

# Analyse eines Forschungsthemas

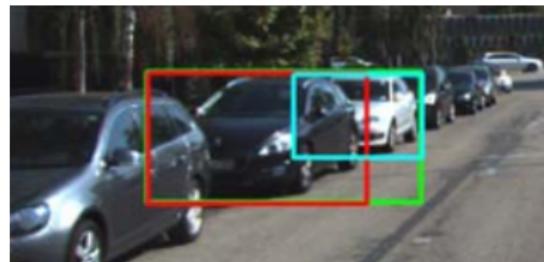
- 2 of 3 papers deal with pose estimation -

Josef Schulz

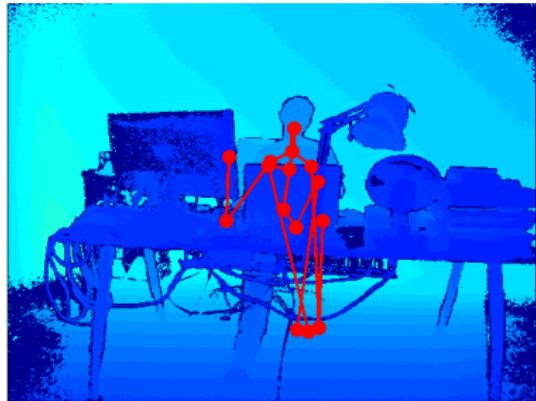
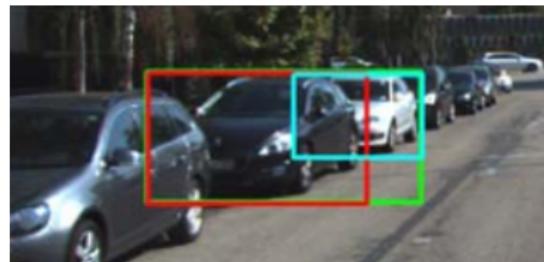
April 19, 2016

# Example Problems

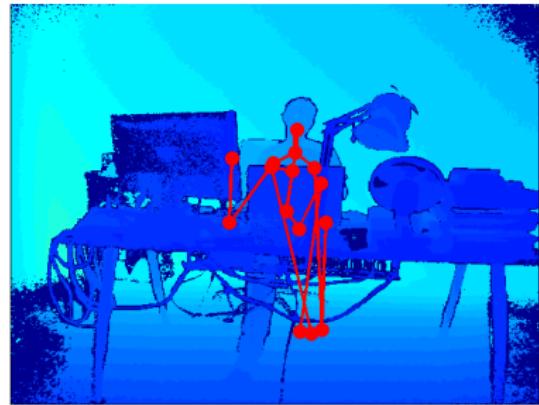
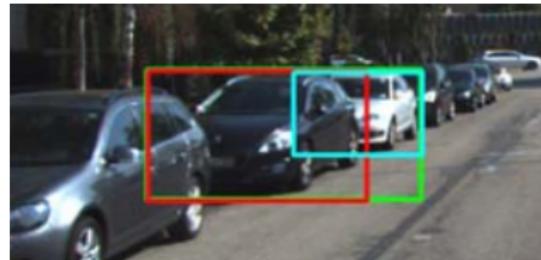
## Example Problems



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# Example Problems



# Content

## 1 Examples

## 2 Algorithms

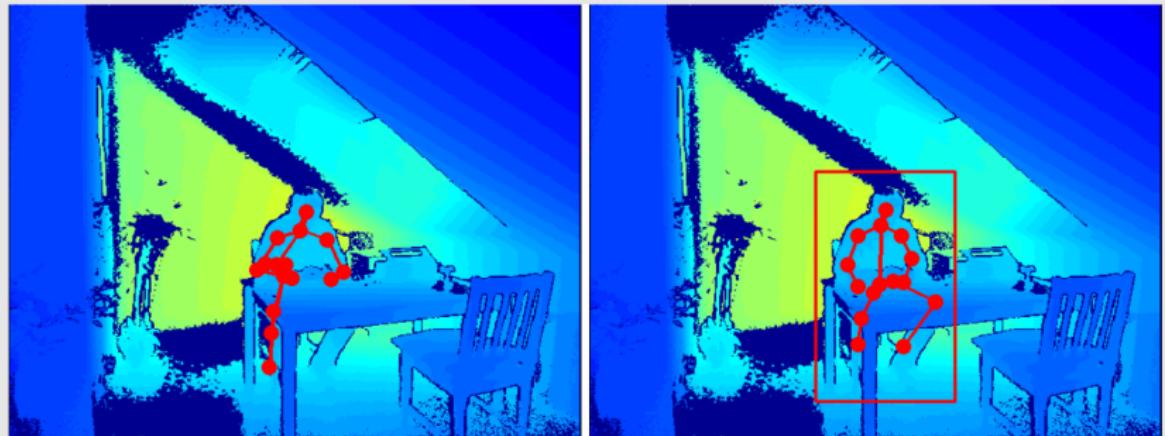
- Semantic Occlusion Model
- Occlusion Patterns
- Robust Instance Recognition

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# A Semantic Occlusion Model For Human Pose Estimation



