



Image-Based Situation Awareness Audit 28.2.2018

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Previous Audit 11.1.2018

Previous Audit

Open questions:

- Role of classical object tracking algorithms?
- What to do with multiple bounding boxes around one object?
- Appropriate minimum confidence level?
- What to do with false detections inside other objects?
- What to do with false detections from the background?
- How to set Kalman filter parameters for image object filtering?
- Hungarian algorithms special case for hidden objects

To do:

- Close open questions
- Image object status
- Image object velocity estimation
- Probabilistic approach for matching detected and image objects
- 2d -> 3d transformation
- World object state estimation

Other:

- Semantic segmentation
- Organisations to follow: ICCV, ICRA, NIPS, IROS, arXiv
- Camera motion (yaw, pitch)
- Grid or continuous presentation?
- Class specific attributes
- Object history

The slide features a white central area with the title 'Project Plan'. The background is composed of four geometric shapes: a dark gray triangle in the top-left, a light gray triangle in the top-right, a light gray triangle in the bottom-left, and a yellow triangle in the bottom-right. All triangles have a diagonal edge that meets at the center of the slide.

Project Plan

Project Plan

	2018				2019				2020				2021			
Methodology																
Preparation of research infra																
Method survey																
Building test cases																
Testing and comparison																
Prototype																
Definition																
Planning																
Implementation																
Testing and fixing																
Method follow-up																
Writing thesis																
Dissertation																

1. Methodology / Preparation of research infra
 - a. Software platforms are constructed and tested
 - b. Off-the-shelf models are acquired and tested
 - c. Necessary skills on platforms are learned
2. Methodology / Method survey
 - a. Current state-of-art methods are studied
 - b. Methods are constructed and tested on the software platforms
3. Method follow-up
 - a. Screening of conference papers related to the subject
 - b. Possibly integrating new methods to the project



Work Done

Method Follow-Up

Computer Vision and Pattern Recognition

Authors and titles for recent submissions

- Fri, 19 Jan 2018
- Thu, 18 Jan 2018
- Wed, 17 Jan 2018
- Tue, 16 Jan 2018
- Mon, 15 Jan 2018

[Total of 54 entries: 1-25 (25/55) 151-75 76-94]
[showing 25 entries per page: fewer | more | all]

Fri, 19 Jan 2018

[1] [arXiv:1801.06104 \[pdf, other\]](#)
Invariants of multidimensional time series based on their iterated-integral signature
Joscha Diehl, Jeremy Reizenstein
Subjects: Computer Vision and Pattern Recognition (cs.CV); Representation Theory (math.RT)

[2] [arXiv:1801.06066 \[pdf, other\]](#)
RED-Net: A Recurrent Encoder-Decoder Network for Video-based Face Alignment
Xi Peng, Rogério S. Feris, Xaboyi Wang, Dimitris N. Metaxas
Comments: International Journal of Computer Vision, arXiv admin note: text overlap with arXiv:1608.05477
Subjects: Computer Vision and Pattern Recognition (cs.CV)

[3] [arXiv:1801.05968 \[pdf, other\]](#)
3D CNN-based classification using sMRI and MD-DTI images for Alzheimer disease studies
Alexander Khvachkov, Karim Adenigral, Jenny Benois-Pineau, Andrey Krivos, Genevieve Catheline
Subjects: Computer Vision and Pattern Recognition (cs.CV)

[4] [arXiv:1801.05944 \[pdf, other\]](#)
PTB-TIR: A Thermal Infrared Pedestrian Tracking Benchmark
Qiao Liu, Zhenyu He
Comments: 10 pages
Subjects: Computer Vision and Pattern Recognition (cs.CV)

[5] [arXiv:1801.05918 \[pdf\]](#)
Extend the shallow part of Single Shot MultiBox Detector via Convolutional Neural Network
Liuwen Zheng, Canmiao Fu, Yong Zhao
Comments: 7 pages, 3 figures, 3 tables
Subjects: Computer Vision and Pattern Recognition (cs.CV)

[6] [arXiv:1801.05912 \[pdf, other\]](#)
On the influence of Dice loss function in multi-class organ segmentation of abdominal CT using 3D fully convolutional networks
Chen Shen, Holger R. Roth, Hirohisa Oda, Masahiro Oda, Yuichiro Hayashi, Kazunari Misawa, Kensaku Mori
Comments: presented at ML4W- November 2017, Takamatsu, Japan (this hep URL)
Subjects: Computer Vision and Pattern Recognition (cs.CV)

[7] [arXiv:1801.05895 \[pdf, other\]](#)
Sparsely Connected Convolutional Networks
Ligeng Zhu, Ruizhi Deng, Zhenwei Deng, Greg Mori, Ping Tan
Subjects: Computer Vision and Pattern Recognition (cs.CV)

Thu, 18 Jan 2018

[8] [arXiv:1801.05787 \[pdf, other\]](#)
Faster gaze prediction with dense networks and Fisher pruning
Lucas Theis, Iryna Korshunova, Aliyhan Tegan, Ferenc Huszar

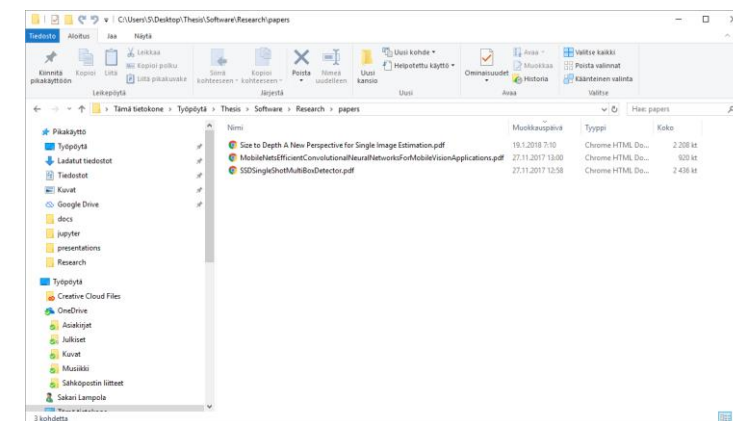


Image Object Velocity Estimation

Image object velocity is necessary for:

- predicting image object locations when matching new measurements
- identifying image objects
- predicting image object locations for hidden objects

Image object

- id
- status
- x_min
- x_max
- y_min
- y_max
- vx_min
- vx_max
- vy_min
- vy_max
- class
- confidence
- appearance

Estimation algorithm

Image Object Kalman Filtering

Bounding box corner location

State vector s :

$$s = \begin{bmatrix} l \\ v \end{bmatrix}$$

where

l = location coordinate (x_{min} , x_{max} , y_{min} , y_{max}) of the bounding box corner in the image

v = velocity (vx_{min} , vx_{max} , vy_{min} , vy_{max}) of the bounding box corner in the image

State equation in differential form:

$$\frac{ds(t)}{dt} = \begin{bmatrix} 0 & 1 \\ 0 & 0 \end{bmatrix} * s(t) + \epsilon(t) = A_1 * s$$

State equation in difference form:

$$s(k+1) = (I + \Delta * A_1) * s(k) + \epsilon(k)$$

$$= \begin{bmatrix} 1 & \Delta \\ 0 & 1 \end{bmatrix} * s(k) + \epsilon(k) = A * s(k) + \epsilon(k)$$

where Δ is the time increment and ϵ Gaussian noise with covariance R .

Measurement equation

$$z(k) = \begin{bmatrix} 1 & 0 \end{bmatrix} * s(k) + \delta(k) = C * s(k) + \delta(k)$$

Where δ is Gaussian noise with covariance matrix Q .

Kalman filter initialization:

$$\mu(0) = \begin{bmatrix} l(0) \\ 0 \end{bmatrix}$$

where $l(0)$ is the first location measurement.

$$\Sigma(0) = \begin{bmatrix} 10.0 & 0 \\ 0 & 10000.0 \end{bmatrix}$$

where 10.0 and 10000.0 are believed initial error variances of location and velocity.

$$R = \begin{bmatrix} 1.0 & 0 \\ 0 & 1.0 \end{bmatrix}$$

where diagonal elements are believed state equation variances of location and velocity.

$$Q = [10.0]$$

Where 10.0 is the believed measurement variance.

Kalman filter update:

$$\mu_1(k) = A * \mu(k-1)$$

$$\Sigma_1(k) = A * \Sigma(k-1) * A^T + R$$

$$K(k) = \Sigma_1(k) * C^T * (C * \Sigma_1(k) * C^T + Q)^{-1}$$

$$\mu(k) = \mu_1(k) + K(k) * (z(k) - C * \mu_1(k))$$

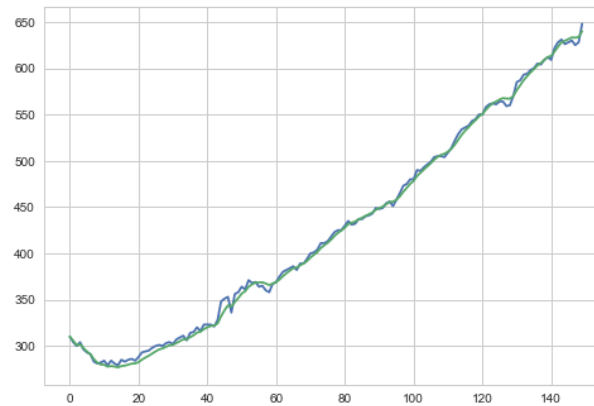
$$\Sigma(k) = (I - K(k) * C) * \Sigma_1(k)$$

Asiakirjan loppu ■

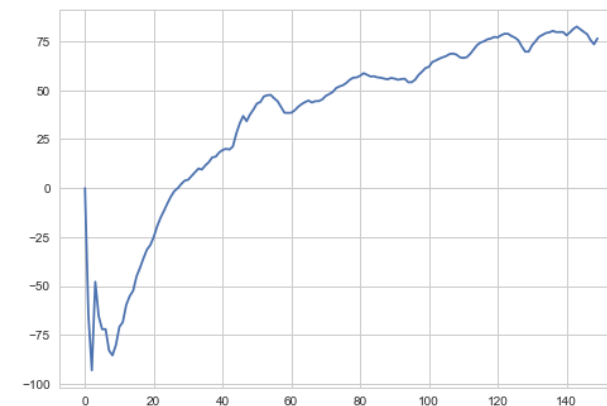
Numerical values are estimated using grid search and 10 step ahead mean prediction error. Values rounded. Later adjusted by experiments.

Image Object Velocity Estimation

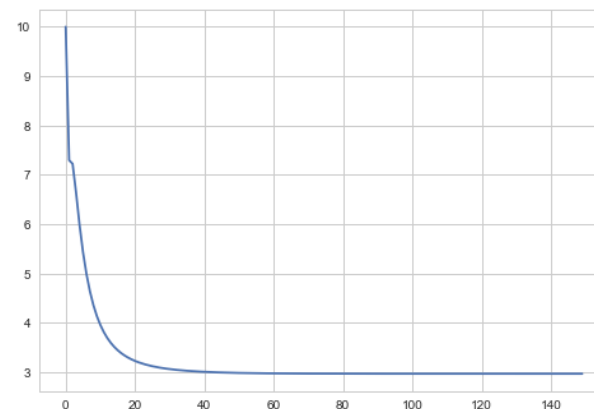
Moving object (car)



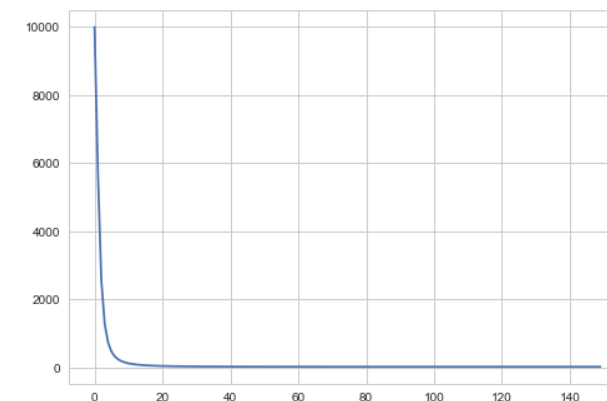
Measured and filtered location (upper left corner)



Estimated velocity



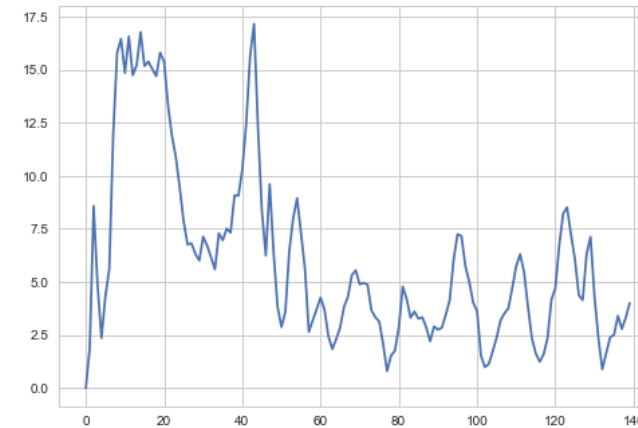
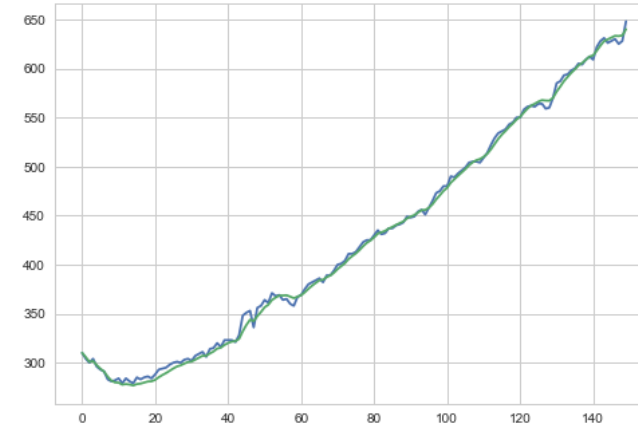
Location variance



Velocity variance

Image Object Velocity Estimation

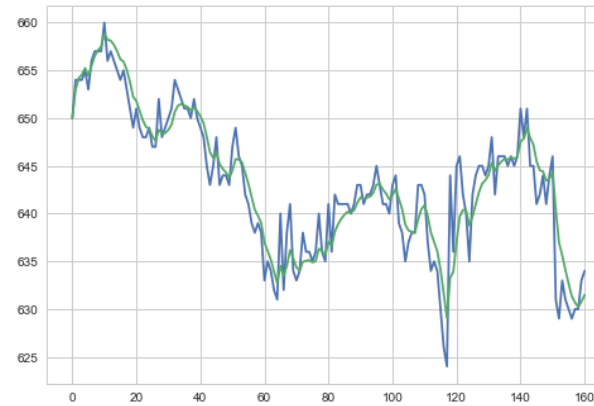
Moving object (car)



