Learning a Deep Compact Image Representation for Visual Tracking

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Abstract

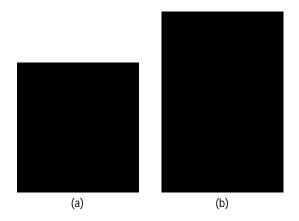
In this paper, we study the challenging problem of tracking the trajectory of a

that the tracked object can be represented by a sparse combination of overcomplete basis vectors. Many extensions [26, 25, 4, 21] have also been proposed. On the other hand, the discriminative approach treats tracking as a binary classification problem which learns to explicitly distinguish the object being tracked from its background. Some representative trackers in this category are the *online AdaBoost* (OAB) tracker [6], *multiple instance learning* (MIL) tracker [3], and *structured output tracker* (Struck) [8]. While generative trackers usually produce more accurate results under

What is specific to the particle filter approach is that it approximates the true posterior state distribution $p(\mathbf{s}^t \ | \ \mathbf{y}^{1:t})$ by a set of n samples, called particles, $f\mathbf{s}$

contains a "bottleneck" which is a hidden layer with fewer units than the input units. We show the architecture of DAE in Fig. 1(a).

Let there be a total of k training samples. For the ith sample, let \mathbf{x}_i denote the original data sample and \mathbf{x}_i be the corrupted version of \mathbf{x}_i , where the corruption could be masking corruption, additive Gaussian noise or salt-and-pepper noise. For the network weights, let \mathbf{W} and \mathbf{W}^{ℓ} denote the weights for the encoder and dee and respe



environment is very dark with illumination in the cluttered background. Since the car being tracked

References

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