*Input* : single Depth-Image

*Output* : estimated poses of all parts

# Regression Forest

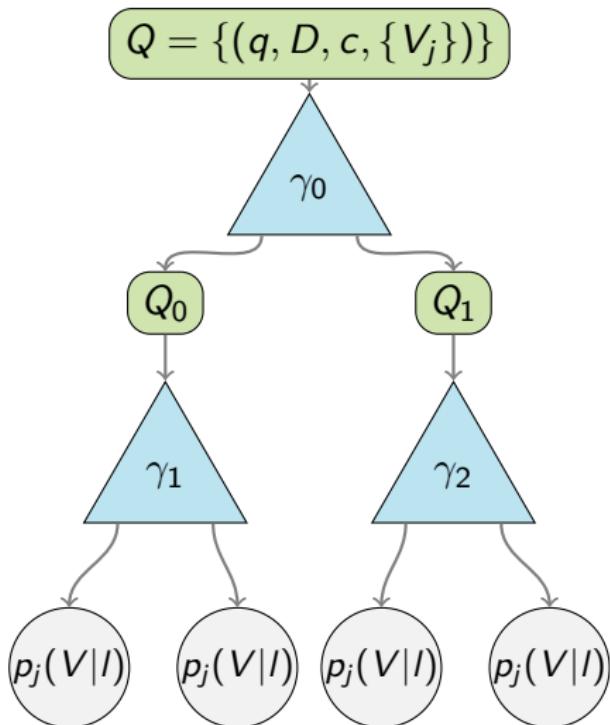
## Training Set

$$Q = \{(q, D, c, \{V_j\}), \dots\}$$

- $q$  pixel location
- $D$  reference depth image
- $c$  class label corresponding to limbs

$\{V_j\}$  is set of vectors:

$$V_j = q_j - q$$



## Slit Node

$$\gamma = (\textcolor{blue}{u}, \textcolor{blue}{v}, \tau)$$

$$\Phi_\gamma(q, D) \mapsto \{0, 1\}$$

$$\Phi_\gamma(q, D) = \begin{cases} 1 & \text{if } D(q + \frac{\textcolor{blue}{u}}{D(q)}) - D(q + \frac{\textcolor{blue}{v}}{D(q)}) > \tau \\ 0 & \text{else} \end{cases}$$

$\textcolor{blue}{u}, \textcolor{blue}{v}$  - offset vectors

$\tau$  - threshold

$D(q)$  - depth value

## Evaluating The Splitting Functions Information Gain

$$\Phi^* = \arg \max_{\Phi} g(\Phi)$$

$$g(\Phi) = H(Q) - \sum_{s \in \{0,1\}} \frac{|Q_s(\Phi)|}{|Q|} H(Q_s(\Phi))$$

$$H(Q) = - \sum_c p(c|Q) \log(p(c|Q))$$

$H(Q)$  - Shannon entropy

$g(\Phi)$  - information gain

## Leaf Node

$$p_j(V|I) \propto \sum_{k \in K} w_{ljk} \cdot \exp\left(-\left\|\frac{V - V_{ljk}}{b}\right\|_2^2\right)$$

$K$  - cluster

$w_{ljk}$  - is determined by offset vectors ended in the cluster k,  
support

$V_{ljk}$  - cluster center

## Pose Estimation

$$p_j(x|D) \propto \sum_{(x_j, w_j) \in X_j} w_j \cdot \exp\left(-\left\|\frac{x - x_j}{b_j}\right\|_2^2\right)$$

$$X_j = \{(x_j, w_j)\}$$

$x_j$  - absolute joint position,  $x_j = q + V_{ljk}$

$w_j$  - confidence value,  $w_j = w_{ljk} \cdot D^2(q)$

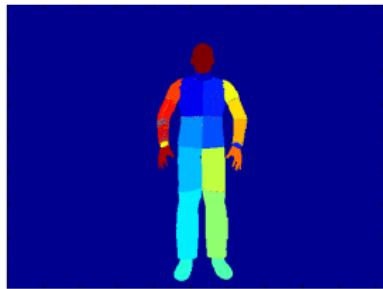
the clusters with the highest summed weights  $w_j$  are used for prediction.

# Occlusion Aware Regression Forests

$$Q = Q \cup \{(q_{occ}, D, C_{occ}, \{v_{jocc}\})\}$$

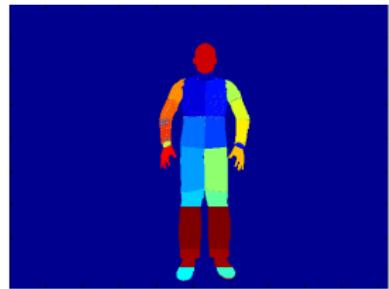
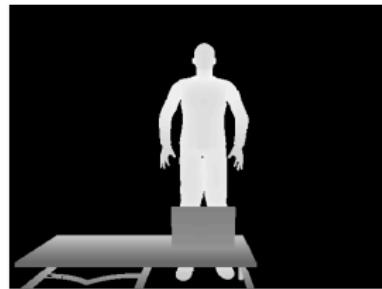
without Semantics