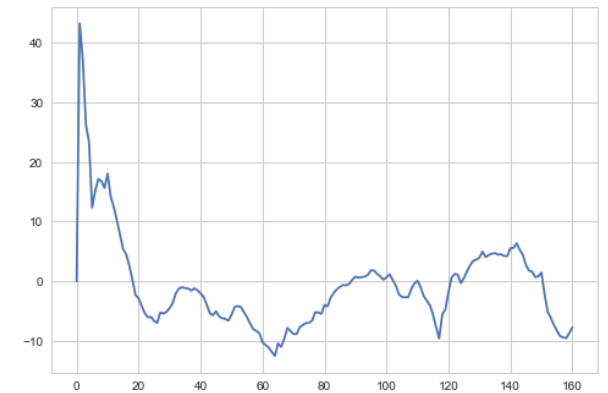
10 step ahead mean prediction error

Image Object Velocity Estimation

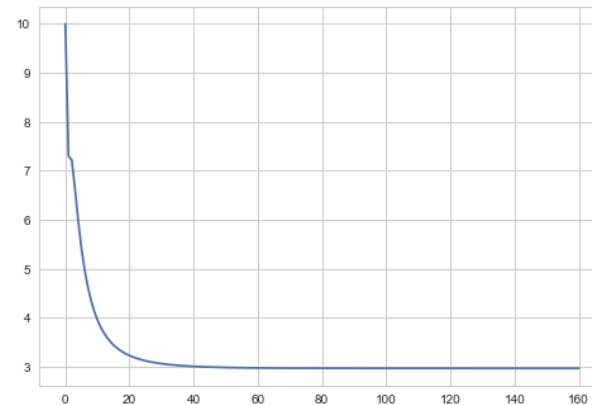
Static object (calf)



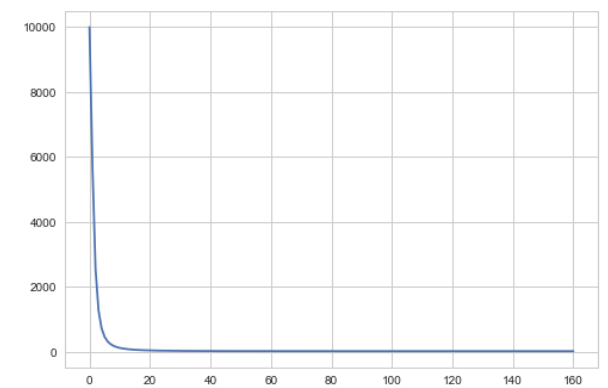
Measured and filtered location (upper left corner)



Estimated velocity



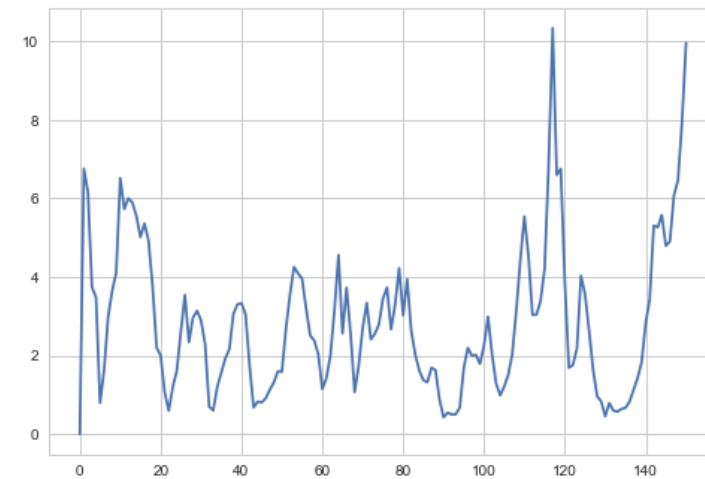
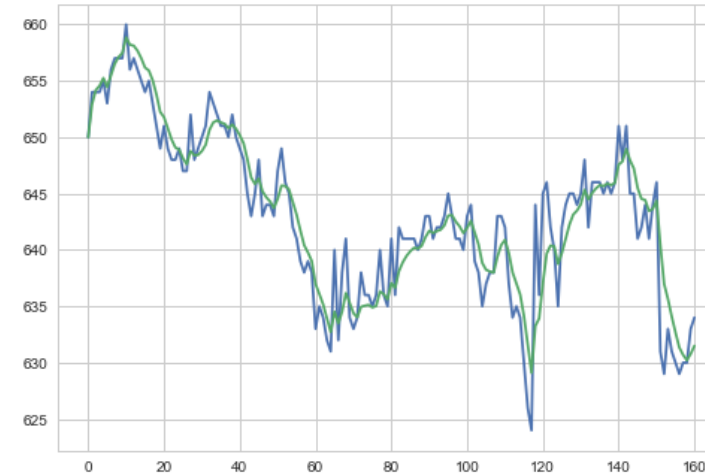
Location variance



Velocity variance

Image Object Velocity Estimation

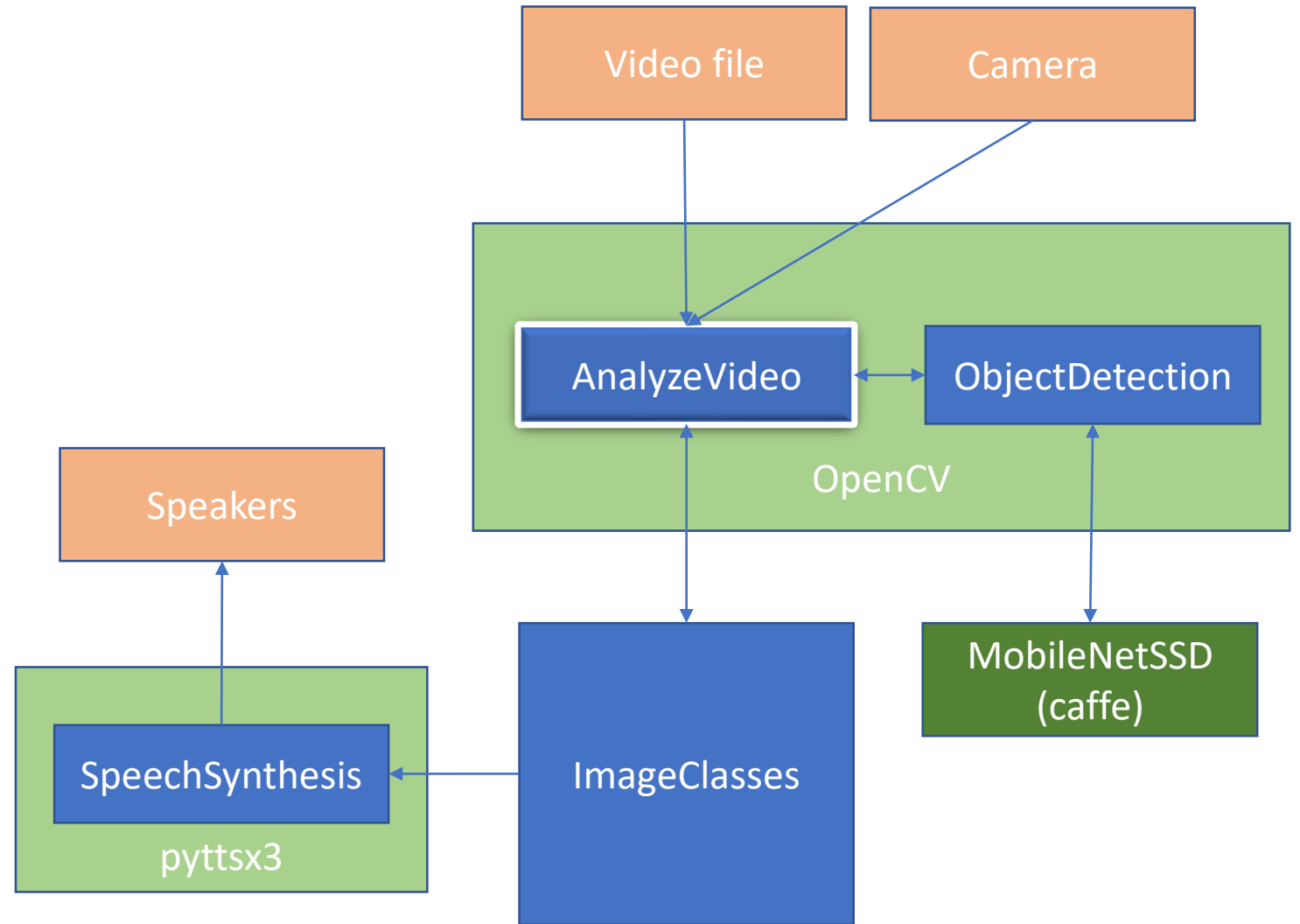
Static object (calf)



10 step ahead mean prediction error

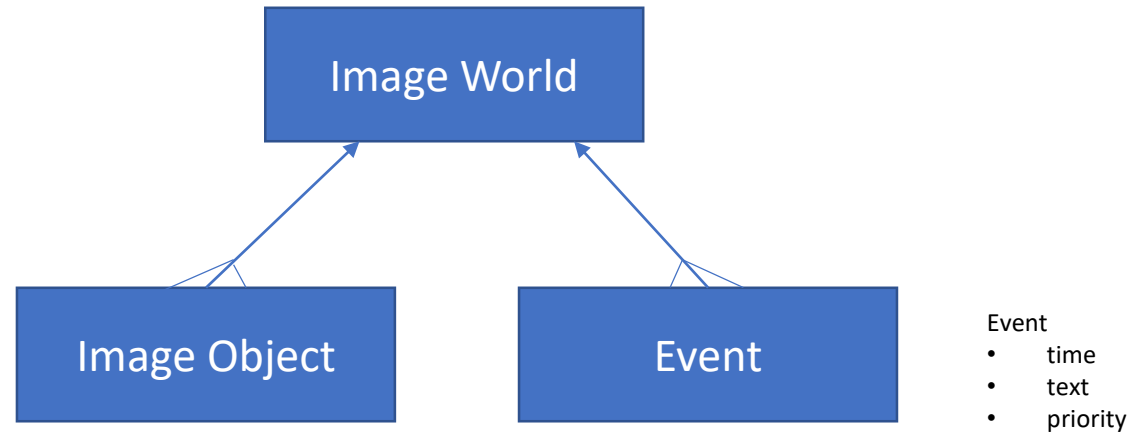
Speech Synthesis

Software Architecture



Speech Synthesis

Entities



- Event is generated when
 - new image object is created
 - image object status is changed
- Event will pause the video for the duration of speech (not in the final version)
- Events are collected (history)

Confidence Level

SSD Mobilenet implementation:

extract the confidence (i.e., probability) associated with the prediction

	A	B	C	D	E	F	G	H	I	J
1	Objects detected		Confidence level							
2	Video	Correct	0,00	0,20	0,40	0,60	0,80	0,90	0,95	1,00
3	CarsOnHighway001.mpg	39	49	49	39	36	34	32	32	0
4	Calf-2679.mp4	1	2	2	2	2	1	1	1	0
5	Dunes-7238.mp4	1	7	7	6	5	2	2	2	0
6	Sofa-11294.mp4	1	2	2	1	1	1	1	1	0
7	Cars133.mp4	5	9	9	6	5	5	5	5	0
8	BlueTit2975.mp4	1	3	3	2	1	1	1	1	0
9	Railway-4106.mp4	1	10	10	5	3	3	1	1	0
10	Hiker1010.mp4	1	4	4	0	0	0	0	0	0
11	Cat-3740.mp4	1	3	3	2	2	1	1	1	0
12	SailingBoat6415.mp4	1	1	1	1	1	1	1	1	0
13	AWomanStandsOnTheSeashore-10058.mp4	1	1	1	1	1	1	1	1	0
14	Dog-4028.mp4	1	4	4	2	1	1	1	1	0
15	Boat-10876.mp4	1	2	2	1	1	1	1	0	0
16	Horse-2980.mp4	1	3	3	3	2	2	1	1	0
17	Sheep-12727.mp4	1	1	1	1	1	1	1	1	1

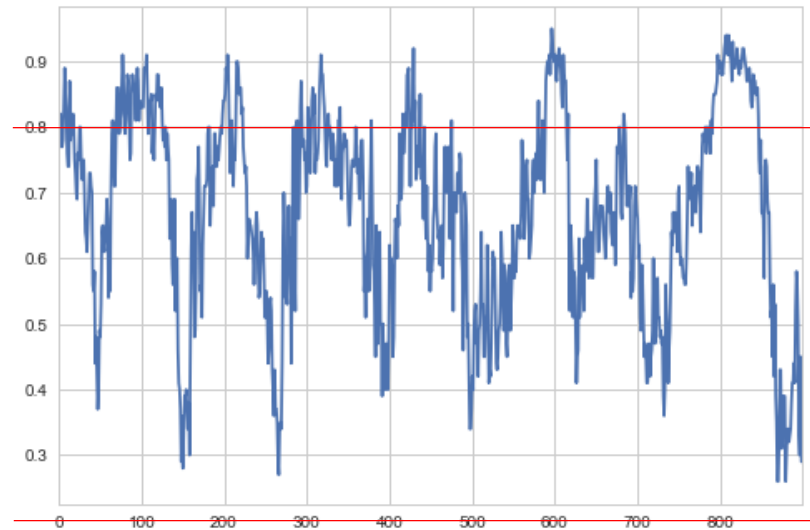
Good value for creating a new image object is between 0.8 and 0.9.

The 'good' value also depends on other hyperparameters.

