Visual Object Tracking applying ensemble of multiple trackers

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Declaration of Authorship

I, John SMITH, declare that this thesis titled, 'Thesis Title' and the work presented in it are my own. I confirm that:

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"Thanks to my solid academic training, today I can write hundreds of words on virtually any topic without possessing a shred of information, which is how I got a good job in journalism."

Dave Barry

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Abstract

Faculty Name
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The Thesis Abstract is written here (and usually kept to just this page). The page is kept centered vertically so can expand into the blank space above the title too...

Acknowledgements

> Not enough people do things that leave others to wonder. RT @BrianMendicino: Wondering why @neiltyson is watching Glee.
>
> —— Neil deGrasse Tyson

The acknowledgements and the people to thank go here, don't forget to include your project advisor...

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Abbreviations

LAH   **L**ist **A**bbreviations **H**ere

Physical Constants

Speed of Light $\quad c \quad = \quad 2.997\ 924\ 58 \times 10^8$ ms^{-S} (exact)

Symbols

a	distance	m
P	power	W (Js^{-1})
ω	angular frequency	rads^{-1}

For/Dedicated to/To my. . .

Chapter 1

Introduction

Visual object tracking is an important problem in computer vision. This field has a wide range of applications such as surveillance,en success building trackers for specific object classes, a generic object tracker represents a challenging task. In general case, tracking an arbitrary object in an unknown scenario is still considered unsolved. Common challenges are for example, object deformations, illumination human-computer interaction and motion analysis. Althought there has be changes, partial and complete occlusions, drifting, background clutter and similar objects in the scene. This particular situations make some trackers better than others. However, there is no algorithm that has mastered all possible problems that a scenario might generate.

Recently, the evaluation performed in [**?**] shows, each tracking algorithm performs well on different sequences. This explains that different tracking algorithms avoid challenges that can occur in general object tracking. We consider an approach that combines the virtues of different algorithms while evading their weaknesses could outperform each single algorithm. Just as "two heads are better than one", making trackers perform this task together in an unknown scenario, may result in a higher level of performance and achievement, than could be obtained individually. This is what in psychology states as "positive interdependence", the ability of group members to encourage and facilitate each other's efforts [**?**].

1.1   Goals

In this paper, we focus on the problem of tracking an arbitrary object in videos, with no prior knowledge other than its location in the first frame, also known as "model free tracking". We are motivated to link trackers together so one cannot succeed, unless all

group members succeed. A common tracking system consists of an appearance model, which can evaluate the likelihood of the object of interest at a given location. A motion model, that stores and contains the locations of the object over time. Finally, a search strategy to find the best location in the current frame [**?**].All methods share the same goal, meaning that each tracker's individual "effort" is required and is indispensable for group success. Using these models, we make trackers correct each other, increasing performance and ensuring the group is united to a common goal, a concrete reason of being, a purpose for existence.

Chapter 2

Moving Object Detection Approaches, Challenges and Object Tracking

2.1 Moving Object Detection

In a video, there are two sources of information that can be used for object detection and tracking: Visual features (color, texture and shape) and motion information. Robust approaches suggest that combining the statistical analysis of visual features and temporal analysis of motion information. Moving object detection targets the extraction of moving objects that are of interest in sequences (e.g. people and vehicles).

A large number of methodologies have been proposed for object tracking, focusing on the task of object detection first. Most of them apply combinations and intersections among different methodologies, making it very difficult to create a uniform classification of existing approaches. This section classifies different approaches available for object detection from videos.

2.1.1 Background Substraction

Background subtraction is a commonly used technique for object segmentation in static scenarios [1]. This task consist in detecting moving regions by subtracting the current image pixel-by-pixel from a reference background image. The pixels above some threshold are classified as foreground (belongs to an object). The background image is created averaging images over time in an intiialization period, and is updated with new images to

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adapt to dynamic scene changes. Also, the foreground map is followed by morphological operations such as closing and erosion (elimination of small-sized blobs).

Although background subtraction techniques extracts well most of the relevant pixels, this method is sensitive to changes when some background and foreground pixels have similar value.

2.1.2   Temporal differencing

In temporal differencing, objects are detected by taking pixel-by-pixel difference of consecutive frames (generally two or three) in a video sequence. This method is most common for moving object detection in scenarios where camera is moving. Unlike static camera scenarios, the background is changing in time for moving camera (not appropiate to create a background model). Alternatively, the moving object is detected by taking the difference between frames $t - 1$ and t.

This method is highly adaptive to dynamic changes in the scene as most recent frames are involved in the process. However, it fails detecting small regions as moving objects (ghost regions). Detection will not be correct also, for objects that preserve uniform regions (static objects).

A two-frame differencing method is presented in [2], where the pixels that satisfy the following equation are marked as foreground.

$$|I_t(x, y), I_{t-1}(x, y)| > Th$$

Other methods were developed in order to overcome drastic changes of two frame differencing in some cases. For instance, a three-frame differencing method [3] and a hybrid method that combines three-frame differencing with an adaptive background subtraction model [4].

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