

Image Morphing



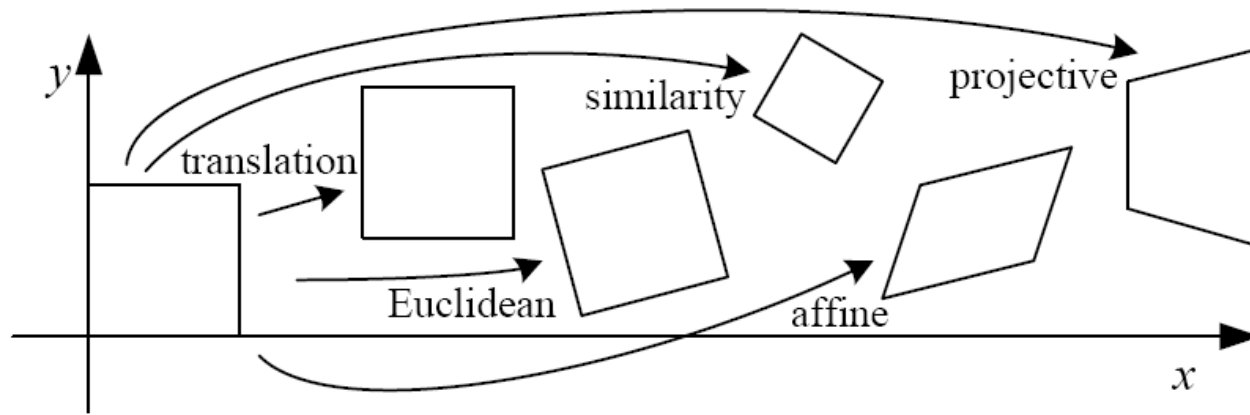
Computational Photography
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Slides adopted from Derek Hoiem

Project 3: Gradient Domain Editing

- General concept: Solve for pixels of new image that satisfy constraints on the gradient and the intensity
 - Constraints can be from one image (for filtering) or more (for blending)

2D image transformations



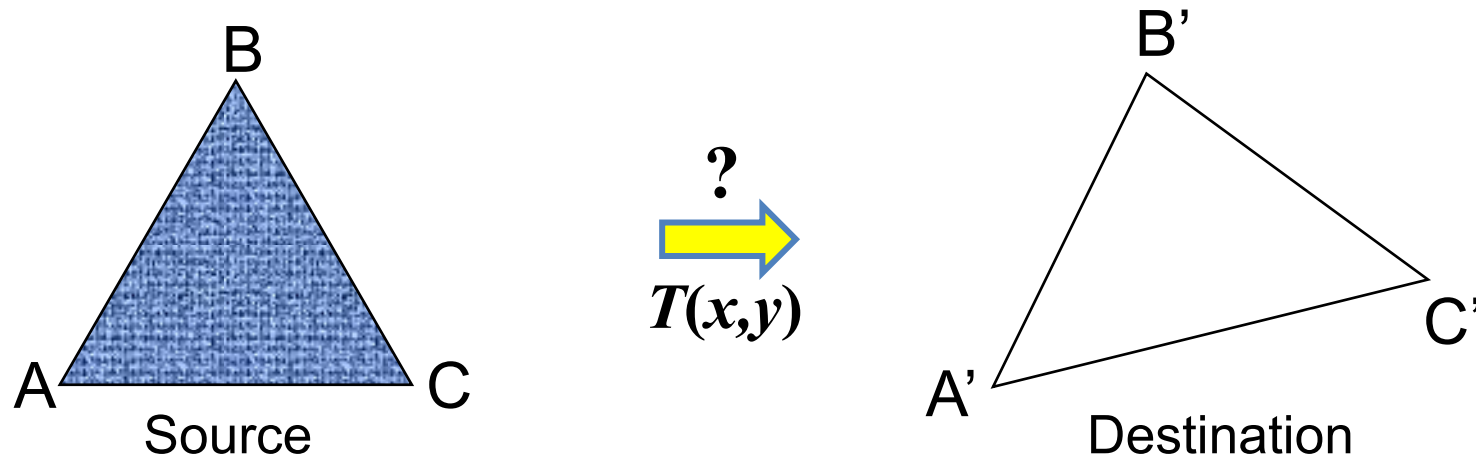
Name	Matrix	# D.O.F.	Preserves:	Icon
translation	$\begin{bmatrix} \mathbf{I} & \mathbf{t} \end{bmatrix}_{2 \times 3}$	2	orientation + ...	
rigid (Euclidean)	$\begin{bmatrix} \mathbf{R} & \mathbf{t} \end{bmatrix}_{2 \times 3}$	3	lengths + ...	
similarity	$\begin{bmatrix} s\mathbf{R} & \mathbf{t} \end{bmatrix}_{2 \times 3}$	4	angles + ...	
affine	$\begin{bmatrix} \mathbf{A} \end{bmatrix}_{2 \times 3}$	6	parallelism + ...	
projective	$\begin{bmatrix} \tilde{\mathbf{H}} \end{bmatrix}_{3 \times 3}$	8	straight lines	

These transformations are a nested set of groups

- Closed under composition and inverse is a member

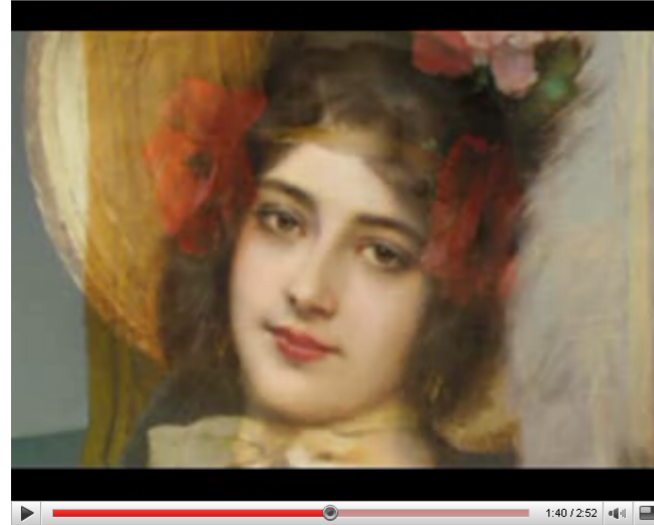
Take-home Question

Suppose we have two triangles: ABC and $A'B'C'$. What transformation will map A to A' , B to B' , and C to C' ? How can we get the parameters?



