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A Novel Method for Low Resolution Video Enhancement using Super Resolution Technique

Thota Mary Ragni[1], Sathuluri Mallikharjuna rao[2]

[1] PG Scholar, Department of ECE, Andhra Loyola Institute of Engineering and Technology, Vijayawada, Andhra Pradesh, India

[2] Assistant Professor, Department of ECE, Andhra Loyola Institute of Engineering and Technology, Vijayawada, Andhra Pradesh, India

Abstract

The super-resolution of images is a growing technique because of its simple structure with high accuracy as well as reliability. Due to the very high complex nature of motion fields, super resolution technique is used. The spatial resolution is improved by a novel blind technique known as Super Resolution (SR), while the parameters like noise statistics, point spread function as well as motion fields are unknown. In this the blur is estimated by multiscale process but before that the frames are up sampled with the help of non uniform interpolation super resolution method. Huber-Markov random field (HMRF) is used for frame reconstruction because of its very high resolution outputs with preservation of the edges and fine details. Two important terms like fidelity and regularization are analyzed before applying the random field. Advantage of proposed work are it can handle complex motion problems, deformable regions can be estimated accurately, efficient under different brightness condition, detailed structure is obtained as well as it can be applied to fast moving objects.

Keywords*: Fidelity, Regularization, Super Resolution, Blur Estimation and Huber Markov Random Field (HMRF)***.**

1. Introduction

Super-resolution is method that uses a combination of low resolution (noisy) sequence of images of a scene to generate a high resolution image or image sequence. Multi image super resolution is the recent trend and prominent study is going on it which is the reconstruction of a high resolution image from a series of low resolution images degraded by noise factor, aliasing effect and blurring. Video super resolution on contrast is the process of reconstruction of a high resolution video from one or multiple low resolution videos in order to increase the spatial and temporal resolution.

Spatial resolution depends on the spatial density as well as point spread function (PSF). On other hand temporal resolution is depends on frame rate as well as exposure time required by particular camera. The most commonly used method to increase the resolution of a video is sliding window technique .by overlaying the window frame on each frame of the video sequence ,later the frames which fall inside the window are combined to form a high resolution frame.

Another example of single video super resolution is given by the learning based; example based and patches based video SR. The main theme for this is small space-time patches from the video sequence are repeated within the video for replacing low resolution patches with equivalent HR patches. By doing this high resolution patches are obtained with repeatedly replacing the patches obtained from degraded video.

While estimating blur, the input video is first up-sampled (in case of SR) employing a heterogeneous interpolation or non-uniform interpolation (NUI) SR method, then iterative procedure is applied under the given considerations: 1) Throughout the number of iterations, the blur is calculated completely employing a few important edges while weak structures square measure smoothened out, 2) The quantity of contributing edges step by step will increase the chances of getter good performance, 3) structures finer than the blur support can be easily removed or avoided from estimation, 4) the estimation is finished within the filter domain except using pixel domain calculation, finally 5) the estimation is performed at multiple scales to avoid the getting local minima at some points present at edges.

2. Existing methods

[1] “Limits on super-resolution and how to break them”, by Baker and Kanade, 2002 also discussed about enhancement of resolution under different conditions of images blurs. In this we worked on two different databases to get the enhanced results. The conversion of image into low and high frequencies will give us the least information also present in image. Different types of constrains are used to get the output with high resolution, in addition we also used reconstruction constrains.

[2]. “Determining optical flow Artificial Intelligence”, given by Horn and Schunck, 2002 in this optical flow can’t be calculated locally so we developed second constrains which will calculate the optical flow pattern. It is very helpful to get the image variations which are nothing but where exactly the variation is more and where smoothness of an image is degraded. Brightness level and additive noise in an image will give us the exact where image reformatted and applying proposed work we can easily remove those deformations.

[3] “Blind image deconvolution” by Kundur and Hatzinakos,1996 in IEEE Signal Processing Magazine, for each and every implementation related to recovery of an image that image restoration we are facing the problems like convergence properties, complexity, and other implementation issues. To overcome this type of problems we developed a recent technique known as blind image Deconvolution. Blind in the sense we are not going to consider any references while applying this processing.

[4] “Fundamental limits of reconstruction based super resolution algorithms under local translation”, by the authors Z. Lin and H-Y Shum,2006 as we discussed in all existing techniques there is very less probability of getting success under the condition it should validates the perturbation theorem. So special algorithm is developed to get the better super-resolution compare to existing state of art techniques.

