Application of Fuzzy Reasoning for Filtering and Enhancement of Ultrasonic Images

J. P. Sacha*, K. J. Cios†, D. J. Roth‡, L. Berke‡ and A. Vary‡

† Edison Industrial Systems Center
‡ University of Toledo
§ NASA Lewis Research Center

Abstract - This paper presents a new type of an adaptive fuzzy operator for detection of isolated abnormalities, and enhancement of raw ultrasonic images. Fuzzy sets used in decision rules are defined for each image based on empirical statistics of the color intensities. Examples of the method are also presented in the paper.

I. INTRODUCTION

Ultrasonic testing is one of the techniques used for nondestructive characterization of materials. In this work our interest is in one of its variations called contact scanning, where one front surface and two back surface ultrasonic pulses obtained using the pulse-echo configuration are digitized and stored at every scan location. These digitized pulses are used to compute ultrasonic properties versus frequency like phase velocity, cross-correlation velocity (not a function of frequency), reflection coefficient, attenuation coefficient and others [2-4]. Ultrasonic properties can be used to form ultrasonic images where values of a given property (at any frequency within transducer bandwidth) are represented by corresponding gray or color scale values. On a raw ultrasonic image each point (pixel) represents a single location for which ultrasonic data were collected. An example of a raw ultrasonic image representing a phase velocity1 at 60 MHz is shown in Figure 1. Ultrasonic images from contact scans are typically enhanced using linear or cubic interpolation. Enhanced images are used to determine areas which correspond to undesired properties of a tested material. Figure 2 represents an enhanced ultrasonic

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1 Explanation of phase velocity is given in the Appendix.
image obtained directly from the raw image shown in Figure 1. Note three red and two blue "circles" in the image (dark circles on black and white illustrations). Each of these circles corresponds to a single point on the raw ultrasonic image; they are examples of "undesired phenomena" for further image analysis. In general, while constructing an ultrasonic image we are interested in global trends, thus properties of separated points are irrelevant. These "undesired" isolated points on the raw ultrasonic image should be identified and filtered before the image is enhanced. Figure 3 shows an enhanced image created from a filtered ultrasonic image of Figure 1.

Existence of the undesired points on the ultrasonic images can be attributed to:

1. Corruption of the ultrasonic pulse data. It usually occurs during digitization of analog data and has random nature. There are several types of these pulse data abnormalities, and only few of them can be detected by a direct analysis of digital pulses.

2. Ultrasonic pulse data is collected and digitized correctly, but properties of the tested material at these isolated points are "significantly" different from its neighbors.

3. Intrinsic uncertainties in data used for calculation of ultrasonic properties, like total difference in phase between first and second back reflection, used to calculate phase velocity.

The aim of this paper is to construct adaptive fuzzy operators for automatic detection of isolated suspicious points on an ultrasonic image. These points once detected can be either removed to facilitate creation of smoother enhanced image, or further investigated to determine the nature of their origin.

A method of fuzzy operator synthesis, presented in this paper, employs usage of statistical data obtained from a raw ultrasonic image, like histograms of pixel intensity or histograms of intensity differences between neighboring pixels. The data are processed and used to generate fuzzy sets representing desired versus undesired image contents.

II. STRUCTURE OF THE FUZZY OPERATOR

Let us start with a description of a fuzzy operator for image processing similar to the one presented in [1].

A. Generalized description of fuzzy variables

Each pixel of an image is processed by fuzzy rules applied to a set of pixels belonging to a rectangular window (neighborhood) centered on that pixel. As the window scans each pixel of the image, one at a time, a new pixel of the resulting image is generated by means of fuzzy reasoning. Fuzzy variables can be defined by using any function (or relationship) of interest for the processing and can be expressed as followings:
\[ v_1 = f_1(p_1, p_2, \ldots, p_m) \]
\[ v_2 = f_2(p_1, p_2, \ldots, p_m) \]
\[ \vdots \]
\[ v_n = f_n(p_1, p_2, \ldots, p_m) \]
\[ o = f(p_c, p'_c) \]

where \( v_1, v_2, \ldots, v_n \) are the input variables, \( o \) is the output variable, \( p_1, p_2, \ldots, p_m \) are luminance (intensity) values of the pixels in the window, \( p_c \) and \( p'_c \) indicate luminance of the pixel in the center of the window before and after processing, respectively.

