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Panorama view with spatio-temporal occlusion compensation for 3D video coding

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Abstract—The future of novel 3D display technologies largely depends on the design of efficient techniques for 3D video representation and coding. Recently, multiple-view plus depth video formats have attracted many research efforts since they enable intermediate view estimation and permit to efficiently represent and compress 3D video sequences. In this paper we present Spatio-Temporal Occlusion compensation with Panorama view (STOP), a novel 3D video coding technique based on the creation of a panorama view and occlusion coding in terms of spatio-temporal offsets. The panorama picture represents most of the visual information acquired from multiple views using a single virtual view, characterized by a larger field of view. Encoding the panorama video with state of the art HEVC and representing occlusions with simple spatio-temporal ancillary information STOP achieves high compression ratio and good visual quality with competitive results with respect to competing techniques. Moreover, STOP enables free view point 3D TV applications whilst allowing legacy display to get a bi-dimensional service by using a standard video codec and simple cropping operations.

Index Terms—3D-TV, 3D video coding, HEVC, AVC, Depth image based rendering

I. INTRODUCTION

HUMAN visual perception of depth is achieved in 3D display devices by rendering two or more scene views simultaneously. There has been much innovation in 3D displays in the last few years achieving promising levels of visual immersivity. Popular stereoscopic displays in the market show two images of the same scene from slightly different viewing angles that are discriminated through active or passive glasses. The more recent autostereoscopic technology removes the hurdle of glasses by exploiting the principles of parallax barrier or lenticular arrays that allow the user to discriminate a pair of stereoscopic pictures depending on the relative position between the display and the viewer. These autostereoscopic displays use several views, usually up to 50, to generate the perception of depth and to enable the so called free viewpoint TV, where the viewer can roam around these views changing his view-point.

The technological evolution of 3D displays clearly needs to be accompanied by the design of efficient 3D video representations and coding formats able to achieve high level of compression, given the huge amount of data that need to be managed. This is of paramount importance in the context of broadcasting, where the precious radio spectrum must be used as parsimoniously as possible. Moreover, the broadcasting scenario involves other strict constraints represented by presence of legacy devices and backward compatibility issues [1].

Recently, many pilot commercial 3D television (3DTV) services have been launched, following the requirements of the first phase of the 3DTV specified by the DVB [2]. Current technical solutions are based on the so called frame compatible formats [3] that are used to feed stereoscopic display sacrificing the resolution of the individual views.

Up to date the most successful 3D video coding format is represented by the multiview extension (MVC) of the widespread AVC standard [4]; MVC exploits the spatial redundancy among several views adopting the usual block based compensation mechanism and it is backward compatible with any AVC decoder. One of the shortcomings of MVC is the fact that the compression bitrate increases linearly with the number of views [5], making it unfit in the context of free-viewpoint TV. In response to the new requirements novel 3D video formats have emerged, e.g. Depth Enhanced Stereo (DES) [6], Layered Depth Video [7], [8] and Multiview video plus depth (MVD) [9], where pictures are coupled with a per pixel depth map that represents the distance of every pixel from the imaging plane. Such formats enable depth image-based rendering (DIBR) for generation of intermediate views and are catalysing many research efforts in the area of 3D video compression [10].

In this paper we proposed a Spatio-Temporal Occlusion compensation with Panorama view (STOP) technique to efficiently represent and encode MVD formats. The major contributions of the paper are in the following.

- A panorama picture of the scene is created as a mean to capture most of the 3D redundancy of the scene. To this end multiple views are fused in a single panorama picture characterized by a larger viewing angle embracing all the available multiple views.
- DIBR is exploited to extract any desired intermediate view starting from a single panorama view plus depth picture.
- The panorama video undergoes standard video encoding allowing legacy 2D devices to obtain the corresponding 2D pictures by standard decoding and simple cropping.
- The image quality guaranteed by STOP on the decoder side is improved by adding an ancillary compressed bit-stream representing spatio-temporal offsets that are
exploited to recover dis-occluded details after DIBR. An accurate and automatic mechanism for the selection of the dis-occluded areas that will be visually relevant on the decoder side is proposed, achieving excellent rate/quality trade-offs.

The proposed STOP 3D video representation approach jointly achieves many goals that are of paramount importance in the 3D video broadcasting framework, namely:

- **2D compatibility**: the proposed STOP codec supports stereoscopy and autostereoscopy while allowing standard 2D service for existing legacy displays. In particular, STOP exploits simple pre/post processing and can be used along with any existing standard video codec. By signaling the coordinates of the 2D image to the decoder, legacy devices can enjoy 2D service by simply cropping the panorama picture. As an example, the cropping area can be signaled in the compressed bitstream by extending the syntax of supplemental enhancement information messages defined in AVC/HEVC [10].

- **Efficient compression**: by using HEVC STOP is capable to encode three views plus depths at a bitrate that is only 1.5 times that of a standard 2D video.

- **Low complexity**: The computational cost of STOP approaches that of single view video plus depth coding. Our experiments show that the panorama picture is usually less than 10% larger than the original picture; this characteristic significantly reduces the coding time compared to simulcast coding and competing MVD coding approaches.

- **Promising visual quality**: High visual quality of coded and synthesized videos is guaranteed with values of SSIM that are almost the same as those guaranteed by simulcast of multiple views plus depths.

- **FTV application**: Free-view point TV applications can be easily implemented on the receiver side. To achieve stereoscopy one additional view can be obtained by projecting the central view to the left (or right) viewpoint through DIBR plus occlusion filling using spatio-temporal offsets. For large field of view autostereoscopy, additional intermediate views can be estimated using DIBR.