3. Proposed Method

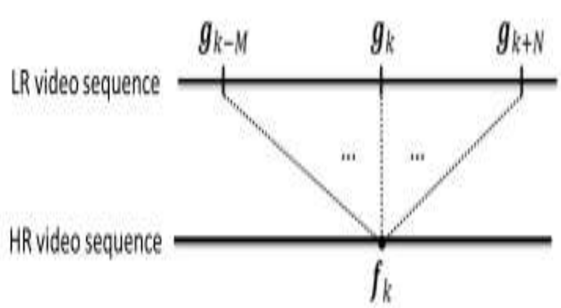

Fig 1: Reconstructed HR frame f_k by SR method by combining LR frames in the window.

3.1 Observation Model

As we observed in above figure, a sliding window (temporal) of length M + N + 1 (with M frames backward and N frames forward) is overlaid around each Low resolution (LR) frame g_k of size $N_x^g \times N_y^g \times C$, and all LR frames inside the window can be obtained with the help of SR process to generate the HR reference frame f_k of size $N_x^f \times N_y^f \times C$. Here, N_x and N_y are frame dimensions for two directions like x and y-directions and C is the number of color channels which is C=3 in color image. The linear forward imaging can be used for generating a LR frame g_i inside the window from the HR frame f_k is given by:

$$g_i(x\downarrow, y\downarrow; c) = \left[m_{k,i}\big(f_k(x, y; c)\big) * h(x, y)\right] \downarrow L + n_k, (x\downarrow, y\downarrow; c),$$
$$c = 1, \ldots, C, k = 1, \ldots p, i = k - M, \ldots, k + N$$

Where, we can say P is the total number of frames, (x↓, y↓) and (x, y) indicate the pixel coordinates in LR and HR image planes respectively, L is given the down sampling factor or SR up scaling ratio (so that $N_x^f = LN_y^g$ and $N_y^f = LN_y^g$), and $*$ is the two-dimensional convolution operator used in the above formula. According to this model, the HR frame fk is warped with the warping function $m_{k,i}$, blurred by PSF h, down sampled by L, and finally corrupted by the additive noise $n_{k,i}$. It is extremely easy to express this linear process in the vector-matrix notion as given by

$$g_i = DHM_{k,i}f_k + n_i$$

In [Horn and Schunck,1980] f_k is the kth HR frame in lexicographical notation indicating a vector of size $N_x^f N_y^f C \times 1$, matrices $M_{k,i}$ and H are the motion (warping) and convolution operators of size $N_x^f N_y^f C \times N_x^f N_y^f C$, , D is the down sampling matrix of size $N_x^g N_y^g C \times N_x^f N_y^f C$, and g_i and n_i are vectors of the ith LR frame and noise respectively, both of size $N_x^g N_y^g C \times 1$.

3.2 Color Space

The human visual system (HVS) is a smaller amount sensitive to chrominance (color) than to brightness (light intensity). Within the RGB (red, green, blue having three components) color house, all the given three color elements have equal importance so all square measure typically keeps or processed at identical resolution for a pixel. However a lot of economical advantages to take the HVS perception under consideration are by separating the brightness from the color data and representing luma with higher resolution than vividness present in image.

A popular application to accomplish this separation is to use the YCbCr color house wherever Y is that the luminance part (computed as a weighted average of R, G, and B) and Cb and Cr square measure the blue-difference and red-difference vividness elements. The YUV color space is mostly used for video process algorithms to explain video sequences encoded mistreatment YCbCr color space.

In this proposed work, video sequences will be processed in either RGB or YUV color formats depending on the application. Within the former case, SR is employed to extend the resolution of all R, G, and B channels, but within the latter one, solely the Y channel is processed by SR for quicker computation whereas the Cb and Cr channels are mostly used up scaled to the resolution of the super-resolved Y channel employing a single-frame up sampling methodology which are already present like linear or Bi-cubic form interpolation. The obtained results associated with given two existing cases are comparable employing a subjective quality assessment.

