S11/Venue A(Oral)/ Image and Video Processing VI/12-Jan-10, 16:00-18:20

Session Chair: Dr. Junaidi Abdullah, Multimedia University

Authors	Paper Title
Tong Hau Lee, Mohammad Faizal Ahmad Fauzi	Two-stage segmentation for abnormalities and ventricles extraction
Serkan Kiranyaz , Moncef Gabbouj , Jenni Pulkkinen , Turker Ince , Kristian Meissner	Classification and retrieval on macroinvertabrate image databases using evolutionary RBF neural networks
Chee Suit Chan, Mohammad Faizal bin Ahmad Fauzi2	Gender and ethnicity classification of malaysian faces
Jedong Kim, Chang Yeol Choi , Manbae Kim	Stereoscopic perception improvement using color and depth transformation
Young-Min Seong, Bo-Gyu Jeong, Il-Kyu Eom	CFA interpolation using color difference rule in wavelet domain
Sang-Beom Lee , Yo-Sung Ho	Temporally consistent depth map generation using motion compensation for 3dtv

Temporally Consistent Depth Map Generation using Motion Compensation for 3DTV

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ABSTRACT

In this paper, we propose a new method to generate temporally more consistent depth sequences using motion compensation for 3DTV. We first calculate the matching cost using the left and right views. In order to enhance temporal consistency, we modify the matching function by adding the temporal weighting function and we perform the motion compensation operation on the previous depths of moving objects. Experimental results show that the proposed algorithm improves temporal consistency of the depth sequence and reduces flickering artifacts in the synthesized view, while maintaining good visual quality.

Keywords: Three-dimensional television, Multi-view video, Depth estimation, Temporal consistency.

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1. INTRODUCTION

Owing to advancements in computing power, interactive computer graphics, digital transmission, and immersive visual displays, we experience and reproduce simulations of reality. In other words, the gap between the real world and the virtual environment is getting closer. When users are exposed to such immersive, interactive, and perceptually realistic media, they report a sense of presence in the mediated environment [1][2]. Especially, technological advances in displays have been aimed at improving the range of vision, such as a wide-screen, high-definition, immersive, and 3D displays.

Recently, a three-dimensional television (3DTV) using multi-view video is in the spotlight as one of the next-generation broadcasting services [3]. In order to acquire multi-view video, we utilize multiple cameras with parallel or convergent configuration to capture a 3D scene with wide-viewing angle. We believe that the 3DTV is the next-generation broadcasting system in the history of TV. By aiding of advances in display devices, such as stereoscopic displays, the 3DTV provides users with a feeling of presence, from the simulation of reality. In this decade, we expect that the technology will be progressed enough to realize the 3DTV including content generation, coding, transmission, and display. Figure 1 shows the conceptual framework of the 3DTV system [4].

In general, there are two major problems in multi-view video. The first problem is the reliability of distance between cameras. The other problem is the sudden viewpoint change. When users change their views while watching contents through the 3D display, they feel unnatural viewpoint change on the display if the distance between adjacent cameras is large and the scene is changed suddenly. It causes a visual discomfort to viewers' eyes.

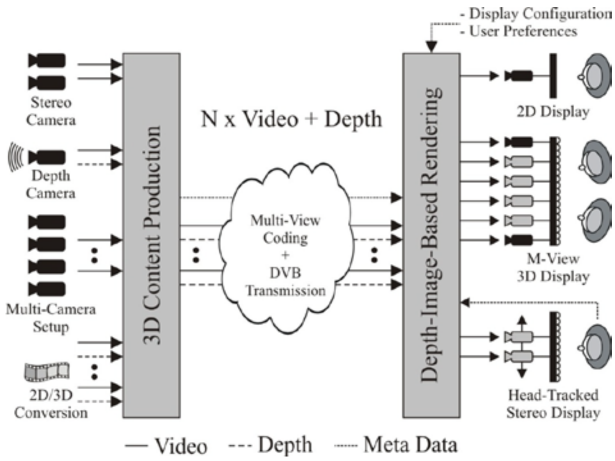


Figure 1. Three-dimensional television system

In order to reconstruct intermediate views of virtual viewpoints, we need depth information. Many works have been carried out for the acquisition of 3D depth information [5][6]. Recently, 3D video coding subgroup members in Moving Picture Experts Group (MPEG) recognized the importance of multi-view video and the corresponding depth sequence, and they tried to develop the depth estimation and the view synthesis tools [7]. As a result, they implemented and distributed the graph cut-based depth estimation software [8].

