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### Pose estimation systems and methods trained using motion capture data

#### Abstract

A training system includes: a neural network model configured to determine three-dimensional coordinates of joints, respectively, representing poses of animals in images, where the neural network model is trained using a first training dataset including: images including animals; and coordinates of joints of the animals in the images, respectively; and a training module configured to, after the training of the neural network model using the first training dataset, train the neural network model using a second training dataset including motion capture data, where the motion capture data does not include images of animals and includes measured coordinates at points, respectively, on animals.

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## **Background/Summary**

### **FIELD**

(1) The present disclosure relates to human pose estimation systems and methods and more particularly to human pose estimation systems and methods trained using motion capture data.

### **BACKGROUND**

(2) The background description provided here is for the purpose of generally presenting the context of the disclosure. Work of the presently named inventors, to the extent it is described in this background section, as well as aspects of the description that may not otherwise qualify as prior art at the time of filing, are neither expressly nor impliedly admitted as prior art against the present disclosure.

(3) Neural network models could be trained to determine three dimensional (3D) pose and shape of humans in images or video using large datasets of images with annotated 3D poses and shapes. Such datasets, however, are not readily available and tend to be very costly to collect. For example, the collection of such data may involve setting up multiple inertial measurement units (IMUs), calibrating a multi camera system, and considering static poses. In practice, only two-dimensional (2D) information such as 2D keypoint locations or semantic part segmentation may be manually annotated.

(4) There is therefore a need to be able to train models to accurately determine 3D pose and shape of humans using images and video without a large dataset of annotated 3D poses and shapes.

#### SUMMARY

(5) In a feature, a training system includes: a neural network model configured to determine three-dimensional coordinates of joints, respectively, representing poses of animals in images, where the neural network model is trained using a first training dataset including: images including animals; and coordinates of joints of the animals in the images, respectively; and a training module configured to, after the training of the neural network model using the first training dataset, train the neural network model using a second training dataset including motion capture data, where the motion capture data does not include images of animals and includes measured coordinates at points, respectively, on animals.

(6) In further features: the neural network model includes batch normalization layers; and the training module is configured to, after the training of the neural network model using the first training dataset, train the neural network model by selectively adjusting at least one parameter of at least one of the batch normalization layers.

(7) In further features, the training module is configured to selectively adjust only parameters of the batch normalization layers and maintain all other parameters of all other portions of the neural network model constant after the training of the neural network model using the first training dataset.

(8) In further features, the training module is configured to, after the training of the neural network model using the first training dataset, train the neural network model further using data from the first training dataset.

(9) In further features, the training module is configured to: render models of animals based on the motion capture data; texturize the models using textures from a texture dataset; apply backgrounds to the models from a background dataset; and train the neural network model using the texturized models with the backgrounds.

(10) In further features, the training module is further configured to selectively: render second models of the animals in the images using the coordinates of the joints of the animals, respectively; texturize the second models using textures from the texture dataset; apply second backgrounds to the models from the background dataset; and train the neural network model using the texturized second models with the second backgrounds.

(11) In further features, the model is the SPIN model.

(12) In further features, the motion capture data in the second training dataset includes motion capture data from the AMASS dataset.

(13) In a feature, a system includes: a neural network model configured to determine three-dimensional coordinates of joints, respectively, representing a pose of an animal in an image, where the neural network model is trained using: a first training dataset including: images including animals; and coordinates of joints of the animals in the images, respectively; and a second training

dataset including motion capture data that: does not include images of animals; and includes measured coordinates at points, respectively, on animals; and a camera configured to capture images; and a control module configured to selectively actuate an actuator based on three-dimensional coordinates of joints representing a pose of an animal determined by the neural network model based on an image captured by the camera.

(14) In a feature, a training system includes: a neural network model configured to determine three-dimensional coordinates of joints, respectively, representing poses of animals in sequences of images, where  $T$  is an integer greater than one; and a training module configured to train the neural network model using a training dataset including sets of time series of motion capture data, where the motion capture data does not include images of animals and includes measured coordinates at points, respectively, on animals.

(15) In further features, the training module is configured to: render a time series of models of animals based on one of the sets of time series of motion capture data; and train the neural network model based on outputs of the neural network model generated in response to the time series of models.

(16) In further features, a masking module is configured to replace at least one of the models in the time series of models with a predetermined masking token.

(17) In further features, the masking module is configured to replace a predetermined percentage of the models in the time series of models with a predetermined masking token.

(18) In further features, the predetermined percentage is approximately 12.5 percent.

(19) In further features, a masking module is configured to replace at least one of the models in the time series of models with a different model.

(20) In further features, the masking module is configured to replace a predetermined percentage of the models in the time series of models with different models.

(21) In further features, a noise module is configured to add noise to at least one of the models in the time series of models.

(22) In further features, the noise includes Gaussian noise.

(23) In further features, a position encoding module is configured to add positional encodings to the time series of models.

(24) In further features, the training module is configured to train the neural network model based on minimizing a pose loss determined based on differences between: three-dimensional coordinates determined by the neural network model based on the time series of models of animals; and coordinates of the motion capture data stored in the training dataset.

