

Classification of Pixel Data using a Support Vector Machine

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Chapter 1

Operational Information

1.1 Overview

Classifying the picture accurately and efficiently means generating a basis upon which to relate the output of the neural network with that of a human-based classification. To generate such a basis, we need to construct three major parts:

- Class Mask
- Training Point Pool
- Kernel & Hyperplane Selection

The class mask will designate to the neural network which part of the training image belongs to which class. The training point pool is used to allow certain parts of the mask to be weighted more than other parts when training the neural network for classification. The kernel and hyperplane functions are chosen to maximize the accuracy at similar point pool sizes.

1.2 Class Masking

To classify the picture as closely as possible to the desired result, it was necessary to review the details of the image for any features that could be extracted at an elementary level. The elementary level in this case is the raw image data available through individual pixel values. The support vector machine implementation in Matlab allowed for as many classification parameters to be passed for generating the classification structure.



Figure 1.1: Classification Mask used to determine class of training points

In our case, we narrowed the classification parameters down to a subset of the following:

- Cartesian Coordinates (X,Y)
- $L*a*b^*$ pixel values
- Gaussian filtered $L*a*b^*$
- Sobel filtered $L*a*b^*$

When using the class mask, as seen in 1.1, it was necessary to generate a set of points to apply to the mask which maximized the positive effect on the support vector machine while reducing the requirement for an overly high number of required points.

The support vector machine internally tries to maximize the distance between the points it is currently training against and the desired hyperplane(Haykin, 2008b). The points are known, while the hyperplane is unknown. Randomly generating points from the entire images with no concern for position doesn't benefit the areas in the image where the distinction between both classes is quite complex.

1.3 Point Generation and Pooling

A method for promoting certain parts of the image while also allowing for automation of point generation is shown below. By applying a Gaussian blur filter to the previous hard-edged mask, a new mask where the point densities increase relative to the distance to the mask boundary is generated. By edge-detecting and Gaussian blur filtering the class mask, the image can be extracted with ease from the class mask.



Figure 1.2: Mask relating desired point density to position

The training point generator works by sampling points through probability specified by the pixel values on this density mask. Visually the colormap, as shown in 1.3, is an example in which the points will be more likely to be generated from. For small training sizes, there is no guarantee that points will exist from those levels in the produced training set as the pool itself is sampled and culled to bring forth the final training set.

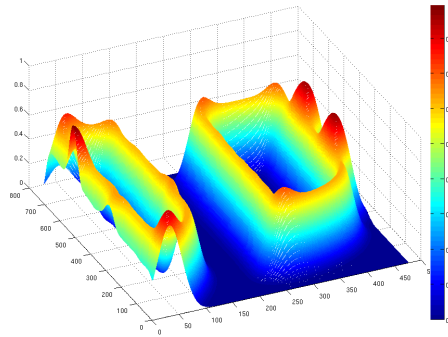


Figure 1.3: Colormap demonstrating point densities at different pixel locations

1.4 Kernel Function

For selecting the kernel to be used in the support vector machine, it was necessary to test those available to us from Matlab. The kernel functions

available to us were as follows:

- Linear
- Quadratic
- Polynomial
- Radial Basis Function (RBF)
- Multilayer Perceptron (MLP)

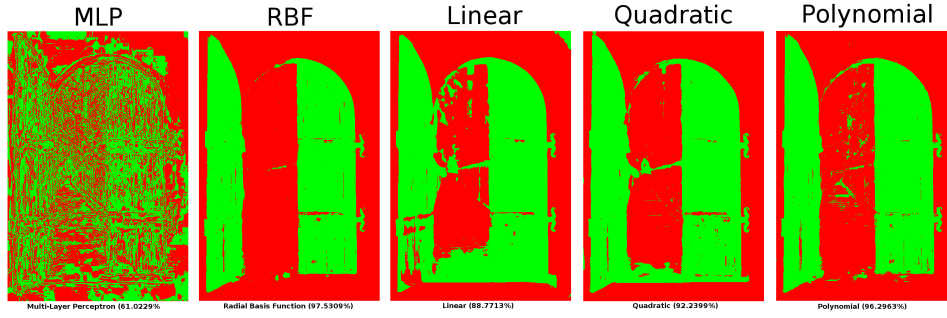


Figure 1.4: Comparison of the Different kernels using 1000 training points

We decided to use the RBF kernel as it worked well in conjunction with the image processing done during training. To compare the kernels, we can examine the accuracy at sampling 1000 points from the image for training. When using the MLP kernel, we noticed the accuracy dropped over 40 percentile points for a similar calculation time to the RBF. Interestingly enough, the polynomial function was not only faster than the RBF and MLP but also had a comparable accuracy to the RBF. The quadratic kernel function had a time almost halfway between the linear and RBF kernels.

1.5 Hyperplane Method

For the method of determining the appropriate hyperplane, we chose to use "Least Squares". The choices available to us were:

- Least Squares (LS)
- Quadratic Programming (QP)

- Sequential Minimal Optimization (SMO)

Quadratic Programming was highly resource intensive for generating a classifier in respect to both Least Squares and Sequential Minimal Optimization. When using QP, Matlab failed to finish generating the hyperplane, thus we were unable to generate a classifier with the resources we had with QP. Due to this fact, we had to exclude it from our methods.