However, the software includes several problems such as boundary mismatch, textureless regions, or wide baseline. Especially, since the software estimates depth sequence for each frame separately, the depth sequence is temporally inconsistent. In other words, we notice the inconsistent depth values at the same background but in a different time. This problem causes flickering artifacts and it discomforts the users.

Therefore, we propose a new algorithm for enhancing temporal consistency of the depth sequence. The main contribution of this paper is that we add a temporal weighting function to the conventional matching function for consistent depth map estimation. The temporal weighting function refers to the previous depth when estimating the current depth. In order to exploit the temporal weighting function for the moving objects, we reconstruct the depth map from the previous depth map by using motion estimation technique. In addition, we prevent the border error propagation to reduce the depth errors.

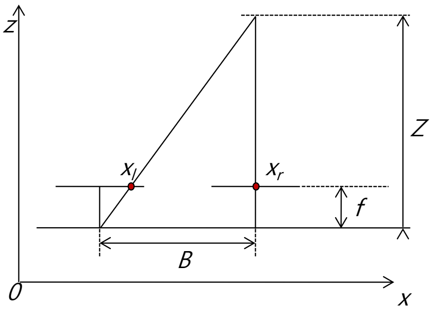


Figure 2. Relationship between disparity and depth

2. MULTI-VIEW DEPTH ESTIMATION

2.1 Disparity and Depth

Figure 2 illustrates the relationship between disparity and depth. Suppose that a certain 3D point is projected onto the right image plane and it is located at (x_r,y). This 3D point is also projected onto the left image plane and it is located at (x_l,y). Then, the relationship between disparity d and depth Z can be defined by

$$Z = \frac{Bf}{d} = \frac{Bf}{x_l - x_r} \tag{1}$$

where B represents the camera distance and f represents the focal length of each camera. This equation proves that we can find the depth if we estimate the disparity by using the correspondence of multi-view video.

2.2 Disparity Computation

As mentioned before, 3D video coding subgroup members in MPEG tried to develop the depth estimation and the view synthesis tools. As a result, they implemented and distributed the depth estimation and view synthesis softwares. The software is categorized by three parts: disparity computation, graph cut-based error minimization, and disparity-to-depth conversion.

The first step is to aggregate the matching costs for whole pixels of the center view. Since we have three and more views of multi-view video, we can compare center view to the left and right view simultaneously. Thus, we can easily handle the occlusion region that is visible in the center view but become invisible in the left or right views. The matching function is defined by

$$E_{sim}(x,y,d) = \min\{E_L(x,y,d), E_R(x,y,d)\} \tag{2}$$

$$E_L(x,y,d) = |I_C(x,y) - I_L(x+d,y)| \tag{3}$$

$$E_R(x,y,d) = |I_C(x,y) - I_R(x-d,y)| \tag{4}$$

where $I(x,y)$ indicates the intensity at the point (x,y).

The second step is graph cut-based error minimization. The optimum disparity value is determined in this step by comparing matching costs of neighbor pixels.

The third step is disparity-to-depth conversion. The depth map can be represented by 8-bit grayscale image with the gray level 0 specifying the farthest value and the gray level 255 defining the nearest value. The metric space between the near clipping plane and the far clipping plane is divided into the same 256 spaces. Then, the depth value Z which corresponds to the pixel (x,y) is transformed into the 8-bit gray value v as follows:

$$v = \left\lfloor 255 - \frac{255(Z - Z_{near})}{Z_{far} - Z_{near}} + 0.5 \right\rfloor \tag{5}$$

where Z_{far} and Z_{near} represent the farthest and nearest depth values. Figure 3 shows the 3D scene limited by two clipping planes, far and near clipping planes.