(25) In further features, the training module is configured to train the neural network model based on minimizing a three-dimensional keypoint loss determined based on differences between: three-dimensional coordinates determined by the neural network model based on the time series of models of animals; and coordinates of the motion capture data stored in the training dataset.

(26) In a feature, a system includes: a neural network model configured to determine three-dimensional coordinates of joints, respectively, representing poses of animals, where the neural network model is trained using a training dataset including motion capture data that: does not include images of animals; and includes measured coordinates at points, respectively, on animals; and a camera configured to capture time series of images; and a control module configured to selectively actuate an actuator based on three-dimensional coordinates of joints representing a pose of an animal determined by the neural network model based on a time series of images captured by the camera.

(27) In a feature, a training method includes: training, using a first training dataset, a neural network model to determine three-dimensional coordinates of joints, respectively, representing poses of animals in images, the first training dataset including: images including animals; and coordinates of joints of the animals in the images, respectively; and after the training of the neural network model using the first training dataset, training the neural network model using a second

training dataset including motion capture data, where the motion capture data does not include images of animals and includes measured coordinates at points, respectively, on animals.

(28) In a feature, a method includes: using a neural network model, determining three-dimensional coordinates of joints, respectively, representing a pose of an animal in an image, where the neural network model is trained using: a first training dataset including: images including animals; and coordinates of joints of the animals in the images, respectively; and a second training dataset including motion capture data that: does not include images of animals; and includes measured coordinates at points, respectively, on animals; capturing images using a camera; and selectively actuating an actuator based on three-dimensional coordinates of joints representing a pose of an animal determined by the neural network model based on an image captured by the camera.

(29) In a feature, a training method includes: using a neural network model, determining three-dimensional coordinates of joints, respectively, representing poses of animals in sequences of images, where T is an integer greater than one; and training the neural network model using a training dataset including sets of time series of motion capture data, where the motion capture data does not include images of animals and includes measured coordinates at points, respectively, on animals.

(30) In a feature, a training method includes: training a neural network model to determine three-dimensional coordinates of joints, respectively, representing poses of animals using a training dataset including motion capture data that: does not include images of animals; and includes measured coordinates at points, respectively, on animals; capturing time series of images using a camera; and selectively actuating an actuator based on three-dimensional coordinates of joints representing a pose of an animal determined by the neural network model based on a time series of images captured by the camera.

(31) Further areas of applicability of the present disclosure will become apparent from the detailed description, the claims and the drawings. The detailed description and specific examples are intended for purposes of illustration only and are not intended to limit the scope of the disclosure.

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## Description

### BRIEF DESCRIPTION OF THE DRAWINGS

(1) The patent or application file contains at least one drawing executed in color. Copies of this patent or patent application publication with color drawing(s) will be provided by the Office upon request and payment of the necessary fee.

(2) The present disclosure will become more fully understood from the detailed description and the accompanying drawings, wherein:

(3) FIG. 1 is a functional block diagram of an example robot;

(4) FIG. 2 is a functional block diagram of an example implementation of a training system;

(5) FIG. 3 is a functional block diagram of an example implementation of a model;

(6) FIG. 4 is a functional block diagram of an example implementation of a convolutional neural network module;

(7) FIG. 5 includes examples of synthesized (synthetic) samples;

(8) FIG. 6 is a flowchart depicting an example method of training the model;

(9) FIG. 7 includes an example pose determination system of the model that determines poses of humans in sequences of images;

(10) FIG. 8 is a functional block diagram of a pose module;

(11) FIG. 9 is a functional block diagram of an example training system;

(12) FIG. 10 includes an illustration of an example sequence of images and models generated based on poses predicted;

(13) FIG. 11 includes an example graph of percentage of motion capture data used in each batch

during training versus error for different datasets.

(14) In the drawings, reference numbers may be reused to identify similar and/or identical elements.

## DETAILED DESCRIPTION

(15) Robots can be trained to perform tasks in various different ways. For example, a robot can be trained using positions of joints of humans in images or video captured while performing tasks.

(16) The present disclosure involves training a neural network model to determine three dimensional (3D) poses and shapes of humans in images and video using motion capture (MoCap) data. The motion capture data includes motion sequences of humans and measured ground truth 3D poses. The present disclosure also involves a pose estimator that receives the output of a bidirectional encoder representations from transformers (BERT) model and directly regresses 3D pose. While the example of use in a robot is provided and will be described, the present disclosure is also applicable to other uses of estimated 3D poses generated based on input images or video, such as for avatar animation, video and image indexing, virtual try on of clothing, body language detection, and other places.

(17) FIG. 1 is a functional block diagram of an example robot **100**. The robot **100** may be stationary or mobile. The robot may be, for example, a 5 degree of freedom (DoF) robot, a 6 DoF robot, a 7 DoF robot, an 8 DoF robot, or have another amount of degrees of freedom. In various implementations, the robot **100** may be an autonomous vehicle.

