

# Matrix computations with applications

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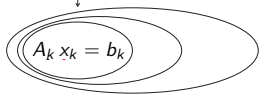
## Main collaborators

- ▶ Marie Kubínová (Emory University, USA)
- ▶ Martin Plešinger (Technical University of Liberec)
- ▶ Rosemary Renaut (Arizona State University, USA)
- ▶ Maria Diana Sima (Katholieke Universiteit Leuven, Belgium)
- ▶ Zdeněk Strakoš (Charles University in Prague)
- ▶ Sabine Van Huffel (Katholieke Universiteit Leuven, Belgium)

## Problems of interest

- ▶ Linear algebraic systems  $Ax = b$ ,  $A \in \mathbb{R}^{n \times n}$  nonsingular: discretization of differential or integral equations from modelling, e.g., in material science, continuum mechanics
- ▶ Linear approximation problems  $Ax \approx B$ ,  $A \in \mathbb{R}^{n \times m}$ ,  $B \in \mathbb{R}^{n \times d}$ : errors-in-variables modeling, e.g, in statistical applications
- ▶ Linear ill-posed problem  $Ax \approx b$ : image processing (medical, radar, sonar imaging, astronomical observations), bioelectrical inversion problems, seismology

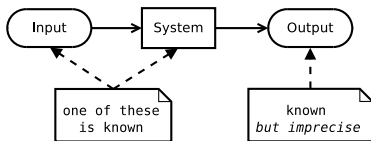
Often,  $A$  (representing a model) is large and sparse, thus Krylov subspace iterative methods are used to solve them,



$$\mathcal{K}_k(A, b) = \text{Span}\{b, Ab, \dots, A^{k-1}b\}.$$

# Inverse problems in image processing

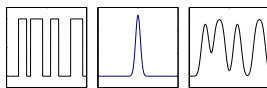
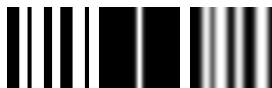
## Inverse Problem



Inverse problems are often modeled by a **Fredholm integral of the first kind** with a kernel  $K(s, t)$  having a **smoothing property**,

$$g(s) = \int_I K(s, t) f(t) dt.$$

**Example:** barcode reading



sharp      kernel      blurred

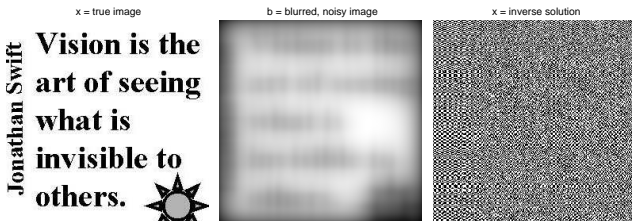
$f(t)$        $K(s, t)$        $g(s)$

# Naive solution

Discretization leads to complicated **noise contaminated problems**

$$b \approx Ax + e.$$

The presence of noise in the measured data and the **properties of the problem** result in “naive” solution  $x := A^\dagger b$  that is **meaningless**.



# Regularization and denoising

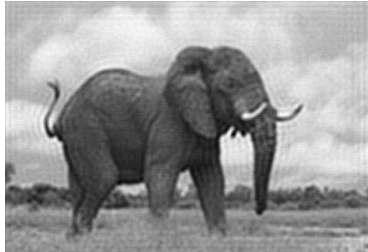
Theoretical analysis of **Krylov subspace method** – Golub-Kahan iterative bidiagonalization led to cheap **estimator of the unknown noise**. This allows to denoise the problem.

$b^{\text{exact}} + b^{\text{noise}}$



$n = 152280$ , 10% noise

TSVD-LSQR reconstruction using DP



reconstruction

# Research projects

- ▶ **Image Processing in Jewellery Industry with Emphasize on Defect Analysis:** financed by Preciosa a.s. (2014 - 15)  
→ **image processing** methods in detection of defects in the produced stones
- ▶ **Iterative Methods in Numerical Mathematics: Analysis, Preconditioning, and Applications:** GAČR grant (2013 - 17)  
→ **fundamental research** of **Krylov subspace** methods
- ▶ **University Center for Mathematical Modeling, Applied Analysis and Computational Mathematics:** University Center of Excellence (2012 - 17)  
→ apply state-of-art **mathematical tools in applied sciences**
- ▶ **Necas Center for Mathematical Modeling:** (2013 - ?)  
→ theoretical and applied math in **continuum mechanics**

Thank you for your kind attention.