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# Detecting Motion Blur in Images

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## Abstract

Our project aims to estimate motion blur from a single, blurry image. We propose a deep learning approach to predict the probabilistic distribution of motion blur at the patch level using a Convolutional Neural Network (CNN).

## 1 Our approach

We approached the problem by slicing 100 images into 30x30 patches, and applied our own motion blur algorithm to them (with a random rate of 50%). We then labeled the blurry and non-blurry patches with 0s and 1s (0 for still, 1 for blurry), and loaded the modified images in as our training data.

### 1.1 Generating the training data

We generated the training data using images from the *Pascal Visual Object Classes Challenge 2010 (VOC2010)* data set. Our work was done in Python using the *PIL*, *numpy*, *opencv*, and *os* libraries.

Once we had the original images from *Pascal*, we had to modify them to fit our needs. We needed to have 100 images, each partially blurred and with a corresponding matrix indicating which part of the image is blurred.

We achieved this by:

1. Making a blurred copy of the original image.
2. Cutting both images (original and blurry) into  $30 \times 30$  patches.
3. Creating a 2D List in Python of size  $30 \times 30$ , to represent each image patch We initialize each element to 0 (to represent non-blurry).
4. Picking half the patches from the list and marking them as 1 (to represent blurry).
5. Putting the final image together to get a partially-blurred, qualifying image (and its corresponding matrix).
6. Saving the image as "n.jpg" (where n is the serial number of the image), and adding the matrix to a list (to form a 3D 'list of lists') containing the matrices of all the image.



*Image of the original-to-blur process.*



*Image of the image splitting process.*



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[[0, 0, 1, 1, 1, 0, 0, 1, 1, 0, 0],
[1, 0, 0, 1, 0, 0, 0, 1, 0, 1, 0],
[0, 0, 0, 1, 1, 1, 1, 0, 1, 0, 1],
[1, 1, 1, 1, 0, 0, 0, 0, 0, 1, 1],
[1, 0, 0, 0, 1, 0, 0, 0, 1, 0, 0],
[0, 1, 0, 0, 0, 0, 0, 0, 0, 1, 0],
[1, 0, 0, 0, 0, 0, 1, 0, 1, 1, 1],
[0, 0, 1, 0, 0, 0, 1, 1, 0, 0, 0],
[0, 0, 0, 1, 1, 0, 1, 1, 0, 0, 0],
[0, 0, 0, 0, 0, 0, 1, 0, 0, 0, 1],
[1, 0, 0, 0, 1, 0, 1, 0, 1, 0, 0],
[1, 1, 0, 1, 0, 1, 0, 0, 1, 0, 0],
[0, 0, 0, 0, 1, 1, 0, 0, 1, 0, 1],
[0, 0, 1, 0, 0, 1, 1, 1, 0, 0, 0],
[0, 1, 1, 0, 1, 0, 1, 0, 1, 0, 0],
[0, 1, 1, 1, 1, 0, 1, 1, 0, 1, 1]]
```

*The final image with its corresponding matrix.*

We repeat the above for all 100 images, until we end up with a folder containing partially-blurred images "0.jpg" through "100.jpg", and a 3D list (named "labels") that contains 100 matrices. This lets us access the matrix for image "31.jpg", for example, by querying for "labels[31]".

## 2 Learning the Convolutional Neural Network (CNN)

Once we had the prepared images, **we loaded them into our training set**. We ran into a problem loading the images into a *numpy* array, where our images were of the form (30,30,3), while the *Keras.Conv2D* layer required input to be of the form (3,30,30). We solved this by using the *numpy.swapaxes()* function to alter the images' shape in order to fit the convolutional layer.

**We then apply the CNN learning model.** First, we apply a Convolution2D layer with  $7 \times 7$  filters, followed by a *ReLU* function. The *Conv* layer's parameters consist of a set of learnable filters. Each filter is small spatially, but extends through the depth of the input volume.

**During the forward pass,** we slide each filter across the width and height of the input volume and compute the dot products between the entries of the filter and the input at any position. *ReLU* is the rectifier function- an activation function that can be used by neurons, just like any other activation function. A node using the rectifier activation function is called a *ReLU node*. *ReLU* sets all negative values in the matrix  $x$  to 0, and all other values are kept constant. *ReLU* is computed after the convolution, and thus a nonlinear activation function (like *tanh* or *sigmoid*).

After that, **we add a *MaxPooling2D* layer** with a pool size of  $2 \times 2$ . *MaxPooling* is a sample-based discretization process. The objective is to down-sample an input representation, reducing its dimensionality and allowing for assumptions to be made about features contained in the binned sub-regions.

We then **add a *Dropout* layer** with dropout rate of 0.2, which makes our learning process faster. *Dropout* randomly ignoring nodes is useful in CNN models because it prevents interdependencies from emerging between nodes. This allows the network to learn more and form a more robust relationship. We then do the '*Conv2D*, *ReLU*, *MaxPooling2D*, *Dropout*' circle again. Finally, we add a fully-connected layer with *ReLU*, and then *softmax* the result. *Softmax* is a classifier at the end of the neural network — a logistic regression to regularize outputs to a value between 0 and 1.

**We set our model's learning rate to be 0.01.** This might generally be too big, but we made this decision for the sake of brevity - it was the fastest way to show a result. We chose a batch size of 126 (because we had large training data). We also chose *Adam* as our optimizer as it's the most efficient optimizer for our model.

After training with 100 epochs, **we had testing accuracy of 92%**, which is a very optimal rate for our model. Our training model is saved in an HDF5 file, "*motionblur.h5*".

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## References

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