(18) The robot **100** is powered, such as via an internal battery and/or via an external power source, such as alternating current (AC) power. AC power may be received via an outlet, a direct connection, etc. In various implementations, the robot **100** may receive power wirelessly, such as inductively.

(19) The robot **100** may include a plurality of joints **104** and arms **108**. Each arm may be connected between two joints. Each joint may introduce a degree of freedom of movement of an end effector **112** of the robot **100**. The end effector **112** may be, for example, a gripper, a cutter, a roller, or another suitable type of end effector. The robot **100** includes actuators **116** that actuate the arms **108** and the end effector **112**. The actuators **116** may include, for example, electric motors and other types of linear and rotational actuation devices. In vehicles, the actuators **116** may control movement of the vehicle.

(20) A control module **120** controls the actuators **116** and therefore the actuation of the robot **100** using a model **124** that is a neural network model. The control module **120** may, for example, control the application of power to the actuators **116** to control actuation. The model **124** is trained using motion capture data as described below.

(21) The control module **120** may control actuation based on measurements from one or more sensors **128**, such as using feedback and/or feedforward control. Examples of sensors include red green blue (RGB) cameras, position sensors, force sensors, torque sensors, etc. For example, the control module **120** may determine a 3D pose and a shape of a human captured in an image or video from an RGB camera and control actuation based on at least one of the 3D pose and shape of the human. The control module **120** may control actuation additionally or alternatively based on input from one or more input devices **132**, such as one or more touchscreen displays, joysticks, trackballs, pointer devices (e.g., mouse), keyboards, and/or one or more other suitable types of input devices. In vehicles, examples of input devices include a steering wheel, an accelerator pedal, a brake pedal, etc. The control module **120** may control actuation, for example, to avoid colliding with humans in images captured. While the example of humans is discussed herein, the present disclosure is also applicable to other types of animals with joints, such as dogs, cats, etc.

(22) FIG. 2 is a functional block diagram of an example implementation of a training system. A training module **200** trains the model **124** using a training dataset **204**. The training dataset **204** includes motion capture data **208**. The motion capture data **208** includes sequences of measured (ground truth) 3D coordinates of human body parts and do not include any images. The training



dataset **204** may also include real image data **212**, such as images with humans and annotations including 3D pose and shape of the humans in the images. Examples of the real image data **212** include 2D pose estimation datasets like the COCO dataset, the LSP dataset, the LSPE dataset, and the MPII dataset, and/or 3D pose estimation datasets, such as the MPI-INF-3DHP dataset.

(23) The model **124** may include a SPIN model (having a SPIN architecture) as described in Nikos Kolotourous, et al., titled “*Learning to Reconstruct 3D Human Pose and Shape Via Model-Fitting In The Loop*”, ICCV, 2019, also published on arXiv as 1909.12828, on Sep. 27, 2019, which is incorporated herein in its entirety. While the example of the SPIN model will be described, the model **124** may be another suitable type of neural network model. The model **124** is trained to determine a pose of a human in an image (i.e., the localization of human joints in an image). The pose includes 3D positions (x, y, and z) of each joint (or keypoint, e.g., elbows, knees, wrists, etc.) of the human visible in the image. Humans may have, for example, 22 joints (or another suitable number of joints) that can be estimated. In some images, however, one or more joints may not be visible and may therefore not be estimated by the model **124**.

(24) FIG. 3 is a functional block diagram of an example implementation of the model **124**. The model **124** may include a convolutional neural network (CNN) module **304** that receives images. An iterative regressor module **308** iteratively regresses a 3D pose and a shape of a human in the image based on output from the CNN module **304**. The iterative regressor module **308** may also regress one or more parameters (e.g., pose) of the camera used to capture the image. The parameters regressed by the iterative regressor module **308** may be referred to as SMPL parameters, which are discussed in more detail in Matthew Koper, et al., *SMPL: A Skinned Multi-Person Linear Model*, ACM Transactions On Graphics, 2015, which is incorporated herein in its entirety.

(25) FIG. 4 is a functional block diagram of an example implementation of the CNN module **304**. The CNN module **304** includes L residual neural network (ResNet) modules **404** connected in series. L is an integer greater than or equal to one. Each ResNet module **404** includes a convolutional layer (module) **408**. The convolutional layer **408** of the first ResNet module receives an image as input. The convolutional layers of following ResNet modules receive the output of the preceding ResNet module.

(26) Each ResNet module includes one or more batch normalization (norm) layers (modules) **412** that receive output from the convolutional layer **408**. A rectification linear unit (ReLu) module **416** receives output from the batch normalization layer(s) **412**. A convolutional layer (module) **420** receives output from the batch normalization layer(s) **412**. One or more batch normalization (norm) layers (modules) **424** receive output from the convolutional layer **420**. A summation module **428** sums (adds) the input to the convolutional layer **408** with the output of the batch normalization layer(s) **424**. A rectification linear unit (ReLu) module **432** receives output from the summation module **428**.

(27) Before fine tuning (training) the model **124** with the motion capture data **208**, the training module **200** first trains the model **124** using pre-training data **216** (e.g., shown in FIG. 2) that includes RGB (red green blue) images and annotated 2D and/or 3D poses. The fine tuning performed using the motion capture data **208** exposes the model to a more diverse set of poses, viewpoints, textures, and backgrounds and therefore results in the model **124** being more accurate when faced with real world images.