$$C_{occ} = \{c_{occ}\}$$



with Semantics

$$C_{occ} = \{c_{obj1}, c_{obj2}, \dots\}$$



## Training Data

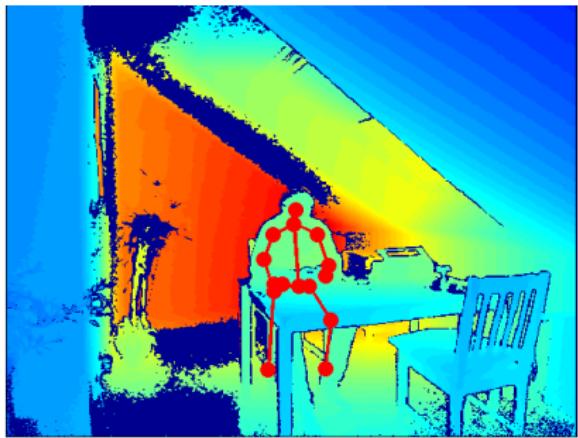
### Synthetic Data (552 images)

- ▶ Human Poses from CMU-Database [9]
- ▶ body part labels for each pixel

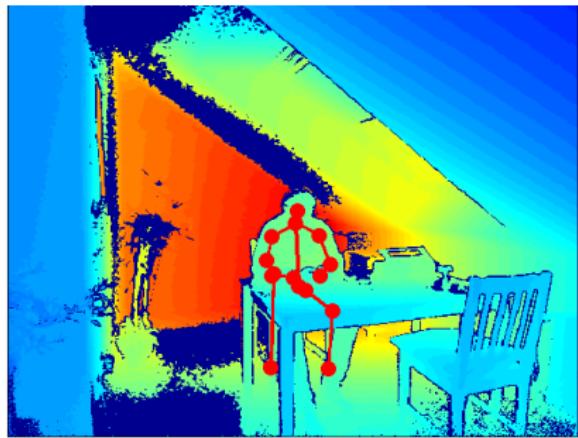
### Real Data (552 images)

- ▶ Kinect2 SDK, all fails are discarded

# With And Without Semantics

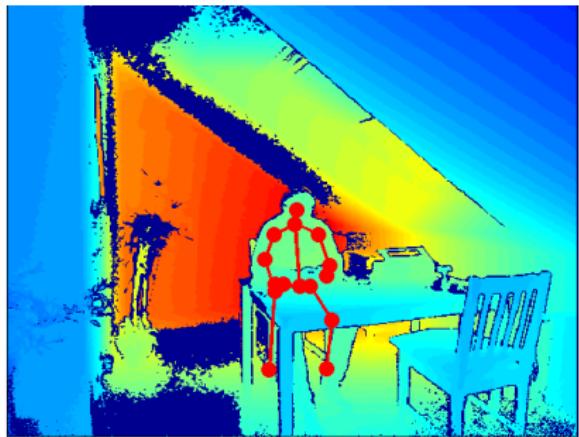


with semantics

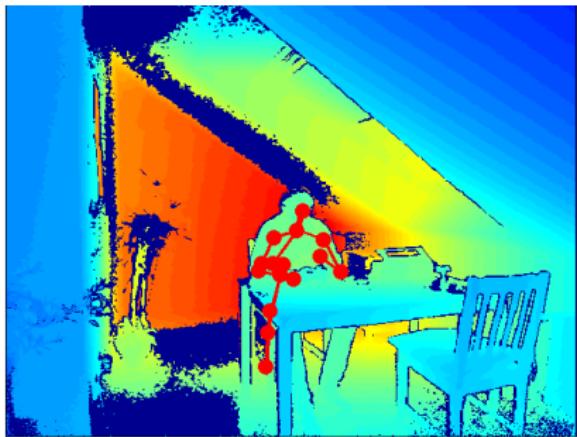


without semantics

# OARF vs. Kinect2 SDK



OARF with semantics



Kinect2 SDK

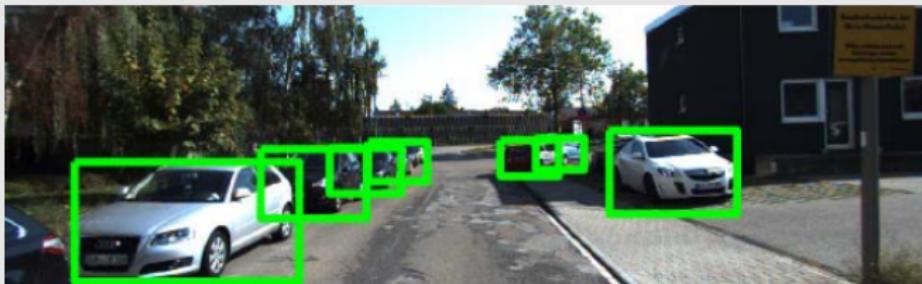
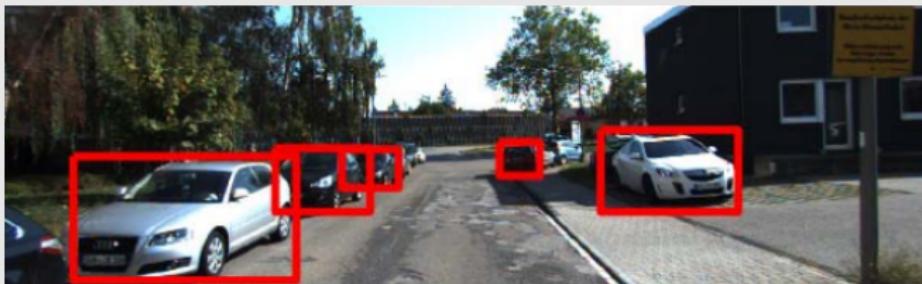
## Results