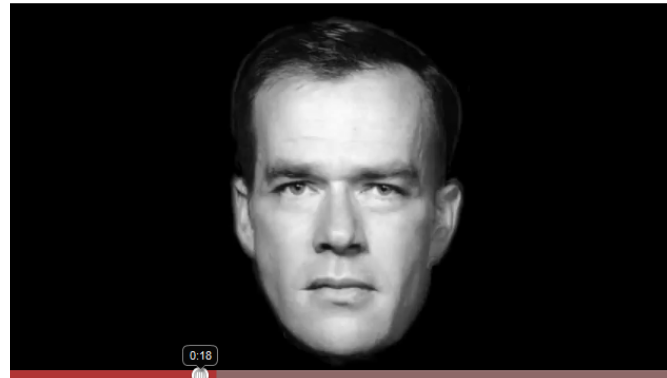
Today: Morphing

Women in art



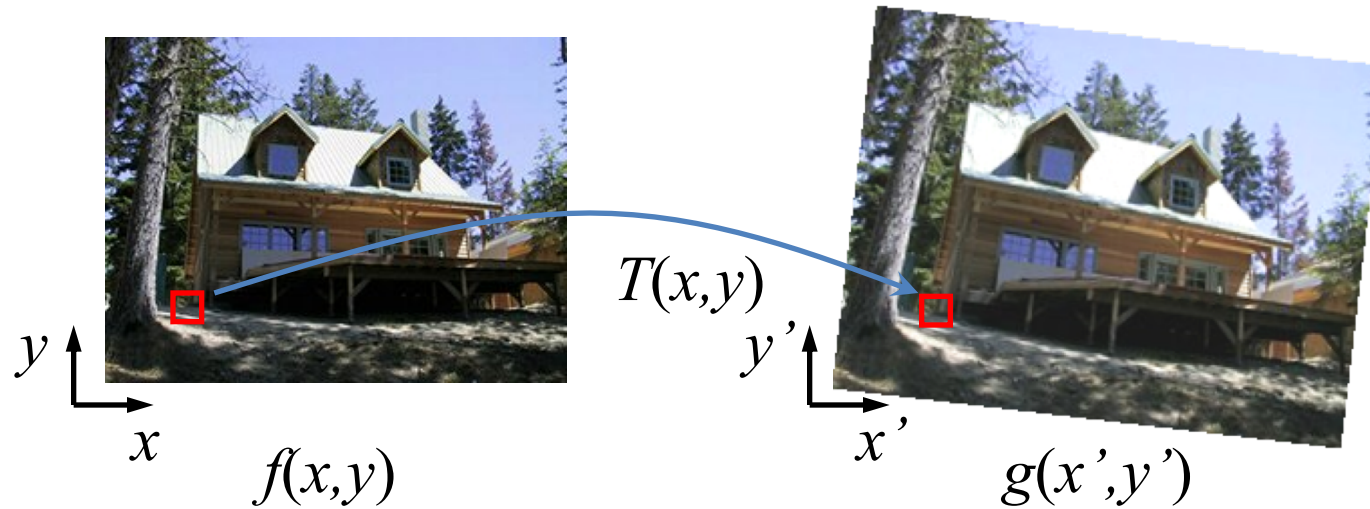
<http://youtube.com/watch?v=nUDIoN-Hxs>

Aging



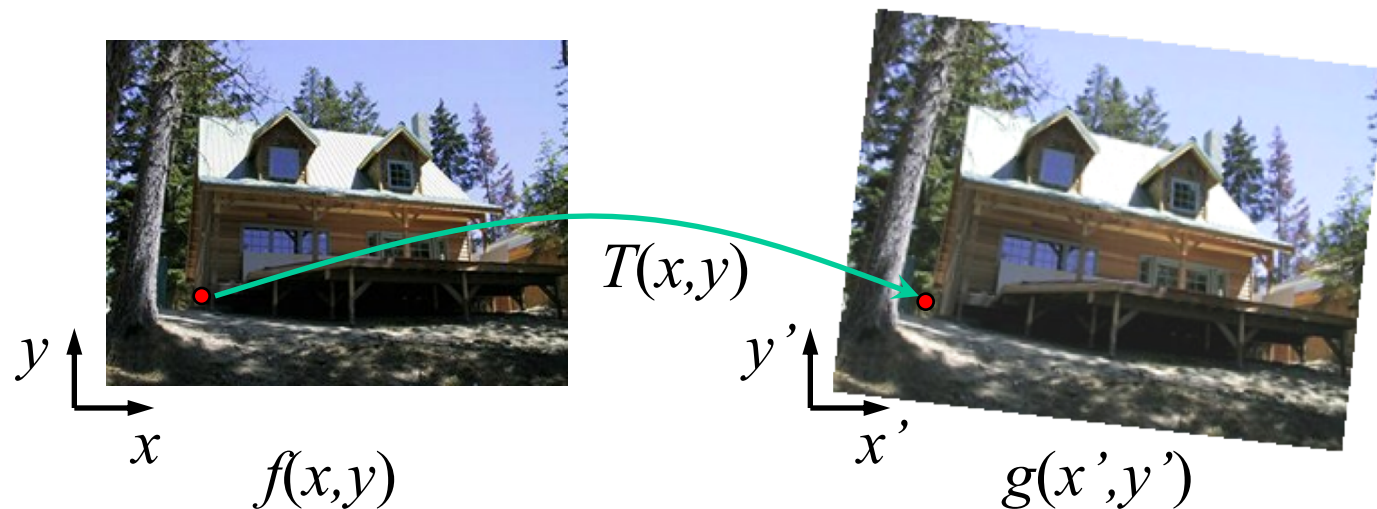
<http://www.youtube.com/watch?v=LOGKp-uvjO0>

Texturing in transformed coordinates



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

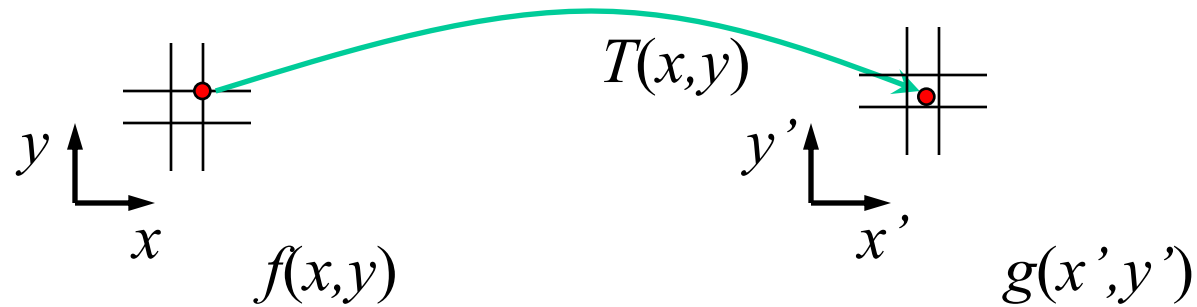
Forward mapping



Send each pixel $f(x,y)$ to its corresponding location
 $(x',y') = T(x,y)$ in the second image

Forward mapping

What is the problem with this approach?



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

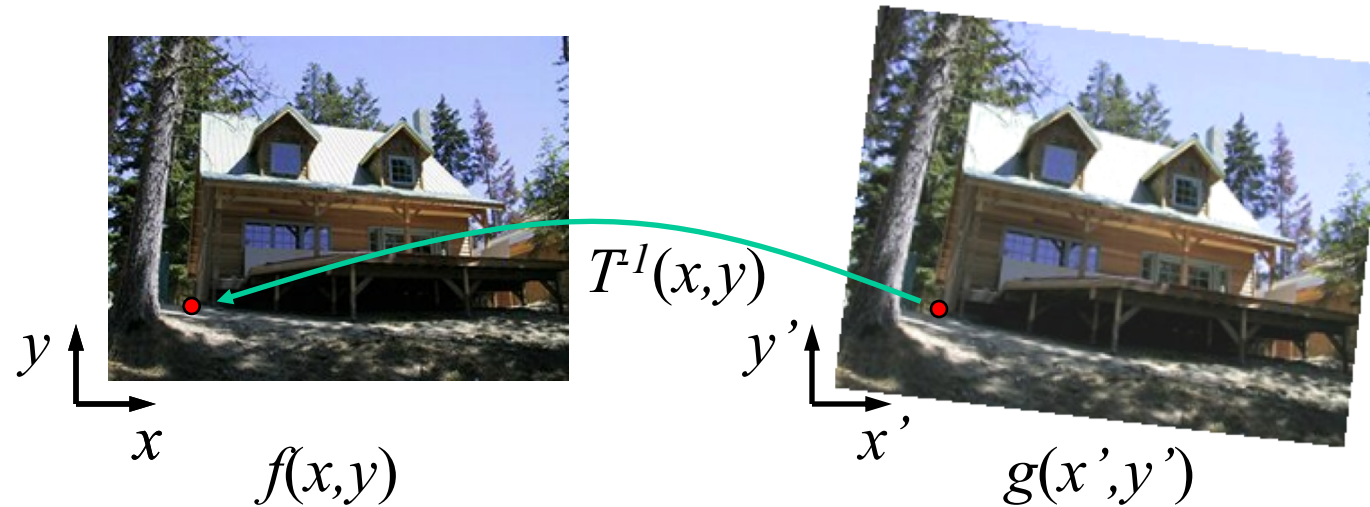
$(x',y') = T(x,y)$ in the second image

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

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

– Known as “splatting”