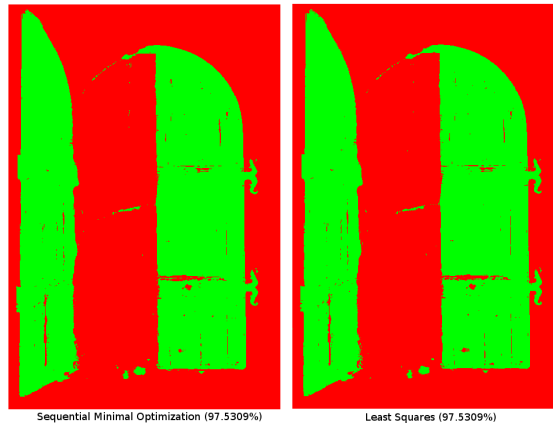


Figure 1.5: Comparison between methods of Least Squares and Sequential Minimal Optimization

When comparing least squares versus sequential minimal optimization, there was no appreciable difference between the accuracies of the two. The differences between the images in 1.5 are very minimal, to the degree of the sixth significant digit or more.

Chapter 2

Process Decision and Details

2.1 Choice of Parameters

When choosing the parameters to train the support vector machine, we decided to expand on the data available from the image. By applying certain filters to the image, it is possible to expand on the features of the image without requiring manual editing of the image.

Chapter 3

Testing & Results of Support Vector Classification

3.1 Classification of Testing Data

To determine optimal performance, we wanted to test the system setup with different numbers of training points. Variable number of parameters were extracted from the image to test the improvement in performance of the SVM classification.

The testing data was gathered by hand, and later automated for ease of testing. After gathering the points they were classified into their respective categories with a premade mask selecting whether specific points were part of the door or not.

3.2 Overall Effect

Over the numerous types of parameters we could specify for the support vector machine to operate on, the order of effectiveness can be determined by the relative accuracy increase through its inclusion into the training data.

The main parameters tested were as follows:

L*ab (Direct Pixel Value)

L*ab (Radial Blur Pixel Value)

XY (Pixel Location)

The pixel location had a surprisingly opposite reaction to the effectiveness of the system upon adding its values to the training data. Using only



(a) L*ab Pixel data (b) L*ab Radial Blur (c) XY Pixel Location

Figure 3.1: Results of Differing SVM information, individual testing

the pixel coordinates to train the system had detrimental effects on the performance of the SVM.

Seen in figure 3.1, the hardest parts for the SVM to properly classify were the places with both similar colour and texture to the door. In these areas, the SVM had a higher probability to return false positive results.

In the end it was determined that the inputs that yielded the most optimal results were the L*ab colour data, the Sobel filter data, and the Gaussian Radial Blur. In effect, the pixel colour, the derivation, and the integration of the pixel value. This was done in an attempt to maximize the amount of information, without adding too many inputs to keep complexity too high.

3.3 Outcome

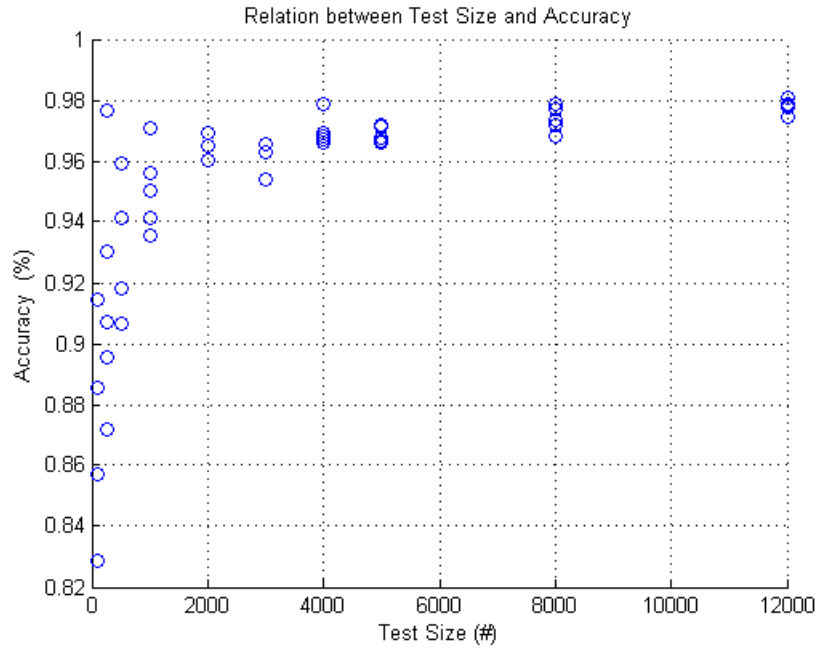


Figure 3.2: Changes in accuracy in the SVM from variance in the training set size.

By limiting the data sent to the training set for the support vector machine, it was possible to observe 90% and above performance for even small amounts of training data. The position of these points had a greater effect on the results than when the number of points was higher. The variance in the accuracy with differing test sets decreased when the total number of points increased. As expected, the results are very sensitive to the position of the training points; more points will become support vectors that are further away from the optimal hyperplane.

Bibliography

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