

Efficient Moving Object Tracking with Hybrid Detection Approaches

UNSW

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Abstract

1. What is the problem
2. Why is it still a problem
3. What is the solution and what theory is solution based on
4. what is found

1 Introduction

When perceiving surroundings, human beings do not repeatedly identify the same objects. Instead, they spent a lot of energy on recognizing new objects at the very beginning, then paid a little bit effort to track them rather than re-recognize them. Therefore, the workload of the brain can be significantly decreased and more resources can be used for other purposes. For example, after identifying all participants in the traffic scenario, driver would just effortlessly track them and split some extra attentions on possible new coming objects or predicting abnormal situations, instead of being in particularly alert state to re-detect every details in the scenario. In most cases, our brain just tries to maintain safe driving with minimum effort consumption so that fatigue will not happen too quickly.

Such kind of intelligent detection and tracking mechanism

2 Literature Review

Papers on tracking.

Papers on detection.

Papers on how to fuse the expensive computation and cheap computation together.

Papers on uncertainty evolution with changing sensor model.

3 Evolution of Estimation Uncertainty under Time Varying Measurement Complexity

$$p(X_k|Y_k) \propto p(y_k|X_k) \int p(X_k|X_{k-1})p(X_{k-1}|Y_{k-1})dX_{k-1}$$

Likelihood function, $p(y_k|X_k)$, denotes the sensor model. How does estimation evolve when $p(y_k|X_k)$ is time varying.

3.1 General distribution

$p(y_k|X_k)$ is any form distribution function and is approximated with summation of gaussian function.

When the sensor noise follows Gaussian distribution, we can justify the idea from Riccati equation.

3.2 Gaussian Distribution

$p(y_k|X_k)$ follows Gaussian distribution. Introduce the Riccati equation and what is solution with sensor uncertainty R hypothesis.

3.2.1 Uncertainty Evolution with increasing R

Generation of R is based on series and sequence theory.

The R will increase with time, for example, sensor gradually degrades with time due to aging. What is the solution of Riccati equation?

3.2.2 Uncertainty Evolution with periodical R

The R periodically changes with time, just like replacing the sensor regularly, which is our case. What is the solution of Riccati equation?

4 Detection Approaches

4.1 Expensive detection

Expensive detection method based on deep learning[1]

4.2 Cheap detection

Cheap detection method based on simple segmentation

5 Moving Object Tracking

Using the tracking mechanism to combine them together.

5.1 Tracking Filter

Extended Kalman filter or Phd filter are used for moving object tracking.
(Finish the tracking book to get all theoretical fundamentals for tracking)

5.2 Tracking with Hybrid Detection Methods

6 Experiments

6.1 Implementation

6.2 Results

References

- [1] Y. Zhou and O. Tuzel. Voxelnet: End-to-end learning for point cloud based 3d object detection. *CoRR*, abs/1711.06396, 2017.