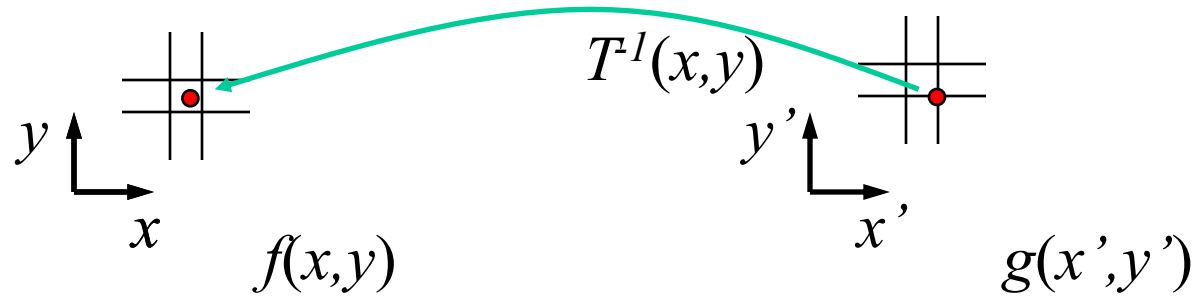
Inverse mapping



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 mapping



Get each pixel $g(x', y')$ from its corresponding location
 $(x, y) = T^{-1}(x', y')$ in the first image

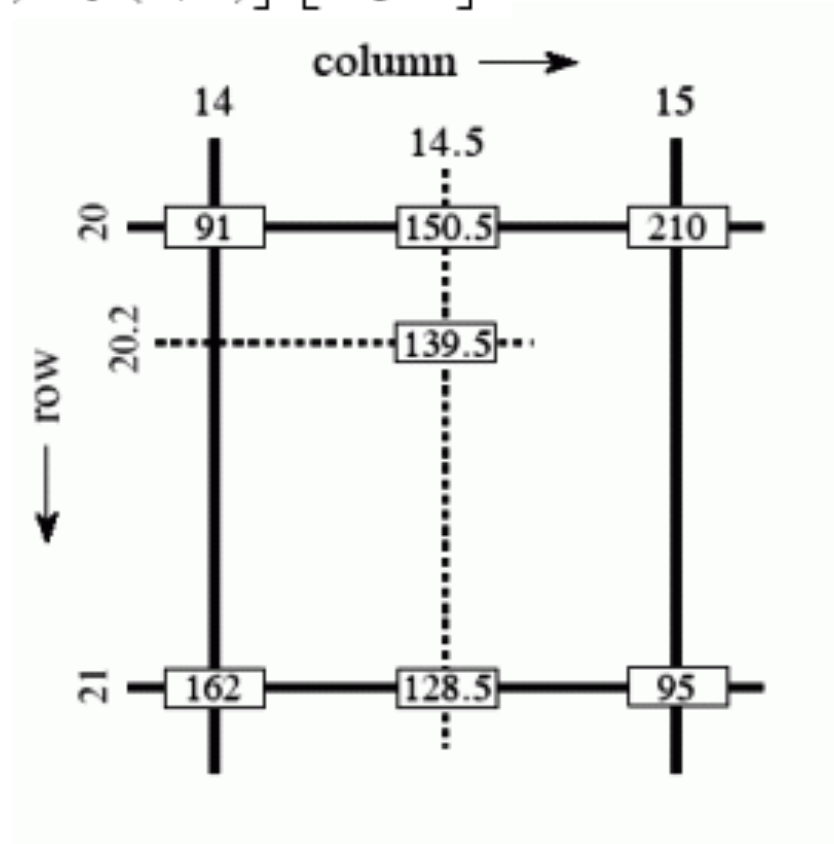
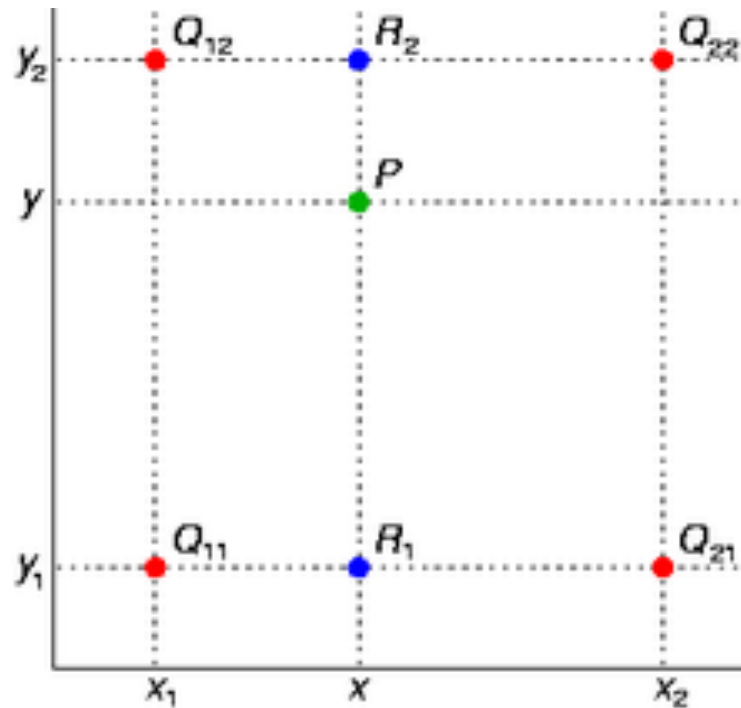
Q: what if pixel comes from “between” two pixels?

A: *Interpolate* color value from neighbors

- nearest neighbor, bilinear, Gaussian, bicubic
- E.g. `interpolate.interp2` or `ndimage.map_coordinates` in Python `scipy`

Bilinear Interpolation

$$f(x, y) \approx \begin{bmatrix} 1 - x & x \end{bmatrix} \begin{bmatrix} f(0, 0) & f(0, 1) \\ f(1, 0) & f(1, 1) \end{bmatrix} \begin{bmatrix} 1 - y \\ y \end{bmatrix}.$$



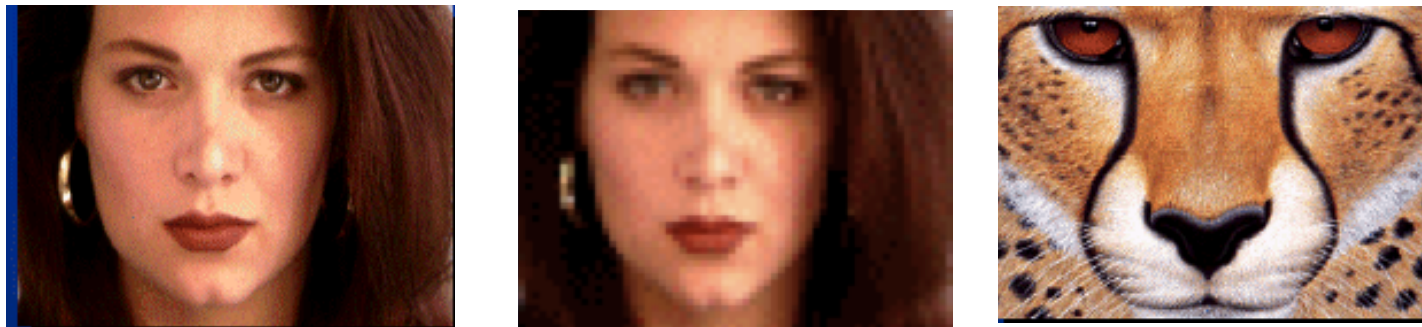
Forward vs. inverse mapping

Q: which is better?