(28) The SPIN model, discussed above which in an embodiment may be included in the model **124**, can be explained as follows and includes a deep convolutional neural network encoder  $f$  that performs feature extraction from cropped images and an iterative regressor  $r$ . Let  $x \in \mathbb{R}^{sup.d}$  in a cropped image input to the model,  $\phi.sub.x = f(x)$  be the extracted feature(s), and  $r(\phi.sub.x) = \{\Theta.sub.x, \Pi.sub.x\}$  be the regressed prediction for the  $d.sub.\theta$ dimensional body model parameters  $\Theta.sub.x$  and  $d.sub.\pi$ dimensional camera parameters  $\Pi.sub.x$ . The regressor  $r$  is initialized with mean pose parameters  $\Theta.sub.mean$  and is run for a number  $N$  of iterations. 6 dimensional (6D)

representations (3D position and 3D orientation) may be used for 3D joint positions.

(29) The training module **200** trains the one or more of the batch normalization layers of the CNN module **304** based on the motion capture data **208**. The training module **200** may fine tune (train) parameters of the batch normalization layer(s), for example, based on minimizing at least one of a shape loss, a 3D keypoint loss, and a re-projection loss. Known reference data is stored for each piece of training data. The output of the model **124** generated based on an image is compared to the known reference data for the image to determine the loss(es).

(30) After the pre-training using the pre-training data **216**, the training module **200** samples (e.g., randomly) from the motion capture data **208** and the real image data **212** to further train the model **124**. In various implementations the motion capture data **208** used to train the model **124** may be or include the AMASS (Archive of Motion Capture as Surface Shapes) dataset. The AMASS dataset is described in Naureen Mahmood, et al., *AMASS: Archive of Motion Capture As Surface Shapes*, ICCV, 2019.

(31) The training module **200** synthesizes some of the selected samples, such as by at least one of changing a viewpoint, changing a background, and changing texturing of a human in the sample. FIG. 5 includes examples of synthesized (synthetic) samples. For example, the top row in FIG. 5 includes one example sample of a human body from a sample of the motion capture data **208** illustrated in the left most image in the top row. The images to the right in the top row of FIG. 5 are different synthetic images produced from the left most image, such as by changing a viewpoint, changing a background, or changing texturing of the human.

(32) The bottom row of FIG. 5 includes pairs of images. Each pair of images includes a real image (on left) from the real image data **212** and a synthetic image (on right) generated based on the real image by the training module **200**. The training module **200** may, for example as shown in pairs of images in the bottom row of FIG. 5, change a background or a texture of a human in the real image (on left) to generate a synthetic image (on right). The training module **200** trains (fine tunes) the model **124** using synthetic images generated based on the motion capture data **208** (e.g., top row of FIG. 5), real images from the real image data **212**, and synthetic images generated based on the real image data **212** (e.g., bottom row of FIG. 5).

(33) Fine tuning the model **124** using only synthetic data (after the pre-training) may decrease performance of the model **124** due to the synthetic/real data domain shift. The training module **200** therefore fine tunes the model **124** using batches that include both real images from the real image data **212** from the pre-training and synthetic images generated from samples of the motion capture data **208**. The weights of the model **124** may be initialized to predetermined values and direct supervision may be used: for synthetic images, the corresponding ground-truth parameters from the motion capture data **208** may be used; and for real images, the parameters output from the model **124** for the real images after the pre-training may be used.

(34) Regarding rendering synthetic humans/images, to generate a human in a given pose, the training module **200** renders the SMPL model with a texture selected (e.g., randomly or in a predetermined order) from a texture dataset **220**, and with a background image selected (e.g., randomly or in a predetermined order) from a background image dataset **224**. Examples of synthetic renderings are illustrated in the top row of FIG. 5 with the left most image of the top row being a SMPL model generated based on a sample of the motion capture data **208**.

(35) Camera 3D orientation may be sampled considering a Tait-Bryan parameterization (e.g.,  $\pm 180$  degrees yaw,  $\pm 45$  degrees pitch,  $\pm 15$  degrees roll, with yaw and roll axes horizontal when considering the identity rotation). This may model typical variability observed in the real data. The synthetic images/samples and the real images may be cropped by the training module **200** around the human in the image based on the location of 2D joints of the model. The fact that the entire human may not always be visible in the real images may be accounted for by cropping only upper body keypoints at the knees or hips in a predetermined portion (e.g., 20%) of the samples used. Examples of such croppings are illustrated in the top row of FIG. 5. The synthetic renderings from

the real image data **212** may be generated by the training module **200** in the same way. Example pairs of real images and synthetic images generated from the real images are presented in the bottom row of FIG. 5.

(36) FIG. 6 is a flowchart depicting an example method of training the model **124**. Control begins with **604** where the training module **200** sets a counter value (I) equal to 1. At **608**, the training module **200** selects a sample from the training dataset **204**, such as from the motion capture data **208** or the real image data **212**. At **612**, the training module **200** selectively synthesizes the selected sample.