**B. Fuzzy Rulebase**

The reasoning structure uses two types of rules: \textit{THEN-rules} and \textit{ELSE-rules}. Each \textit{THEN-rule} includes \( n \) antecedents linked by fuzzy "AND" logical operators and only one consequent. The antecedents are related to input variables and the consequent to the output variable. The overall rulebase is composed of many \textit{THEN-rules} and only one (global) \textit{ELSE-rule}. The following rulebase contains \( r \) \textit{THEN-rules}:

\[ \text{IF} \ (v_1 \text{ is } A_{i1}) \ \text{AND} \ \ldots \ \text{AND} \ (v_n \text{ is } A_{iN}) \ \text{THEN} \ (o \text{ is } B_i) \]
\[ \text{IF} \ (v_1 \text{ is } A_{i2}) \ \text{AND} \ \ldots \ \text{AND} \ (v_n \text{ is } A_{iN}) \ \text{THEN} \ (o \text{ is } B_i) \]
\[ \vdots \]
\[ \text{IF} \ (v_1 \text{ is } A_{iN}) \ \text{AND} \ \ldots \ \text{AND} \ (v_n \text{ is } A_{iN}) \ \text{THEN} \ (o \text{ is } B_i) \]
\[ \text{ELSE} \ (o \text{ is } C_o) \]

where \( A_{ij} \) is a fuzzy set associated with variable \( v_i \) in the \( j \)-th rule, \( B_i \) is the consequent set of the same rule and \( C_o \) is the consequent of the \textit{ELSE-rule}. The \textit{ELSE-rule} assures that the inference is successfully executed even if no \textit{THEN-rules} are fired.

**III. SYNTHESIS OF THE FUZZY OPERATOR**

**A. Approach**

In the approach presented here we attempt to follow a human way of deciding which points on an a raw ultrasonic image might be considered "suspicious". A typical decision is simple:

\textit{A point is suspicious if its intensity is significantly different from the intensity of the surrounding points.}

We shall try to implement this "simple" decision in a fuzzy rulebase. The main difficulty is
establishing what "significantly different" constitutes. The difficulty stems from the fact that
human decisions are more qualitative than quantitative, and are not easily translated into
numerical values.

We shall approach this problem by investigating statistical properties of image intensities.
Figure 4 shows a histogram of pixel intensities of the raw ultrasonic image of Figure 1. Figure
5 presents histogram of an absolute value of intensity difference between neighboring points.
Underlying distributions, represented by these histograms, can be used to represent "suspicious"
points. We can mark a point as suspicious if its intensity value is in a tail of the image intensity
value histogram, and its minimum difference of intensity to neighboring points is in a tail of the
image intensity difference histogram. Since distribution types (image intensity, intensity
differences) are unknown and are dependent on an image content, standard methods of statistical
analysis are not well applicable here. Thus, we shall investigate possibility of using these
histograms to generate fuzzy sets representing points with "atypical" intensity values and fuzzy
sets representing points in which intensities are "quite" different than their neighborhood.

B. Creation of fuzzy sets

Let us introduce a normalization operator, $N$:

$$ N[f(x)] = \frac{f(x) - \min f(x)}{\max f(x) - \min f(x)} $$(3)

After normalization, function $f(x)$ takes on values from the interval $[0,1]$. Let $s$ denote pixel intensity value, and $d$ denote a minimum difference between the given point intensity and intensities of its neighboring points.

The fuzzy set, $A_d$, representing high-intensity-difference is created by taking the negation of the normalized inverted sum of an intensity value histogram, $h_f(d)$:

$$ A_d(d) = 1 - N[\int_{d} h_f(x) dx] $$

Plot of the membership values of the fuzzy set $A_d$ versus intensity difference $d$ is shown in Figure 6.

The fuzzy set $A_s$ representing atypical-intensity is obtained by taking a minimum of the negated cumulative sum, and the negated inverted cumulative sum, of the image intensity value histogram, $h_f(s)$.

$$ H_s^*(s) = \int_{s} h_f(x) \ dx $$

(5)
\[ H^\nu_s(s) = \int h^\nu_x(x) \, dx \]  

\[ A^\nu_s(s) = \min\{1 - N[H^\nu_s(s)], 1 - N[H^\nu_s(s)]\} \]

Plot of membership values of the fuzzy set \( A^\nu_s \) versus intensity value \( s \) is shown in Figure 7.