A: Usually inverse—eliminates holes

- however, it requires an invertible warp function

Morphing = Object Averaging

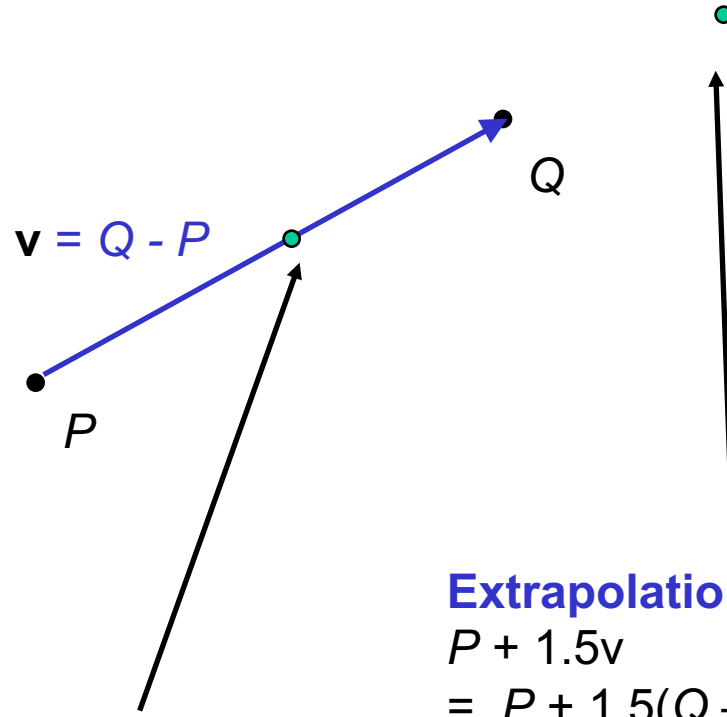


The aim is to find “an average” between two objects

- Not an average of two images of objects...
- ...but an image of the average object!
- How can we make a smooth transition in time?
 - Do a “weighted average” over time t

Averaging Points

What's the average of P and Q?



Linear Interpolation

New point: $P + t*(Q-P)$

Or equivalently: $(1-t)P + tQ$

$0 < t < 1$

$$\begin{aligned} P + 0.5v \\ &= P + 0.5(Q - P) \\ &= 0.5P + 0.5Q \end{aligned}$$

Extrapolation: $t < 0$ or $t > 1$

$$\begin{aligned} P + 1.5v \\ &= P + 1.5(Q - P) \\ &= -0.5P + 1.5Q \quad (t=1.5) \end{aligned}$$

P and Q can be anything:

- points on a plane (2D) or in space (3D)
- Colors in RGB (3D)
- Whole images (m-by-n D)... etc.

Idea #1: Cross-Dissolve



Interpolate whole images:

$$\text{Image}_{\text{halfway}} = (1-t) \cdot \text{Image}_1 + t \cdot \text{Image}_2$$

This is called **cross-dissolve** in film industry

But what if the images are not aligned?

Idea #2: Align, then cross-dissolve



Align first, then cross-dissolve

- Alignment using global warp – picture still valid

Dog Averaging



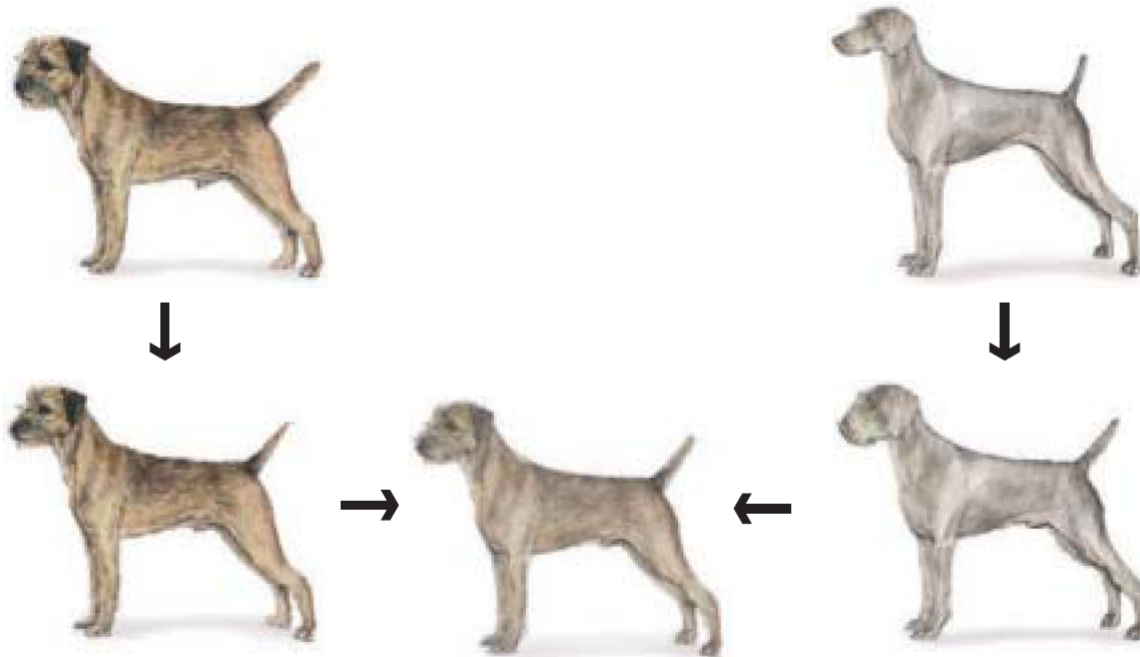
What to do?

- Cross-dissolve doesn't work
- Global alignment doesn't work
 - Cannot be done with a global transformation (e.g. affine)
- Any ideas?

Feature matching!