Confidence Level



Confidence level has dynamics



create

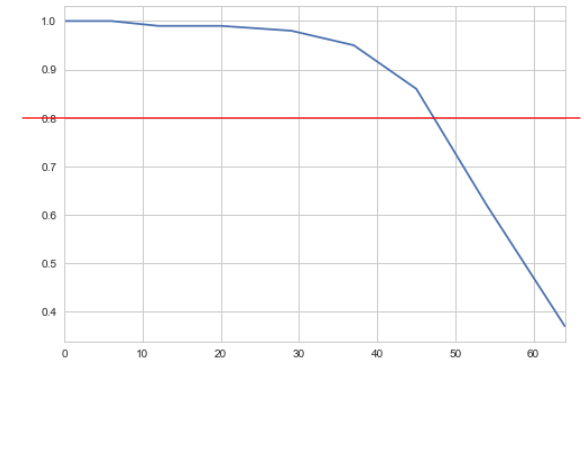
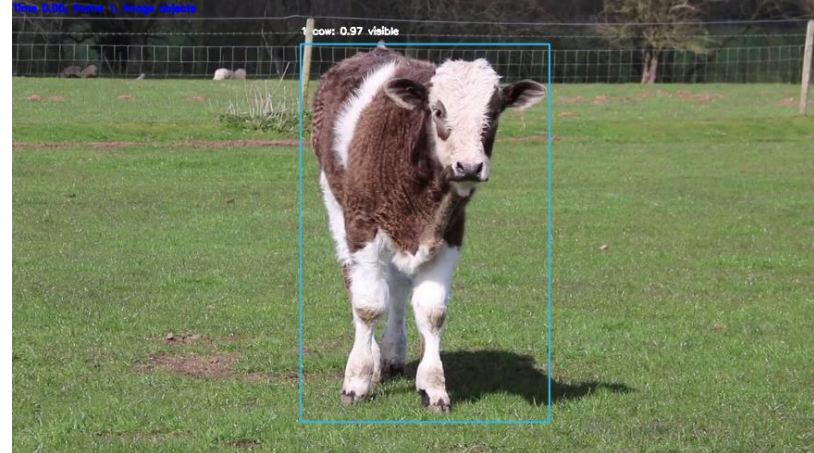
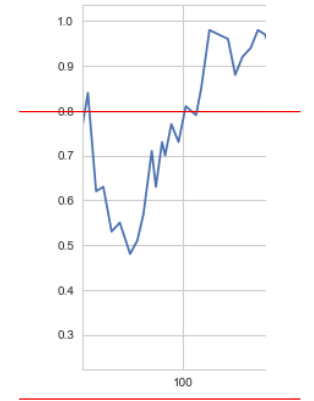
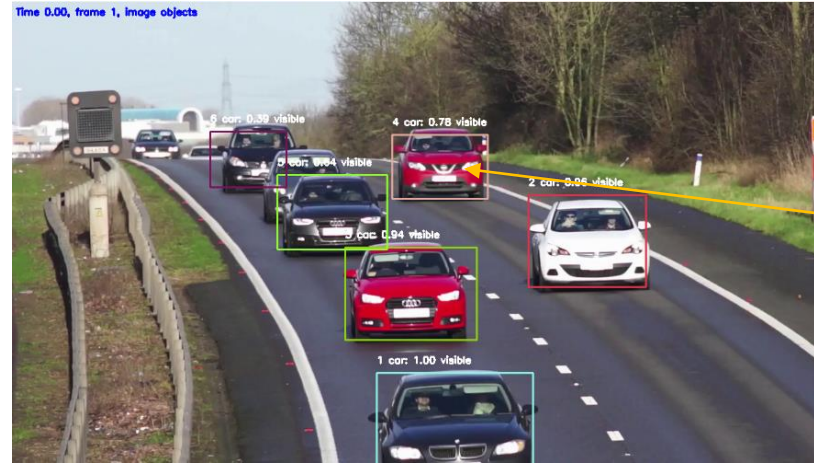
Update (not class)

ignore

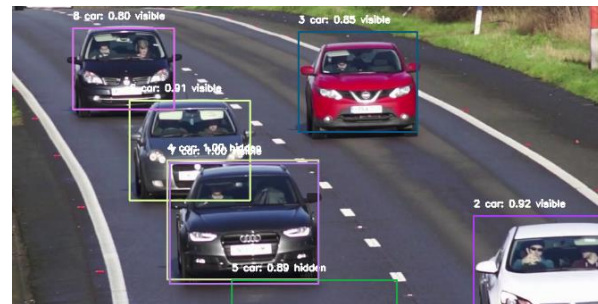
Different levels for creating and updating image object. Hyperparameters:

- CONFIDENCE_LEVEL_CREATE (0.8)
- CONFIDENCE_LEVEL_UPDATE (0.2)

Confidence Level



Border Behaviour



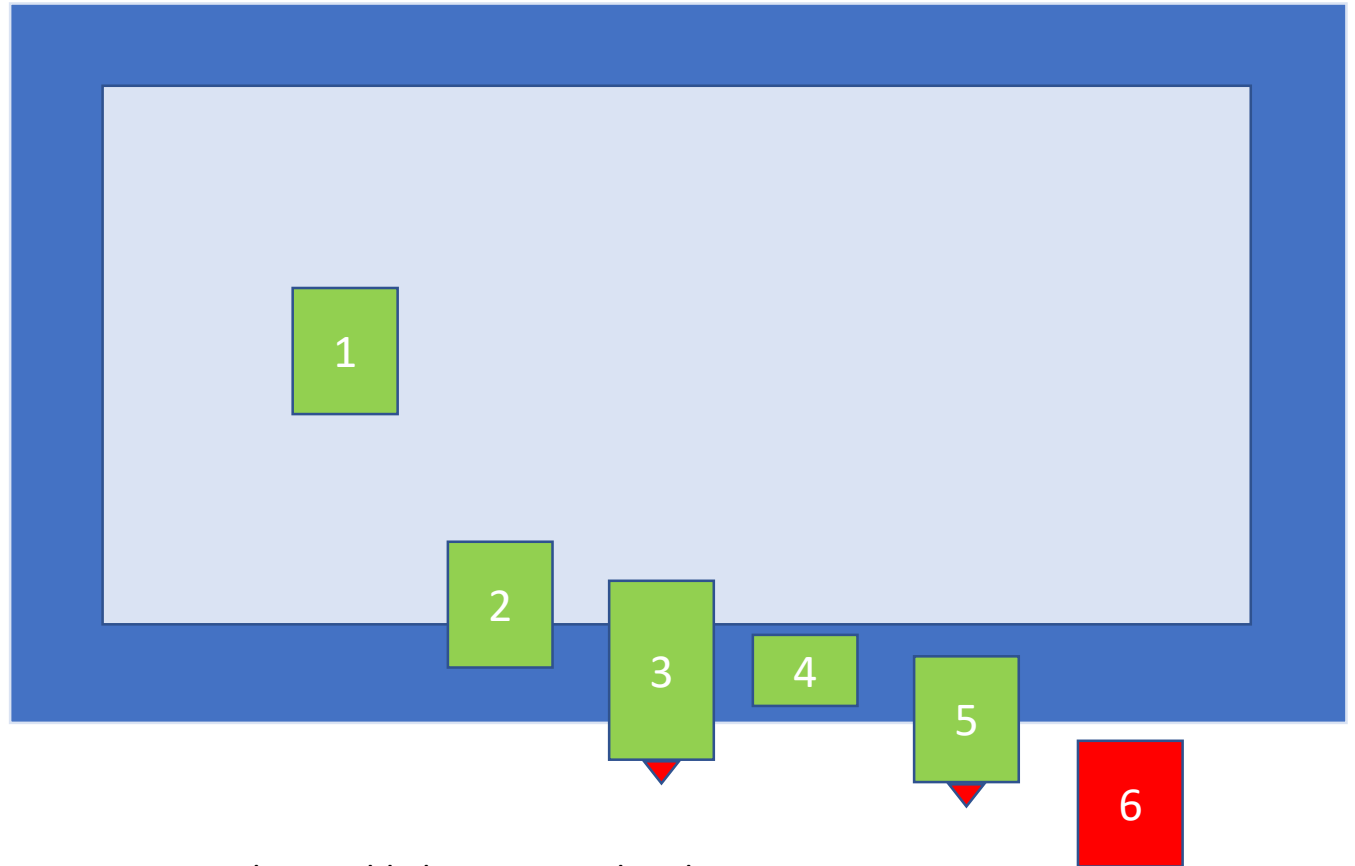
Box size and form distorted

	x_max_c	x_max_m	x_max_p	y_max_c	y_max_m	y_max_p
time						
1.48	1208.859	1209.0	1205.616	646.300	652.0	640.731
1.52	1221.500	1236.0	1212.044	653.697	656.0	649.501
1.56	1232.488	1242.0	1224.941	660.427	661.0	656.939
1.60	1241.599	1246.0	1236.095	668.758	673.0	663.679
1.64	1251.081	1256.0	1245.282	677.391	682.0	672.083
1.68	1258.430	1258.0	1254.848	687.143	694.0	680.794
1.72	1265.965	1266.0	1262.190	694.428	695.0	690.663
1.76	1272.740	1271.0	1269.725	704.340	711.0	697.956
1.80	1280.741	1282.0	1276.471	711.433	711.0	707.979
1.84	1287.573	1286.0	1284.493	717.291	714.0	715.066
1.88	1292.323	1286.0	1291.299	722.517	718.0	720.869
1.92	1292.517	1276.0	1295.946	728.172	725.0	726.022
1.96	1291.385	1273.0	1295.873	731.168	722.0	731.626
2.00	1291.974	1279.0	1294.445	732.465	720.0	734.474
2.04	1291.500	1277.0	1294.826	732.500	718.0	735.572
2.08	1290.547	1276.0	1294.121	733.994	724.0	735.375
2.12	1289.259	1275.0	1292.938	736.016	728.0	736.711
2.16	1289.533	1280.0	1291.424	736.959	727.0	738.606
2.20	1290.113	1282.0	1291.548	737.402	727.0	739.392
2.24	1290.640	1283.0	1292.000	735.994	722.0	739.671

Hyperparameter BORDER_WIDTH (30)

In [10]: # image size 1280 * 720

Border Behaviour

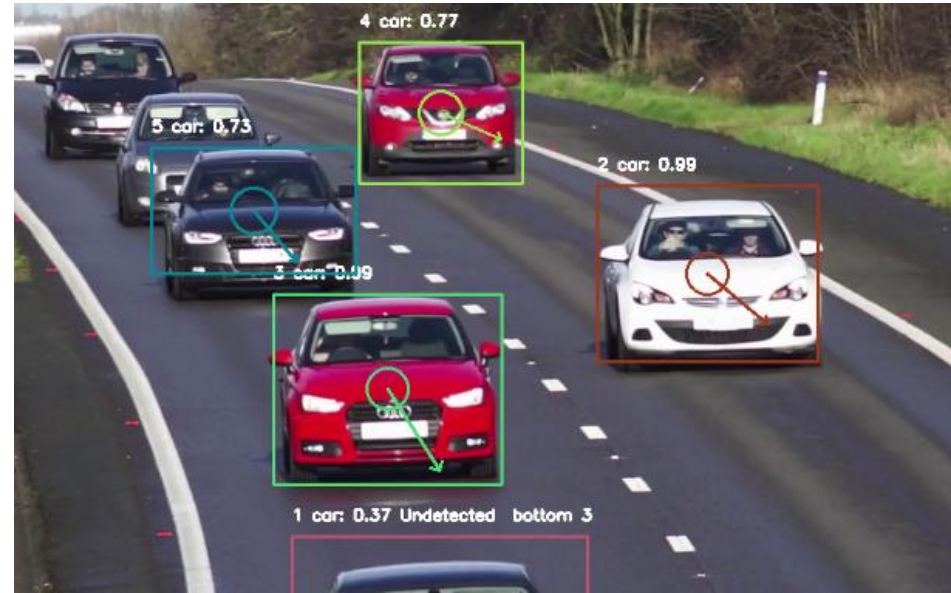


- Type 3 and 5: world object not updated
- Type 6: removed, world object acceleration fixed
- If an object touches 3 borders, it is removed

Done for:

- left
- right
- top
- bottom

Visual Presentation



- Ellipse axes proportional to the standard deviation of the location ($2 \times \text{std}$, corresponding to 95% probability)
- Arrow direction and length proportional to velocity (measured in pixels/second)

Object Retention

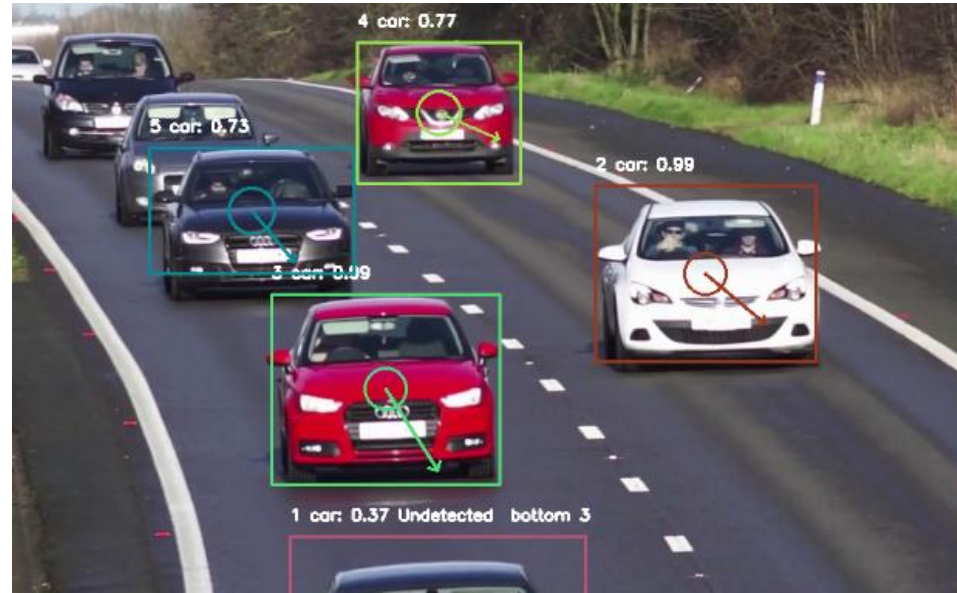
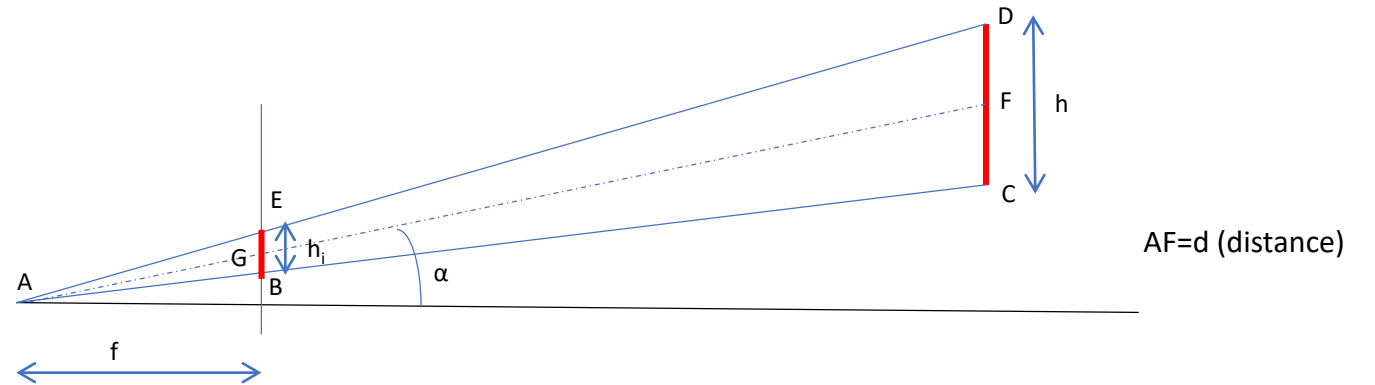


Image objects are removed if not detected in RETENTION_COUNT_MAX (30) successive frames.