The rest of the paper is organized as follows. In Sect. II related work is briefly discussed. In Sect. III the construction of the proposed panorama view is presented, followed by Sect. IV that describes the overall STOP technique based on panorama view representation of the scene and spatio-temporal occlusion/dis-occlusion estimation and coding. Sect. V shows the experimental results obtained on a standard dataset to evaluate the performance of the proposed coding tool. In Sect. VI our conclusions are drawn.

### II. RELATED WORK

In this section we briefly recall some related works that help in contextualizing our contributions. In particular, we mention current research efforts in the fields of 3D video coding and DIBR algorithms related to our proposal.

As already mentioned in Sect. I pilot 3D TV services are based on simple frame compatible solution: the most well-known are the top-bottom and side by side approaches that simply place two views of a stereoscopic video into a single picture by stacking them vertically or horizontally [3]. Another frame compatible approach [11] reduces the overall pixel resolution in each dimension but provides some advantages such as potential compatibility with 2D display. The frame compatible formats allow one to use a standard high definition video to carry a stereoscopic pair by clearly sacrificing the spatial resolution of the individual views.

Various video coding formats have been proposed to efficiently encode multiple views required for 3DTV. The MVC extension of AVC must be recalled as the first efficient mean to encode multiple views. MVC shows much better compression ratio as compared to its standard ancestors. However, there are a couple of limitations: MVC bitrate increases linearly with the number of views [5] and produces blur effect when it is used to encode depth [12].

Recently, video plus depth formats have attracted much attention. Using the depth of the scene one can generate intermediate viewpoints using DIBR techniques [13]–[16]. Consequently, many works have been devoted to the compression of depth and its exploitation for view prediction [17]–[19]. Since 2011 MPEG has issued a call for proposal on 3D video coding technology [20] and in 2012 an ISO/ITU collaborative effort [21] has been started to cope with novel evolutions of the 3D video. The Joint Collaborative Team on 3D Video Coding Extensions (JCT-3V) is pursuing the standardization of 3D extensions of both AVC (3D-AVC) [22] and the novel High Efficiency Video Coding (3D-HEVC) [10]. The first achievement is represented by Multiview High Efficiency Video Coding (MV-HEVC), where the same approach used by MVC on top of AVC has been adopted to encode multiple views. Inter-view prediction has been implemented by including the inter-view pictures in the reference lists used for prediction. The average compression gain of MV-HEVC over HEVC Simulcast and MVC is reported up to 30% and 50%, respectively. The design of novel and efficient 3D coding tool exploiting MVD formats is the main focus of the current efforts in JCT-3V [23]–[25]. 3D-HEVC is expected to exploit new tools and coding mode capable to improve significantly the compression performance. The base view and corresponding depth map are encoded by unmodified HEVC; the dependent views and depths exploit additional tools e.g. disparity compensated prediction, inter-view prediction of motion parameters, inter-view prediction of residual data, etc. The 3D-HEVC is emerging as the state of the art 3D coding tool and provides 50% and 20% bit rate savings over HEVC Simulcast and MV-HEVC respectively [23].

In [26] a new multiview video representation is introduced, where foreground objects are extracted from the scene and represented as discrete surfaces using a Monte-Carlo method. The obtained surfaces can be easily reconstructed and warped to any virtual camera position. One limitation of [26] is the intrinsic assumption of a static background. Finally, a 3D coding technique sharing some idea with STOP is the one proposed in [27]; this latter has been used in our experiments as a reference.

In STOP we propose a spatio-temporal approach to conceal dis-occlusions produced by DIBR. Many techniques have been proposed in the past to handle the dis-occlusions.
The most popular methods to recover occlusion are based on inpainting techniques. These latter can be categorized into four major classes: i) texture-based inpainting, ii) patch-based inpainting, iii) depth guided inpainting, and iv) spatio-temporal methods. In first class methods, the missing region is filled using the color and texture information of the surrounding pixels [28]–[31]. In patch-based inpainting the missing region is filled with similar patches that can be generally found in the neighboring area in the same image. A patch around the hole is selected and searched for in the rest of the image; then the best match is used to recover the occlusion [32]–[34]. In depth based inpainting either the depth map is inpainted first and then used to find (by 3D warping) the pixels that can cover the holes or the recovered depth map is used in conjunction with texture-based or patch-based inpainting [35]–[38].

Finally, other techniques in literature aim at filling the DIBR holes by maintaining a background sprite. If the background is static or changing slowly it can be estimated and exploited to fill the disocclusions [39]–[43]. Few other techniques that used spatial and temporal information to fill the large holes may be found in [44]–[46].

III. PANORAMA REPRESENTATION

Let us consider a horizontal set-up where the scene is captured by \( n \) cameras with co-planar and parallel camera vectors and using the same focal length \( f \). We denote as \( V_i \), \( i = 1, \ldots, n \) the \( i \)-th view image (moving from left to right), where \( V_i(u, v) \) represents a pixel with row \( u = 1, \ldots, H \) and column \( v = 1, \ldots, W \), being \( W \times H \) the image resolution. In the following we always assume horizontal camera arrangement and rectified images. We further consider the availability, thanks to stereo matching algorithms or physical measurements, of dense depth maps. We denote as \( D_i \) the depth map associated to the view \( V_i \), with \( D_i(u, v) \) the depth of the pixel \((u, v)\) of the \( i \)-th view.