- Nose to nose, tail to tail, etc.
- This is a local (non-parametric) warp

Idea #3: Local warp, then cross-dissolve



Morphing procedure

For every frame t ,

1. Find the average shape (the “mean dog” 😊)
 - local warping
2. Find the average color
 - Cross-dissolve the warped images

Local (non-parametric) Image Warping



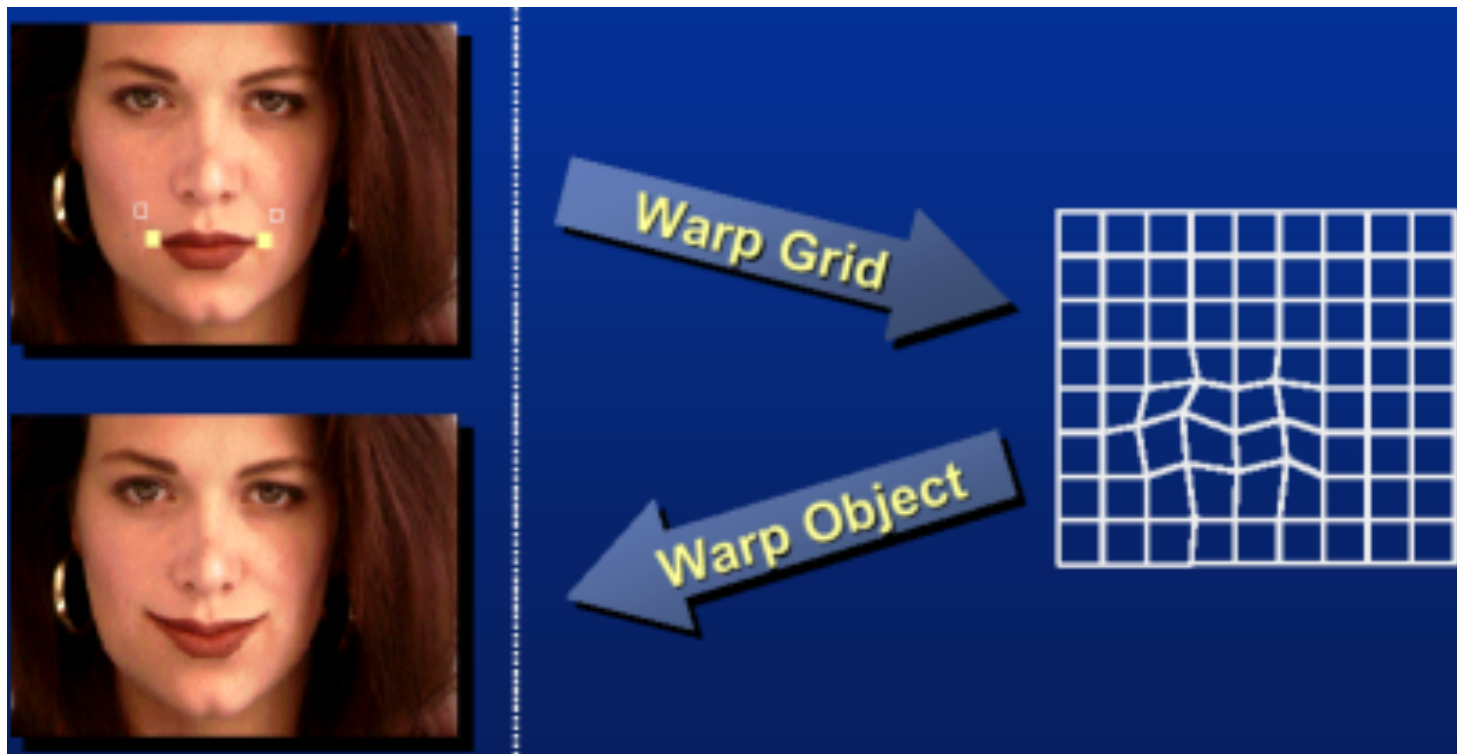
Need to specify a more detailed warp function

- Global warps were functions of a few (2,4,8) parameters
- Non-parametric warps $u(x,y)$ and $v(x,y)$ can be defined independently for every single location x,y !
- Once we know vector field u,v we can easily warp each pixel (use backward warping with interpolation)

Image Warping – non-parametric

Move control points to specify a spline warp

Spline produces a smooth vector field

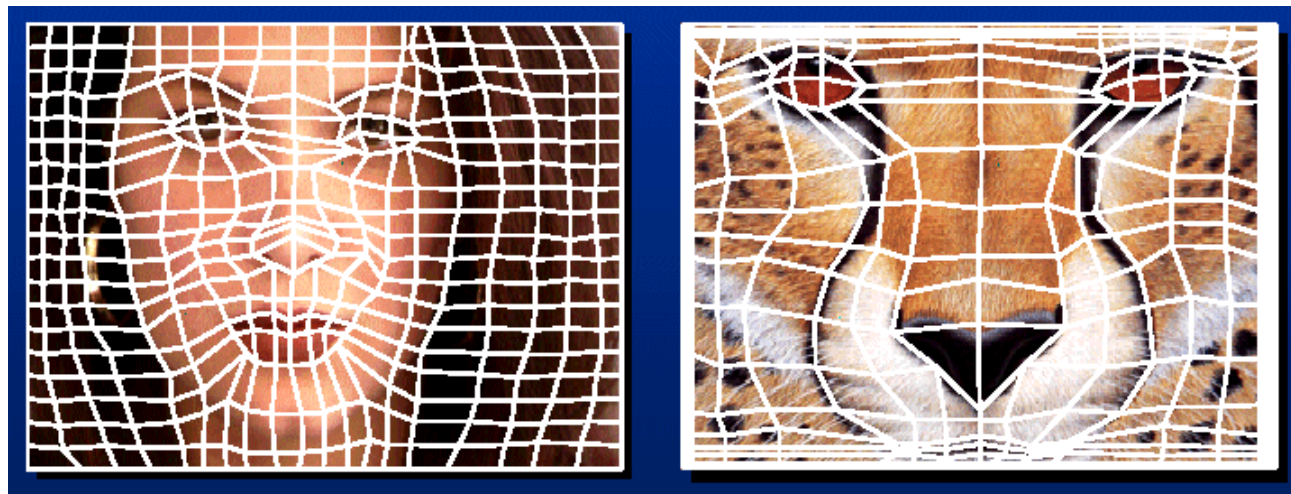


Warp specification - dense

How can we specify the warp?

Specify corresponding *spline control points*

- *interpolate* to a complete warping function



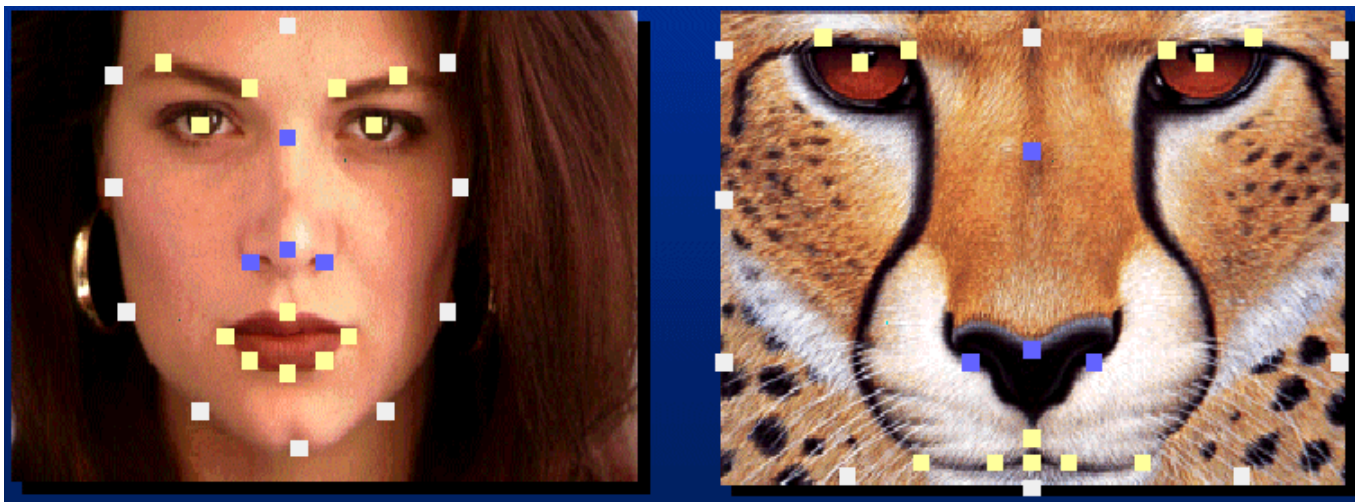
But we want to specify only a few points, not a grid

Warp specification - sparse

How can we specify the warp?