3.3 Motion Estimation

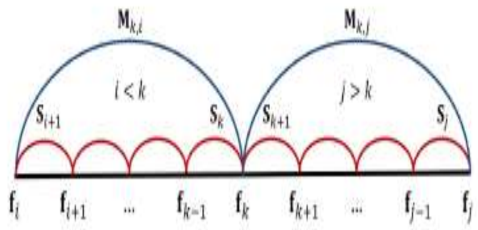

Fig 2: Central motion (blue) versus sequential motion (red)

Accurate motion estimation (registration of the blur present in image) with sub component exactitude is crucial for video SR to attain an honest performance. Two completely different approaches are thought-about for registration in video SR: central and serial (Fig. 2). Within the former, motion is directly computed between every system and every one LR frames within its window (Fig. 1). In contrast, within the latter, every frame is registered against its previous frame; then to use with SR, serial motion fields should be reborn to central fields for registration as follows: if $S_i = [\ S_{xi}, S_{yi}\ ]$ is the sequential motion field for the ith frame (w.r.t. the (i −1)th frame), then $M_{k,i} = [\ M_{xk,i}\ ,\ M_{yk,i}\ ]$, the central motion field for the ith frame when the central frame is the kth frame is obtained as:

$$M_{k,i} = -\sum_{n=i+1}^{k} Sn = -S_{i+1} + M_{k,i+1}, \quad k - M \le i < k$$

$$M_{k,k} = I$$

$$M_{k,i} = \sum_{n=k+1}^{j} S_n = S_j + M_{k,j-1}, \quad k < j \le k + N$$

Where, I is the identity matrix.
With the improvement in successive approach in SR, every frame must be registered solely against the previous frame, whereas with the central approach every frame is registered against all neighboring frames at intervals its reconstruction window. Therefore, the procedure quality and therefore the storage size of the motion fields within the central approach is above that of victimization the successive approach given by this algorithm.

3.4 Blur Estimation

Blur estimation is one of the important steps in super-resolution of this proposed work. In a multi-channel BE drawback, the blurs may be calculable accurately alongside the time unit pictures, but in an exceedingly blind SR drawback with a probably completely different blur for every frame, and some ambiguity within the blur estimation is inevitable owing to the down sampling operation for the estimation of blur. In contrast, in an exceedingly blind SR drawback during which all blurs area unit purported to be identical or have gradual changes over time, such associate ambiguity will be avoided [Horn and Schunck,1980]. Moreover, as mentioned in Section 3.1, the belief of identical (or bit by bit changing) blurs makes it attainable to separate the registration and up sampling procedures from the deblurring method that considerably decreases the blur estimation quality. In Section 3.1, the non-uniform interpolations abbreviated as NUI technique to reconstruct the up sampled frame is explained. This up sampled yet-blurry frame is employed to estimate the PSF(s) and therefore the deblurred frames through associate repetitive various diminutions (AM) methods. The blur and frame estimation procedures area unit mentioned in Sections 3.7 and 3.9, severally. The calculable frames area unit used just for the deblurring method so omitted thenceforth. Finally, the general AM improvement method is delineated in Section 3.9.

3.5 Frame up sampling

In [Kundur and Hatzinakos, 1996] we implemented the things within which the distortion and blurring operations which are present in [Kundur and Hatzinakos, 1996] square measure commutable. Though for videos with arbitrary native motions this commutability doesn't hold specifically for all pixels, but we tend to assume here that this is often around glad. The final word appropriateness of the approximation is valid by the ultimate performance of the formula that's derived supported this model. With this assumption, [Kundur and Hatzinakos, 1996] is rewritten as:

$$g_i = DM_{k,i}Hf_k + n_i = DM_{k,i}z_k + n_i$$

Where $\mathbf{z_k}$= $\mathbf{Hf_k}$ is the up sampled but still blurry frame. Equation (4) shows that we have to construct the up sample frames z_k using a proper fusion method and then apply a deblurring method to $\mathbf{z_k}$ to estimate $\mathbf{f_k}$and h.

3.6 Frame Deblurring

After up sampling the frames, we are going to use the following cost function, J, to estimate the HR frames f_k having an estimate of the blur h (or H):

$$J(f_k) = ||\rho(Hf_k - z_k)||_1 + \lambda^n \sum_{j=1}^{4} ||\rho(\nabla_j f_k)||_1$$

where · 1 denotes the l1- norm (defined for a sample vector x with elements xi as x = i | xi|), λn is the regularization coefficient, ρ(·) is the vector Huber function, ρ(·) 1 is called the Huber norm, and ∇ j (i = 1,. . ., 4) are the gradient operators in 0°, 45°, 90° and 135° spatial directions. The first term in [Liu AND Sun, 2011] is called the fidelity term which is the Huber norm of error between the observed and simulated LR (low resolution) frames. While in most works the l2-norm is used for the fidelity term, we use the robust Huber norm to better suppress the outliers resulting from inaccurate registration. The next two terms in [Liu AND Sun, 2011] are used for the different applications like the regularization terms which apply spatiotemporal smoothness to the HR video frames while preserving the edges.