Distance Estimation



Similar triangles AGE and AFD:

$$\frac{0.5 * h_i}{0.5 * h} = \frac{AG}{d} = \frac{\frac{f}{\cos(\alpha)}}{d} = \frac{f}{d * \cos(\alpha)}$$

$$d = \frac{f * h}{\cos(\alpha) * h_i}$$

Similar equations for horizontal direction
(β =azimuth)

Distance Estimation

$$d = \frac{f * h}{\cos(\alpha) * \cos(\beta) * h_i} = \frac{f * h}{\cos(\alpha) * \cos(\beta) * h_i * s_h / p_h}$$

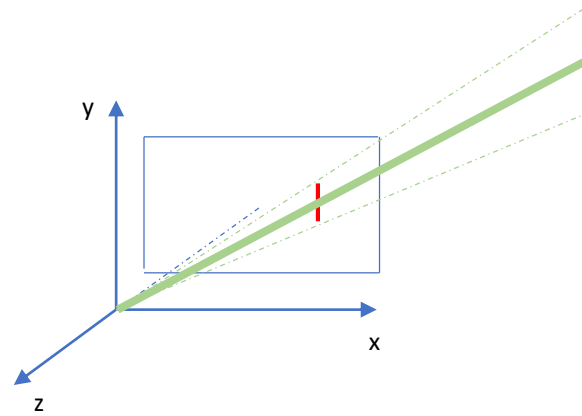
s_w = sensor width (m)
 s_h = sensor height (m)
 p_w = image width (pixels)
 p_h = image height (pixels)
 h_i = object height (pixels)
 h = object height (m)
 f = focal length (m)
 α = altitude (rad)
 β = azimuth (rad)

Example (Nikon D800E):

s_w = sensor width (m) = 0.0359 m
 s_h = sensor height (m) = 0.0240 m
 p_w = image width (pixels) = 7360
 p_h = image height (pixels) = 4912
 h_i = object height (pixels) = 100
 h = object height (m) = 1.0 m
 f = focal length (m) = 0.050 m
 α = altitude (rad) = 0.0
 β = azimuth (rad) = 0.0

$$d = \frac{0.050m * 1m}{1.0 * 1.0 * 100 * 0.024m / 4912} = 102.33 m$$

2d -> 3d Transformation



From pixel coordinates (sensor plane) to 3d camera coordinates:

$$(x_c, y_c, z_c) = \left(-\frac{s_w}{2} + xp * \frac{s_w}{p_w}, \frac{s_h}{2} - yp * \frac{s_h}{p_h}, -f \right)$$

Object center will be on the line:

$$(x_o, y_o, z_o) = t * (x_c, y_c, z_c)$$

The length of the line is:

$$d = \frac{f * h}{\cos(\alpha) * \cos(\beta) * h_i * s_h / p_h}$$

$$\alpha = \arctan(y_c / f)$$

$$\beta = \arctan(x_c / f)$$

s_w = sensor width (m)
 s_h = sensor height (m)
 p_w = image width (pixels)
 p_h = image height (pixels)
 h_i = object height (pixels)
 h = object height (m)
 f = focal length (m)
 α = altitude (rad)

2d -> 3d Transformation

$$t^2 * (x_c^2 + y_c^2 + z_c^2) = d^2$$

$$t = \frac{d}{\sqrt{x_c^2 + y_c^2 + z_c^2}}$$

2d -> 3d Transformation

Example:

s_w = sensor width (m) = 0.0359 m

s_h = sensor height (m) = 0.0240 m

p_w = image width (pixels) = 7360

p_h = image height (pixels) = 4912

h_i = object height (pixels) = 100

h = object height (m) = 1.0 m

f = focal length (m) = 0.050 m

x_p = 1200

y_p = 2000



$$(x_c, y_c, z_c) = \left(-\frac{s_w}{2} + x_p * \frac{s_w}{p_w}, \frac{s_h}{2} - y_p * \frac{s_h}{p_h}, -f\right)$$

$$= \left(-\frac{0.0359}{2} + 1200 * \frac{0.0359}{7360}, \frac{0.0240}{2} - 2000 * \frac{0.0240}{4912}, -0.050\right) = (-0.0121, 0.0022, -0.0500)$$

$$\alpha = \arctan(y_c/f) = 0.0445 \quad \beta = \arctan(x_c/f) = -0.2374$$

$$d = \frac{f * h}{\cos(\alpha) * \cos(\beta) * h_i * s_h/p_h}$$

$$= \frac{0.050 * 1}{\cos(0.0445) * \cos(-0.2374) * 100 * 0.0240/4912} = 105.39$$

$$t = \frac{105.39}{\sqrt{-0.0121^2 + 0.0022^2 + -0.0500^2}} = 2.0468e+03$$

2d -> 3d Transformation

Object location in 3d camera coordinates:

$$(x_o, y_o, z_o) = t^* (x_c, y_c, z_c)$$

$$= 2.0468e+03 * (-0.0121, 0.0022, -0.0500)$$

$$(-24.7593, 4.5602, -102.3389)$$



Open questions:

- Derivation ok?
- Assumptions ok?
 - Optical axis in sensor center?

2d -> 3d Transformation

Parameters:

s_w = sensor width (m)

s_h = sensor height (m)

p_w = image width (pixels)

p_h = image height (pixels)

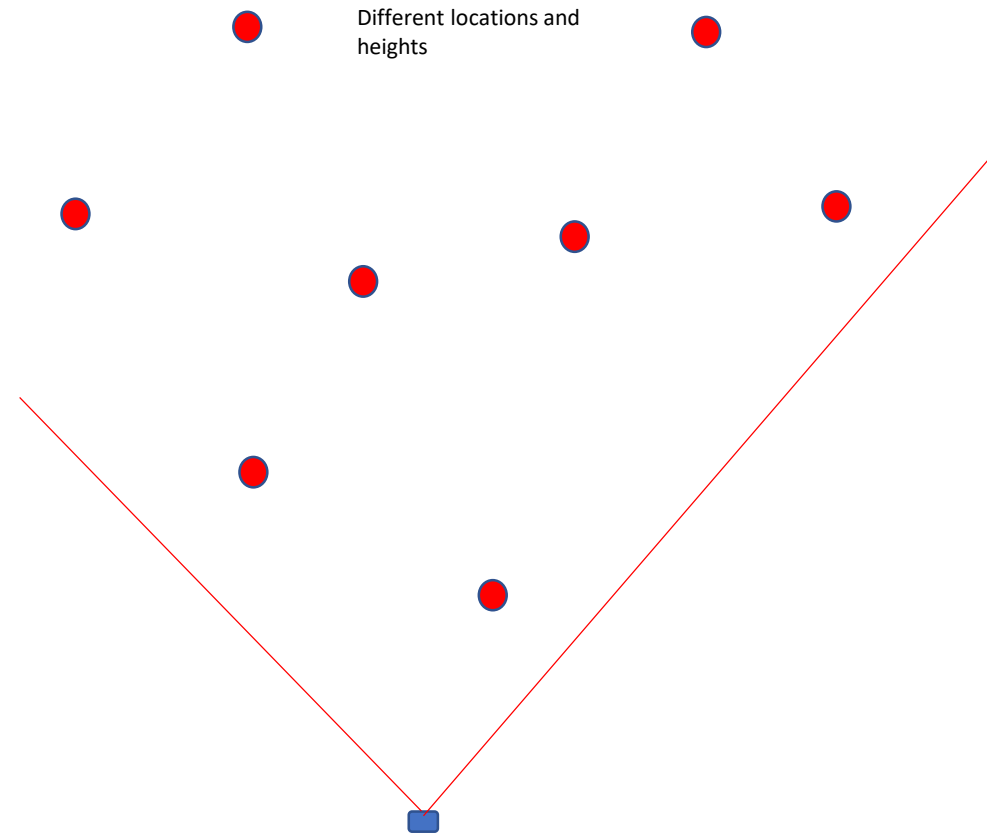
f = focal length (m)

Open questions:

- Video metadata often lacks sensor and focal parameters
- Focal length can change during shooting (zooming)

2d -> 3d Transformation

Experiment 1 in the wild (locations)



Nikon D800E:

s_w = sensor width (m) = 0.0359 m

s_h = sensor height (m) = 0.0240 m

p_w = image width (pixels) = 7360

p_h = image height (pixels) = 4912

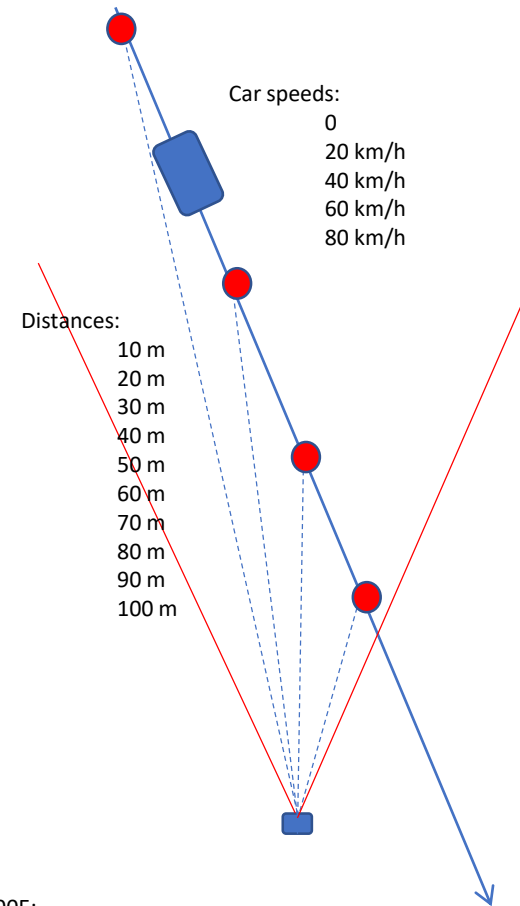
h = object height (m) = 1.5 m

f = focal length (m) = 0.020 m

$fov = 2 * \arctan\left(\frac{s_w}{2 * f}\right) = 83.81^\circ$

Experiment 2 in the wild (moving car)

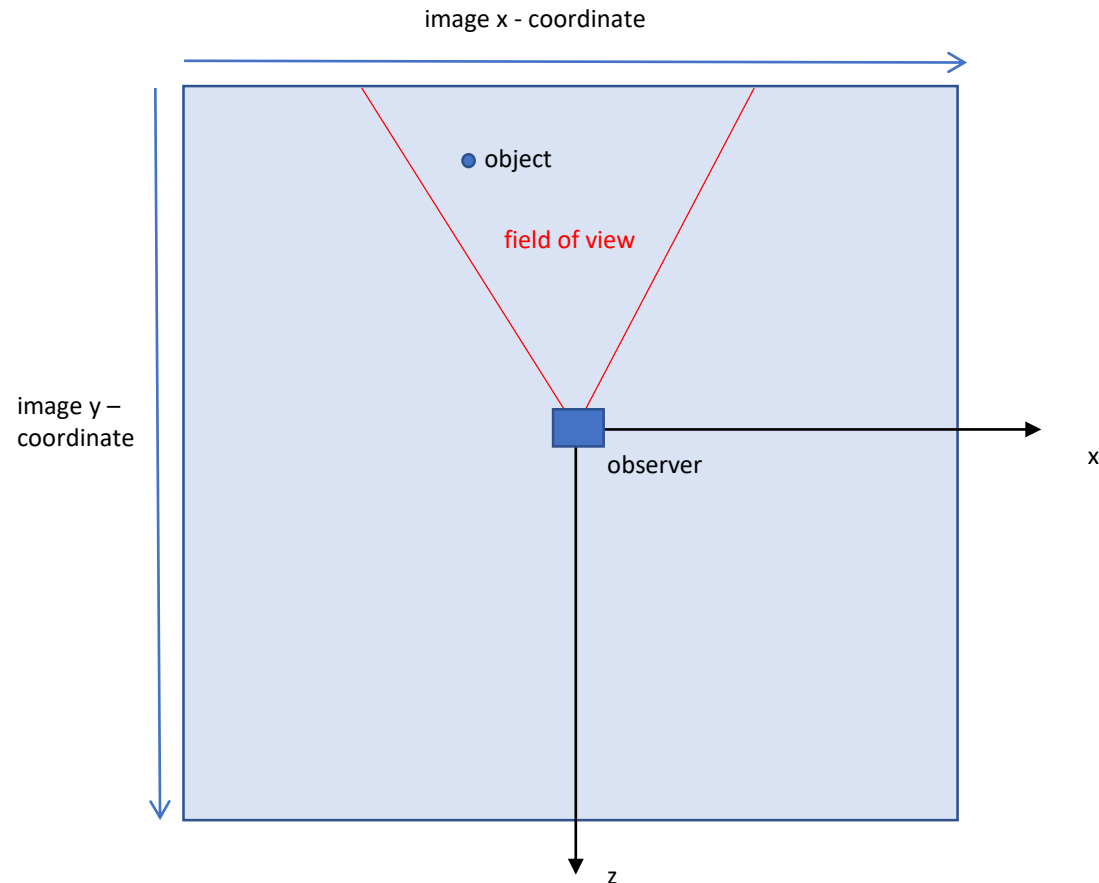
2d -> 3d Transformation



Nikon D800E:

s_w = sensor width (m) = 0.0359 m
 s_h = sensor height (m) = 0.0240 m
 p_w = image width (pixels) = 7360
 p_h = image height (pixels) = 4912
 h = object height (m) = 1.5 m
 f = focal length (m) = 0.050 m
 $fov = 2 * \arctan(\frac{s_w}{2*f}) = 39.49^\circ$