Fig. 1 shows an example of multiview camera setup comprising 3 cameras with horizontal shifts. The distance between the viewpoints \( b_i \) of the different cameras, termed as baseline, is usually limited to guarantee a smooth 3D experience, e.g. when using an autostereoscopic display. As graphically represented in Fig. 1, this yields a high overlap among the field of views of the different cameras, that in turn can be recognized in terms of redundancy in the collected images.

At very high level one may imagine to summarize all the collected information using a single virtual camera with focal point in an intermediate reference position and a field of view larger than the ones of the single cameras. Unfortunately, because of occlusions and dis-occlusions, e.g. background pixels that appear behind foreground objects, it is not possible to compact all the information acquired by several cameras into a single image plane of the virtual intermediate camera. Nonetheless, in practical settings with limited baseline, the creation of the virtual intermediate view, that we termed panorama view, represents a viable approach for representing a set of multiview images, compactly. Finally, using DIBR techniques one shall be able to estimate the required intermediate views.

![Fig. 1. A multiview camera setup with horizontal arrangement.](Image)

A. Background on Depth Based Image Rendering

DIBR process consists in reprojecting the pixels of a set of acquired images (typically 2) into the image plane of an intermediate virtual view, exploiting the depth information and the knowledge of the camera intrinsic and extrinsic matrices.

Let \( V_s \) be the source view with corresponding depth \( D_s \) and viewpoint \( b_s \). Let \( b_t \) the position of a target view \( V_t \) with disparity \( b = b_t - b_s \) from the source view. Assuming the horizontal camera setup, \( V_t \) can be obtained applying horizontal shifts \( \delta_s,t \) to the pixels of \( V_s \). Given \( V_s(u, v) \) this latter can be mapped to the corresponding \( V_t(u, v + \delta_s,t(u, v)) \) with

\[
\delta_{s,t}(u, v) = \frac{b f}{D_s(u, v)}
\]

being the shift required to map pixel \((u, v)\) in the coordinate system of the image plane of the target camera. Clearly, the shift depends on the depth of each pixel and generally requires sub-pixel precision. DIBR techniques compete in designing the best solutions to overcome a series of issues that arise when shifting pixels, e.g. recovering from occlusion and dis-occlusion, high quality virtual image re-sampling, robustness to depth estimation errors, etc.

Finally, we recall that in practical cases the depth is mapped onto its inverse \( 1/D_s \) represented over 255 levels, usually termed as quantized disparity. Denoting as \( d_s \) the 255 levels image used to represent the quantized disparity, one can compute the depth map as:

\[
D_s(u, v) = \frac{1}{\frac{d_s(u, v)}{255} \left( \frac{1}{Z_n} - \frac{1}{Z_f} \right) + \frac{1}{Z_f}}
\]

where \( Z_n \) and \( Z_f \) are the minimum and maximum depth, respectively.

B. Panorama View Generation

Without loss of generality we assume that the number of camera \( n \) is odd. Let \( V_m \) be the intermediate view, \( 1 \)In the general case with arbitrary camera positions both horizontal and vertical shifts must be taken into account determining the so called image warping process
$V_1, \ldots, V_{m-1}$ the views on its left side and $V_m, \ldots, V_n$ the views on the right side. As discussed earlier, the camera views share a large portion of their field of view due to their limited disparity. When moving from $V_m$ towards $V_{m-1}$ a new part of the scene shows up on the left side of $V_{m-1}$ because of camera translation, whereas another part disappears to the right. Moreover, some occlusions and dis-occlusions will occur, especially around the edges of foreground objects.

For the sake of the panorama view construction we make the assumption that no occlusions and dis-occlusions are to be taken into account. We will remove this limiting assumption later in Sect. IV.

Under this simplifying assumption any view $V_i$ can be obtained from the intermediate $V_m$ with the exception of a band of pixels (appearing on the right or on the left side), that in the following we refer to as the slit $s_i$. It is worth noting that the slits get larger while moving farther away from the intermediate position. Fig. 1 shows a multi views setup with 3 cameras where one can select the central view $V_2$ as a reference. As an example, it can be noted that $V_3$ shares a large portion of image plane except for a small slit $s_3$ on the right side. It is worth pointing out that other views on the right side, e.g. $V_4, V_5, \ldots$ would yield larger slits $s_4, s_5, \ldots$, including $s_3$. In general, we can state that:

\[
\begin{align*}
    s_i &\subseteq s_{i-1} & \text{if } 1 \leq i < m; \\
    s_{i+1} &\subseteq s_i & \text{if } m < i \leq n; \\
\end{align*}
\]

Hence, a panorama view $V_{\text{pan}}$ with size $W' \times H$ can be generated concatenating $s_1, V_m$ and $s_n$ so as to create a single picture collecting most of the information in the scene. The same approach can be followed to create a single panoramic depth $D_{\text{pan}}$ that carries the information required to synthesize any desired intermediate view.

The panorama width $W' > W$ clearly depends on the size of the left and right slits, that in turns depends on the maximum shift that a pixel can undergo when moving from the leftmost/rightmost view to the reference view. The maximum shift varies with the scene depth and possibly changes as a function of time within the video sequence. Nonetheless, we can easily assume that the minimum depth $z_n$ of the considered scene is known; since the maximum shift is produced by the scene point that is closest to camera one can upperbound all shifts by

\[
\Delta = \left[ \frac{(b_m - b_1)f}{z_n} \right] \quad (3)
\]

As a consequence, we set the panorama width to be $W' = W + 2\Delta$, i.e. the panorama view contains the pixels $V_{\text{pan}}(u, v)$ with $u = 1, \ldots, H$, and $v = 1, \ldots, W + 2\Delta$.

