

PA2 Problem 3

In [1]:

```
from google.colab import drive
drive.mount('/content/drive')
```

Mounted at /content/drive

In [2]:

```
import os
import sys
sys.path.append(os.path.abspath('/content/drive/MyDrive/2_pose_estimation'))

from model import *
import torch
import numpy as np
import torchvision
import tqdm
from torch.utils.data import Dataset
from torch.utils.data import DataLoader
import cv2
import math
import torch.nn as nn
import torch.optim as optim

from glob import glob
import pandas
import matplotlib.pyplot as plt

device = 'cuda:0'
num_joints = 21
```

In [3]:

```
class Dataset(Dataset):
    def __init__(self, method=None):
        self.root = '/content/drive/MyDrive/2_pose_estimation/dataset/'
        self.x_data = []
        self.y_data = []
        if method == 'train':
            self.root = self.root + 'train/'
            self.img_path = sorted(glob(self.root + 'rgb/*.jpg'))

        elif method == 'test':
            self.root = self.root + 'test/'
            self.img_path = sorted(glob(self.root + 'rgb/*.jpg'))

        for i in tqdm.tqdm(range(len(self.img_path))):
            img = cv2.imread(self.img_path[i], cv2.IMREAD_COLOR)
            b, g, r = cv2.split(img)
            img = cv2.merge([r, g, b])
            self.x_data.append(img)

            num = self.img_path[i].split('.')[0].split('/')[1]
            img_pkl = self.root + 'meta/' + str(num) + '.pkl'
            pkl = pandas.read_pickle(img_pkl)
            coords_2d = pkl['coords_2d']
            self.y_data.append(coords_2d)

    def __len__(self):
        return len(self.img_path)

    def __getitem__(self, idx):
        transform1 = torchvision.transforms.ToTensor()
        new_x_data = transform1(self.x_data[idx])
```

```
return new_x_data, self.y_data[idx]
```