Map Presentation



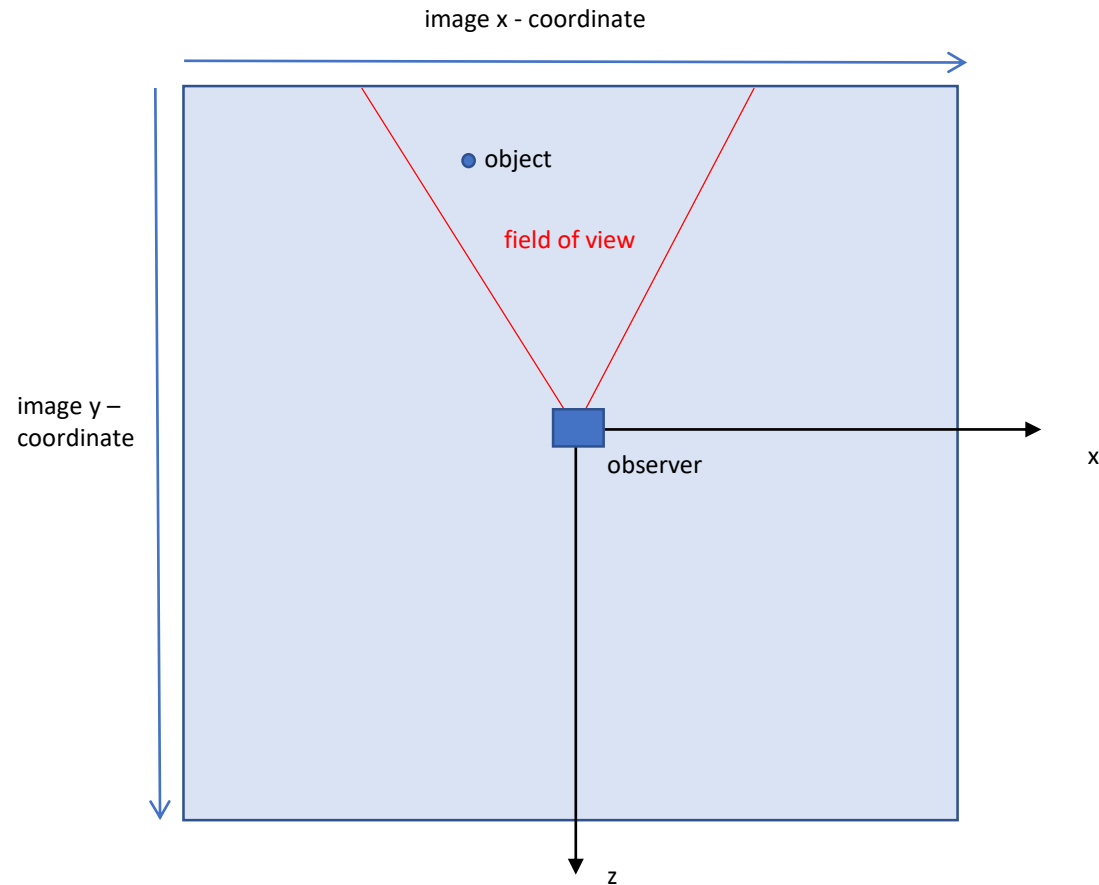
x_w = object world x coordinate (m)
 z_w = object world z coordinate (m)
 x_i = object image x coordinate (pixel)
 y_i = object image y coordinate (pixel)
 h_w = image area world height (m)
 h_i = image area image height (pixels)
 w_w = image area world width (m)
 w_i = image area image width (pixels)

$$(x_i, y_i) = \left(\frac{w_i}{2} + x_w * \frac{w_i}{w_w}, \frac{h_i}{2} + z_w * \frac{h_i}{h_w} \right)$$

$$\frac{w_i}{w_w} = \frac{h_i}{h_w} = p \text{ (pixel/meter ratio)}$$

$$(x_i, y_i) = \left(\frac{w_i}{2} + x_w * p, \frac{h_i}{2} + z_w * p \right)$$

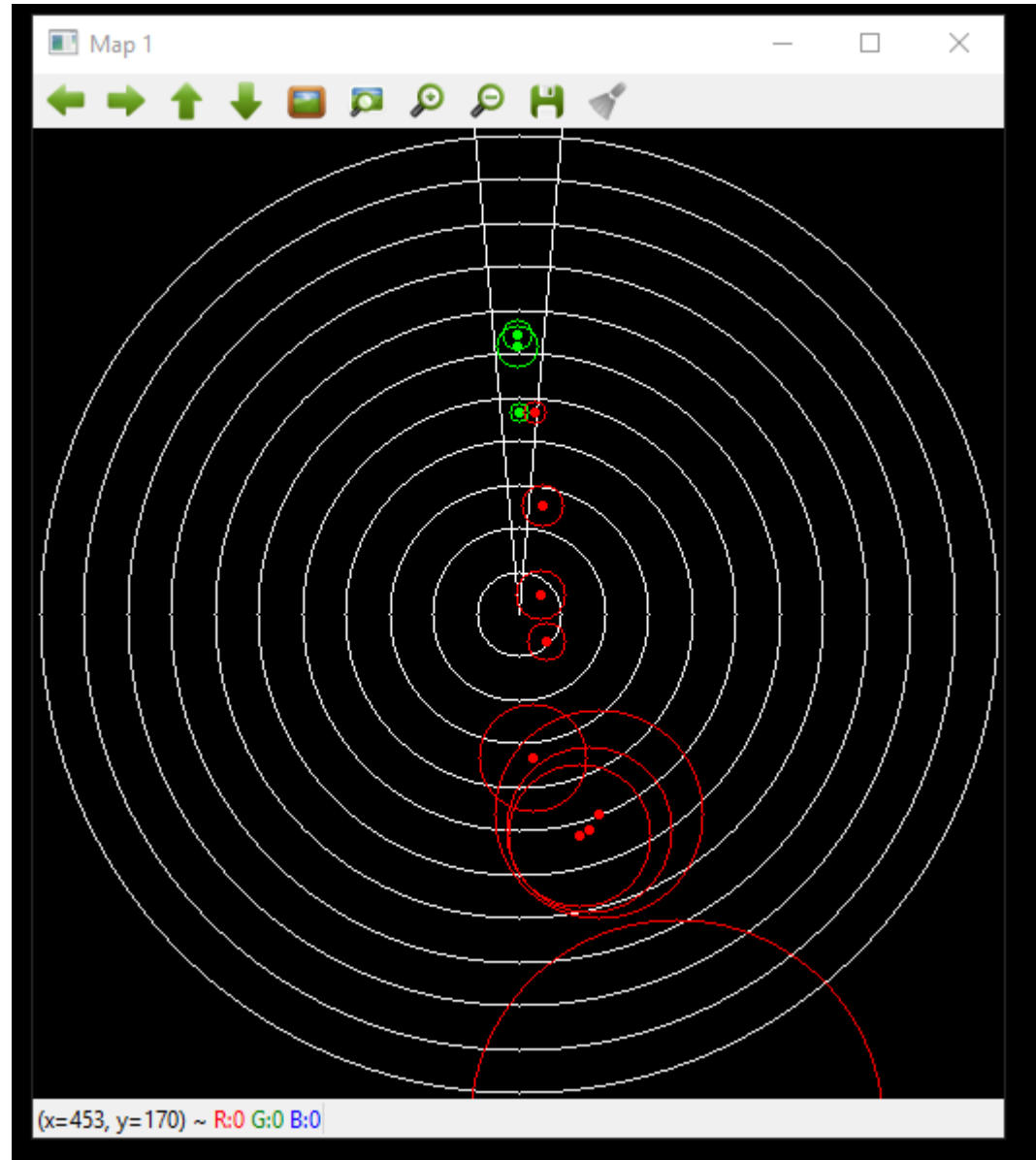
Map Presentation



$$FOV = 2 * \operatorname{atan}\left(\frac{s_w}{2 * f}\right)$$

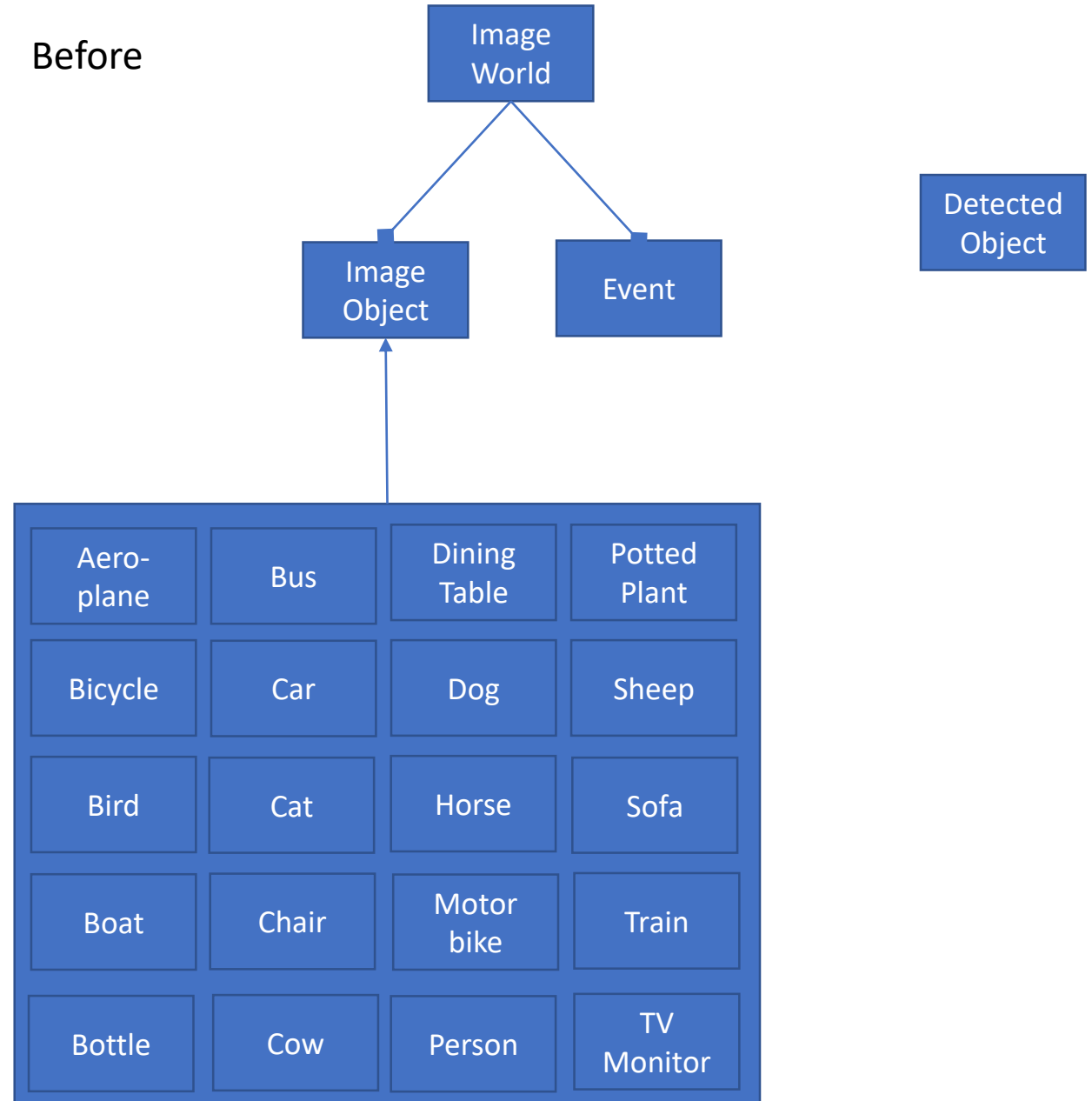
s_w = sensor width (m)
 f = focal length (m)

Map Presentation



Entity Diagram

Before



Entity Diagram

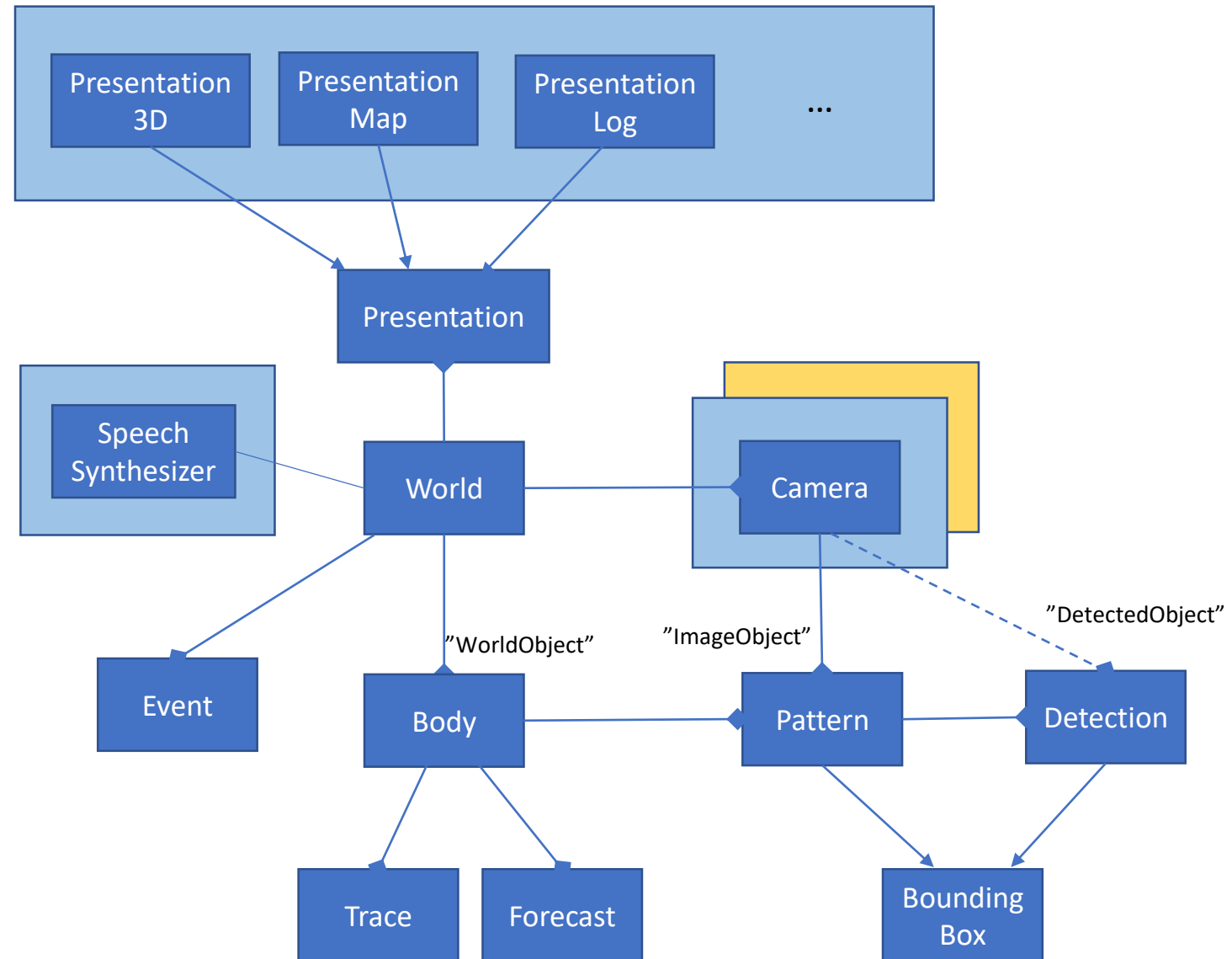
V2.0 goal

- Detected classes not hardcoded
- Object class may change
- Support for many cameras , rotations
- Names less awkward
- Cleaning
- Python style guide followed, excluding line length
- Code optimization
- One package

Name of the software package: ShadowWorld
(Plato: Allegory of the Cave)

Entity Diagram

V2.0



Body Kalman Filtering

- Second order model does not work, constant acceleration makes bodies bounce back or get enormous velocities.
- In world, constant acceleration for several (tens) of seconds is not common
- First order model works! (No wonder it's popular in robotics...)
- When measurement is lost, the body is switched into constant velocity mode
- In filtering terminology: velocity mode = only prediction, no correction
- Algorithms described in [docs] folder documents

Body Kalman Filtering

State vector s :

$$s = \begin{bmatrix} x \\ y \\ z \\ v_x \\ v_y \\ v_z \end{bmatrix}$$

where

(x, y, z) = location of the world object center point

(v_x, v_y, v_z) = velocity of the object

State equation in differential form:

$$\frac{ds(t)}{dt} = \begin{bmatrix} 0 & 0 & 0 & 1 & 0 & 0 \\ 0 & 0 & 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 0 & 0 & 1 \\ 0 & 0 & 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 & 0 & 0 \end{bmatrix} * s(t) + \epsilon(t) = A_1 * s + \epsilon(t)$$

State equation in difference form:

$$s(k+1) = (I + \Delta * A_1) * s(k) + \epsilon(k)$$

$$= \begin{bmatrix} 1 & 0 & 0 & \Delta & 0 & 0 \\ 0 & 1 & 0 & 0 & \Delta & 0 \\ 0 & 0 & 1 & 0 & 0 & \Delta \\ 0 & 0 & 0 & 1 & 0 & 0 \\ 0 & 0 & 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 0 & 0 & 1 \end{bmatrix} * s(k) + \epsilon(k) = A * s(k) + \epsilon(k)$$

where Δ is the time increment and ϵ Gaussian noise with covariance R .