Two alternative strategies can be used to create $V_{\text{pan}}$ and $D_{\text{pan}}$ images, respectively. In the following we focus on the construction of the panorama view; the same process can be followed to build the corresponding depth map, as well.

1) Panorama construction via Inward Projection: In inward projection approach the left view $V_1$ and the right view $V_n$ are warped to the central view $V_m$; the pixels of $V_1$ and $V_n$ that are warped outside image plane of the central view are those that forms the slits $s_1$ and $s_n$.

The panorama view can be constructed as follows:

\[
V_{\text{pan}}(u, v) = \begin{cases}
V_{1,m}(u, v - \Delta) & \text{if } v \leq \Delta \\
V_m(u, v - \Delta) & \text{if } \Delta < v \leq W + \Delta \\
V_{n,m}(u, v - \Delta) & \text{if } v > W + \Delta 
\end{cases} \quad (4)
\]

being $V_{i,m}(u, v)$, $i = 1, n$ the pixel synthesized by warping $V_i$ according to the point of view of $V_m$. In particular, the panorama will collect the warped pixels $V_{1,m}(u, v)$ with $v < 1$, i.e. falling outside the field of view of $V_m$ and those of $V_{n,m}(u, v)$ with $v > W$. For this reason in previous equation we assume that $V_{1,m}(u, v)$ is defined also for column coordinates that are 0 or negative and $V_{n,m}(u, v)$ takes values also when $v > W$. Clearly, during the warping process more than one pixel of $V_1$ (or $V_n$) may be shifted to the same coordinate $(u, v)$; in such case only the pixel closest to the camera is copied in the panorama view. Moreover, shifts are not guaranteed to map on integer coordinates and proper interpolation is required as in common DIBR algorithms. This process is schematically shown in Fig. 2.

2) Panorama construction via Outward Projection: The slits’ pixels can be identified with a process that is the dual of the previous one; indeed, one can warp the reference view $V_m$ according to the viewpoint of $V_1$ and record the pixel coordinates of $V_1$ that cannot be covered shifting pixels of $V_m$.

Under our assumption of absence of occlusions/disocclusions this process permits to identify the pixel in slit $s_1$. The same result is obtained for $s_n$ by warping $V_m$ towards $V_n$.

Let $H_{\text{in}}(u, v)$ be a binary map representing the coordinates of view $V_1$ that cannot be obtained warping $V_m$. In this case we can form a panorama picture by setting:

\[
V_{\text{pan}}(u, v) = \begin{cases}
V_1(u, v') & \text{if } v \leq \Delta, H_{\text{in}}(u, v') = 1, \\
V_m(u, v - \Delta + \text{rt}(H_{\text{in}}(u, v'))) & \text{if } \Delta < v \leq W + \Delta \\
V_n(u, v') & \text{if } v > W + \Delta, H_{\text{in}}(u, v') = 1 \\
v' = v - \Delta - \text{lt}(H_{\text{in}}(u, v')) & \text{if } v > W + \Delta 
\end{cases} \quad (5)
\]

where rt($H_{\text{in}}(u, v)$) returns the rightmost column of the $u$-th row where $H_{\text{in}}$ is equal to 1 and lt($H_{\text{in}}(u, v)$) returns the leftmost column of the $u$-th row where $H_{\text{in}}$ is equal to 1. According to previous equation the pixels $V_1(u, v')$ that cannot be warped from $V_m$ to $V_1$ are copied on the left side of
The process is graphically show in Fig. 3. In the following we termed this panorama construction process as the outward projection approach. It can be noted that in this case the right edge of $s_1$ is not guaranteed to be straight; for simplicity the panorama image is constructed aligning each row of $s_1$ on the right side of the panorama row by row.

Analogously, pixels $V_n(u, v')$ that cannot be warped from $V_m$ to $V_n$ are appended to the right side of the panorama row by row.

The process is graphically show in Fig. 3. In the following we termed this panorama construction process as the outward projection approach. It can be noted that in this case the right edge of $s_1$ is not guaranteed to be straight; for simplicity the panorama image is constructed aligning each row of $s_1$ on the right side of the panorama row by row.

In the following a method is proposed to represent (at the encoder side) and recover (at the decoder side) the occlusion and dis-occlusion areas\(^2\) that have been neglected during the generation of the panoramic view. This approach will allow us to design STOP, based on standard coding of the panoramic view and depth, followed by a novel mechanism for handling occlusions.

The proposed solution aims at representing every occluded patch by encoding its spatio-temporal offset pointing to the best approximation of the missing area that can be found in pictures that are already available on both encoder and decoder. This goal can be achieved by exploiting the fact that occluded pixels of a given frame are likely to be visible in the subsequent or preceding frames, thanks to camera and/or objects movements; alternatively, missing areas can be concealed by means of similar areas that can be found in the same frame.

### IV. THE STOP VIDEO CODING METHOD

Before presenting the details of the procedure used to cope with occlusions we need to provide a high level description of the whole encoding and decoding process.

In Fig. 4 the block diagram of the encoder is shown. The first stage consists in the creation of the panoramic view and depth, taking the original views and depths as input. Without loss of generality, in the following, a camera setup with 3 views and 3 depth will be considered as it is assumed in Fig. 4.