In [4]:

```
class Tester(object):
    def __init__(self, batch_size):
        self.batch_size = batch_size
        self._build_model()

        self.root = '/content/drive/MyDrive/2_pose_estimation/dataset/'

        # Load of pretrained_weight file
        weight_PATH = '/content/drive/MyDrive/2_pose_estimation/dataset/pretrained_weight
.pth'

        self.poseNet.load_state_dict(torch.load(weight_PATH))

        print("Testing...")

    def _build_model(self):
        # 2d pose estimator
        poseNet = CPM2DPose()
        self.poseNet = poseNet.to(device)

        print('Finish build model.')

    def heatmap2skeleton(self, heatmapsPoseNet):
        skeletons = np.zeros((heatmapsPoseNet.shape[0], heatmapsPoseNet.shape[1], 2))
        for m in range(heatmapsPoseNet.shape[0]):
            for i in range(heatmapsPoseNet.shape[1]):
                u, v = np.unravel_index(np.argmax(heatmapsPoseNet[m][i]), (32, 32))
                skeletons[m, i, 0] = u * 8
                skeletons[m, i, 1] = v * 8
        return skeletons

    @staticmethod
    def plot_hand(coords_hw, axis, color_fixed=None, linewidth='1'):
        colors = np.array([[0., 0., 1.],
                           [0., 0., 1.],
                           [0., 0., 1.],
                           [0., 0., 1.],
                           [1., 0., 1.],
                           [1., 0., 1.],
                           [1., 0., 1.],
                           [1., 0., 1.],
                           [1., 0., 1.],
                           [1., 0., 0.],
                           [1., 0., 0.],
                           [1., 0., 0.],
                           [1., 0., 0.],
                           [0., 1., 0.],
                           [0., 1., 0.],
                           [0., 1., 0.],
                           [0., 1., 0.],
                           [1., 0.5, 0.],
                           [1., 0.5, 0.],
                           [1., 0.5, 0.],
                           [1., 0.5, 0.]])
        bones = [((1, 0), colors[0, :]),
                  ((2, 1), colors[1, :]),
                  ((3, 2), colors[2, :]),
                  ((4, 3), colors[3, :]),
                  ((0, 5), colors[4, :]),
                  ((5, 6), colors[5, :]),
                  ((6, 7), colors[6, :]),
                  ((7, 8), colors[7, :]),
                  ((0, 9), colors[8, :]),
                  ((9, 10), colors[9, :]),
                  ((10, 11), colors[10, :]),
                  ((11, 12), colors[11, :]),
                  ((0, 13), colors[12, :]),
                  ((13, 14), colors[13, :]),
```

```

        ((14, 15), colors[14, :]),
        ((15, 16), colors[15, :]),
        ((0, 17), colors[16, :]),
        ((17, 18), colors[17, :]),
        ((18, 19), colors[18, :]),
        ((19, 20), colors[19, :]))
    for connection, color in bones:
        coord1 = coords_hw[connection[0], :]
        coord2 = coords_hw[connection[1], :]
        coords = np.stack([coord1, coord2])
        if color_fixed is None:
            axis.plot(coords[:, 1], coords[:, 0], color=color, linewidth=linewidth)
        else:
            axis.plot(coords[:, 1], coords[:, 0], color_fixed, linewidth=linewidth)

# test '106.png' image
def test106(self, epochs, batch_size, learning_rate, finetuned=False):
    print("Finetuned" if finetuned else "Not finetuned")

    # load weight file
    if finetuned:
        weight_PATH = "/content/drive/MyDrive/2_pose_estimation/dataset/train/finetuned_{epochs}_{batch_size}_{learning_rate}.pth".format(epochs=epochs, batch_size=batch_size, learning_rate=learning_rate)
    else:
        weight_PATH = '/content/drive/MyDrive/2_pose_estimation/dataset/train/pretrained_weight.pth'

    self.poseNet.load_state_dict(torch.load(weight_PATH))
    path = self.root + 'test/rgb/106.jpg'
    pkl_path = self.root + 'test/meta/106.pkl'
    print(path)
    print(pkl_path)

    img = cv2.imread(path, cv2.IMREAD_COLOR)
    b, g, r = cv2.split(img)
    img = cv2.merge([r, g, b])
    transform1 = torchvision.transforms.ToTensor()
    x_data = transform1(img)
    pkl = pandas.read_pickle(pkl_path)
    y_test = pkl['coords_2d']

    self.poseNet.eval()

    print("Testing 106.jpg heatmap")

    print(x_data.size())

    heatmapsPoseNet = self.poseNet(x_data.unsqueeze(0).cuda()).cpu().detach().numpy()
    heatmap = np.transpose(heatmapsPoseNet[0], (1, 2, 0))

    save_path = "/content/drive/MyDrive/2_pose_estimation/dataset/"
    plt.rcParams['figure.figsize'] = [12, 5]
    for i in range(num_joints):
        ax = plt.subplot(3, 7, i + 1)
        ax.imshow(heatmap[:, :, i])
    plt.savefig(save_path + "heatmap_{epochs}_{batch_size}_{learning_rate}.png".format(epochs=epochs, batch_size=batch_size, learning_rate=learning_rate))
    plt.show()

    print("Testing 106.jpg heatmap")

    ax = plt.subplot(1, 1, 1)
    ax.imshow(img)
    pred = self.heatmap2skeleton(heatmapsPoseNet)[0]
    self.plot_hand(pred, ax)
    error = self.calc_error(y_test, pred)
    print(f"Error is {error}")
    plt.savefig(save_path + "result_{epochs}_{batch_size}_{learning_rate}.png".format(epochs=epochs, batch_size=batch_size, learning_rate=learning_rate))

```

```

plt.show()

# test all images
def test(self, epochs, batch_size, learning_rate, finetuned=False):
    print("Finetuned" if finetuned else "Not finetuned")

    # load weight file
    if finetuned:
        weight_PATH = "/content/drive/MyDrive/2_pose_estimation/dataset/train/finetuned_{epochs}_{batch_size}_{learning_rate}.pth".format(epochs=epochs, batch_size=batch_size, learning_rate=learning_rate)

    else:
        weight_PATH = '/content/drive/MyDrive/2_pose_estimation/dataset/train/pretrained_weight.pth'

    self.poseNet.load_state_dict(torch.load(weight_PATH))

    totalError = 0
    for i in range(500):
        img_path = self.root + 'test/rgb/%d.jpg' % (i)
        pkl_path = self.root + 'test/meta/%d.pkl' % (i)
        print(img_path)

        img = cv2.imread(img_path, cv2.IMREAD_COLOR)
        b, g, r = cv2.split(img)
        img = cv2.merge([r, g, b])
        transform1 = torchvision.transforms.ToTensor()
        x_data = transform1(img)
        pkl = pandas.read_pickle(pkl_path)
        y_test = pkl['coords_2d']

        self.poseNet.eval()

        heatmapsPoseNet = self.poseNet(x_data.unsqueeze(0).cuda()).cpu().detach().numpy()

        heatmap = np.transpose(heatmapsPoseNet[0], (1, 2, 0))

        pred = self.heatmap2skeleton(heatmapsPoseNet)[0]
        error = self.calc_error(y_test, pred)
        print(f"Testing {i}-th image's error is {error}")
        totalError += error

    print(f"Total Error is {totalError/500}")

def calc_error(self, gt, pred):
    k = 21 # num of keypoints
    err = 0
    for i in range(k):
        err += math.sqrt(math.pow((gt[i][0] - pred[i][0]),2) + math.pow((gt[i][1] - pred[i][1]),2)) # calculate Loss

    err = err/k # Loss average of keypoints
    return err