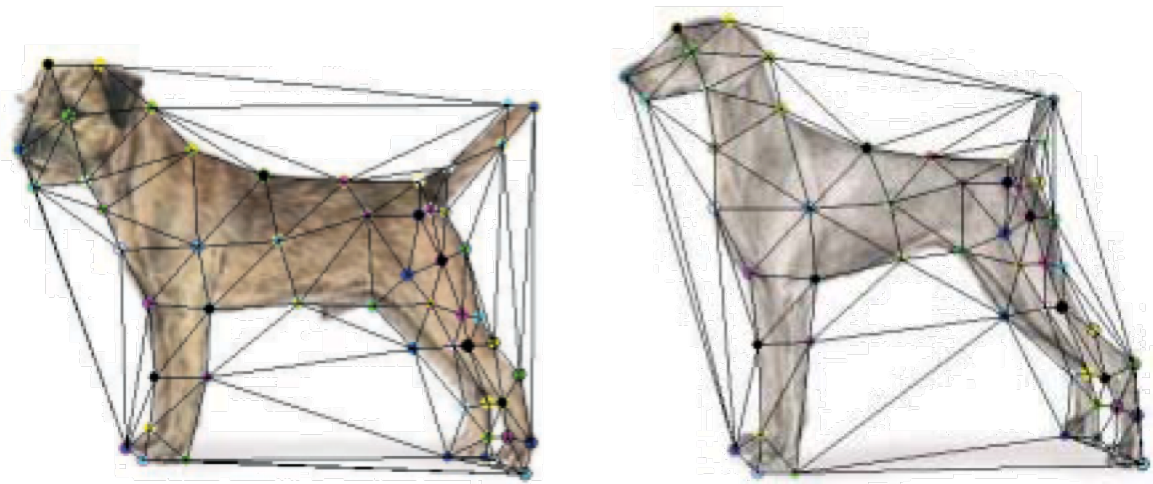
Specify corresponding *points*

- *interpolate* to a complete warping function
- How do we do it?



How do we go from feature points to pixels?

Triangular Mesh

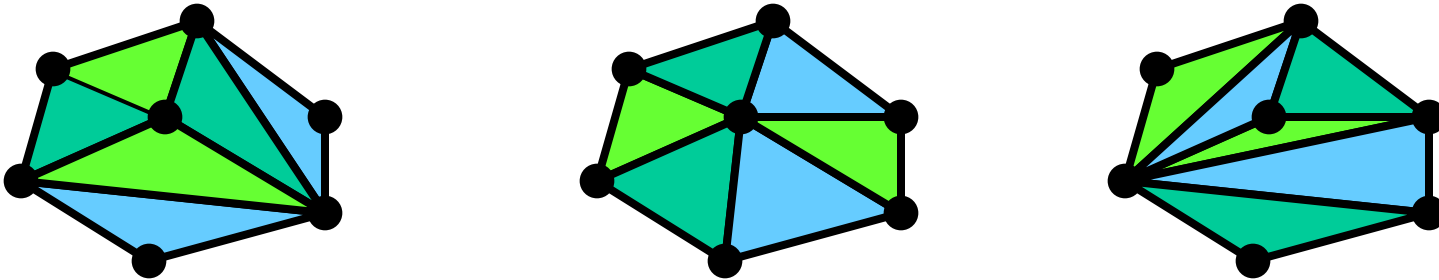


1. Input correspondences at key feature points
2. Define a triangular mesh over the points
 - Same mesh (triangulation) in both images!
 - Now we have triangle-to-triangle correspondences
3. Warp each triangle separately from source to destination
 - Affine warp with three corresponding points (just like take-home question)

Triangulations

A *triangulation* of set of points in the plane is a *partition* of the convex hull to triangles whose vertices are the points, and do not contain other points.

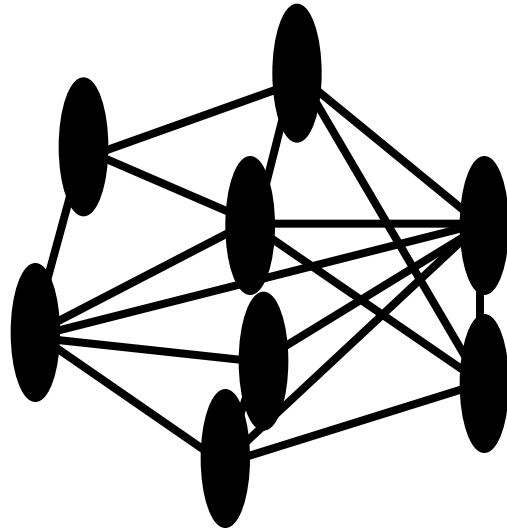
There are an exponential number of triangulations of a point set.



An $O(n^3)$ Triangulation Algorithm

Repeat until impossible:

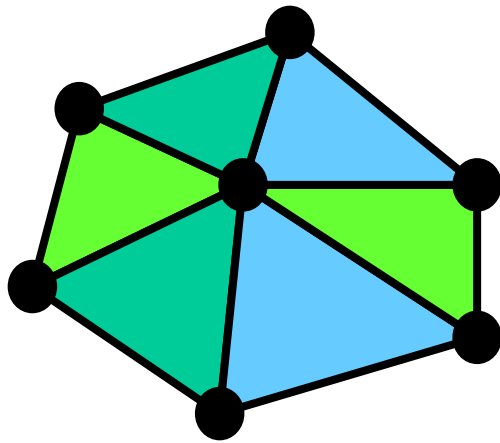
- Select two sites.
- If the edge connecting them does not intersect previous edges, keep it.



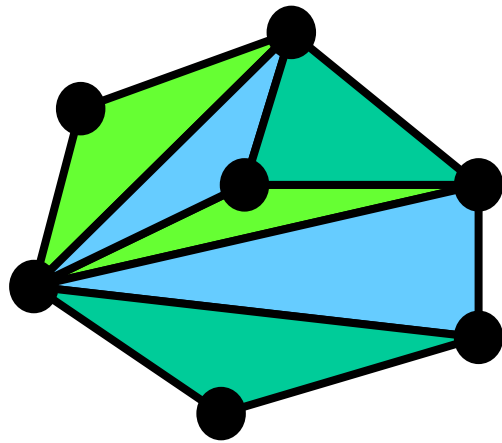
“Quality” Triangulations

Let $\alpha(T_i) = (\alpha_{i1}, \alpha_{i2}, \alpha_{i3}, \dots)$ be the vector of angles in the triangulation T in increasing order:

- A triangulation T_1 is “better” than T_2 if the smallest angle of T_1 is larger than the smallest angle of T_2
- Delaunay triangulation is the “best” (maximizes the smallest angles)



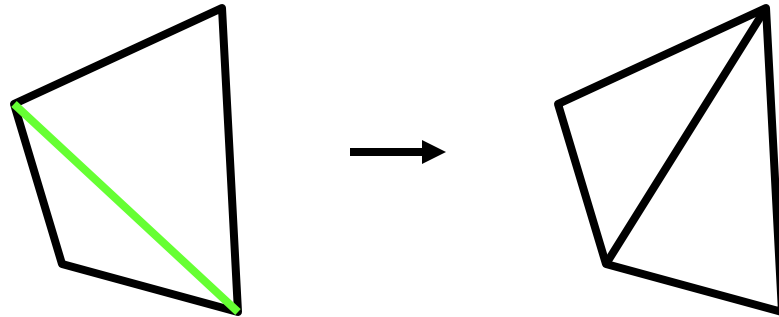
good



bad

Improving a Triangulation

In any convex quadrangle, an *edge flip* is possible. If this flip *improves* the triangulation locally, it also improves the global triangulation.