Then, the panorama view and depth are encoded with any existing technique, e.g. AVC or HEVC. In the following, we need to enrich previous notation by adding the temporal index of a frame of a video sequence, e.g. $V_{pan}^{t}$ refers to the $t$-th panorama view of the video sequence. The output of the first stage are the corresponding compressed bitstream $\mathbf{V}_{pan}^{t}$ and $\mathbf{D}_{pan}^{t}$, $t = 1, 2, \ldots$. The reconstructed views and depths can be used to compute on the encoder side the occlusions that will be experienced by the decoder when generating a given view.

The proposed encoder DIBR is used to compute the occlusions that show up when

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\(^2\)In the following, for conciseness, we use the term occlusion to identify both occlusion and dis-occlusion
estimating the leftmost and rightmost views, respectively. The best approximation of each occlusion is then searched in the decoded frames \( \hat{V}_b^n \), and the corresponding spatio-temporal offset is encoded and sent as ancillary data as detailed in Sect. IV-B.

On the receiver side, the various components of the compressed bitstream are parsed and decoded. Backward compatibility towards legacy 2D devices can be easily obtained by letting them decode the standard panorama video that can be simply displayed after cropping the central view. On the contrary 3D receivers use the panorama view and depth to estimate \( \hat{V}_b^t, \hat{D}_b^t \) using DIBR. Thanks to the presence of the slits the area of the view appearing on the left hand side is obtained. The remaining occlusions are filled using the spatio-temporal offset information provided by the encoder. Those areas are simply copied from frames that have already been decoded; indeed, we observed that in the proposed spatio-temporal hole filling no post-processing such as boundary matting is useful because the patches are very small in size and they usually belong to nearby frames. Therefore additional processing would increase the complexity of the technique without carrying significant quality improvements. Finally, the rightmost view and depth can be estimated with the same process. Given \( \hat{V}_b^t, \hat{V}_m^t \) and \( \hat{V}_n^t \) (and corresponding depth) DIBR can be used to estimate any desired intermediate view. Fig. 5 shows the block diagram of proposed decoder.

1) Occlusion selection: The encoder aims at selecting and encoding only the occlusions that potentially have a sensible impact on the rendered visual quality. The most significant occlusions are clearly obtained when using \( \hat{V}_b^t, \hat{D}_b^t \) to render \( \hat{V}_b^t \) and \( \hat{V}_b^n \).

By means of a standard DIBR algorithm the encoder is able to identify the area of the target images \( \hat{V}_b^t \), \( i = 1, n \) that cannot be recovered with pixels of \( \hat{V}_b^t \) (usually referred to as holes). The occlusions of the \( i \)-th view at time \( t \) are organized into a list of connected components, e.g., by using the flood-fill algorithm to label all the pixels of the binary image representing the holes left by DIBR. Let \( O_{i,j}^t \) refers the \( j \)-th connected component, i.e. patch of occluded pixels, of the \( i \)-th rendered view at time \( t \) of the video sequence and \( \vert O_{i,j}^t \vert \) its size measured in number of pixels.

To limit the coding overhead the occlusions with size \( \vert O_{i,j}^t \vert \leq \tau_S \) are simply discarded. On the decoder side such occlusions can be recovered by standard inpainting [31], [47].

It is worth pointing out that, because of the horizontal camera setup, some very tiny vertical cracks will show up. These holes are generally only few pixels wide and can be recovered efficiently by inpainting. As a consequence, we add a criterion to drop occlusion patches that have a very skewed aspect ratio. In particular, we define the following ratio

\[
r(O_{i,j}^t) = \frac{\vert O_{i,j}^t \vert}{\min_{\text{row}} O_{i,j}^t}
\]

between the patch size and its vertical length \( \vert O_{i,j}^t \vert \); this latter can be simply computed as \( \vert O_{i,j}^t \vert = \max_{\text{row}} O_{i,j}^t - \min_{\text{row}} O_{i,j}^t + 1 \), where \( \max_{\text{row}} \) and \( \min_{\text{row}} \) evaluates the maximum and minimum row indexes in a patch, respectively. Then, patches with \( r(O_{i,j}^t) \leq \tau_R \) are discarded for further processing.

The size of the occlusions generated by an object depends on its size and depth. If a large object is close to the camera, then an occlusion of large size, especially in the vertical direction, is to be expected. To easy the following task of occlusion matching it is preferred to segment large occlusions into smaller patches. Indeed, smaller patches are likely to represent more homogeneous areas that in turn are matched more easily in the surrounding images (both temporally and spatially). Moreover small patches are more robust to distortions introduced by camera and/or object movements. As a consequence, if \( \vert O_{i,j}^t \vert > \tau_L \), the corresponding occlusion is segmented into smaller chunks (with height less or equal to \( \tau_L \)) cutting it horizontally.

To avoid cluttering the notation we keep using the symbol \( O_{i,j}^t \) to identify the occlusions surviving the pruning process described above.

2) Occlusion matching: The next step consists in the search for the best match of every occlusion \( O_{i,j}^t \) given the views that have already been decoded at the receiver. This task is very similar to motion estimation techniques adopted in standard video codecs, based on block matching. Nonetheless, in our encoder we avoid using blocks and we aim at estimating the best match of every occlusion patch \( O_{i,j}^t \) by keeping its original shape. As for motion estimation we use the Sum of Absolute Differences (SAD) as a computationally
effective metric of similarity. Clearly, our method can be easily extended to the case of more complex metrics that take into account other image features such edges, orientations and color [48]–[51]. It is worth pointing out that the occlusions can be matched also in the depth domain; this possibility is not exploited by our encoder from one hand to limit the computational cost, and from the other hand because depth images offer less details and are usually error prone due to disparity estimation errors.