Each element present in the vector function ρ (·) is the Huber function which can be given as,

$$\rho(x) = \begin{cases} x^2 \; if \; |x| \leq T \\ 2T|x| - T^2 \; if|x| > T \end{cases}$$

The Huber perform ρ(x) could be an umbel-like perform that features a quadratic type for values but or adequate to a threshold T and a linear growth for values bigger than T. The Gibbs PDF of the Huber perform is heavier within the tails than a Gaussian. Consequently, edges within the frames area unit less punished with this previous than with a Gaussian (quadratic) previous.

With the help of a sample vector x, at the nth iteration the non-quadratic Huber-norm ρ(xn)1 is replaced by the following quadratic form which is

$$||\rho(X^n)||_1 = (X^n)^T V^n (X^n) = ||X^n||^2_{V^n}$$

Where Vn is the following diagonal matrix given as

$$\mathrm{V^n} = \mathrm{diag}\left(\begin{cases} 1 & \mathrm{X^{n-1}} \leq \mathrm{T} \\ \mathrm{T/X^{n-1}} & \mathrm{X^{n-1}} > \mathrm{T} \end{cases}\right)$$

In [Schultz and Stevenson, 1994] the dots present above the division and comparison operators indicate element-wise operations. Applying the FP method to [Liu AND Sun,2011] and setting the derivative of the cost function with respect to f_k to zero results in the following linear equation set:

$$\mathrm{H^{nT}V^nH^n} + \lambda^n \sum_{j=1}^{4} \nabla_j^T \mathrm{W_j^n} \nabla_j = \mathrm{H^{nT}V^n z_k}$$

Where,

$$\mathrm{V^n} = \mathrm{diag}\left(\rho(\mathrm{Hf_k^{n-1}} - \mathrm{z_k})\right), \mathrm{W_j^n} = \mathrm{diag}\left(\rho\left(\nabla_j \mathrm{f_k^{n-1}}\right)\right)$$

We discussed above how to update the regularization parameter λ_n at each iteration in Section 3.9.

3.7 Blur Estimation

Within a picture or video frame, non-edge regions and weak structures don't seem to be acceptable for blur estimation. Hence, a lot of correct results would be obtained if the estimation isn't performed in such regions. For this reason, the user ought to 1st manually choose a neighborhood with made edge structure, the foremost salient edges square measure mechanically chosen.
In our proposed work, we tend to use the edge-preserving smoothing technique during which the amount of living edges once smoothing is globally controlled by the regularization constant. This feature is useful once one needs to limit the amount of salient edges at every iteration. This smoothing technique aims to stay associate degree meant variety of non-zero gradients through l_0 gradient diminution victimization the subsequent value function:

$$J(f'^{n}_{k}) = ||f'^{n}_{k} - f^{n}_{k}||_2^2 + \beta^n(||\nabla_x f'||_0 + ||\nabla_y f'||_0)$$

Where, f^n_k is the output of the edge-preserving smoothing algorithm and the l_0 norm is defined as $\|x\|_0 = \#(i|\ xi = 0)$. Unlike shock filtering, this smoothing method does not need pre-filtering of noise.
Though adequate edge pixels area unit needed for correct blur estimation, it's shown in one of the given references that structures with scales smaller than the FTO support might hurt blur estimation. Galvanized by that employment, we have a tendency to outline R^n_k in [Tsai and Huang, 1984] to live the quality of every constituent for blur estimation:

$$R^n_k = |ABf'^n_k|$$

Where A and B is the basic convolution operators for the spatial filters a and b, respectively, as defined below:

$$a = \begin{bmatrix} 1 & \cdots & 1 \\ \vdots & \ddots & \vdots \\ 1 & \cdots & 1 \end{bmatrix}$$

$$b = \nabla_x + \nabla_y = \begin{bmatrix} 2 & -1 \\ -1 & 0 \end{bmatrix}$$

Algorithm 1 Blur Estimation Procedure

Require: $g_1,\ldots,g_p,\lambda_{min},\Upsilon_{min}$ and initials $h^o,\lambda^o,\gamma^o,\beta^o,T_1^0,T_2^0$

Set n: =0 **% Am loop iteration number**
S: = # of scales

Use luma or one color channel of $g_1,\ldots,g_{p1}$
for k: =1 **to** $P1$ **do** **% Loop on $P1$ reference frames**

if L>1 then **% For SR reconstruction**
  $z_k = NUI(g_{k-M},\ldots,g_{k+N})$
else **% For BD reconstruction**
  $z_k = g_k$
end if
$f_0^k = z_k$