	Occluded Joints	Non Occluded Joints	All Joints
OARF W/O	32.60	55.50	50.66
OARF W	35.77	56.01	51.72
Kinect2 SDK	18.13	66.36	56.94

in %

Real + Synthetic Data

# Occlusion Patterns for Object Class Detection



*Input* : Single RGB-Image

*Output* : Object-Bounding-Boxes

# Deformable Models Approach

- ▶ Consider each object as a deformed version of a template
- ▶ Compact representation

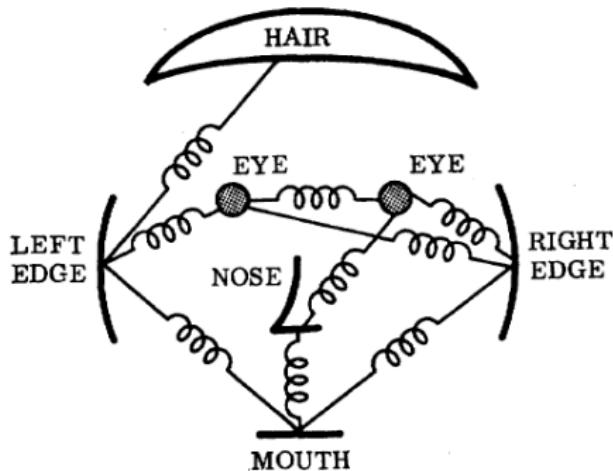


Figure : Pictorial Structure Model [8]

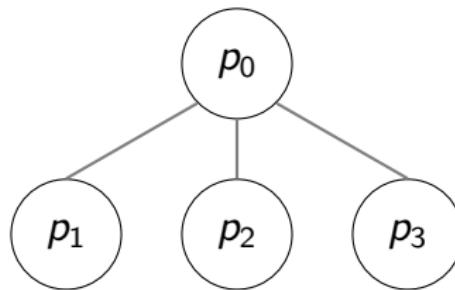
Matching model to image involves joint optimization of part locations "stretch and fit"

# Model

Model is represented by a Graph

- ▶  $p = \{p_0, \dots, p_M\}$  are the parts
- ▶  $p_i$  is parameterized through their bounding box  $(l_i, r_i, t_i, b_i)$

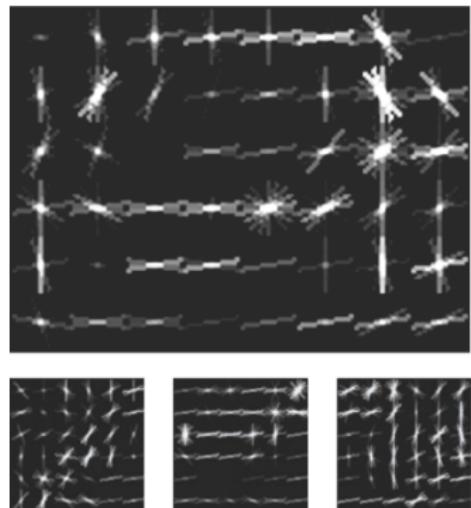
$E_c$  - is the Energy function



$$E_c(p; I) = \underbrace{\sum_{i=0}^M \langle v_i^c, \Phi(p_i; I) \rangle}_{\text{placing cost}} + \underbrace{\sum_{i=1}^M \langle w_i^c, \Phi(p_0, p_i) \rangle}_{\text{deformation cost}}$$

# Filter

- ▶ images with bounding boxes
- ▶ histograms of oriented gradients (HOG) for placement
- ▶ twice the resolution for every level
- ▶ Gaussians for deformation



## KITTI Data Set

KITTI contains 7481 images

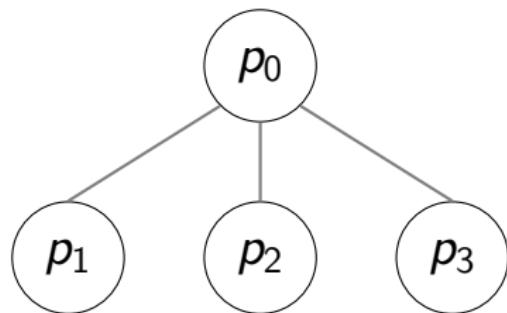
	#objects	#occluded objects	%
Car	28521	15231	53.4
Pedest.	4445	1805	40.6
Cycles	1612	772	44.5

Parts:

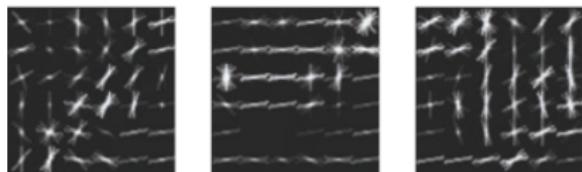
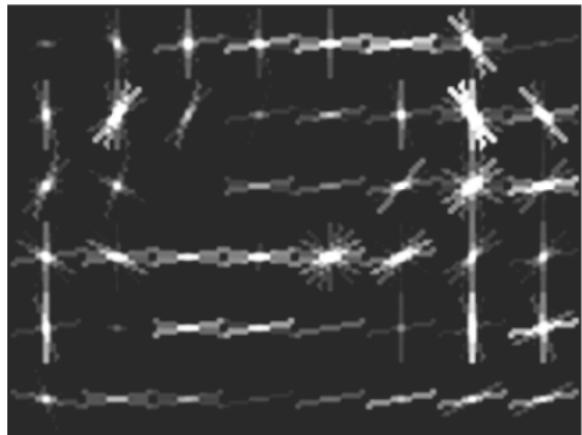
visible 6

occluded 16 – 15

$$C = \{1, \dots, C_{visible}\} \cup C_{invisible}$$

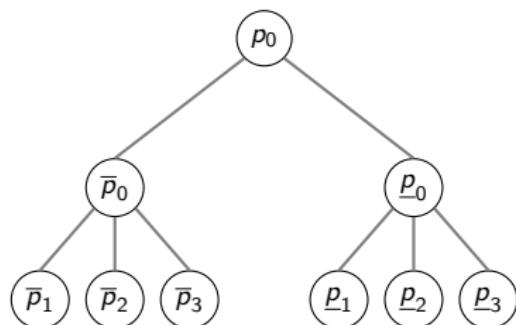


- ▶ like standard dpm
- ▶ trained with occlusion
- ▶  $C$  are components

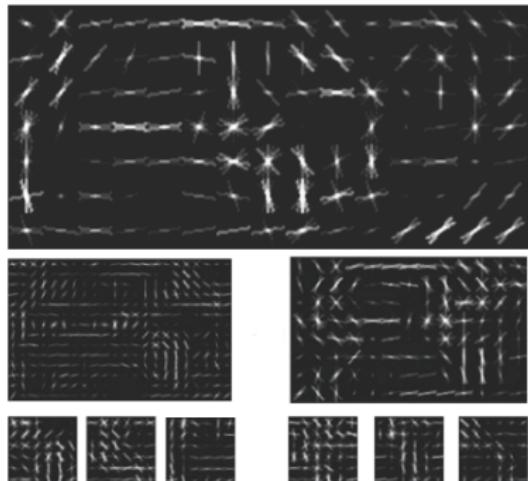


# SYM-DPM

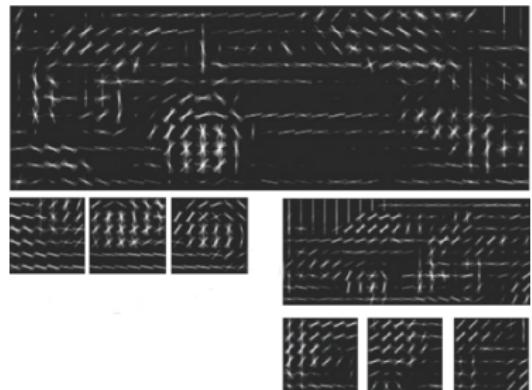
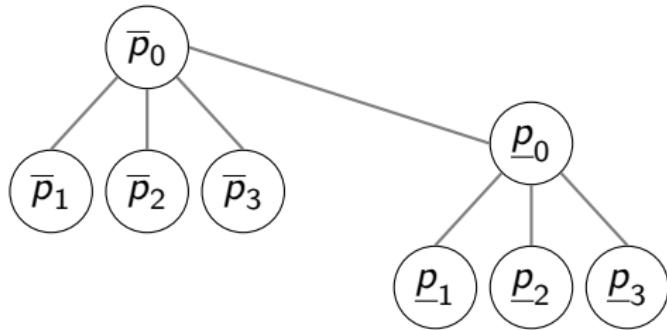
$$\begin{aligned} E'_c(p; I) = & \langle v^c, \Phi(p_0; I) \rangle + \langle \bar{w}^c, \Phi(p_0, \bar{p}_0) \rangle + \langle \underline{w}^c, \Phi(p_0, \underline{p}_0) \rangle \\ & + E_c(\bar{p}_0; I) \qquad \qquad \qquad + E_c(\underline{p}_0; I) \end{aligned}$$



- ▶ one root part
- ▶ occluder  $\bar{p}_0$  root part
- ▶ occludee  $\underline{p}_0$  root part