(37) Some selected samples may be made synthetic before being input to the model **124**, and some samples from the real image data **212** may be input to the model **124** without being synthesized. The training module **200** may, for example, synthesize a sample by selecting a texture from the texture dataset **220** and/or selecting a background from the background image dataset **224** and applying the selections to the selected sample. The training module **200** may also crop the sample as described above. The training module **200** inputs the sample to the model **124**.

(38) At **616**, the training module **200** receives the output of the model **124** generated based on the input. At **620**, the training module **200** determines whether the counter value I is equal to a predetermined number, such as 1,000 or another suitable number. If **620** is false, the training module **200** increments the counter value I by 1 at **624** (set  $I=I+1$ ) and control returns to **608**. If **620** is true, the training module **200** determines the losses (e.g., SMPL shape loss, 3D keypoint loss, 2D keypoint re-projection loss) based on the outputs of the model **124** and the associated annotations in the training dataset **204**. The training module **200** fine tunes the model **124** based on minimizing the losses at **628**. More specifically, the training module **200** fine tunes (adjusts) parameters of the batch normalization layer(s) of the model **124**.

(39) While the example of FIG. 6 is illustrated as ending, the example of FIG. 6 may be performed multiple times, such as a predetermined number of times or until one or more predetermined conditions occur (e.g., the losses are less than predetermined values).

(40) FIG. 7 includes an example pose determination system of the model **124** that determines poses of humans in sequences (time series) of images (e.g., video). The model **124** may include a bidirectional encoder representations from transformers (BERT) architecture. A linear layer (module) **704** receives a time series of T vectors (for T images) corresponding to a temporal sequence of poses of length T. T is an integer greater than 1.

(41) An embedding module **708** embeds the output of the linear layer **704** using an embedding algorithm. Embedding may also be referred to as encoding. A summation module **712** adds positional encodings from a position encoding module **716** to the output of the embedding module **708**. For example, the summation module **712** may concatenate the positional encodings on to a vector output of the input embedding module **708**. A pose module **720** determines poses of humans in the T images based on the output of the summation module **712** and a mean pose in the T images based on an output of a mean pose module **724** that determines the mean (average) pose.

(42) FIG. 8 is a functional block diagram of the pose module **720**. The pose module includes L blocks (layers) **804** connected in series. L is an integer greater than or equal to 1. The first one of the blocks **804** receives the output of the summation module **712**. The second block receives feature vectors output from the previous block, etc. Each block includes a multi-head scaled dot product attention mechanism that generates output for regressor modules of that block. Regressor parameters are shared across the T inputs.

(43) Linear layers (modules) **808** of a block **804** generate key (K), query (Q), and values (V) vectors based on their inputs. Matmul, scale, and softmax modules **812** apply a matmul function on the key and query values, scale the result, and apply a softmax after the scaling. Matmul and concatenation modules **816** apply a matmul function on the output of the matmul, scale, and softmax modules **812** and concatenate the result with the values to generate feature vectors.

(44) Regressor modules **820** attend to parts of the input sequence and directly regress the SMPL



(54) The percentage of synthetic renderings in each batch of training data used may impact accuracy of the trained model. FIG. 11 includes an example graph of percentage of motion capture data used in each batch during training versus MPJPE for different datasets. The average (Average) is also plotted. As illustrated, a U-shaped curve appears on all datasets as the percentage of synthetic data increases meaning that an optimal value is not an extreme value (i.e., neither only real data nor only synthetic data). 50 percent synthetic data may provide a good compromise.

(55) Regarding the example of FIG. 7, PA-MPJPE on three datasets is reported in Table 2 below. 12.5% of the input poses were masked. Table 3 illustrates that the example of FIG. 7 consistently provides a gain of 1 to 3 millimeters (mm) on all datasets. Removing the positional encoding may lead to decreased performance, indicating that incorporating temporal information within the model is key to improved accuracy. Sharing the regressor allows for a reduction in the number of learnable parameters and provides better predictions. Iteration over the regressor only a single time after each layer may be performed given that more iterations may not provide an improvement and may even decrease performance.

(56) As illustrated by Table 2, the number of blocks (L) of the example of FIG. 7 may be 4 to perform suitably, and an embedding dimension of  $D_t=512$  may be used. Increasing the model complexity may provide only minimal improvements. For temporal length of training sequences, T may be equal to 16 as longer sequence may not provide further improvements.