%HR frame and blur estimation
for s: =1 **to** S **do** **% Multi-scale approach**
  Rescale z_k, f_k^n and h^n

% AM loop iteration
while "AM stopping criterion "is not satisfied **do**
n=n+1

% Updating procedure for f
compute V^n and W_j^n using (10)
update λ^n
while f^n does not satisfy "CG stopping criterion" **do**
f_k^n: = CG iteration for system in (9); starting at f_k^{n-1}
end while
Apply constraints on f_k^n

  % Updating procedure for h^n
  Update γ^n,β^n,T_1^n and T_2^n
  Compute the smoothed frame f'^n_k from (11)
  Compute $\nabla f''^n_k$ from (15)
  Edge tapping of $\nabla f''^n_k$
  Compute $h_k^n(x,y)$ from (17)
  Apply constraints on h^n
   end while
 end for
end for

In [Xu and Lu, 2011] and [You and Kaveh, 1996], there is that the all-ones filter of size 11*11 and b is that the sum-of-gradients filter. As we used to computeR_k^n, the total of gradient elements of f_k^n is computed initial, then at every element it's summed up with the values of all neighboring pixels, and eventually its definite quantity is obtained. For pixels on slender structures, the total of gradient values cancels out one another. Therefore, R_k^n sometimes incorporates a tiny worth at the situation of slender edges and sleek regions. Then f_k^n is refined by solely holding robust and non-spike edges:

$$\nabla f''^n_k = \begin{cases} \nabla f'^n_k if \ |\nabla f'^n_k| > T_1^n \ and \ R_k^n > T_2^n \\ 0 \ otherwise \end{cases}$$

Where T_1^n and T_2^n are threshold parameters which decrease at each iteration. To avoid ringing artifact, we apply the MATLAB function edge taper () to $\nabla f_k{}^n$. Then we estimate each blur h_k using the cost function J (h) below:

$$J(h) = \sum_{k=1}^{P_1} ||\nabla_{z_k} - \nabla F''_k h||_2^2 + \gamma^n ||\nabla h||_2^2$$

Where P1 ≤ M + N and $\boldsymbol{F_k}$ is the convolution matrix of f_k. Since J (h) in [Tadeka, MilanfarandProtter, 2009] is quadratic, it can be easily minimized by pixel-wise division in the frequency domain as:

$$h_k^n(x,y) = F^{-1}\left(\sum_{k=1}^{p1}\sum_{i=1}^{2}\left\{\left[\overline{F(\nabla_1) \times F(\dot{f''}^n_k)} \ \dot{\times} \left(F(\nabla_1) \dot{\times} \ F(z_k)\right)\right] - \left[\left|F(\nabla_i) \dot{\times} F(\dot{f''}^n_k)\right|^2 + \gamma^n \left|F(\nabla_i)\right|^2\right]\right\}\right)$$

Where ∇i (i = 1, 2) is ∇x or ∇y, F(·) and F−1(·) are FFT and inverse-FFT operations, and (·) is the complex conjugate operator. We then applied the known constraints for PSF: its negative values are set to zero, then the PSF is normalized to the range [0, 1], and centered which is in support window.

3.8 Overall Optimization for Blur Estimation

The overall optimization procedure which is aimed for estimating the PSF is shown in Algorithm 1. The HR frames and the PSF are sequentially updated within the AM iterations shown in the algorithm. We use a multi-scale approach to avoid trapping in local minima. The regularization coefficients $\boldsymbol{\lambda_n}$ in [Shan, Jia and Agarwala, 2008] and $\boldsymbol{\gamma_n}$ in [Irani and Peleg, 1990] decrease at each AM (alternating minimization) iteration up to some minimum values $\boldsymbol{\lambda_{min}}$ and $\boldsymbol{\gamma_{min}}$, respectively. The variation of these coefficients is given by:

$$\lambda^n = max(r\lambda^{n-1}, \lambda_{min}) \ ,$$

$$\gamma^n = max(r\gamma^{n-1}, \gamma_{min})$$

Where r is a scalar less than 1. Also the values of β_n in [Takeda and milanfar, 2009] and $T_1{}^n$ and $T_2{}^n$ in [Xu and Lu, 2011] fall at each AM iteration which increases the number of contributing pixels to blur estimation as the optimization proceeds.

3.9 Final HR Frame Estimation

After completion of the PSF estimation, the final HR frames are reconstructed through minimizing the following cost function as given below,

$$J(f_1, \dots, f_p) = \sum_{k=1}^{p}\left(\sum_{i=K-M}^{K+N} ||\rho\left(O_{k,i}(DHM_{k,i}f_k^1 - g_i)\right)||_1 + \lambda \sum_{j=1}^{4} ||\rho(\nabla_j f_k)||_1\right)$$

Where $O_{k,i}$ is a diagonal weighting matrix that assigns less weights to the outliers.