Body Kalman Filtering

Measurement equation

$$z(k) = \begin{bmatrix} 1 & 0 & 0 & 0 & 0 & 0 \\ 0 & 1 & 0 & 0 & 0 & 0 \\ 0 & 0 & 1 & 0 & 0 & 0 \end{bmatrix} * s(k) + \delta(k) = C * s(k) + \delta(k)$$

Where δ is Gaussian noise with covariance matrix Q.

Kalman filter initialization:

$$\mu(0) = \begin{bmatrix} x(0) \\ y(0) \\ z(0) \\ 0 \\ 0 \\ 0 \end{bmatrix}$$

where $x(0)$, $y(0)$, $z(0)$ is the first location measurement.

$$\Sigma(0) = \begin{bmatrix} \alpha & 0 & 0 & 0 & 0 & 0 \\ 0 & \alpha & 0 & 0 & 0 & 0 \\ 0 & 0 & \alpha & 0 & 0 & 0 \\ 0 & 0 & 0 & \beta & 0 & 0 \\ 0 & 0 & 0 & 0 & \beta & 0 \\ 0 & 0 & 0 & 0 & 0 & \beta \end{bmatrix}$$

where α and β are believed variances of location and velocity.

$$R = \begin{bmatrix} r_1 & 0 & 0 & 0 & 0 & 0 \\ 0 & r_1 & 0 & 0 & 0 & 0 \\ 0 & 0 & r_1 & 0 & 0 & 0 \\ 0 & 0 & 0 & r_2 & 0 & 0 \\ 0 & 0 & 0 & 0 & r_2 & 0 \\ 0 & 0 & 0 & 0 & 0 & r_2 \end{bmatrix}$$

where r_1 and r_2 are believed variances of location and velocity.

$$Q = \begin{bmatrix} q & 0 & 0 \\ 0 & q & 0 \\ 0 & 0 & q \end{bmatrix}$$

Where q is the believed measurement variance.

Body Kalman Filtering

Kalman filter update:

$$\mu_1(k) = A * \mu(k-1)$$

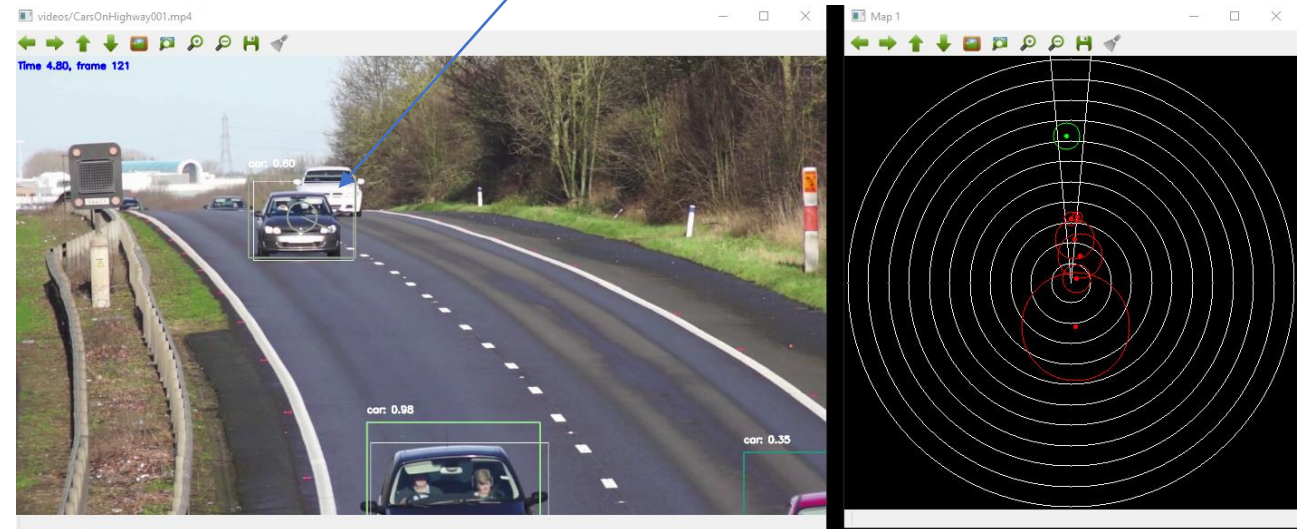
$$\Sigma_1(k) = A * \Sigma(k-1) * A^T + R$$

$$K(k) = \Sigma_1(k) * C^T (C * \Sigma_1(k) * C^T + Q)^{-1}$$

$$\mu(k) = \mu_1(k) + K(k) * (z(k) - C * \mu_1(k))$$

$$\Sigma(k) = (I - K(k) * C) * \Sigma_1(k)$$

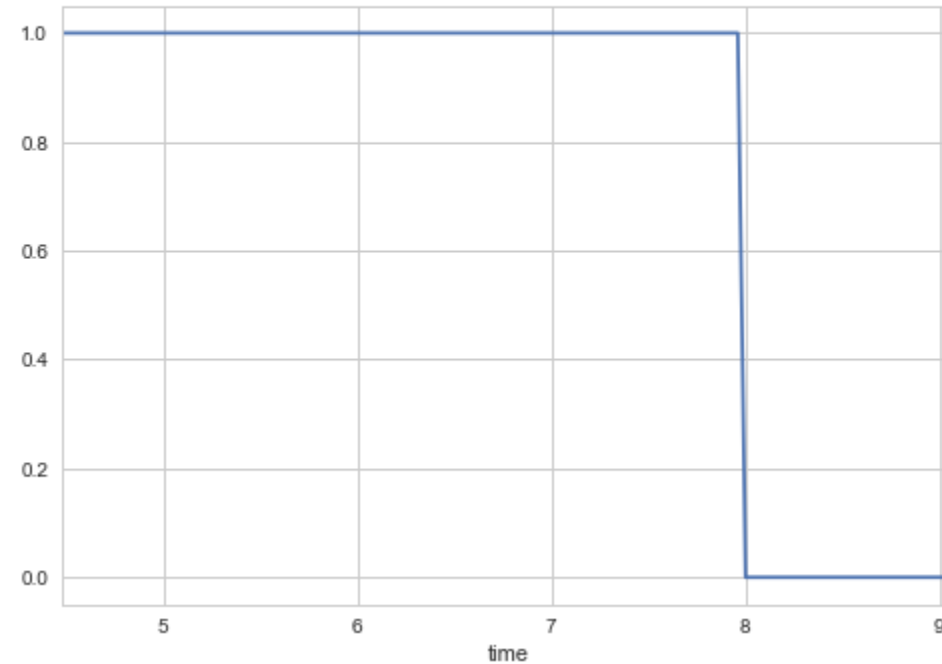
Example: Car



Body Kalman Filtering

```
In [606]: data_one['status'].plot()
```

```
Out[606]: <matplotlib.axes._subplots.AxesSubplot at 0x1f5dbe24be0>
```



Measurement status:

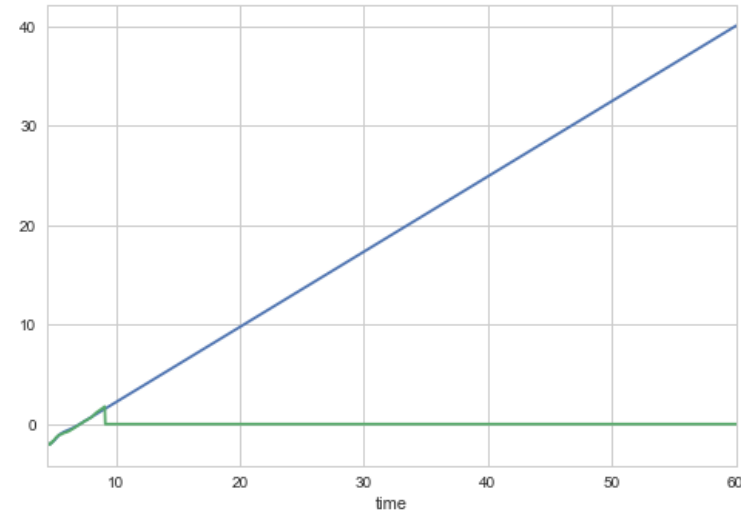
1=measurement

0=no measurement

Body Kalman Filtering

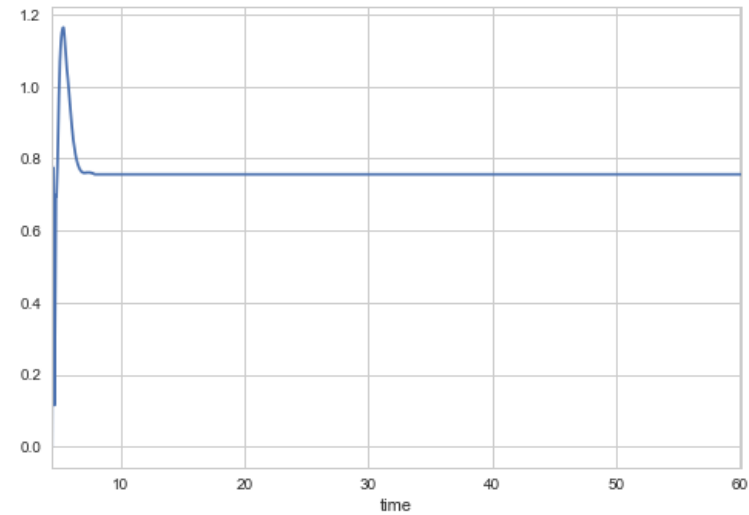
```
In [612]: data_one['x'].plot() # estimated, blue  
data_one['x_pattern'].plot() # measured, green
```

```
Out[612]: <matplotlib.axes._subplots.AxesSubplot at 0x1f5defad828>
```



```
In [613]: data_one['vx'].plot() # blue
```

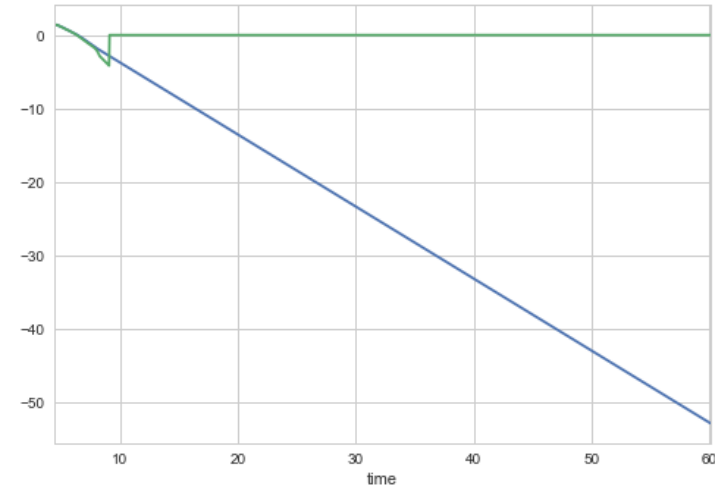
```
Out[613]: <matplotlib.axes._subplots.AxesSubplot at 0x1f5dbf720f0>
```



Body Kalman Filtering

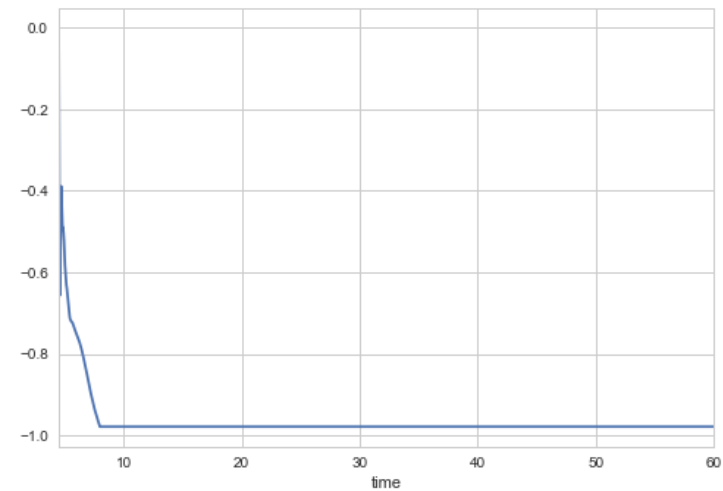
```
In [614]: data_one['y'].plot() # estimated, blue  
data_one['y_pattern'].plot() # measured, green
```

```
Out[614]: <matplotlib.axes._subplots.AxesSubplot at 0x1f5e003d0b8>
```



```
In [615]: data_one['vy'].plot() # blue
```

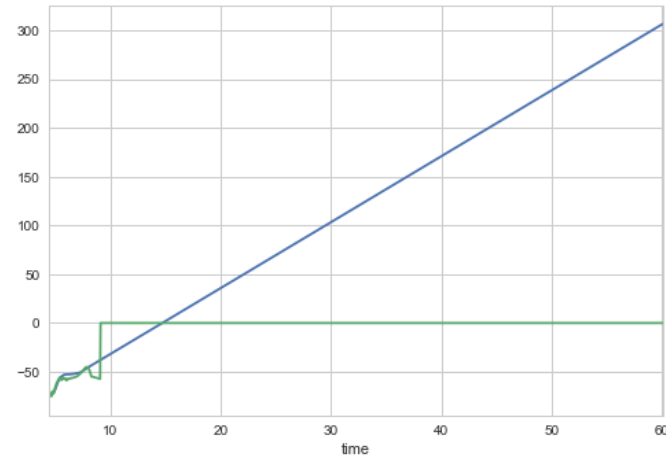
```
Out[615]: <matplotlib.axes._subplots.AxesSubplot at 0x1f5e00cd908>
```