# ASYM-DPM



- ▶ occluder left, occludee right
- ▶ tree structure
- ▶ no extra terms

# Mining Trainingsdata

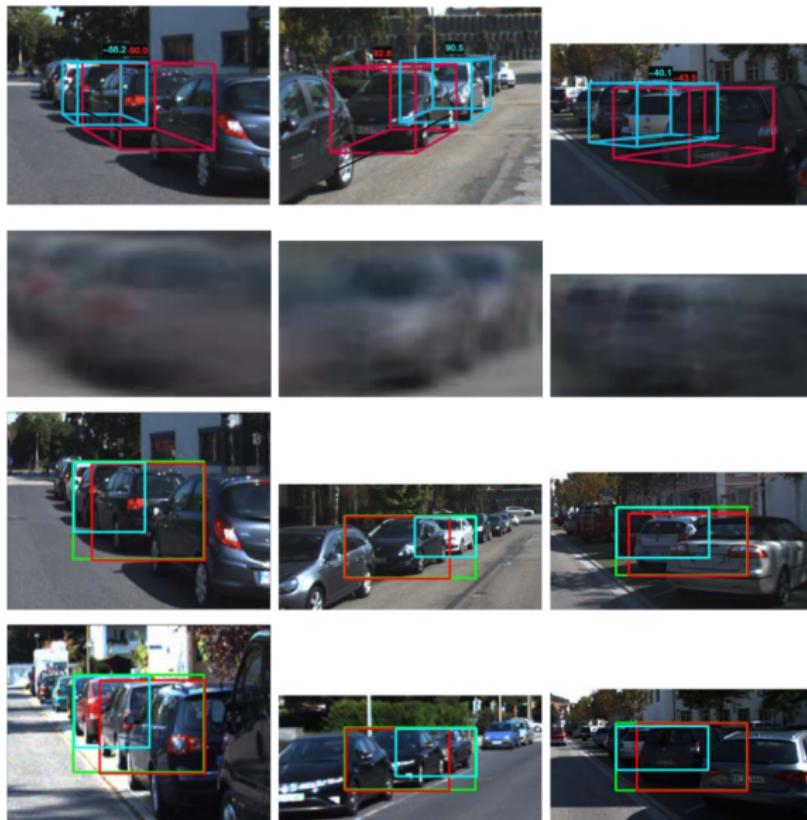
## Feature Space:

- i occluder left/right of occludee
- ii orientation of occluder/occludee
- iii occluder is/is not occluded
- iv degree of occlusion of occludee

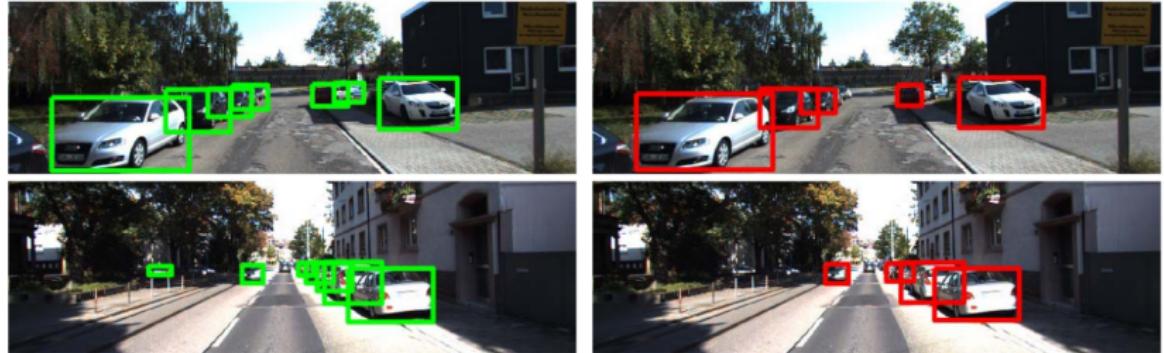
## Rule-based clustering

- repeatedly splitting the training data
- according to the viewing angle of the occluder

# Mining Trainingsdata



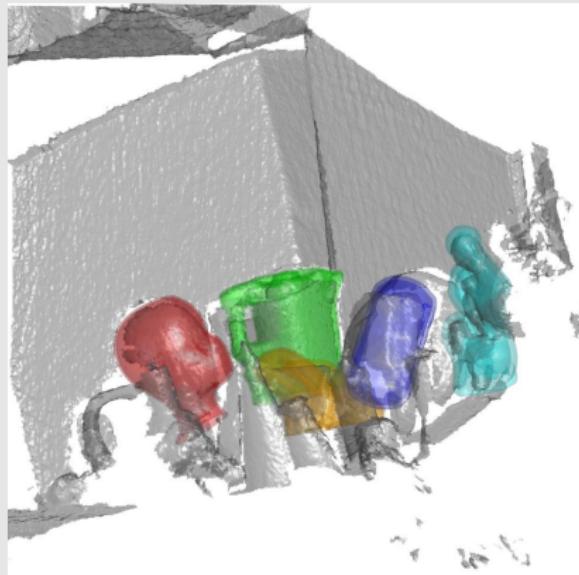
# Results



OC-DPM	DPM	OC-DPM	SYM-DPM	ASYM-DPM	DPM
full dataset	62.8	64.4	53.7	52.3	
Pedestrian	36.2	37.2	31.4	29.4	