```

In [5]:

```

class Trainer(object):
    def __init__(self, epochs, batch_size, lr):
        self.epochs = epochs
        self.batch_size = batch_size
        self.learning_rate = lr
        self._build_model()

        self.cost = nn.MSELoss()
        self.optimizer = optim.Adam(self.poseNet.parameters(), lr=self.learning_rate)

        dataset = Dataset(method='train')
        self.root = dataset.root
        self.dataloader = DataLoader(dataset, batch_size=self.batch_size, shuffle=True)

```

```

# Load of pretrained_weight file
weight_PATH = '/content/drive/MyDrive/2_pose_estimation/dataset/pretrained_weight
.pth'

self.poseNet.load_state_dict(torch.load(weight_PATH))

def _build_model(self):
    # 2d pose estimator
    poseNet = CPM2DPose()
    self.poseNet = poseNet.to(device)
    self.poseNet.train()

def skeleton2heatmap(self, _heatmap, keypoint_targets):
    heatmap_gt = torch.zeros_like(_heatmap, device=_heatmap.device)

    keypoint_targets = (((keypoint_targets)) // 8)
    for i in range(keypoint_targets.shape[0]):
        for j in range(21):
            x = int(keypoint_targets[i, j, 0])
            y = int(keypoint_targets[i, j, 1])
            heatmap_gt[i, j, x, y] = 1

    heatmap_gt = heatmap_gt.detach().cpu().numpy()
    for i in range(keypoint_targets.shape[0]):
        for j in range(21):
            heatmap_gt[i, j, :, :] = cv2.GaussianBlur(heatmap_gt[i, j, :, :], ksize=
(3, 3), sigmaX=2,
                                                    sigmaY=2) * 9 / 1.1772
    heatmap_gt = torch.FloatTensor(heatmap_gt).to(device)
    return heatmap_gt

def heatmap2skeleton(self, heatmapsPoseNet):
    skeletons = np.zeros((heatmapsPoseNet.shape[0], heatmapsPoseNet.shape[1], 2))
    for m in range(heatmapsPoseNet.shape[0]):
        for i in range(heatmapsPoseNet.shape[1]):
            u, v = np.unravel_index(np.argmax(heatmapsPoseNet[m][i]), (32, 32))
            skeletons[m, i, 0] = u * 8
            skeletons[m, i, 1] = v * 8
    return skeletons

# Prob 2
def train(self):
    date = '202211'
    for epoch in tqdm.tqdm(range(self.epochs + 1)):
        totalLoss = 0
        if epoch % 2 == 0:
            torch.save(self.poseNet.state_dict(), self.root + "_".join(['model_', str(
epoch), '.pth']))

            for batch_idx, samples in enumerate(self.dataloader):
                ##-----
                # Implement your code here
                x_train, y_train = samples

                self.poseNet.eval()

                heatmapsPoseNet = self.poseNet(x_train.cuda()) # pred value
                loss = self.cost(heatmapsPoseNet, self.skeleton2heatmap(heatmapsPoseNet,
y_train)) # calculate loss

                # leaning
                self.optimizer.zero_grad()
                loss.backward()
                self.optimizer.step()
                totalLoss += loss.item()

                print(f"Epoch {epoch}/{self.epochs}, Batch {batch_idx} loss is {loss.ite
m()) \n")

                ##-----

                ## Write train result
                if batch_idx % 20 == 0: # 21개의 keypoint

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        with open('train_result_' + date + '.txt', 'a') as f:
            f.write('Epoch {:4d}/{:} Batch {:}/{:}\n'.format(
                epoch, self.epochs, batch_idx, len(self.dataloader)
            ))
        print('Epoch {:4d}/{:} Batch {:}/{:}'.format(
            epoch, self.epochs, batch_idx, len(self.dataloader)
        ))

    print('Loss is {}'.format(
        totalLoss/len(self.dataloader)
    ))

    # save trained weight
    train_path = self.root + "finetuned_{:}_{:}.pth".format(self.epochs, self.batch
_size, self.learning_rate)
    torch.save(self.poseNet.state_dict(), train_path)
    print('Finish training.')

