaga and Nayar

- Again, we can only solve up to a scale. Thus, add a constraint f(1)=1. It reduces to M variables.
- How to solve it?

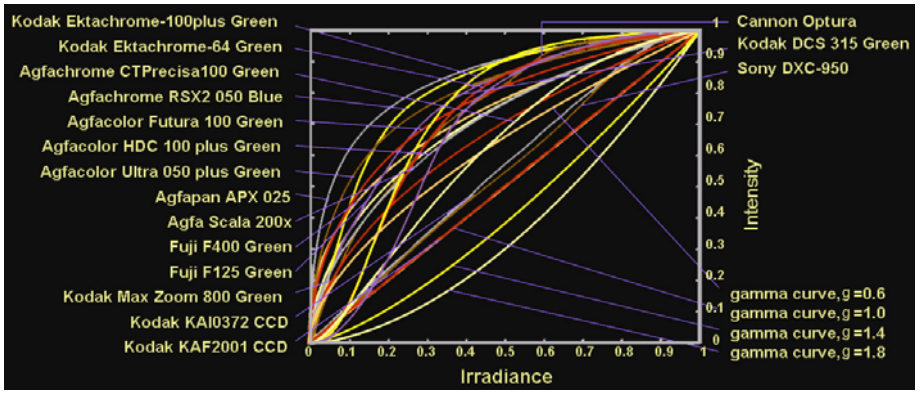
Mitsunaga and Nayar

- We solve the above iteratively and update the exposure ratio accordingly

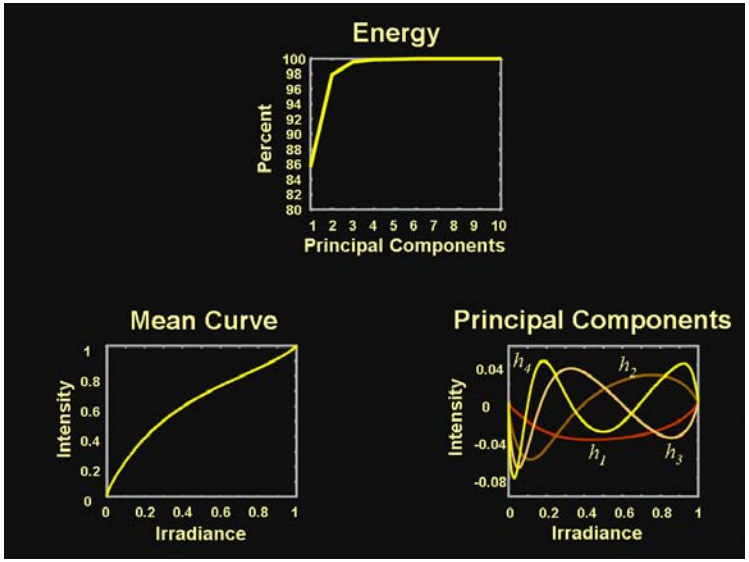
$$R_{j,j+1}^{(k)} = \frac{1}{N}\sum_{i=1}^{N}\frac{\sum_{m=0}^{M} c_{m\ k}^{(k)} Z_{ij}^{m}}{\sum_{m=0}^{M} c_{m}^{(k)} Z_{i,j+1}^{m}}$$

- How to determine M? Solve up to M=10 and pick up the one with the minimal error. Notice that you prefer to have the same order for all channels.