Using definitions of the above defined fuzzy sets we construct the following decision rule:

The output of evaluating a rule is a certainty value\(^2\), in the 0 to 1 range, representing degree to

\[ \text{IF} \quad \text{(point's intensity is a very atypical-intensity)} \]
\[ \text{AND} \]
\[ \text{(minimum difference of point's intensity is a very high-intensity-difference)} \]

\[ \text{THEN} \quad \text{this point is suspicious} \]

which a point is "suspicous". For the purpose of filtering we can set some certainty level, so when it is met we can mark the point as the one to be filtered out.

IV. EXAMPLES

The algorithm was tested on phase velocity images for four circular ceramic samples, named SN2, SN3, SN4 and SN6 [5]. The first sample, SN2, was used for calibration, the other samples were used for testing. Figures 8 to 11 shows examples of modification of fuzzy sets by hedge operators. Two standard hedge operators, very and extremely, were tested. They are implemented by rising membership values of a fuzzy set to the power of 3 and 5 respectively. First two columns of Table 1 compare number of points selected as "undesired" (suspicious) using different certainty levels shown in first column, and high and extremely hedges shown in second and third column. In general, extremely is less permissive than very in selecting points, qualitatively however the points selected are usually the same. Samples SN3, SN4 and SN4 were evaluated using the hedge very.

\[^2\text{Certainty value should not be mistaken with probability.}\]
<table>
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<th>Certainty value</th>
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<th>SN2\textsubscript{extremely}</th>
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<th>SN4</th>
<th>SN6</th>
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Table 1: Number of points selected for different samples.

Figures 12 through 17 represent graphically how different confidence levels, using sample SN2, affect the quality of the filtered and then enhanced image. Based on these results level of confidence 0.9 was chosen. Figures 18 through 23 show comparison between raw enhanced images and images which were first filtered using our algorithm and then enhanced. The confidence level used for all of them was 0.9. Note changes in color scale: for filtered images the ranges are smaller. It is a highly desirable effect since it helps to better visualize microstructural gradients.

V. CONCLUSIONS

In this paper an adaptive fuzzy image processing operator was presented. The operator was primary developed for processing of raw ultrasonic images, however it can be easily applied in other image processing areas. The adaptiveness of the operator stems from the way the fuzzy sets used in the operator's fuzzy rulebase are generated. The sets are generated for each processed image individually using statistical data about image pixel intensities and intensities differences.

The introduced, relatively simple adaptive fuzzy operator is quite robust in finding suspicious points in raw ultrasonic images. In the presented fuzzy operator detects only isolated points, it would be desirable, however, to make it sensitive not only to isolated points but also to small areas. Other fuzzy rules can be added to the operator rulebase, for instance to improve treatment of border points.

In presented examples the adaptive fuzzy operator was used for filtering of ultrasonic images. Other interesting are of its application is location of suspicious points which are than further processed by other means to investigate the origin of points abnormality.
REFERENCES


APPENDIX - ULTRASONIC PROPERTIES

Notation

t - time.

f - frequency.

b1(t), b2(t) - First and second back surface reflection.

B1(f), B2(f) - Fourier transforms of first and second back surface reflections.

X - sample thickness.

Phase Velocity

\[ \nu(f) = \frac{(2X)2\pi f}{arg(B_1(f)) - arg(B_2(f))} \]  (9)

where \( arg(B(f)) \) is an argument of Fourier transform of pulse B(t).
Figure 1: Raw ultrasonic image.

Figure 2: Enhanced raw image.

Figure 3: Raw image filtered than enhanced.

Figure 4: Intensity value histogram.

Figure 5: Intensity difference histogram.
Figure 6: Fuzzy set: high-intensity-difference.

Figure 7: Fuzzy set: unaverage-intensity-value.

Figure 8: Fuzzy set: very high-intensity-difference.

Figure 9: Fuzzy set: very unaverage-intensity-value.

Figure 10: Fuzzy set: extremely high-intensity-difference.

Figure 11: Fuzzy set: extremely unaverage-intensity-value.
Figure 12: Confidence 0.99, marked 1 point.

Figure 13: Confidence 0.99, filtered out 1 point.

Figure 14: Confidence 0.95, marked 5 points.

Figure 15: Confidence 0.95, filtered out 5 points.

Figure 16: Confidence 0.90, marked 8 points.

Figure 17: Confidence 0.90, filtered out 8 points.
Figure 18: SN3: Raw enhanced.

Figure 19: Confidence 0.9, filtered out 7 points.

Figure 20: SN4: Raw enhanced.

Figure 21: Confidence 0.9, filtered out 10 points.

Figure 22: SN6: Raw enhanced.

Figure 23: Confidence 0.90, filtered out 9 points.