(57) TABLE-US-00002

TABLE 2	MPI-INF	MuPoTS	3DPW	3DHP	3D	MoCap-SPIN
55.6	66.7	81.0	MoCap-SPIN + 53.2	63.8	80.3	PoseBERT w/o pos. encoding 54.8
64.0	65.0	81.0	with 2 regressor iterations 53.3	64.0	80.5	with 4 regressor iterations 53.4
64.2	80.5	L = 1 54.5	67.0	81.2	L = 2 53.9	65.5
81.0	L = 4 (default) 53.2	63.8	80.3	L = 8 53.4	63.3	80.2
D.sub.t = 128 55.6	69.4	82.0	D.sub.t = 256 53.7	64.0	80.4	D.sub.t = 512 (default) 53.2
63.8	80.3	D.sub.t = 1024 53.4	62.9	80.3	T = 8 53.9	65.2
80.2	T = 16 (default) 53.2	63.8	80.3	T = 32 53.4	63.6	8.3
T = 64 53.3	63.7	80.4				

(58) Masking 12.5% of the samples (e.g., 2 frames out of 16) provides a smoother prediction with lower acceleration while PA-MPJPE remains low. The addition of noise also provides an increase in performance and smoother predictions. Table 3 below illustrates test results for different levels of masking with and without noise.

(59) TABLE-US-00003

TABLE 3	3DPW	MPI-INF	3DHP	MuPoTS	3D	Masking %	$\epsilon \downarrow$	Accel $\downarrow$	$\epsilon \downarrow$	Accel $\downarrow$
MoCap-SPIN 55.6	32.5	66.7	29.5	81.0	23.5	0%	53.3	9.6	62.3	9.8
12.5% 53.2	7.8	63.8	8.7	80.3	12.8	25%	53.3	8.3	64.2	9.0
80.3	13.3	37.5%	53.9	9.0	65.0	9.2	80.8	14.0	12.5% + Noise 52.9	7.8
63.3	8.7	80.2	12.9							

(60) The example of FIG. 7 may be used on top of any image based model to transform it into a video based posed estimation model. Table 4 below illustrates test results on different datasets when the example of FIG. 7 is used with an image based model (including the example of FIG. 4).

(61) TABLE-US-00004

TABLE 4	MPI-INF	MyPoTS	3DPW	3DHP	3D	AIST	SPIN +
59.6	68.0	83.0	71.8	PoseBERT 58.2	( $\downarrow 1.4$ )	64.3	( $\downarrow 3.7$ )
81.7	( $\downarrow 1.3$ )	70.2	( $\downarrow 1.6$ )	VIBE + 56.5	65.4	83.4	71.8
PoseBERT 54.9	( $\downarrow 1.6$ )	64.4	( $\downarrow 1.0$ )	82.6	( $\downarrow 0.8$ )	70.3	( $\downarrow 1.5$ )
MoCAP-SPIN + 55.6	66.7	81.0	71.6	PoseBERT 53.2	( $\downarrow 2.4$ )	63.8	( $\downarrow 2.9$ )
80.3	( $\downarrow 0.7$ )	69.7	( $\downarrow 1.9$ )				

(62) Table 4 above illustrates that the example of FIG. 7 provides improvements relative to the image based model on different datasets.

(63) The foregoing description is merely illustrative in nature and is in no way intended to limit the disclosure, its application, or uses. The broad teachings of the disclosure can be implemented in a variety of forms. Therefore, while this disclosure includes particular examples, the true scope of the disclosure should not be so limited since other modifications will become apparent upon a study of the drawings, the specification, and the following claims. It should be understood that one or more steps within a method may be executed in different order (or concurrently) without altering the principles of the present disclosure. Further, although each of the embodiments is described above as having certain features, any one or more of those features described with respect to any

embodiment of the disclosure can be implemented in and/or combined with features of any of the other embodiments, even if that combination is not explicitly described. In other words, the described embodiments are not mutually exclusive, and permutations of one or more embodiments with one another remain within the scope of this disclosure.

(64) Spatial and functional relationships between elements (for example, between modules, circuit elements, semiconductor layers, etc.) are described using various terms, including “connected,” “engaged,” “coupled,” “adjacent,” “next to,” “on top of,” “above,” “below,” and “disposed.” Unless explicitly described as being “direct,” when a relationship between first and second elements is described in the above disclosure, that relationship can be a direct relationship where no other intervening elements are present between the first and second elements, but can also be an indirect relationship where one or more intervening elements are present (either spatially or functionally) between the first and second elements. As used herein, the phrase at least one of A, B, and C should be construed to mean a logical (A OR B OR C), using a non-exclusive logical OR, and should not be construed to mean “at least one of A, at least one of B, and at least one of C.”

(65) In the figures, the direction of an arrow, as indicated by the arrowhead, generally demonstrates the flow of information (such as data or instructions) that is of interest to the illustration. For example, when element A and element B exchange a variety of information but information transmitted from element A to element B is relevant to the illustration, the arrow may point from element A to element B. This unidirectional arrow does not imply that no other information is transmitted from element B to element A. Further, for information sent from element A to element B, element B may send requests for, or receipt acknowledgements of, the information to element A.

(66) In this application, including the definitions below, the term “module” or the term “controller” may be replaced with the term “circuit.” The term “module” may refer to, be part of, or include: an Application Specific Integrated Circuit (ASIC); a digital, analog, or mixed analog/digital discrete circuit; a digital, analog, or mixed analog/digital integrated circuit; a combinational logic circuit; a field programmable gate array (FPGA); a processor circuit (shared, dedicated, or group) that executes code; a memory circuit (shared, dedicated, or group) that stores code executed by the processor circuit; other suitable hardware components that provide the described functionality; or a combination of some or all of the above, such as in a system-on-chip.