The occlusion matching consists in the following minimization:

$$\mathbf{w}^t_{i,j} = (x, y, k) = \arg\min_{x,y,k : B_k \in B^t} \sum_{u,v \in O^t_{i,j}} |V^t_i(u,v) - B_k(u-x, v-y)|$$

where $B^t$ is a buffer of decoded images selected for the search at time $t$, $(x, y)$ represents the spatial offset and $k$ references a particular decoded image $B_k \in B^t$. The vector $\mathbf{w}^t_{i,j} = (x, y, k)$ represents the spatio-temporal offset to the best occlusion match and will be encoded as described in the following section.

Clearly, the search range must be optimized so as to trade-off accuracy of the matching and the computational cost. In our implementation we include in $B^t$ the central view $\bar{V}^t_{m}$ of the decoded panorama pictures, with $j = t - \theta, \ldots, t + \theta$, i.e. we consider a symmetrical time window around the target view at time $t$. The larger $\theta$, the higher the chance to cover an occlusion exploiting camera and/or object motion. Furthermore $\theta$ must be selected taking into account the video encoder settings, e.g. the GOP structure, and the delay constraint of the application.

Clearly, the above selected set of reference pictures is not enough to recover occlusions generated by stationary objects in a sequence without camera motion (in the following we terms them static occlusions). To overcome this issue we can include in $B^t$ some virtual views where all occlusions are inpainted. These virtual views can be generated by both encoder and decoder warping the decoded panorama view and depth. As an alternative, a set of key frames of the leftmost and rightmost views can be encoded\(^3\), e.g. with the same intra period used to encode $V_{pan}, D_{pan}$ or just when a scene-cut [52]–[54] is detected. The second option incurs some bitrate overhead but generally yields higher image quality. In general, we let $B^t$ include $w$ supplementary reference pictures that serve to match static occlusions. In conclusion, $B^t$ contains $2\theta + 1$ temporal references and $w$ spatial references.

As far as the search in the spatial domain $(x, y)$ one can optimize that range depending on the time offset of the reference frame with respect to $t$ and the depth of the considered occlusion. Clearly, if two frames are far apart in time it is likely that a given occlusion is recovered using larger spatial offset because of the effect of motion. Moreover, a larger search space must be used for occlusion patches that are closer to the camera. As a consequence the spatial search has been constrained to $\chi_{w} \leq x, y \leq \chi_{w}$, where $\chi_{w} = \psi \cdot \omega$, being $\psi$ the temporal offset between the current and the reference

\(^3\)This supplementary option has been neglected in Fig. 4 and Fig. 5 to make them more simple and readable.

### Table I

Test Video Sequences.

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<tr>
<th>ID</th>
<th>Name</th>
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<td>1,3,5</td>
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</table>

\[\omega = \frac{1}{|O^t_{i,j}|} \sum_{u,v \in O^t_{i,j}} |\delta_{m,i}(u,v)|\]

### V. Experimental Evaluation

In this section the performance of the proposed STOP codec will be analyzed and compared with both standard simulcast coding and competing solutions based on coding of occlusions.

The coding tests have been run on a standard set of multiple view plus depth video sequences [55]. The selected sequences include both synthetic and real videos with either static or moving background, and with or without camera motion and zooming. In Tab. I the details of each sequence (sequence name, total number of frames, resolution, frame rate and index of coded views) are summarized; in the following each sequence will be referenced using the label reported in the first column of the table.
A. STOP Settings

In Sect. IV we presented the spatio-temporal estimation and compensation employed in the STOP codec. Such process depends on a number of parameters that can be tuned to achieve different quality/bit-rate trade-offs.

The most important parameter is certainly represented by the threshold $\tau_S$ that allows one to select the most significant occlusions for the following matching and compensation. On the other hand the dropped (smaller) occlusions will be recovered by inpainting. Clearly, this choice has a direct impact on visual quality and bit-rate overhead for occlusion coding.

Usually, the warping process generates a very large number of small occlusions and a limited number of large occlusions; these latter are likely to be related to foreground objects and depend on their position in depth and on the baseline of the cameras. Furthermore, complex or highly textured scenes, e.g. tree leaves, crowd of people, etc, can easily yield a large number of very small occlusions. Moreover, other occlusions can be caused by depth estimation errors.

In Fig. 6 we show some experimental data obtained when warping S2 and S3 sequences, respectively. In particular S2 refers to a sequence with highly textured background (buildings and trees) whereas S3 is characterized by a simpler background. Both sequences have few foreground moving characters.

Fig. 6a shows that warping S2 from view 4 to view 5 one gets a large number of occlusions, on average 5639 occlusions per frame. These are mainly due to the complex nature of the background in S2. Fig. 6b shows the size of each occlusion patch in frame 100 of the sequence; it clearly turns out that most occlusions are very small ones, with only 1.38% of the total covering more than 100 pixels. In Fig. 6d, 6e the same results are shown when warping S3 from view 3 to view 1. In this case, 1127 occlusions per frame were found on average, i.e. 5 times less than S2; looking at frame 100 we note that only 15 occlusions contain more than 100 pixels.

If we fix $\tau_S = 36$ to select only large occlusions and we omit cracks by setting $\tau_R = 2$ as defined in Sect. IV-B we got the results shown in Fig. 6c and Fig. 6f. It can be noted that only 121 and 65 occlusions per frame are selected in S2 and S3, respectively.

Previous thresholds have been selected as reasonable trade-off between image quality and occlusion coding overhead and will be employed in all the following experiments.

The remaining STOP coding parameters are reported in Tab. II. In particular we fixed $\tau_L = 20$ to split vertical occlusions as described in Sect. IV-B and HEVC is used to encode the panorama texture and depth videos. The most significant HEVC settings are shown in Tab. II, as well.