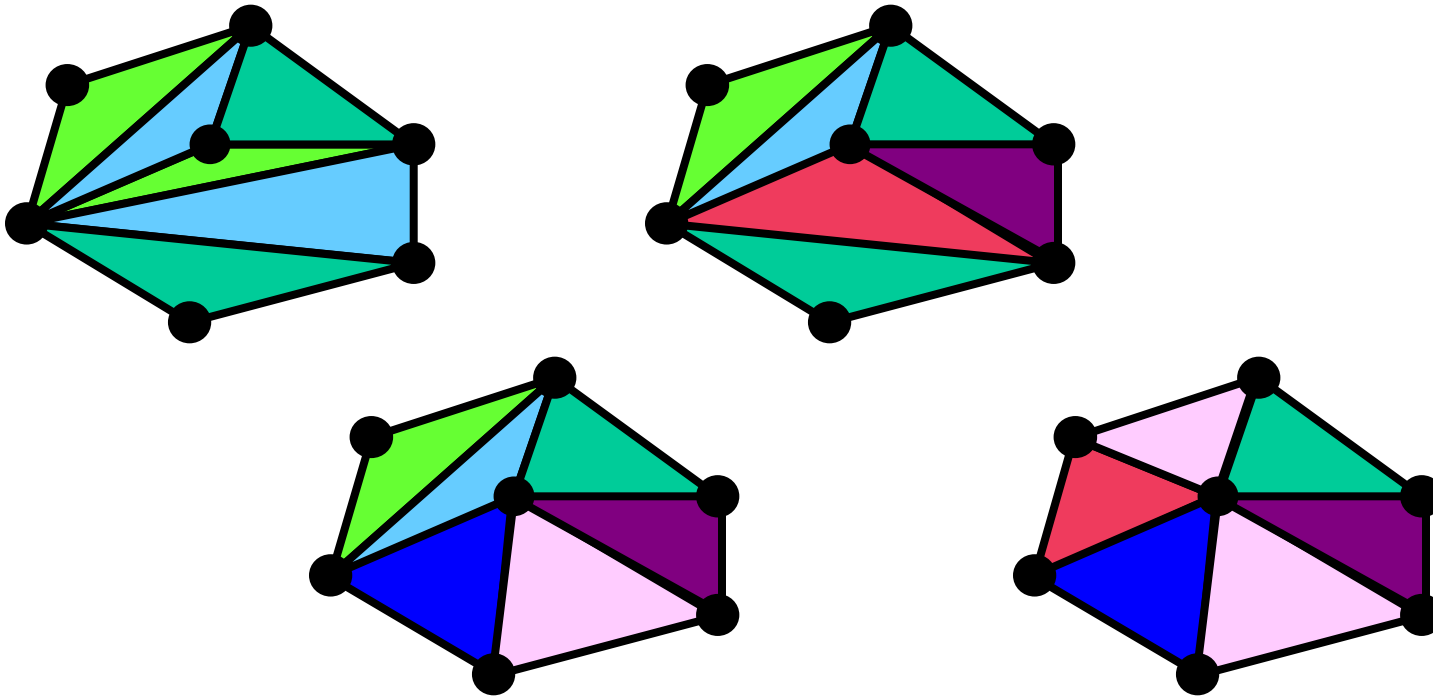


If an edge flip improves the triangulation, the first edge is called “*illegal*”.

Naïve Delaunay Algorithm

Start with an arbitrary triangulation. Flip any illegal edge until no more exist.

Could take a long time to terminate.



Delaunay Triangulation by Duality

Draw the dual to the Voronoi diagram by connecting each two neighboring sites in the Voronoi diagram.

- The DT may be constructed in $O(n \log n)$ time

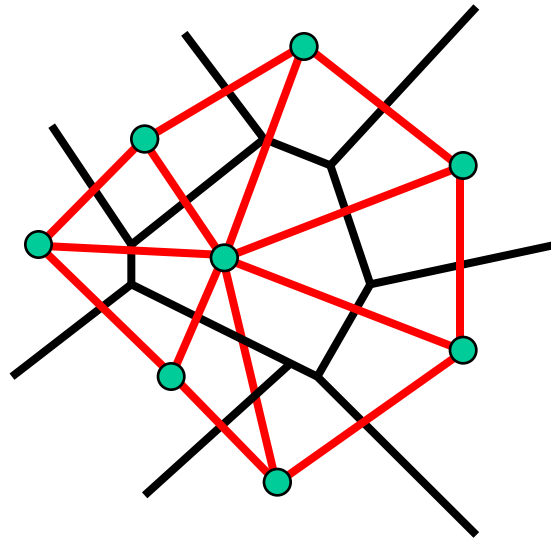
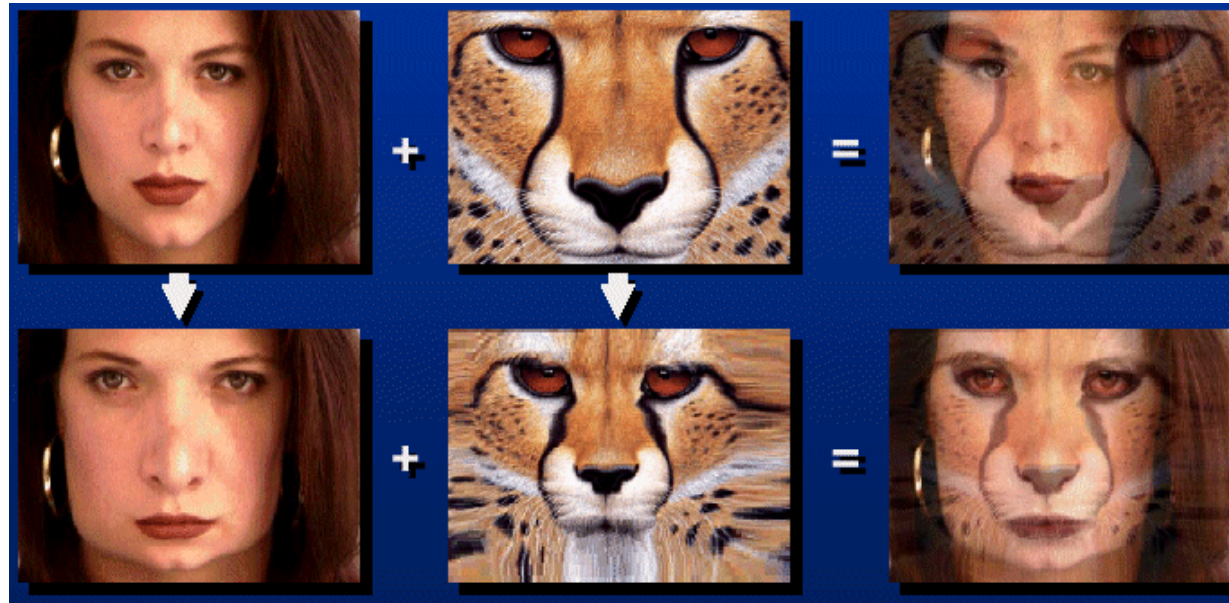


Image Morphing

How do we create a morphing sequence?