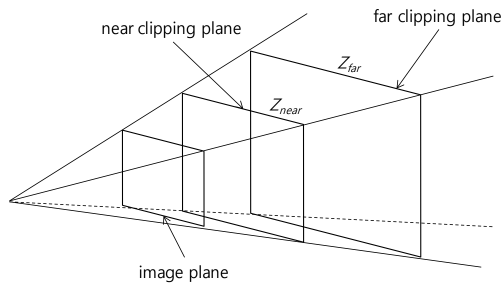


Figure 3. 3D scene limited by two clipping planes

2.3 Sub-pixel Precision

In order to improve the accuracy of the depth map, sub-pixel precision depth estimation is introduced. The left or right views are upsampled by various interpolation techniques, such as bi-linear or bi-cubic filter. Then, we can find the disparity more precisely. The upsampling can be done in half-pixel or quarter-pixel level. Figure 4 shows the sub-pixel precision of depth estimation.

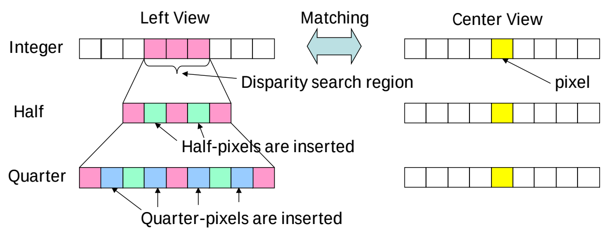


Figure 4. Sub-pel precision of depth estimation

3. TEMPORAL CONSISTENCY ENHANCEMENT

3.1 Temporal Weighting Function using Motion Estimation

As mentioned before, since previous works estimate the depth map for each frame separately, the depth sequence is temporally inconsistent. Therefore, we add a temporal weighting function that refers to the previous depth when estimating the current depth [9]. The temporal weighting function is defined by

$$E_{temp}(x,y,d) = \lambda \,|\, d - D_{prev}(x+\Delta x, y+\Delta y) \,| \quad (6)$$

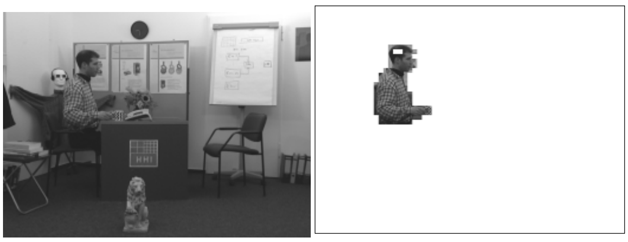
where λ represents the slope of the function and $D_{prev}(x,y)$ represents the previous disparity. Therefore, the updated matching function is defined by

$$E_{new}(x,y,d) = E_{sim}(x,y,d) + E_{temp}(x,y,d) \quad (7)$$

Since viewers mostly feel the flickering artifacts at the background, we first apply the weighting function to the background so as to reduce flickering artifacts. In order to separate the moving object, we calculate mean absolute difference (MAD) for each block and distinguish by threshold whether the block is background or not. Therefore, λ can be defined by

$$\lambda = \begin{cases} 1 & \text{if } MAD_k < Th \\ 0 & \text{otherwise} \end{cases} \quad (8)$$

where MAD_k represents the MAD of the k-th block including the position (x,y) and Th represents the threshold. The threshold is set by the experiments. Figure 5 shows the result of the moving object detection for 'Book Arrival'.



(a) Original image (b) Detected moving object

Figure 5. Moving object detection for 'Book Arrival'

In order to exploit the temporal weighting function for moving objects, we perform the motion estimation technique. Notice that the block size for motion estimation is smaller than that for the moving object detection for more accurate and reliable motion search. Figure 6 shows 80^{th} frame of the reconstructed depth map resulting from motion estimation.

Figure 6. Reconstructed depth map for 'Book Arrival'

3.2 Prevention of Border Error Propagation

One of the noticeable errors of the graph cut-based depth estimation exist near the border of the depth map. If the foreground object suddenly appears from outside of the scene to the inside or approaches near the border, the background near the object has depth values of the object. Figure 7 shows the depth errors near the borders.

(a) 29th frame of view 7

(b) 67th frame of view 7

Figure 7. Depth errors near the border for 'Book Arrival'

If the area near the border is detected as the background, the temporal weighting function refers the wrong depth values and the errors are propagated. It leads to the serious problem for temporal consistency enhancement.