B. Coding Experiments and Comparisons

In this section the compression efficiency provided by STOP codec is evaluated experimentally and compared with other coding approaches based on standard coding tools, i.e. video plus depth simulcast using the widespread diffused AVC and the novel HEVC coding standard. When using simulcast 3

$\tau^*$The experimental results have been obtained with JMVC-8.3 for AVC and HM-11.0 for HEVC coding, respectively.
views plus the corresponding depth maps are separately coded using AVC or HEVC, respectively. The HEVC settings are the same as those selected according to Tab.II for the STOP codec, whereas similar parameters have been used in the case of AVC as shown in Tab. III. In all the following experiments, the sequences are encoded at four quality levels by selecting the values for quantization parameter (QP), namely \( QP = 26, 30, 34, 38 \). The compression performance obtained by simulcast is shown in Tab. IV and will be used as a reference for the following results; the total bitrate in kbps and the average PSNR obtained on the luma component of the 3 views are reported.

Furthermore, a backward HEVC compatible implementation of [27] is used as a benchmark closer to our proposal. In [27] the middle view and depth are encoded with HEVC and the disoccluded regions for the left and the right views are estimated using DIBR on the encoder side. As in STOP, small occlusions are dropped; finally one left occlusion frame (plus corresponding depth) and one right occlusion frame (plus depth) are constructed so as that every \( 16 \times 16 \) block that includes at least an occluded pixel is encoded using a modified HEVC encoder. Fig. 7 shows an example of an occlusion frame (sequence S3) created according to [27], where only a subset of blocks carry occlusions that needs to be coded. For the sake of comparison with our approach, a slight variation of [27] has been implemented, where a standard HEVC encoder is used to compress the left and the right occlusion frames, respectively. In the following we term such coding approach as Middle plus Disoccluded Regions (MDR). The major differences between MDR and STOP are that this latter creates a panoramic picture and does not use video coding on occlusions (that are encoded as spatio-temporal offsets).

The compression performance yielded by MDR is shown in Tab. V, where the amount of bitrate taken by the different components is detailed, namely the bitrate spent to encode the middle view \( V_m \), the corresponding depth map \( D_m \) and the left and the right occlusion frames (texture and depth). The overall bitrate and the PSNR of the middle view are

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TABLE VI
STOP COMPRESSION RESULTS (HEVC BASED): BITRATE AND AVERAGE LUMA PSNR [DB] OF PANORAMIC VIEW \(V_{\text{pan}}\), BITRATE FOR THE DEPTH MAP \(D_{\text{pan}}\), OCCLUSION BITRATE (SPATIO-TEMPORAL OFFSETS), AND OVERALL STOP BITRATE.

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Fig. 7. MDR coding approach: warped image with dis-occlusions (a) and corresponding occlusions frame (b).

Table VI shows the results of STOP compression for different test sequences and quality parameters (QP). The table includes bitrate for the panoramic view \(V_{\text{pan}}\), bitrate for the depth map \(D_{\text{pan}}\), bitrate for occlusions, and total bitrate. The quality metric used is average luma PSNR [dB].

To better analyze the bitrate distribution of STOP in Fig. 9 the average percentage bitrate allocated to texture, depth and occlusion offsets are reported as a function of QP. It can be noted that texture takes from 75% to 82% of the bitrate, depth from 13% to 14% and occlusion offsets from 12% to 4% as a function of QP. In particular, it is worth noticing that occlusion bitrates does depend on QP; in fact, in the current implementation of STOP we kept fixed the parameters for the selection of the occlusions to be coded as discussed in Sect. V-A, independently on the QP value.

A widespread tool for comparing the compression performance is the Bjøntegaard metric [56]. Tab. VII shows the STOP results in terms of Bjøntegaard ΔPSNR and ΔR (PSNR and bitrate differences) when compared to the reference codecs used in this paper. The table shows that the proposed coding tool saves 78% bitrate compared to AVC.
simulcast, 58% compared to HEVC simulcast and 32% compared to MDR.

Finally, it is useful to compare the STOP bitrate with that of a single video channel: in the broadcasting scenario, such metric represents an estimate of the bandwidth overhead with respect to the standard 2D service required to enable 3D TV applications. Previous results show that STOP can be used to grant a 3D video service with a bandwidth overhead below 50%.

### C. 3D Video Quality

In STOP (and similarly in MDR) only the panoramic picture is encoded whereas all the remaining points of views can be synthesized by DIBR technique. In the following we propose to use the well-known Structural SIMilarity (SSIM) index [57] metric as a measure of the obtained image quality. In fact, SSIM has been designed to better match the human visual perception and yields better visual quality assessment with respect to PSNR [57]–[59]. Moreover, PSNR generally estimates values that are not correlated to the visual perception in presence of DIBR: indeed DIBR, can achieve excellent perceived image quality even without guaranteeing a bit faithful reconstruction of the original picture due to resampling issues, color and illumination correction, rectification errors, etc.

In order to rank the overall 3D video quality guaranteed by STOP a set of virtual views has been generated. In particular, a pair of intermediate views is computed in between leftmost and central and central and rightmost views, respectively. Then a supplementary virtual view is created in between in a second iteration, getting a total of 9 views spaced by one quarter of the original baseline. View Synthesis with Inverse Mapping (VSIM) [47] is used for DIBR, employing the Telea fast marching algorithm [31] for inpainting uncoded occlusions.