Body Kalman Filtering

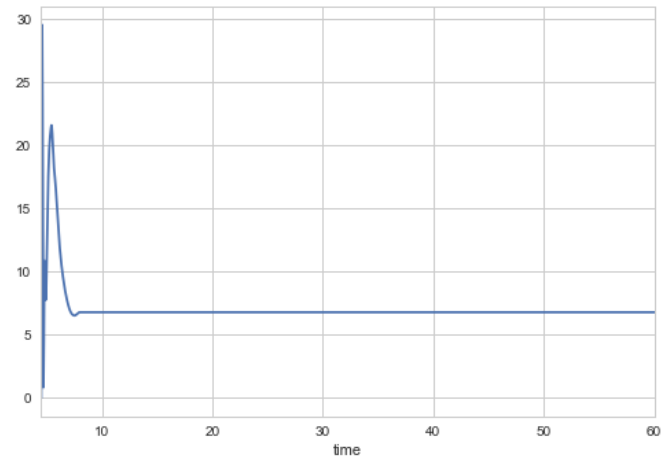
```
In [616]: data_one['z'].plot() # estimated, blue  
data_one['z_pattern'].plot() # measured, green
```

```
Out[616]: <matplotlib.axes._subplots.AxesSubplot at 0x1f5def60780>
```



```
In [617]: data_one['vz'].plot() # blue
```

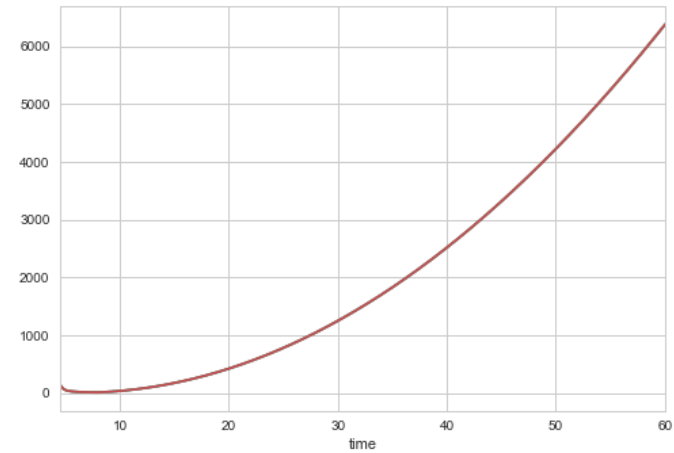
```
Out[617]: <matplotlib.axes._subplots.AxesSubplot at 0x1f5d827f0b8>
```



Body Kalman Filtering

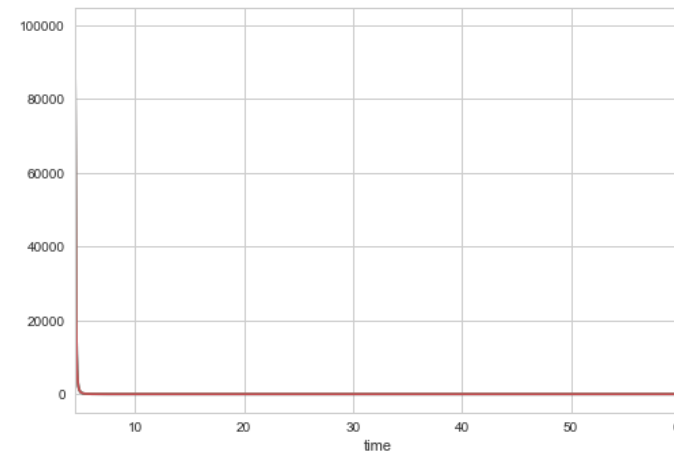
```
In [621]: data_one['sigma_00'].plot() # x variance, blue  
data_one['sigma_11'].plot() # y variance, green  
data_one['sigma_22'].plot() # y variance, green
```

Out[621]: <matplotlib.axes._subplots.AxesSubplot at 0x1f5e0280d68>



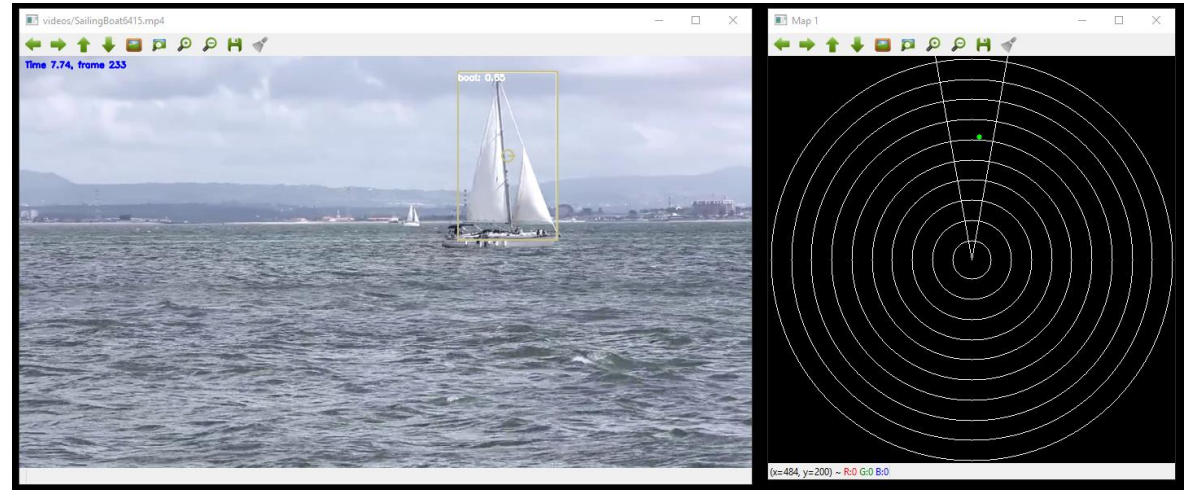
```
In [622]: data_one['sigma_33'].plot() # vx variance, blue  
data_one['sigma_44'].plot() # vy variance, green  
data_one['sigma_55'].plot() # vy variance, green
```

Out[622]: <matplotlib.axes._subplots.AxesSubplot at 0x1f5e03d60b8>



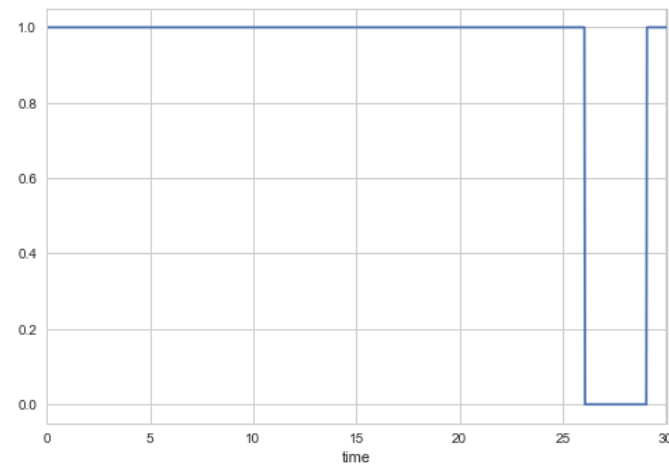
Body Kalman Filtering

Example 2: Slow moving object



```
In [8]: data_one['status'].plot()
```

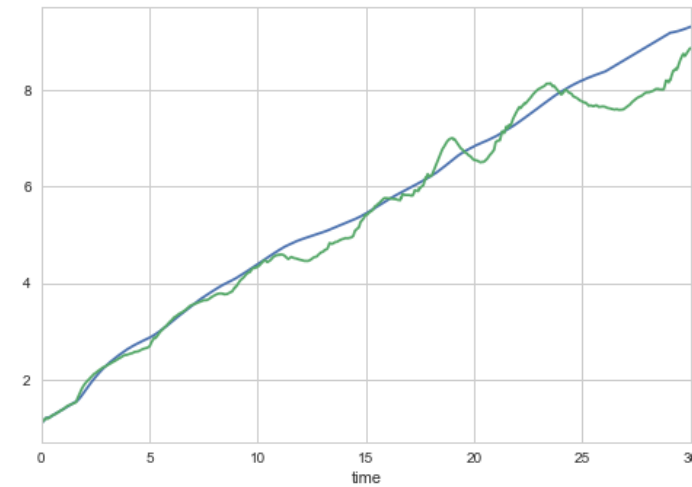
```
Out[8]: <matplotlib.axes._subplots.AxesSubplot at 0x13a6ba38470>
```



Body Kalman Filtering

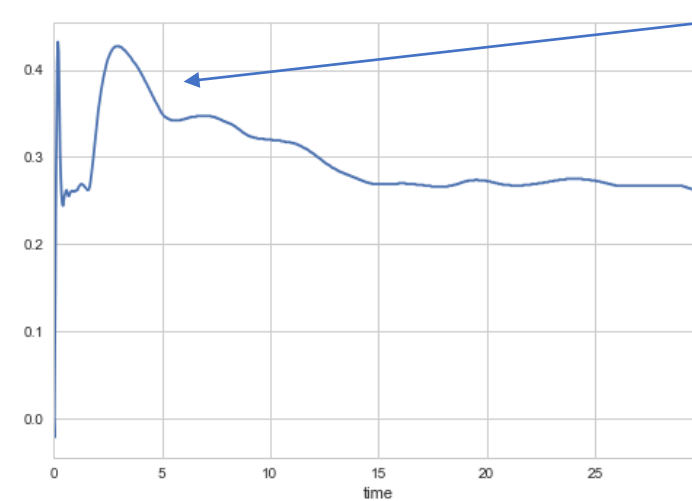
```
In [9]: data_one['x'].plot() # estimated, blue  
data_one['x_pattern'].plot() # measured, green
```

```
Out[9]: <matplotlib.axes._subplots.AxesSubplot at 0x13a6b725e80>
```



```
In [10]: data_one['vx'].plot() # blue
```

```
Out[10]: <matplotlib.axes._subplots.AxesSubplot at 0x13a6b7be780>
```

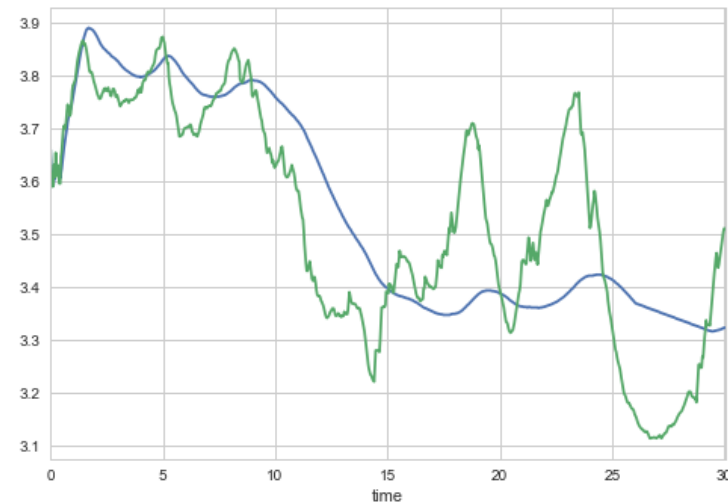


Takes long time
to settle

Body Kalman Filtering

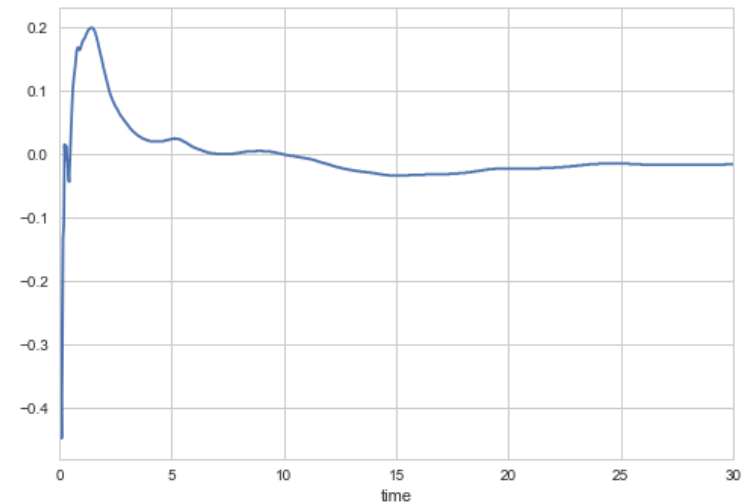
```
In [11]: data_one['y'].plot() # estimated, blue  
data_one['y_pattern'].plot() # measured, green
```

```
Out[11]: <matplotlib.axes._subplots.AxesSubplot at 0x13a6b88ceb8>
```



```
In [12]: data_one['vy'].plot() # blue
```

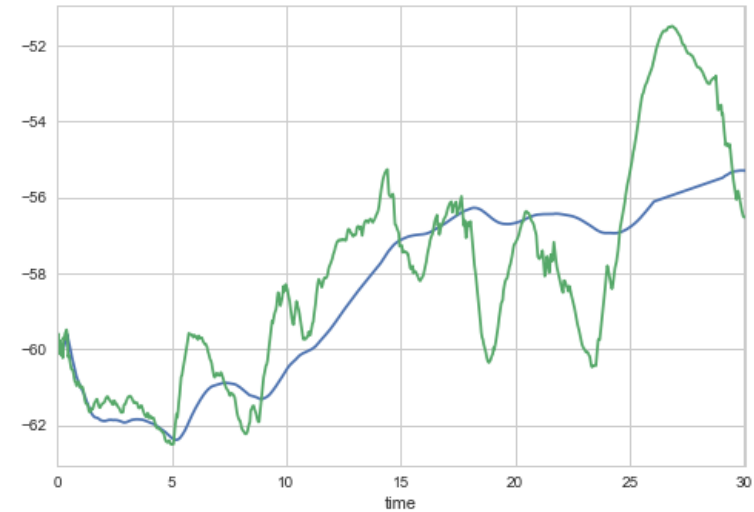
```
Out[12]: <matplotlib.axes._subplots.AxesSubplot at 0x13a6b9c1b00>
```