Therefore, we need to prevent the border error propagation. If λ is equal to 0, we refer to the depth values in the previous frame only when λ is equal to 0. Figure 8 shows how to refer the previous frame when applying the temporal weighting function. As shown in Figure 8, the bold line represents the reference method for the border areas, whereas the dotted line represents the typical reference.

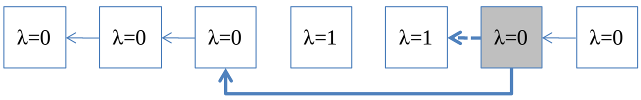
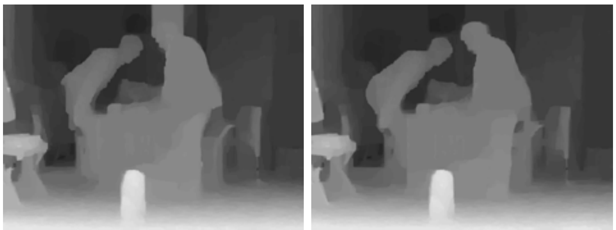


Figure 8. Prevention method for previous frame reference

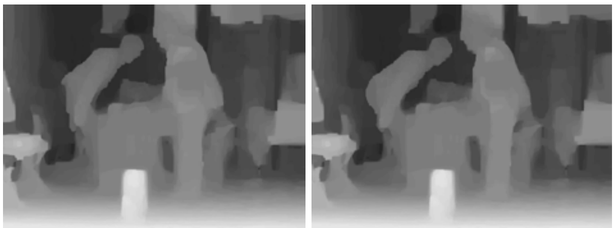
Figure 9 shows the results of prevention of border error propagation. As shown in Figure 9(b), if we do not prevent the border error propagation, the depth sequence has the depth errors near the border and those errors propagate. However, as shown in Figure 9(c), we can enhance the temporal consistency without the border error propagation.

4. EXPERIMENTAL RESULTS

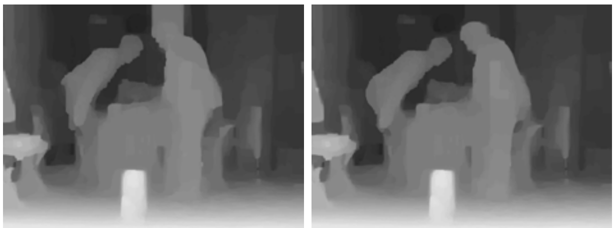
In our experiments, we used four test sequences: 'Alt Moabit', 'Book Arrival' provided by Heinrich-Hertz-Institut (HHI) [10], 'Lovebird1' provided by Electronics and Telecommunications Research Institute (ETRI) and MPEG-Korea Forum [11], and 'Newspaper' provided by Gwangju Institute of Science and Technology (GIST) [12]. These sequences are distributed for the purpose of 3D video coding and the resolution of them is 1024x768.



(a) previous work



(b) no prevention



(c) prevention results

Figure 9. Results of prevention of border error propagation

4.1 Depth Estimation and View Synthesis

In order to obtain the depth sequence, we used the Depth Estimation Reference Software (DERS) provided by the 3D video coding subgroup in MPEG. In our experiments, the block size for the background separation is set to 32 and the block size for motion estimation is 8. The search range is set to be from -16 to +16. The threshold values for moving object detection are selected through several experiments, and shown in Table 1.

Table 1. Threshold for moving object detection

Sequence	Threshold
Alt Moabit	2.50
Book Arrival	3.00
Lovebird1	1.50
Newspaper	1.50

Figure 10 through Figure 12 show the depth sequences for 'Alt Moabit', 'Book Arrival' and 'Newspaper'. As shown in Figure 10(a), through Figure 12(a), we noticed that the depth sequences have inconsistent depth near the background, whereas the depth sequences in Figure 10(b) through Figure 12(b) are temporally consistent.

In order to synthesize the virtual view, we used View Synthesis Reference Software (VSRS) provided by 3D video coding subgroup in MPEG [10]. Figure 13 through Figure 15 show the virtual views for 'Alt Moabit', 'Book Arrival' and 'Newspaper'. The right figures show the difference images between the left and the center figures. We also noticed that the virtual views have errors at the background as shown in Figure 13(a) through Figure 15(a), whereas the virtual views in Figure 13(b) through Figure 15(b) have less errors than those without temporal consistency enhancement.