in %

# Robust Instance Recognition in Presence of Occlusion and Clutter



*Input* : 5-10 consecutive frames as one Pointcloud

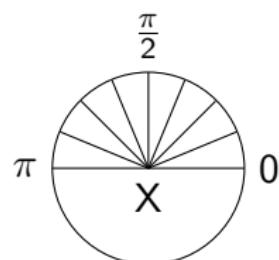
*Output* : 6D-Object-Pose

## Introduction

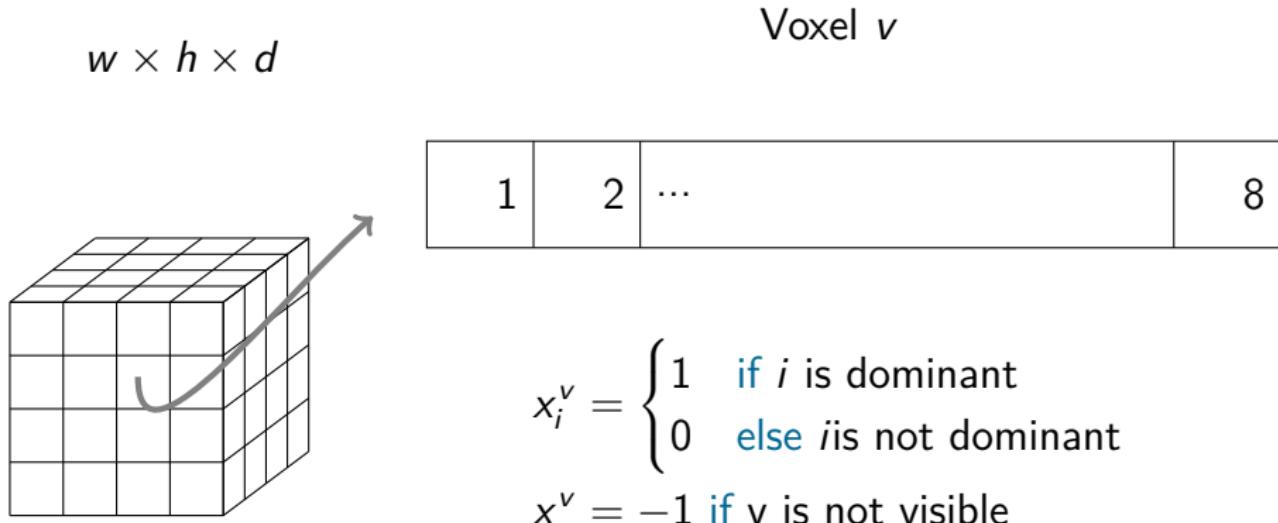
- object shape is invariant to changes in illumination or texture
- Kinect sensors generates cheap depth data
- it is easy to synthesize pointcloud data

# Edgelet

- ▶  $N$  points per Pointcloud  $j$
- ▶ **FOR ALL**  $i \in \{1, \dots, N\}$ 
  - ▶ calc  $\lambda_1$  and  $\lambda_2$
  - ▶  $r = \frac{\lambda_1}{\lambda_2}$
  - ▶  $r \rightarrow \text{curvatureMap}$
- ▶ hysteresisThesholding(`curvatureMap`);
- ▶ nonmaximalSuppression(`curvatureMap`);
- ▶ hysteresisThesholding(`depthMap`);
- ▶ projectToPointcloud(`curvatureMap`, `depthMap`);
- ▶ RANSAC line fitting
- ▶ orientation to 8 bins // (direction %  $\pi$ )



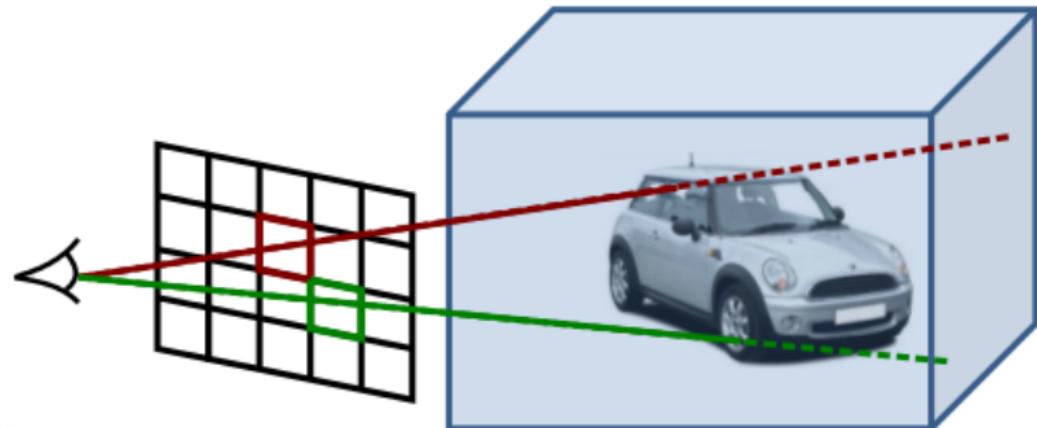
## Feature Vector



The resulting feature vector is the concatenation of all voxels:

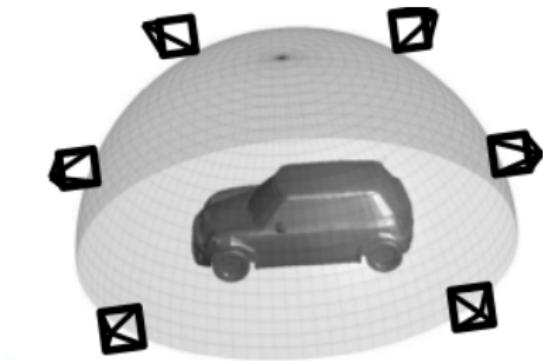
$$w \times h \times d \times 8$$

## Box Model For Occluder



- ▶ occluder are rectangular
- ▶ occluders are restricted to start from the ground plane