Fig. 10 shows the visual quality of the decoded views and intermediate virtual views for frame 13 of sequence S2. From top left to bottom right we report the views at position 5 (leftmost), 4.5, 4 and 3.5. Fig. 10c is the central view in the panorama and its quality depends only on HEVC compression efficiency, whereas other images are obtained by warping the central view and by filling the disocclusions with the proposed spatio-temporal approach. While there is a significant drop in PSNR between the coded view 4 and the interpolated views, the visual quality of all images is high as predicted by the reported values of the SSIM.

Fig. 11 shows the average SSIM provided by STOP compared with HEVC simulcast and MDR as a function of the view position. The quality of the virtual views created from MDR and the proposed coding tool is almost the same since in both techniques the left and the right views are obtained by warping the middle view. As expected both MDR and STOP exhibit a slight penalty on the quality of the extreme views; in fact, those views are directly coded by HEVC with simulcast whereas in the other cases they are estimated by DIBR plus occlusion compensation. Nonetheless the quality impairment turns out to be negligible, e.g. 0.02, if compared to the bitrate savings discussed in Sect. V-B. Moreover, Fig. 11-(e),(f) show that the quality gap turns to be significantly reduced for synthetic video sequences (S5,S6) where ground truth depth maps are available: the greater depth accuracy in turn improves both STOP coding efficiency (better construction of the panorama picture, occlusion estimation and matching) and quality of the view synthesis on the decoder side. This observation also highlight that STOP performance is expected to improve further exploiting future research and advances in depth acquisition/estimation and DIBR algorithms.

### D. Complexity Analysis of STOP

In this section the computational cost of STOP is analyzed and compared against those of standard 2D video codecs, and their forthcoming 3D extensions.

Compared to a standard HEVC encoder, STOP comprises two extra modules: panorama construction, and occlusion matching. Panorama construction involves two warping operations to estimate the slits; either reference view is warped to the outermost views using DIBR or vice versa. The asymptotic cost of DIBR operation is linear in the number of pixels in the image.

Occlusion matching in STOP is a two levels operation. First, their sizes are computed and the smaller occlusions are dropped from further processing as they do not contribute significantly to the decoded image quality; indeed, those can...
be successfully inpainted on the decoder side. Computing the size of the occlusions is again a linear time operation that is carried out by component labeling algorithm. Second, the occlusion offsets must be estimated using a spatiotemporal search. The best match is found using Sum of Absolute Difference (SAD) in a time window of size \( \Theta \). Since a full search would be computationally inefficient, an offset optimization mechanism has been designed to limit the search space. The search space optimization mechanism exploits the average occlusion disparity and the temporal distance (offset) of the target frame as described in details in Sect. IV-B2.

In conclusion, in STOP, the additional computational cost with respect to standard 2D encoding is kept limited by exploiting the pre-processing represented by the panorama construction that is effective in capturing most interview redundancies. Then, a single coding mode is added to process a limited set of occlusions that cannot be handled efficiently in the panorama picture. On the receiver side, the bit stream is decoded with the standard 2D decoder. The base view is obtained by simple cropping of the panorama picture and the occlusions offsets are used to directly copy the target patches for filling the occlusions that show up during DIBR.

The 3D extensions of the most recent HEVC standard follow a different approach based on the design of additional coding modes capable of capturing the inter-view redundancy at the coding unit (CU) level. In 3D-HEVC the dependent views are coded using many additional coding tools: for instance disparity-compensated prediction (DCP) which exploits already coded images of other views, inter-view motion prediction and interview residual prediction. For efficient compression of depth videos 3D-HEVC employs additional coding tools, e.g. depth intra-coding exploiting new depth modeling modes, disparity-compensated prediction and inter-view motion parameter prediction which significantly increases the computational complexity of 3D-HEVC [60], [61]. The new coding modes allows one to reduce significantly the bitrate required to encode multiple views and depths while guaranteeing the same image quality of independent view coding (simulcast). On the other hand, with STOP we exploit DIBR to avoid coding the picture parts that can be estimated by DIBR and we keep additional coding cost as limited as possible. Clearly, as shown in Fig. 11 the STOP picture quality slightly degrades as moving away from the central coded view; nonetheless, if one can tolerate such slight drop (less than about 0.03 in terms of SSIM measured in our experiments) STOP can represent a viable solution for 3D video coding.

VI. CONCLUSIONS

In this paper the novel STOP 3D video codec has been designed building around two main ideas, namely the construction of a panorama view and the exploitation of spatiotemporal correlation for filling occlusions caused by DIBR. By exploiting the mentioned concepts STOP efficiently compresses 3D video while using a standard video codec such as AVC and HEVC to encode most of the data. In this paper we showed promising results in terms of bitrate reduction and visual quality. Beside coding efficiency, STOP enables free viewpoint 3D TV while guaranteeing a simple mechanism to
allow legacy 2D displays to extract the standard 2D video. Future works include the rate/distortion optimization of the occlusion matching criteria, the design of entropy coding tools for occlusion offsets and the exploitation of the coding ideas proposed in this paper as possible novel coding modes for the future 3D extensions of AVC and HEVC under investigation by the MPEG.

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[71] Prof. Grangetto was awarded the Premio Optime by Unione Industriale di Torino in September 2000, and a Fulbright grant in 2001 for a research period with the Department of Electrical and Computer Engineering, University of California at San Diego. He has participated in the ISO standardization activities on Part 11 of the JPEG 2000 standard. He has been a member of the Technical Program Committee for several international conferences, including the IEEE ICME, ICIP, ICASSP, and ISCAS.

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