```

In [6]:

```

epochs = 60
batchSize = 20
learningRate = 2e-5

# Prob 2
# trainer = Trainer(epochs, batchSize, learningRate)
# trainer.train()

# Prob 3
tester = Tester(batchSize)
# Prob 3 - 1)
print("Prob 3 - 1)")
tester.test106(epochs, batchSize, learningRate, True)
# Prob 3 - 2)
print("Prob 3 - 2)")
tester.test(epochs, batchSize, learningRate, True)

```

Finish build model.

Testing...

Prob 3 - 1)

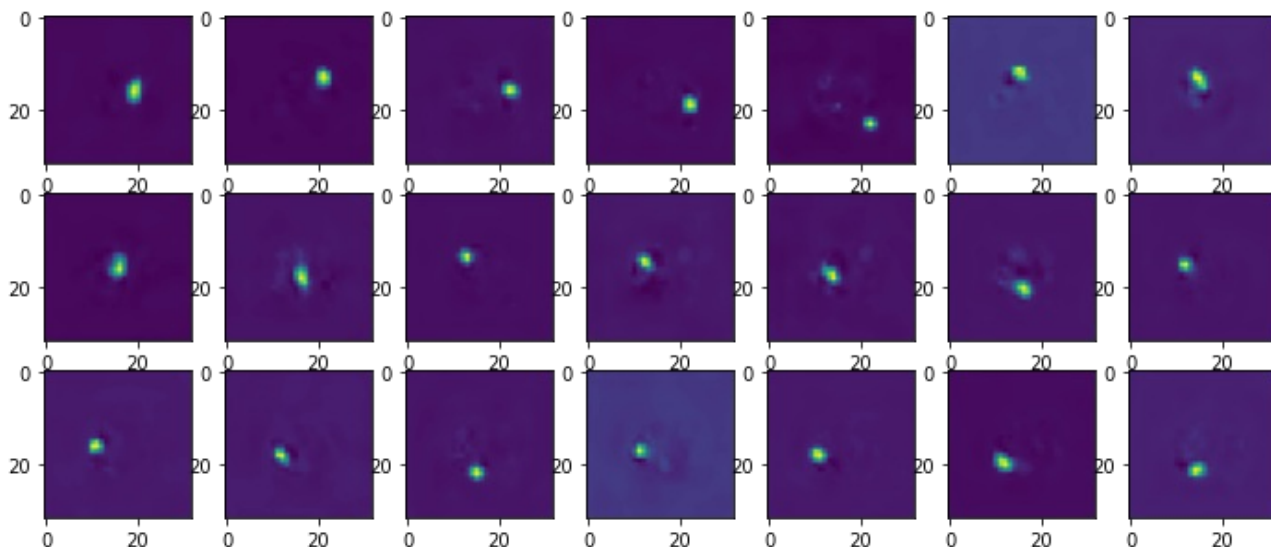
Finetuned

/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/106.jpg

/content/drive/MyDrive/2_pose_estimation/dataset/test/meta/106.pkl

Testing 106.jpg heatmap

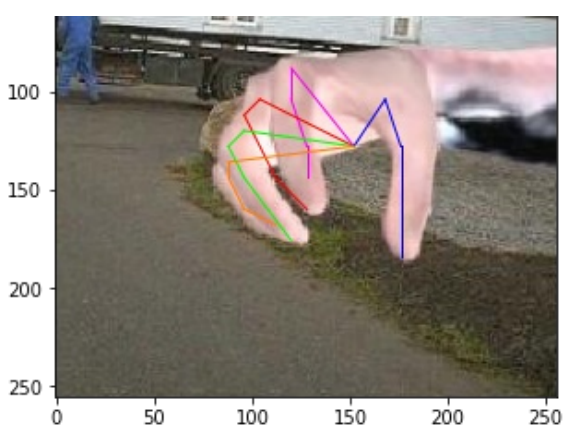
torch.Size([3, 256, 256])



Testing 106.jpg heatmap

Error is 10.020755988449496





Prob 3 - 2)