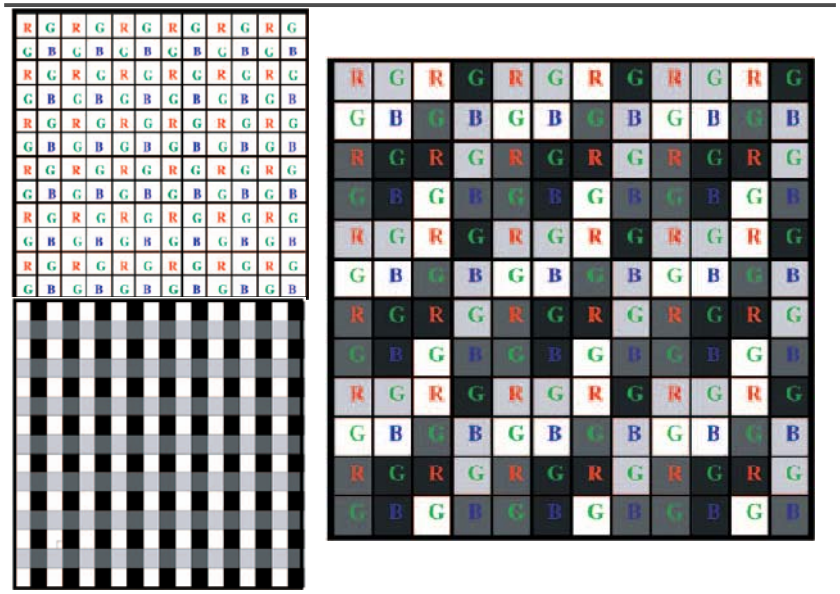
Space of response curves



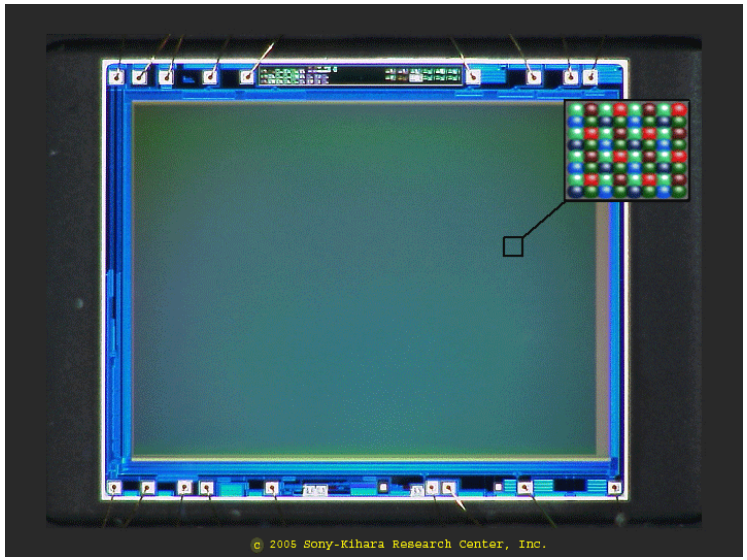
Space of response curves



Assorted pixel



Assorted pixel



Assorted pixel

Assignment #1 HDR image assemble

- Work in teams of two
- Taking pictures
- Assemble HDR images and optionally the response curve.
- Develop your HDR using tone mapping

Taking pictures

- Use a tripod to take multiple photos with different shutter speeds. Try to fix anything else. Smaller images are probably good enough.
- There are two sets of test images available on the web.
- We have tripods and a Canon PowerShot G7 for you to borrow.
- Try not touching the camera during capturing. But, how?

1. Taking pictures

- Use a laptop and a remote capturing program.
  - PSRemote
  - AHDRIA
- PSRemote
  - Manual
  - Not free
  - Supports both jpg and raw
  - Support most Canon's PowerShot cameras
- AHDRIA
  - Automatic
  - Free
  - Only supports jpg
  - Support less models

AHDRIA/AHDRIC/HDRI_Helper

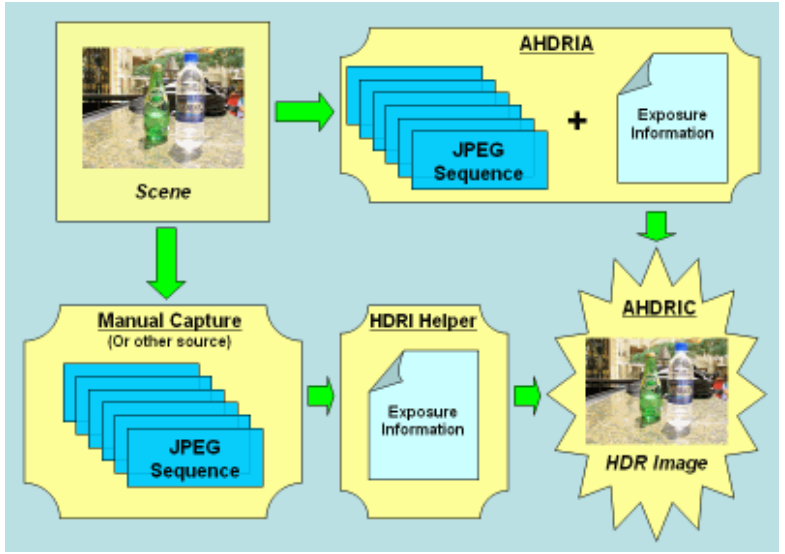


Image registration

- Two programs can be used to correct small drifts.
  - ImageAlignment from RASCAL
  - Photomatix
- Photomatix is recommended.

2. HDR assembling

- Write a program to convert the captured images into a radiance map and optionally to output the response curve.
- We will provide image I/O library, gil, which supports many traditional image formats such as .jpg and .png, and float-point images such as .hdr and .exr.
- Paul Debevec's method. You will need a linear solver for this method.
- Recover from CCD snapshots. You will need dcraw.c.

3. Tone mapping

- Apply some tone mapping operation to develop your photograph.
  - Reinhard's algorithm (HDRShop plugin)
  - Photomatix
  - LogView
  - Fast Bilateral (.exr Linux only)
  - PFStmo (Linux only)
    pfsin a.hdr | pfs_fattal02 | pfsout o.hdr

Bells and Whistles

- Other methods for HDR assembling algorithms
- Implement tone mapping algorithms
- Implement MTB alignment algorithm
- Others

Submission

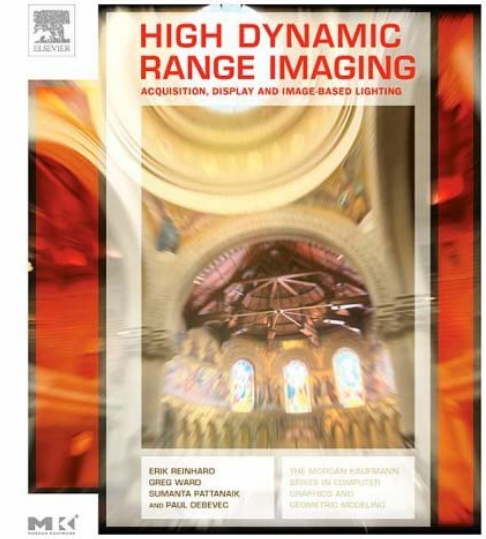
- You have to turn in your complete source, the executable, a html report, pictures you have taken, HDR image, and an artifact (tone-mapped image).
- Report page contains:

  description of the project, what do you learn, algorithm, implementation details, results, bells and whistles…
- The class will have vote on artifacts.
- Submission mechanism will be announced later.

Reference software

- Photomatix
- AHDRIA/AHDRIC
- HDRShop
- RASCAL

References



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