Minimizing this cost function with respect to f_k yields:

$$\left(\sum_{i=K-M}^{K+N} M_{k,i}^T H^T D^T O_{k,i} V^n DHM_{k,i} + \lambda \sum_{j=1}^{4} \nabla_j^T W^n \nabla_j\right) f_k^n = M_{k,i}^T H^T D^T O_{k,i} V^n g_i$$

Where,

$$V^n = diag\left(\rho\left(DHM_{k,i} f_k^{n-1} - g_i\right)\right), W_j^n = diag\left(\rho\left(\nabla_j f_k^{n-1}\right)\right)$$

and the mth diagonal element of $O_{nk,i}$ is computed according to below equation:

$$O_{k,i}[m] = exp\left\{\frac{||R_m\left(\rho\left(DHM_{k,i} f_k^{n-1} - g_i\right)\right)||}{2\sigma^2}\right.$$

Where R_m is a patch operator which extracts a patch of size q × q centered at the mth pixel of $f_{k,i}$. The final frame estimation algorithm is shown in below Algorithm 2.

Algorithm 2 Final Frame Estimation Procedure

Require: g_1,…..,g_p, and λ

Set n: = 0 **% FP loop iteration number**

for k: =1 **to** P **do** **% Loop on P reference frames**

Estimate sequential motion fields S_1,…., S_p

Compute central motion fields M_1,...,M_p, using (??)

Estimate the blur **h** using Algorithm 1

% Estimate HR frames using FP loops

while ‘’FP stopping criterion” is not satisfied **do**

n=n+1

Compute O_{kj}^n using (22)

Compute V^n and W_j^n using (21)

While $\boldsymbol{f^n}$ does not satisfy“CG stopping criterion”**do**

f_k^n:=CG iteration for system in (20);starting at $f_{k,n-1}$

end while

Apply constraints on $f_{k,n}$

end while

end while

4. SIMULATION RESULTS

The proposed work is shown by MATLAB implementation. We compared proposed work with existing super-resolution technique and shown that state of art of the proposed work is better compare to existing techniques for super-resolution.

We used here bicubic as existing technique to show the advantages of PSNR for proposed work compare to existing technique.

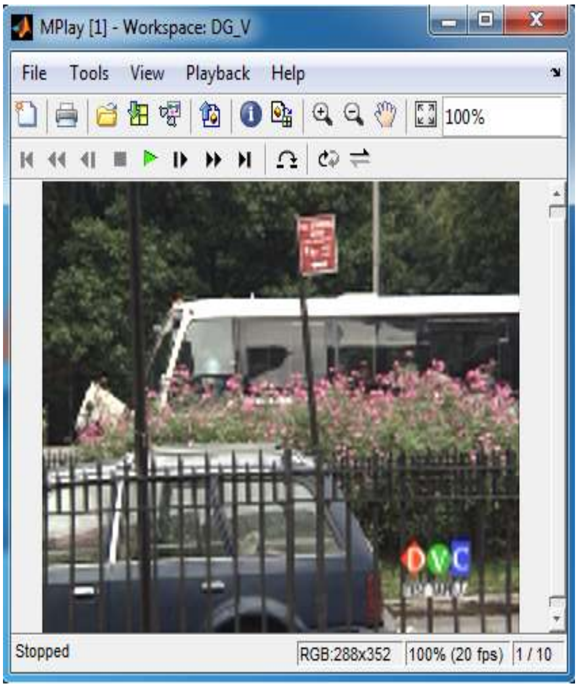

Fig 3: Degraded Video Sequence as an input

In input video there may be different types of degradation like fog, blurness which we have to estimate for enhancement. Our proposed algorithm is considered for three types of degradations.

Motion estimation in the degraded video is done because we want to process the finest elements present in an image which are finest that blur also.