## Soft Label Random Forest



- ▶ 16 pose classes
- ▶ +1 class =  $\begin{cases} 1 & \text{if bg} \\ 0 & \text{else} \end{cases}$
- ▶  $d_j^i = \|I - R_j^i\|_F$

$$l_j^i = \exp(-d_j^{i2}), i \in \{1, \dots, 16\}$$

IF fg THEN  $1 = \sum_{i=1}^{16} l_j^i$  ELSE 0

## Occlusion Queries

$$x_j \in \{-1, 0, 1\}$$

( $> -1$ ) - visible versus occluded voxel

( $> 0$ ) - dominant or not visible voxel

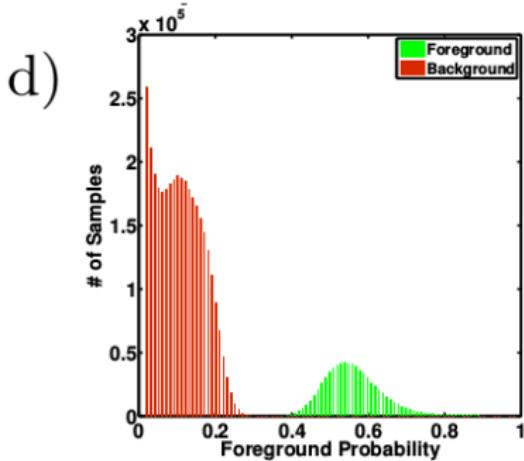
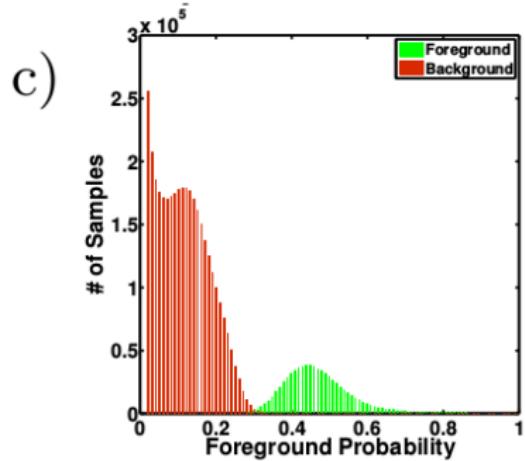
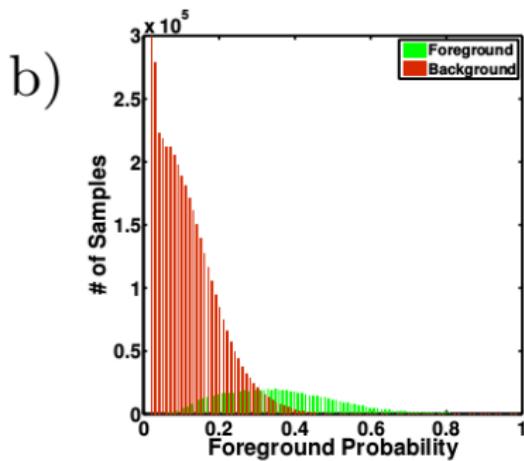
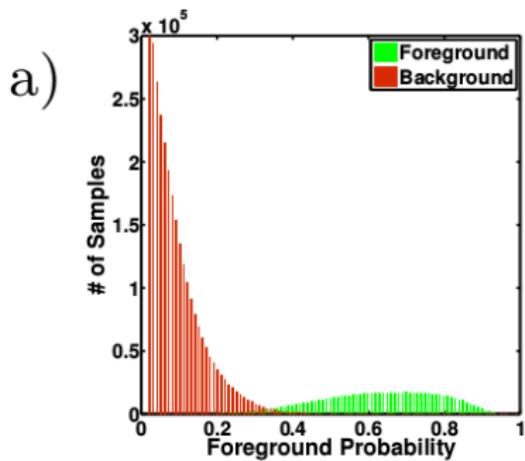
- split questions in the topmost nodes ( $\approx 5 - 10$ ) are restricted to the second type

## training scheme for sLRF

**Input:**  $X = \{x_j, l_j\}$ , ( $\approx 27000$ ) examples

**Output:** Learnt sLRF classifier

1.  $X_s \subset X$ ,  $|X_s| = |X|/20$
2. Train sLRF with  $X_s$ , compute  $p_{fg}$  with  $X$
3. add borderline positive (low  $p_{fg}$ ) and borderline negative (high  $p_{fg}$ )
4. add confusing samples
5. compute  $d_L$  for all positive samples, add samples with high  $d_L$
6. repeat 2-5 till  $p_{fg}$  for all positive data is greater than  $p_{fg}$  for all negative data.



## Results

	D-DPM	LineMod	S-Iterative (Edges)	S-Iterative (Occlusion)
L	40.50	30.15	70.70	81.89
L+P	23.72	13.17	52.62	62.11

in %

L - location

P - pose estimation

## Robustness Against Occlusion - Conclusion

- ▶ semantic (scene understanding)
- ▶ mixture models
- ▶ multiple representation for one object class
- ▶ good feature representation
- ▶ training with occlusion

# Discussion





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