

Introduction

- > Achieving rain removal is beneficial for many practical visual systems like unmanned vehicles, autonomous robots and outdoor surveillance systems. \succ The existing methods often lead to over-blurred de-rained images. In fact,
- the orientation, density and scale of the rain streaks are varied not only across different images but also across different regions within each image, which means that different perceptive fields and scale analysis are required to jointly detect and process rain features.



- task learning strategy would refine the back propagation across all the scales. loss \mathcal{L}_A
- > Ablation study on the right proves that **feature** integration across scales and the top-down image generation strategy in the multi-scale cascading structure is important in de-raining task.



Encoder-decoder framework: encoder is used to extract multiple scale features of a rainy image and the decoder is used to generate the de-rained image from extracted features by a coarse-to-fine approach.

> Cascading feature flow across scales will supplement more spatial and contextual information to enhance the deraining performance. the ground truth is used to optimize the de-rained images at each scale and thus such a multi-

 \succ Hybrid loss function: $\mathcal{L} = \lambda_E \mathcal{L}_E + \lambda_P \mathcal{L}_P + \lambda_A \mathcal{L}_A$ data fidelity loss \mathcal{L}_E , perceptual content loss \mathcal{L}_P and adversarial

Data	Rain100		
	Single scale	Multi-s	
PSNR	26.1869	27.45	
SSIM	0.8502	0.867	
UQI	0.6793	0.699	







CNN	RES	JORDER	IDCGAN	DID-MDN	Ours
3.3917	22.8457	20.4823	24.4715	26.5243	27.4514
.7719	0.7500	0.6247	0.8133	0.8262	0.8676
.5931	0.5767	0.4994	0.6449	0.6723	0.6992
CNN	RES	JORDER	IDCGAN	DID-MDN	Ours
1.8458	27.6553	23.4191	23.9327	26.4789	28.4799
.7692	0.8018	0.7279	0.7932	0.8252	0.8502
.6253	0.6449	0.5590	0.6327	0.6701	0.6922