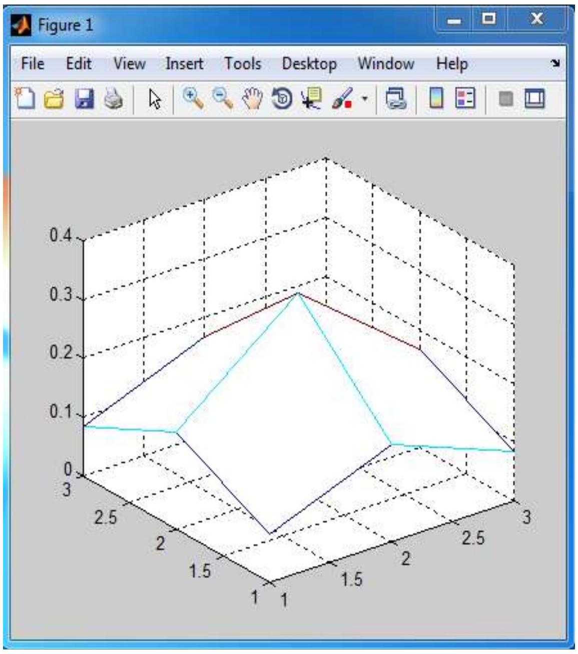

Fig 4: Motion Estimation in Video Sequence

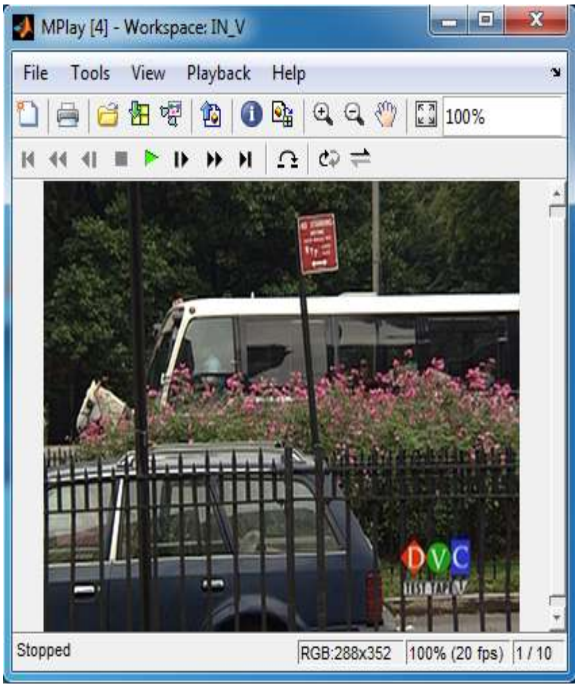

Fig 5: Inverse Video Sequence

Here, we calculated inverse video sequences to get accuracy and this type processing will takes place iteratively. Previously it is calculated at some edges but later it is calculated for all edge gradients.

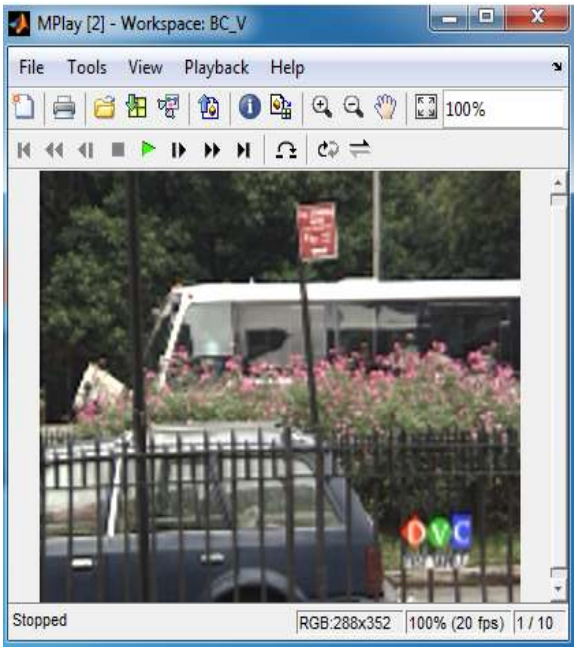

Fig 6: Bi-Cubic Interpolation Method

Bi-cubic interpolation is applied to get the super resolution for single frame up sampling method. We converted Image which is in RGB format to YCbCr format and normally we applied up sampling to Cb and Cr plane but the intensity plane Y is up sampled by using Bi-cubic method.