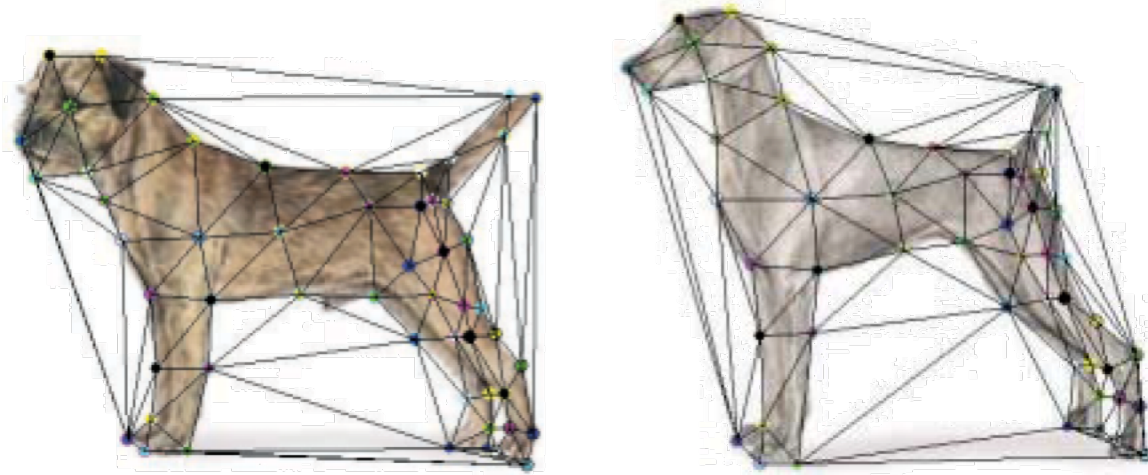
1. Create an intermediate shape (by interpolation)
2. Warp both images towards it
3. Cross-dissolve the colors in the newly warped images



Warp interpolation

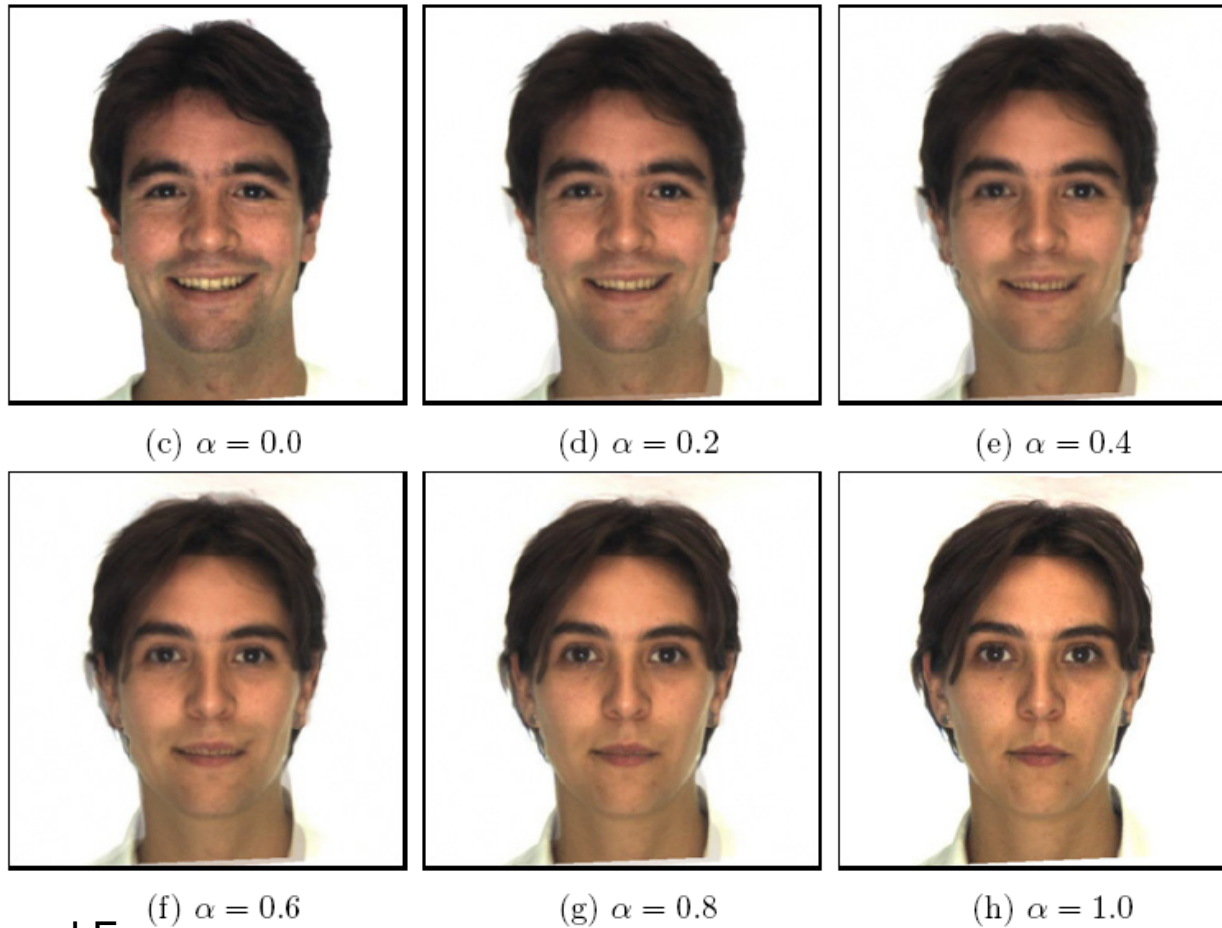
How do we create an intermediate shape at time t ?

- Assume $t = [0,1]$
- Simple linear interpolation of each feature pair
 - $(1-t)*p_1+t*p_0$ for corresponding features p_0 and p_1

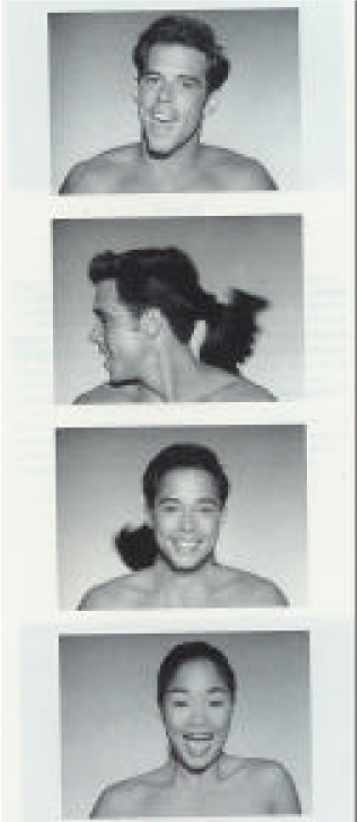


Morphing & matting

Extract foreground first to avoid artifacts in the background



Dynamic Scene



Black or White (MJ):

<http://www.youtube.com/watch?v=R4kLKv5gtxc>

Willow morph: <http://www.youtube.com/watch?v=uLUyuWo3pG0>

Summary of morphing

1. Define corresponding points
2. Define triangulation on points
 - Use same triangulation for both images
3. For each $t = 0:\text{step}:1$
 - a. Compute the average shape (weighted average of points)
 - b. For each triangle in the average shape
 - Get the affine projection to the corresponding triangles in each image
 - For each pixel in the triangle, find the corresponding points in each image and set value to weighted average (optionally use interpolation)
 - c. Save the image as the next frame of the sequence

Next classes

Pinhole camera: start of perspective geometry

Single-view metrology: measure 3D distances
from an image