Table 2 shows the average PSNR using the original view and the virtual view. As shown in the results, PSNR of the proposed algorithm was almost the same as that of the previous work. It means that the flickering artifacts of synthesized views were reduced without any degradation of objective quality.

Table 2. Average PSNR of virtual views

Sequence	View	DERS	Proposed method	Difference (ΔdB)
Alt Moabit	8	35.1473	35.3298	0.1825
	9	35.4158	35.4689	0.0532
Book Arrival	8	34.3986	34.4529	0.0542
	9	35.5694	35.5472	-0.0222
Lovebird1	6	30.9870	30.9866	-0.0004
	7	30.4126	30.4214	0.0087
Newspaper	4	24.3732	24.3695	-0.0037
	5	25.4442	25.4389	-0.0054
Average		31.4685	31.5019	0.0334

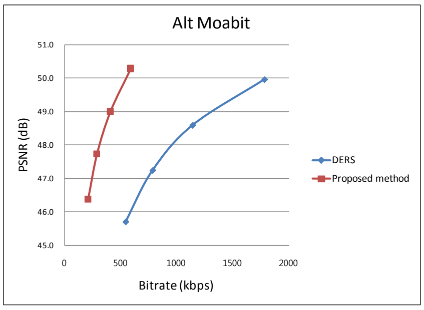
4.2 Depth Map Coding

For the evaluation of the effects on the video coding of our proposed method, we performed depth map coding for each sequence by using the H.264/AVC reference software version JM 14.0. We tested 100 frames for each sequence and the coding structure was IPPP...P. Table 3 represents the depth map coding results and Figure 16 shows the rate-distortion curves for each sequence.

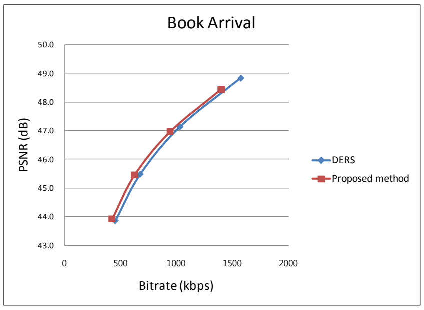
Table 3. Depth map coding results

Sequence	QP	DERS		Proposed method	
		PSNR (dB)	Bitrate (kbps)	PSNR (dB)	Bitrate (kbps)
Alt Moabit (view 7)	22	49.96	1785.46	50.29	592.22
	25	48.59	1144.74	49.00	410.21
	28	47.24	788.39	47.73	290.33
	31	45.70	547.95	46.38	211.50
Book Arrival (view 7)	22	48.83	1573.54	48.43	1396.91
	25	47.13	1032.20	46.96	941.86
	28	45.48	677.70	45.46	625.13
	31	43.86	456.22	43.92	423.30
Lovebird1 (view 5)	22	55.64	384.62	55.66	170.26
	25	54.07	260.00	54.44	114.63
	28	51.92	142.81	52.96	77.36
	31	50.06	87.58	51.37	57.33
Newspaper (view 3)	22	51.47	1229.67	51.25	730.68
	25	49.67	829.03	49.53	488.31
	28	47.83	556.19	47.78	323.41
	31	45.95	383.23	45.97	221.28

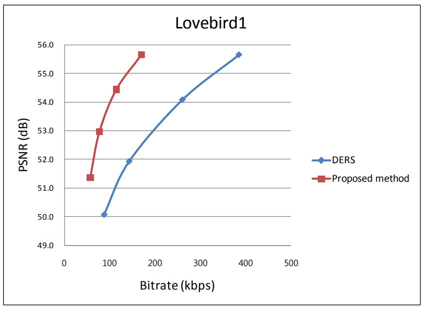
From the depth map coding results, we noticed that the the visual quality of the proposed algorithm was improved about 2.56dB or the bitrate was reduced about 42.55% in Bjontegaard measure [13]. Since the proposed algorithm enhanced the temporal consistency of depth sequences without any degradation of virtual views, the accurate inter prediction of H.264/AVC was possible and the coding efficiency was improved.