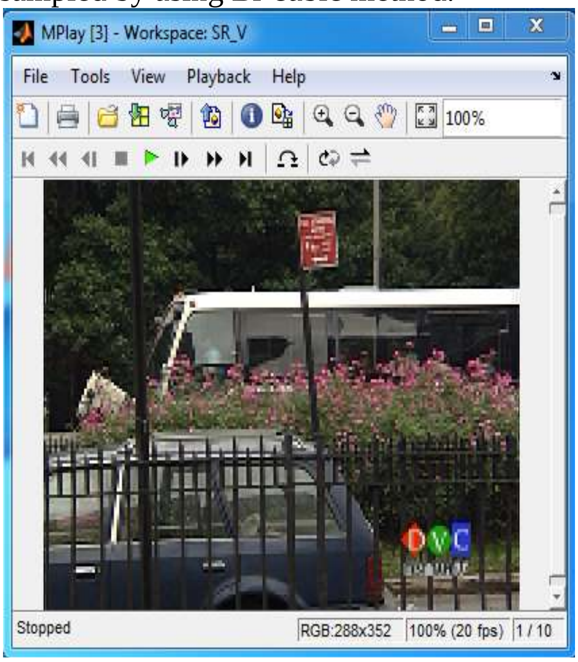

Fig 7: Proposed Method Video Sequence

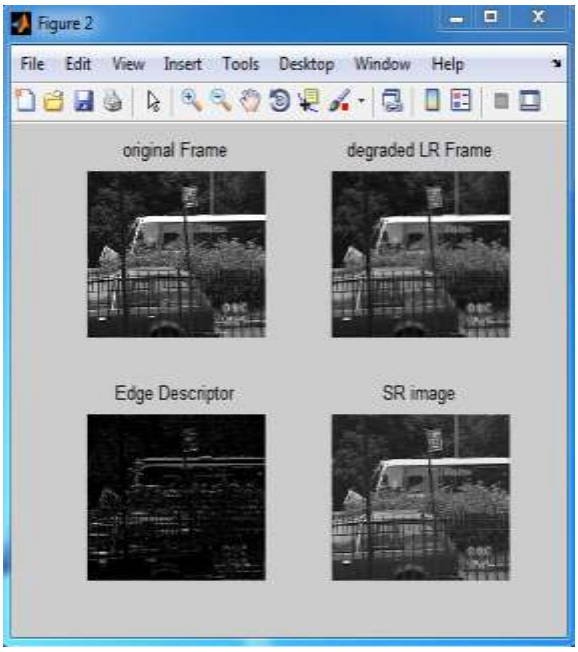

Fig 8: Frame Comparison results

A SR frame is obtained from a degraded low resolution frame and edge descriptor is also observed.

Fig 9: Color space transformation results

Color transformation technique is also used to make the SR video device independent

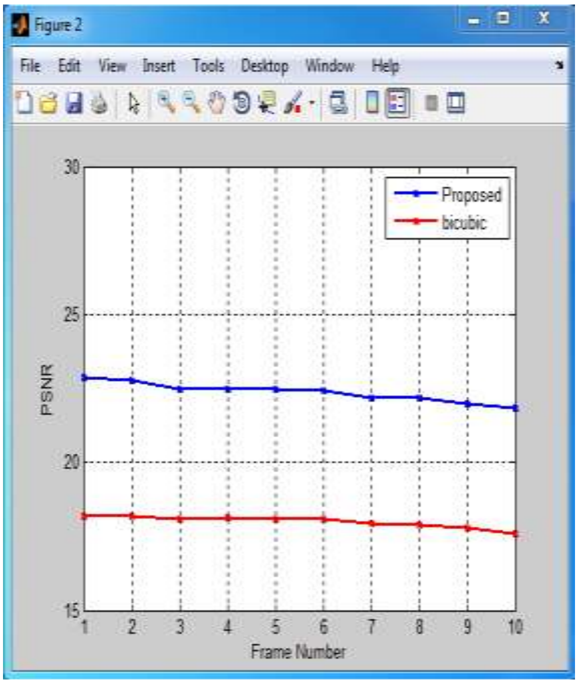

Fig 10: Peak Signal-to-Noise Ratio between Bi-Cubic and Proposed method

Peak Signal-to-noise ratio is calculated between bi-cubic method and our proposed method.

5. CONCLUSION

In this super-resolution and blind deconvolution techniques were used to analyze a low resolution video. Improving the quality of a video is a challenging problem using image enhancement techniques. To estimate the blurs, the non-uniform interpolation (NUI) super resolution method is used to up sample the frames under consideration that the blur is nothing but it's having slow variations as time proceed or it may be identical. From the up sampled frames blur is estimated iteratively on important edges. Finally we reconstructed frames which are blur estimated by application of non blind super resolution iteratively. Masking technique is applied to suppress the artifacts present due to inaccurate motion estimation during each iteration of final frame reconstruction. Color transformation is done in order to make it a device independent video. Peak signal-to-noise ratio is also calculated between bi-cubic and proposed methods. The subjective as well as objective analysis of final results will show that the state of art for implementation. Comparative study will show the superior performance of proposed work.

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