(67) The module may include one or more interface circuits. In some examples, the interface circuits may include wired or wireless interfaces that are connected to a local area network (LAN), the Internet, a wide area network (WAN), or combinations thereof. The functionality of any given module of the present disclosure may be distributed among multiple modules that are connected via interface circuits. For example, multiple modules may allow load balancing. In a further example, a server (also known as remote, or cloud) module may accomplish some functionality on behalf of a client module.

(68) The term code, as used above, may include software, firmware, and/or microcode, and may refer to programs, routines, functions, classes, data structures, and/or objects. The term shared processor circuit encompasses a single processor circuit that executes some or all code from multiple modules. The term group processor circuit encompasses a processor circuit that, in combination with additional processor circuits, executes some or all code from one or more modules. References to multiple processor circuits encompass multiple processor circuits on discrete dies, multiple processor circuits on a single die, multiple cores of a single processor circuit, multiple threads of a single processor circuit, or a combination of the above. The term shared memory circuit encompasses a single memory circuit that stores some or all code from multiple modules. The term group memory circuit encompasses a memory circuit that, in combination with additional memories, stores some or all code from one or more modules.

(69) The term memory circuit is a subset of the term computer-readable medium. The term computer-readable medium, as used herein, does not encompass transitory electrical or electromagnetic signals propagating through a medium (such as on a carrier wave); the term

computer-readable medium may therefore be considered tangible and non-transitory. Non-limiting examples of a non-transitory, tangible computer-readable medium are nonvolatile memory circuits (such as a flash memory circuit, an erasable programmable read-only memory circuit, or a mask read-only memory circuit), volatile memory circuits (such as a static random access memory circuit or a dynamic random access memory circuit), magnetic storage media (such as an analog or digital magnetic tape or a hard disk drive), and optical storage media (such as a CD, a DVD, or a Blu-ray Disc).

(70) The apparatuses and methods described in this application may be partially or fully implemented by a special purpose computer created by configuring a general purpose computer to execute one or more particular functions embodied in computer programs. The functional blocks, flowchart components, and other elements described above serve as software specifications, which can be translated into the computer programs by the routine work of a skilled technician or programmer.

(71) The computer programs include processor-executable instructions that are stored on at least one non-transitory, tangible computer-readable medium. The computer programs may also include or rely on stored data. The computer programs may encompass a basic input/output system (BIOS) that interacts with hardware of the special purpose computer, device drivers that interact with particular devices of the special purpose computer, one or more operating systems, user applications, background services, background applications, etc.

(72) The computer programs may include: (i) descriptive text to be parsed, such as HTML (hypertext markup language), XML (extensible markup language), or JSON (JavaScript Object Notation) (ii) assembly code, (iii) object code generated from source code by a compiler, (iv) source code for execution by an interpreter, (v) source code for compilation and execution by a just-in-time compiler, etc. As examples only, source code may be written using syntax from languages including C, C++, C#, Objective-C, Swift, Haskell, Go, SQL, R, Lisp, Java®, Fortran, Perl, Pascal, Curl, OCaml, Javascript®, HTML5 (Hypertext Markup Language 5th revision), Ada, ASP (Active Server Pages), PHP (PHP: Hypertext Preprocessor), Scala, Eiffel, Smalltalk, Erlang, Ruby, Flash®, Visual Basic®, Lua, MATLAB, SIMULINK, and Python®.

## Claims

1. A training system comprising: a neural network model configured to determine three-dimensional coordinates of joints, respectively, representing poses of animals in images, wherein the neural network model is trained using a first training dataset including: images including animals; and coordinates of joints of the animals in the images, respectively; and a training module configured to, after the training of the neural network model using the first training dataset, train the neural network model using a second training dataset including motion capture data, wherein the motion capture data does not include images of animals and includes measured coordinates at points, respectively, on animals, wherein the neural network model includes batch normalization layers, and wherein the training module is configured to, after the training of the neural network model using the first training dataset, train the neural network model by adjusting only parameters of the batch normalization layers and maintaining all other parameters of all other portions of the neural network model constant after the training of the neural network model using the first training dataset, wherein the training module is configured to, after the training of the neural network model using the first dataset, train the neural network model using texturized body models of animals with backgrounds applied.

2. The training system of claim 1 wherein the training module is configured to, after the training of the neural network model using the first training dataset, train the neural network model further using data from the first training dataset.

3. The training system of claim 2 wherein the training module is configured to generate the

texturized body models of animals with backgrounds applied by: rendering body models of animals based on the motion capture data; texturizing the body models using textures from a texture dataset; and apply backgrounds to the body models from a background dataset.

4. The training system of claim 3 wherein the training module is further configured to selectively: render second models of the animals in the images using the coordinates of the joints of the animals, respectively; texturize the second models using textures from the texture dataset; apply second backgrounds to the models from the background dataset; and train the neural network model using the texturized second models with the second backgrounds.