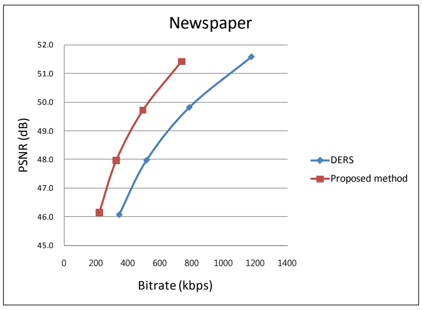
(a) Alt Moabit



(b) Book Arrival



(c) Lovebird1



(d) Newspaper

Figure 16. Rate-distortion curves

5. CONCLUSIONS

In this paper we have proposed the temporal consistency enhancement algorithm for multi-view depth estimation. We used the block-based moving object detection to separate the moving object from the background and applied the temporal weighting function only to the background. As a result, we reduced the flickering artifacts of virtual views without any degradation of visual quality from the experimental results.

ACKNOWLEDGEMENT

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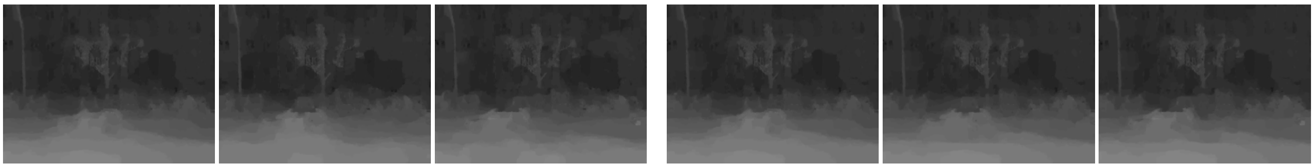
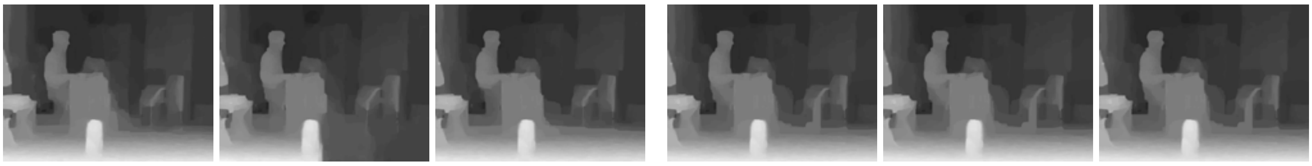


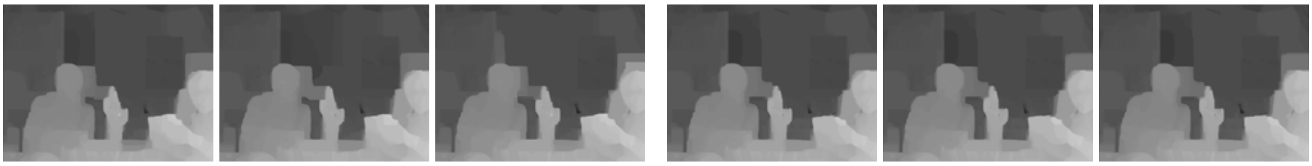
(a) Depth map without temporal consistency enhancement (b) Depth map with temporal consistency enhancement

Figure 10. Depth estimation results for 'Alt Moabit'



(a) Depth map without temporal consistency enhancement (b) Depth map with temporal consistency enhancement

Figure 11. Depth estimation results for 'Book Arrival'



(a) Depth map without temporal consistency enhancement (b) Depth map with temporal consistency enhancement

Figure 12. Depth estimation results for 'Newspaper'

(a) Virtual view without temporal consistency enhancement (b) Virtual view with temporal consistency enhancement

Figure 13. View synthesis results for 'Alt Moabit'

(a) Virtual view without temporal consistency enhancement (b) Virtual view with temporal consistency enhancement

Figure 14. Results of virtual view for 'Book Arrival'

(a) Virtual view without temporal consistency enhancement (b) Virtual view with temporal consistency enhancement

Figure 15. View synthesis results for 'Newspaper'