Body Kalman Filtering

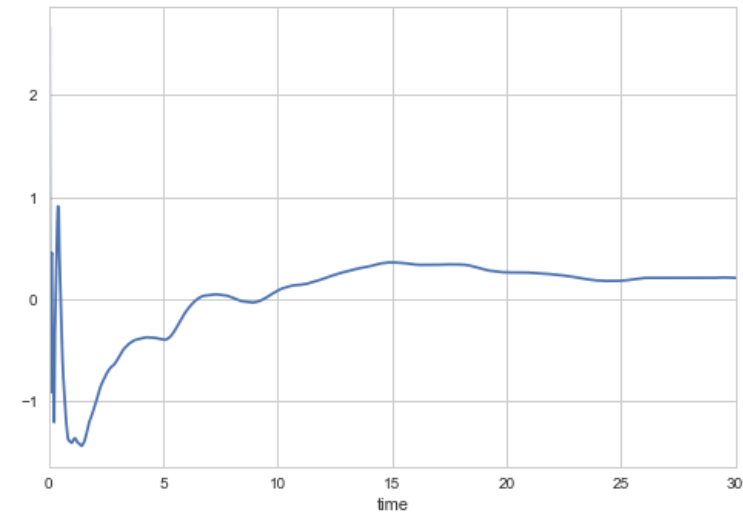
```
In [13]: data_one['z'].plot() # estimated, blue  
data_one['z_pattern'].plot() # measured, green
```

```
Out[13]: <matplotlib.axes._subplots.AxesSubplot at 0x13a6b95dcc0>
```



```
In [14]: data_one['vz'].plot() # blue
```

```
Out[14]: <matplotlib.axes._subplots.AxesSubplot at 0x13a6cd225f8>
```



Body Kalman Filtering

```
16 # Hyperparameters-----
17 BODY_ALFA = 100000.0 # Body initial location error variance 200
18 BODY_BETA = 100000.0 # Body initial velocity error variance 10000
19 BODY_C = np.array([[1.0, 0.0, 0.0, 0.0, 0.0, 0.0],
20                    [0.0, 1.0, 0.0, 0.0, 0.0, 0.0],
21                    [0.0, 0.0, 1.0, 0.0, 0.0, 0.0]
22                    ]) # Body measurement matrix
23 BODY_DATA_COLLECTION_COUNT = 30 # How many frames until notification
24 BODY_Q = np.array([[200.0, 0.0, 0.0],
25                    [0.0, 200.0, 0.0],
26                    [0.0, 0.0, 200.0]]) # Body measurement variance 200
27 BODY_R = np.array([[0.0, 0.0, 0.0, 0.0, 0.0, 0.0],
28                    [0.0, 0.0, 0.0, 0.0, 0.0, 0.0],
29                    [0.0, 0.0, 0.0, 0.0, 0.0, 0.0],
30                    [0.0, 0.0, 0.0, 0.0, 0.0, 0.0],
31                    [0.0, 0.0, 0.0, 0.0, 0.0, 0.0],
32                    [0.0, 0.0, 0.0, 0.0, 0.0, 0.0]
33                    ]) # Body state equation covariance
```

Kalman filter update:

$$\mu_1(k) = A * \mu(k-1)$$

$$\Sigma_1(k) = A * \Sigma(k-1) * A^T + R$$

$$K(k) = \Sigma_1(k) * C^T (C * \Sigma_1(k) * C^T + Q)^{-1}$$

$$\mu(k) = \mu_1(k) + K(k) * (z(k) - C * \mu_1(k))$$

$$\Sigma(k) = (I - K(k) * C) * \Sigma_1(k)$$

- Filtering requires several seconds to achieve reliable results
- Kalman filter parameters are not optimized
- Optimization will be done later

Paper

Image-based situation awareness: Estimating location and velocity using single camera object detection

Contents:

- 1. Abstract
 - 2. Introduction
 - 3. Related work
 - 4. Our approach
 - 1. Definitions
 - 2. Object identity
 - 3. Distance estimation
 - 4. Location and velocity estimation
 - 5. Movement prediction
 - 5. Experiments
 - 1. Test setup
 - 2. Evaluation metric
 - 3. Results
 - 4. Other experiments
 - 6. Conclusion
-
- Topics and their connections:
- ????? (Red) points to 3. Related work
 - detection, pattern... points to 4. Our approach
 - Hungarian algorithm, distance metrics, movement prediction points to 4.2. Object identity
 - geometry points to 4.3. Distance estimation
 - Kalman filtering points to 4.4. Location and velocity estimation
 - Difference equation, uncertainties points to 4.5. Movement prediction
 - In the wild. See previous slides. More? (Red) points to 5.2. Evaluation metric
 - Existing datasets? Which? (Red) points to 5.4. Other experiments

Paper

- One solution for location estimation and movement prediction for video detected object (nearly) solved
- Work needed:
 - Kalman filter parameter adjustment*
 - Experiments in the wild (see previous slides)
 - Other tests? (using existing (tracking) dataset)
- Where to publish?
 - ECCV 2018 (8-14.9, Munich, deadline **14.3.2018, too soon**)
 - CVPR 2019 (6/2019, Long Beach, deadline 11/2018)
 - ICCV 2019 (29.10.-3.11.2019, Seoul, deadline 1/2019)

*Locations and especially velocities take too much time to settle at the moment.

Representations for Interpretation



Representation: Video

Object detection
network

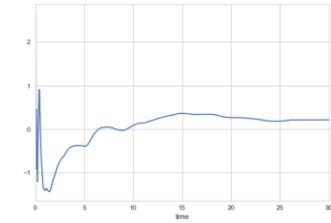
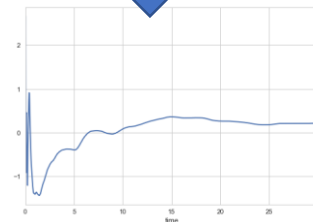
Representation: Pattern

Location and
velocity
estimation

Representation: Body

Forecast

Representation: Time series



Interpretation
Generation

I1 I2 I3

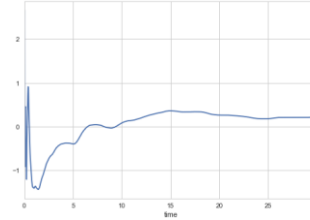
...
Interpretation
representations

Language
Generation



Representations for Interpretation

Example for interpretation representation: collision detection



Time series forecast for body locations



Interpretation
Generation



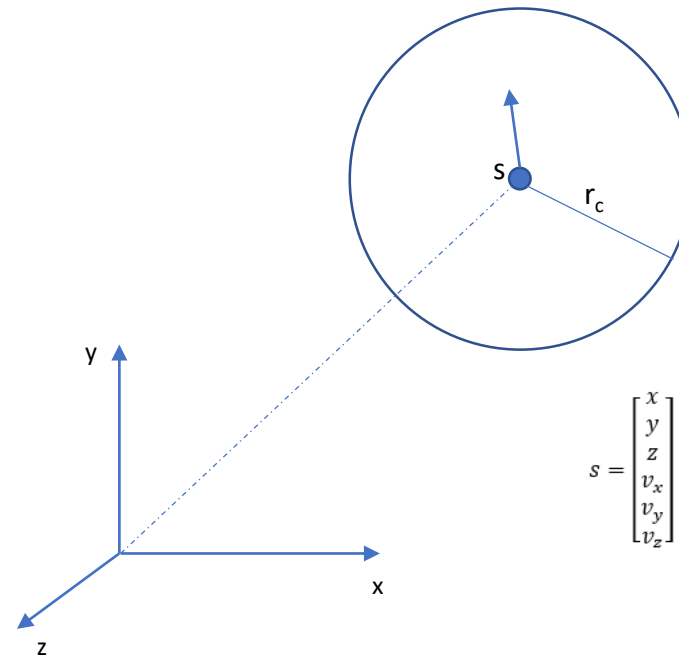
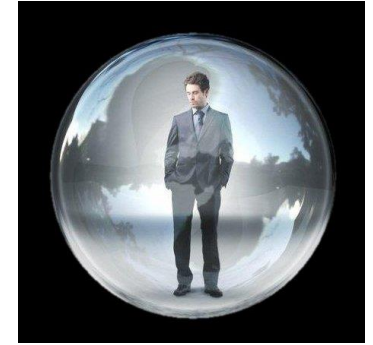
$$\begin{bmatrix} 0 & p_{12} & p_{13} & p_{14} & \dots & p_{1n} \\ p_{21} & 0 & p_{23} & p_{24} & \dots & p_{2n} \\ p_{31} & p_{32} & 0 & p_{34} & \dots & p_{3n} \\ p_{41} & p_{42} & p_{43} & 0 & \dots & p_{4n} \\ \dots & \dots & \dots & \dots & \dots & \dots \\ p_{n1} & p_{n2} & p_{n3} & p_{n4} & \dots & 0 \end{bmatrix}$$

(Symmetric) collision probability matrix
 p_{nm} = probability that bodies n and m will collide

Probabilistic Model for Body

Some form of spatial simplification is needed, like

- cube
- rectangular prism
- cylinder
- **sphere** (probably the easiest math)



$$s = \begin{bmatrix} x \\ y \\ z \\ v_x \\ v_y \\ v_z \end{bmatrix}$$

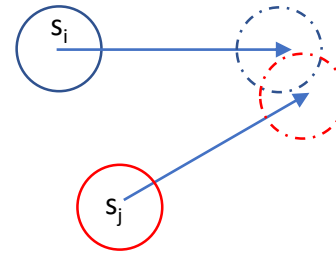
From state estimation

$$P(s) \sim N(s \mid \mu_s, V_s)$$

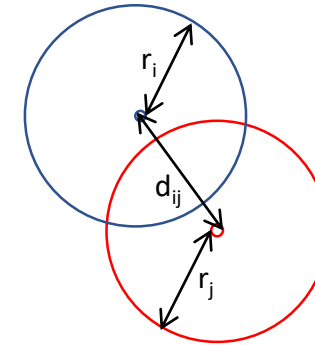
$$P(r_c) \sim N(r_c \mid \mu_{r,c}, V_{r,c})$$

Class specific, a priori

Collision Detection



$$\begin{bmatrix} x_i(t) \\ y_i(t) \\ z_i(t) \end{bmatrix} = \begin{bmatrix} x_i(0) \\ y_i(0) \\ z_i(0) \end{bmatrix} + t * \begin{bmatrix} v_{i,x}(0) \\ v_{i,y}(0) \\ v_{i,z}(0) \end{bmatrix}$$



Collision C_{ij} if $d_{ij} < r_i + r_j$

$$d_{ij}(t) = \sqrt{(x(t)_i - x(t)_j)^2 + (y(t)_i - y(t)_j)^2 + (z(t)_i - z(t)_j)^2}$$

Random variable

$$r = \begin{bmatrix} x_1(0) \\ y_1(0) \\ z_1(0) \\ v_{1,x}(0) \\ v_{1,y}(0) \\ v_{1,z}(0) \\ r_1 \\ \dots \\ x_n(0) \\ y_n(0) \\ z_n(0) \\ v_{n,x}(0) \\ v_{n,y}(0) \\ v_{n,z}(0) \\ r_n \\ t \end{bmatrix}$$

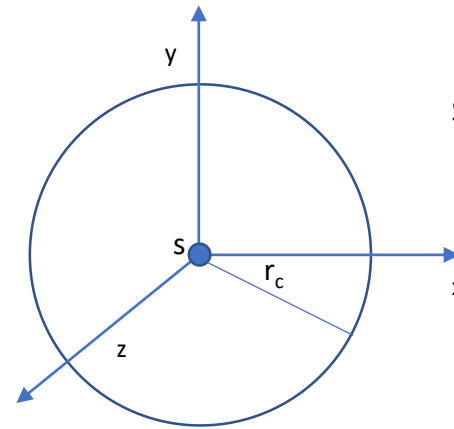
t: uniform distribution on $[0, t_{\text{end}}]$

Sampling:
$$p_{ij} = E\{C_{ij}\} = \sum_{k=1}^m \frac{\delta(C_{i,j})}{m}$$

Open question: More efficient sampling with MCMC / Metropolis-Hastings?

Collision Detection

Collision with the observer (body "0")

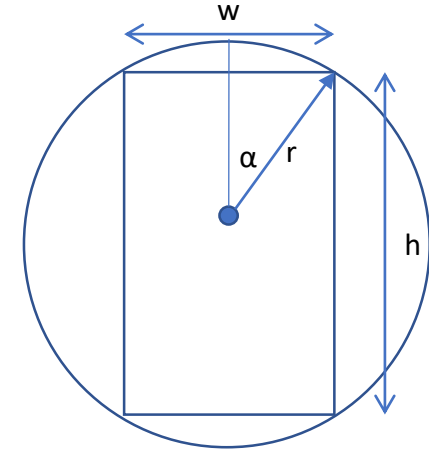


$S=[0,0,0,0,0,0]^T$, deterministic, $r = r[\text{class person}]$

Collision Detection

Side effect: instead of using height in distance estimation, radius of surrounding circle will be used:

From bounding box coordinates to radius:



$$\tan(\alpha) = \frac{w/2}{h/2} = \frac{w}{h}$$

$$\cos(\alpha) = \frac{h/2}{r} = \frac{h}{2r}$$

$$\Rightarrow r = \frac{h}{2 \cdot \cos(\alpha)} = \frac{h}{2 \cos(\arctan(h/w))} = \frac{h \sqrt{1 + (1 + w/h)^2}}{2}$$

$$h = (y_{\max} - y_{\min}) \quad c_y = (y_{\max} + y_{\min})/2$$

$$w = (x_{\max} - x_{\min}) \quad c_x = (x_{\max} + x_{\min})/2$$

Collision Detection

Distance estimation using object radius:

$$d = \frac{f * h}{\cos(\alpha) * \cos(\beta) * h_i * s_h / p_h}$$

s_w = sensor width (m)
 s_h = sensor height (m)
 p_w = image width (pixels)
 p_h = image height (pixels)
 h_i = object height (pixels)
 h = object height (m)
 f = focal length (m)
 α = altitude (rad)
 β = azimuth (rad)

Before

$$d = \frac{f * r}{\cos(\alpha) * \cos(\beta) * r_i * s_h / p_h}$$

s_w = sensor width (m)
 s_h = sensor height (m)
 p_w = image width (pixels)
 p_h = image height (pixels)
 r_i = object radius (pixels)
 r = object radius (m)
 f = focal length (m)
 α = altitude (rad)
 β = azimuth (rad)

Now

Collision Detection

Distance estimation using object radius:

$$t = \frac{d}{\sqrt{x_c^2 + y_c^2 + z_c^2}}$$

$$(x_c, y_c, z_c) = \left(-\frac{s_w}{2} + xp^* \frac{s_w}{p_w}, \frac{s_h}{2} - yp^* \frac{s_h}{p_h}, -f\right)$$

$$(x_o, y_o, z_o) = t^* (x_c, y_c, z_c)$$



Work in Progress

Perception

“The first step in achieving SA is to perceive the status, attributes, and dynamics of relevant elements in the environment. Thus, Level 1 SA, the most basic level of SA, involves the processes of monitoring, cue detection, and simple recognition, which lead to an awareness of multiple situational elements (objects, events, people, systems, environmental factors) and their current states (locations, conditions, modes, actions).”



Next Steps

Next steps

Comprehension:

1. Closing the open questions
2. 2d -> 3d transformation
3. World object state estimation



To Be Discussed

To Be Discussed

- Activity recognition?
- Emotion recognition?
- Turning camera, estimation by background movement?

Thank you!

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<https://github.com/SakariLampola/Thesis>