5. The training system of claim 1 wherein the model is the SPIN model.

6. The training system of claim 1 wherein the motion capture data in the second training dataset includes motion capture data from the AMASS dataset.

7. A system, comprising: a neural network model configured to determine three-dimensional coordinates of joints, respectively, representing a pose of an animal in an image, wherein the neural network model is trained using: a first training dataset including: images including animals; and coordinates of joints of the animals in the images, respectively; and a second training dataset including motion capture data that: does not include images of animals; and includes measured coordinates at points, respectively, on animals; wherein the neural network model includes batch normalization layers, and wherein the neural network model is trained by adjusting only parameters of the batch normalization layers and maintaining all other parameters of all other portions of the neural network model constant after the training of the neural network model using the first training dataset; and a camera configured to capture images; and a control module configured to selectively actuate an actuator based on three-dimensional coordinates of joints representing a pose of an animal determined by the neural network model based on an image captured by the camera, wherein the neural network model is further trained based on texturized body models of animals with generated backgrounds.

8. A training system, comprising: a neural network model configured to determine three-dimensional coordinates of joints, respectively, representing poses of animals in sequences of images; a training module configured to train the neural network model using a training dataset including sets of time series of motion capture data, wherein the motion capture data does not include images of animals and includes measured coordinates at points, respectively, on animals, wherein the training module is configured to render a time series of body models of animals based on one of the sets of time series of motion capture data; and a masking module configured to replace a first predetermined percentage of the body models in the time series of body models with different body models of animals, wherein the training module is configured to train the neural network model based on outputs of the neural network model generated in response to the time series of body models.

9. The training system of claim 8 wherein the training module is configured to: texturize the body models using textures from a texture dataset; apply backgrounds to the body models from a background dataset; and train the neural network model using the texturized body models with the backgrounds.

10. The training system of claim 9 wherein the masking module is further configured to replace at least one of the body models in the time series of models with a predetermined masking token.

11. The training system of claim 10 wherein the masking module is configured to replace a second predetermined percentage of the body models in the time series of body models with a predetermined masking token.

12. The training system of claim 11 wherein the second predetermined percentage is approximately 12.5 percent.

13. The training system of claim 9 further comprising a noise module configured to add noise to at least one of the body models in the time series of body models.

14. The training system of claim 13 wherein the noise includes Gaussian noise.



15. The training system of claim 9 further comprising a position encoding module configured to add positional encodings to the time series of body models.

16. The training system of claim 9 wherein the training module is configured to train the neural network model based on minimizing a pose loss determined based on differences between: three-dimensional coordinates determined by the neural network model based on the time series of body models of animals; and coordinates of the motion capture data stored in the training dataset.

17. The training system of claim 9 wherein the training module is configured to train the neural network model based on minimizing a three-dimensional keypoint loss determined based on differences between: three-dimensional coordinates determined by the neural network model based on the time series of body models of animals; and coordinates of the motion capture data stored in the training dataset.

18. A system, comprising: a neural network model configured to determine three-dimensional coordinates of joints, respectively, representing poses of animals, wherein the neural network model is trained using a training dataset including motion capture data that: does not include images of animals; and includes measured coordinates at points, respectively, on animals; and wherein the neural network model includes batch normalization layers, and wherein the neural network model is trained by adjusting only parameters of the batch normalization layers and maintaining all other parameters of all other portions of the neural network model constant after the training of the neural network model using the training dataset; a camera configured to capture time series of images; and a control module configured to selectively actuate an actuator based on three-dimensional coordinates of joints representing a pose of an animal determined by the neural network model based on a time series of images captured by the camera, wherein the neural network model is further trained based on texturized body models of animals with generated backgrounds.

19. A training method comprising: training, using a first training dataset, a neural network model to determine three-dimensional coordinates of joints, respectively, representing poses of animals in images, the first training dataset including: images including animals; and coordinates of joints of the animals in the images, respectively; and after the training of the neural network model using the first training dataset, training the neural network model using a second training dataset including sets of time series of motion capture data, wherein the motion capture data does not include images of animals and includes measured coordinates at points, respectively, on animals, wherein the training the neural network using the second training dataset includes: rendering a time series of body models of animals based on one of the sets of time series of motion capture data; replacing a first predetermined percentage of the body models in the time series of models with different body models of animals; and training the neural network model based on outputs of the neural network model generated in response to the time series of body models.

20. A method, comprising: using a neural network model, determining three-dimensional coordinates of joints, respectively, representing a pose of an animal in an image, wherein the neural network model is trained using: a first training dataset including: images including animals; and coordinates of joints of the animals in the images, respectively; and a second training dataset including motion capture data that: does not include images of animals; and includes measured coordinates at points, respectively, on animals, wherein the neural network model includes batch normalization layers, and the neural network model is trained by adjusting only parameters of the batch normalization layers and maintaining all other parameters of all other portions of the neural network model constant after the training of the neural network model using the first training dataset; and capturing images using a camera; and selectively actuating an actuator based on three-dimensional coordinates of joints representing a pose of an animal determined by the neural network model based on an image captured by the camera, wherein the neural network model is further trained based on texturized body models of animals with generated backgrounds.

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