Finetuned

```
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/0.jpg
Testing 0-th image's error is 14.57666802079228
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/1.jpg
Testing 1-th image's error is 8.283794718840314
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/2.jpg
Testing 2-th image's error is 8.285075986790012
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/3.jpg
Testing 3-th image's error is 49.65380247414166
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/4.jpg
Testing 4-th image's error is 17.10651721834851
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/5.jpg
Testing 5-th image's error is 9.760886415444515
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/6.jpg
Testing 6-th image's error is 7.501209210835403
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/7.jpg
Testing 7-th image's error is 10.998848529868871
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/8.jpg
Testing 8-th image's error is 8.04320909314365
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/9.jpg
Testing 9-th image's error is 10.6900731421096
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/10.jpg
Testing 10-th image's error is 7.531418018562716
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/11.jpg
Testing 11-th image's error is 8.334675600535556
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/12.jpg
Testing 12-th image's error is 26.942034302590173
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/13.jpg
Testing 13-th image's error is 7.6563221312905485
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/14.jpg
Testing 14-th image's error is 17.35705305551173
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/15.jpg
Testing 15-th image's error is 8.031274481823102
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/16.jpg
Testing 16-th image's error is 11.300824662584645
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/17.jpg
Testing 17-th image's error is 12.228571381934406
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/18.jpg
Testing 18-th image's error is 7.2362757616475974
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/19.jpg
Testing 19-th image's error is 9.60486919856485
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/20.jpg
Testing 20-th image's error is 8.29806843574787
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/21.jpg
Testing 21-th image's error is 10.343819257470445
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/22.jpg
Testing 22-th image's error is 12.110655434077993
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/23.jpg
Testing 23-th image's error is 13.54932344288587
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/24.jpg
Testing 24-th image's error is 20.219486768958014
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/25.jpg
Testing 25-th image's error is 53.883002394544334
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/26.jpg
Testing 26-th image's error is 10.421479733050765
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/27.jpg
Testing 27-th image's error is 10.12601062002205
```

Testing 27-th image's error is 19.13691062982385
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/28.jpg
Testing 28-th image's error is 35.35877547896036
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/29.jpg
Testing 29-th image's error is 18.806104334829385
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/30.jpg
Testing 30-th image's error is 20.072609829878818
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/31.jpg
Testing 31-th image's error is 9.089820426568378
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/32.jpg
Testing 32-th image's error is 18.031724042137828
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/33.jpg
Testing 33-th image's error is 27.999954470999114
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/34.jpg
Testing 34-th image's error is 11.278999149371307
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/35.jpg
Testing 35-th image's error is 8.113234824269643
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/36.jpg
Testing 36-th image's error is 11.86437329827891
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/37.jpg
Testing 37-th image's error is 7.876346327883394
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/38.jpg
Testing 38-th image's error is 16.626519906748303
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/39.jpg
Testing 39-th image's error is 36.55663756420968
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/40.jpg
Testing 40-th image's error is 11.390052312727855
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/41.jpg
Testing 41-th image's error is 44.443163999223295
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/42.jpg
Testing 42-th image's error is 39.55086214586098
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/43.jpg
Testing 43-th image's error is 11.836093416684562
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/44.jpg
Testing 44-th image's error is 30.591048389141108
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/45.jpg
Testing 45-th image's error is 18.465238766587845
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/46.jpg
Testing 46-th image's error is 9.25878330353694
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/47.jpg
Testing 47-th image's error is 32.23312072824347
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/48.jpg
Testing 48-th image's error is 28.359925833716645
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/49.jpg
Testing 49-th image's error is 32.590436054281426
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/50.jpg
Testing 50-th image's error is 24.078696813757418
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/51.jpg
Testing 51-th image's error is 26.800059718871413
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/52.jpg
Testing 52-th image's error is 18.212659178763747
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/53.jpg
Testing 53-th image's error is 21.06444592965359
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/54.jpg
Testing 54-th image's error is 25.99524699868535
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/55.jpg
Testing 55-th image's error is 10.157922449709606
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/56.jpg
Testing 56-th image's error is 20.189800368644285
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/57.jpg
Testing 57-th image's error is 13.97759143111298
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/58.jpg
Testing 58-th image's error is 14.779452974712033
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/59.jpg
Testing 59-th image's error is 20.557782572584753
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/60.jpg
Testing 60-th image's error is 16.997747426676895
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/61.jpg
Testing 61-th image's error is 15.486848668311412
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/62.jpg
Testing 62-th image's error is 12.967378644468951
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/63.jpg
Testing 63-th image's error is 12.180777457621114

Testing 63-th image's error is 12.109777457021114
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/64.jpg
Testing 64-th image's error is 10.923566609237165
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/65.jpg
Testing 65-th image's error is 9.039944905644195
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/66.jpg
Testing 66-th image's error is 27.39323077920885
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/67.jpg
Testing 67-th image's error is 16.29342949906841
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/68.jpg
Testing 68-th image's error is 28.157188745392506
/content/drive/MyDrive/2_pose_estimation/dataset/test/rgb/69.jpg
Testing 69-th image's error is 16.23416665663752
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