

# Learning to Track: Online Multi-Object Tracking by Decision Making

Yu Xiang<sup>1,2</sup>, Alexandre Alahi<sup>1</sup>, and Silvio Savarese<sup>1</sup>

<sup>1</sup>Stanford University, <sup>2</sup>University of Michigan

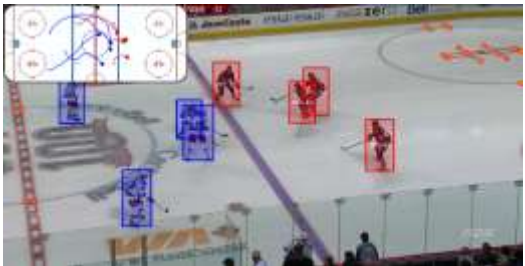
ICCV 2015



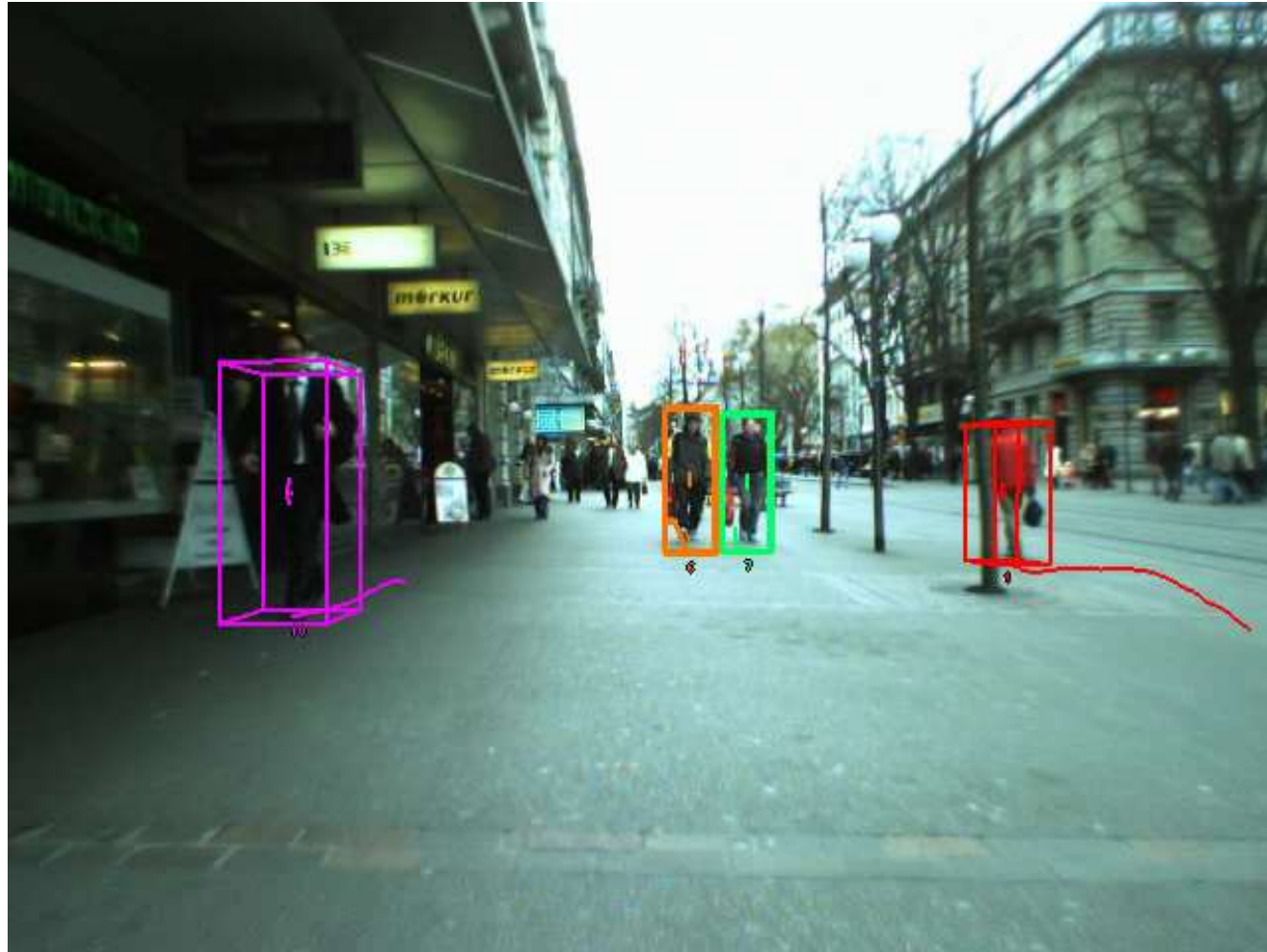
# Multi-Object Tracking



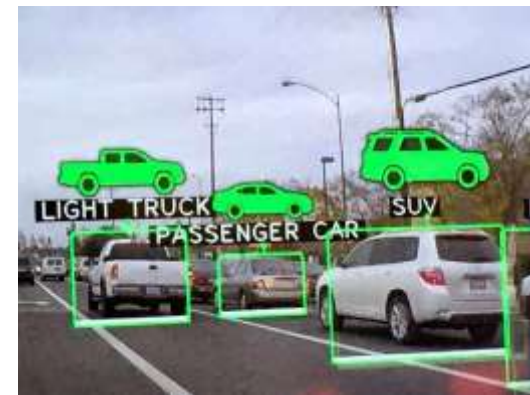
Visual surveillance



Sport Analysis



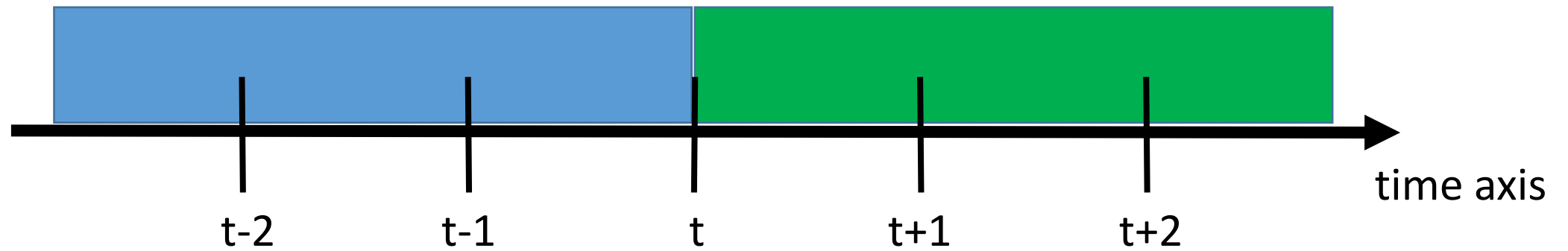
Robot navigation



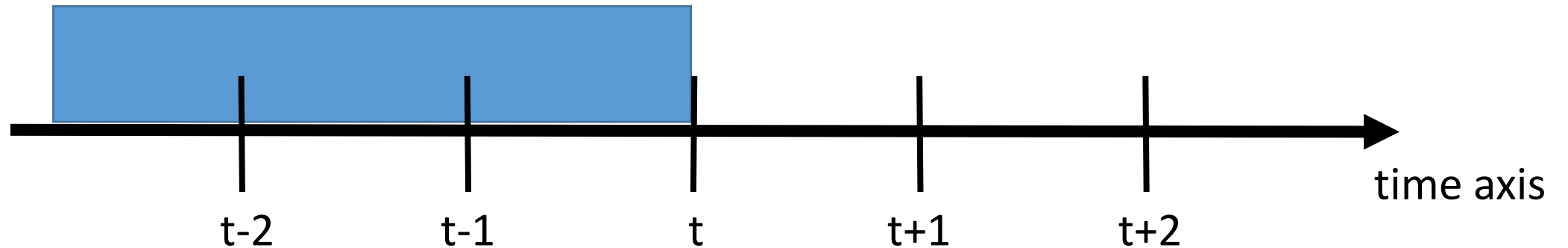
Autonomous driving

# Batch Mode vs. Online Mode

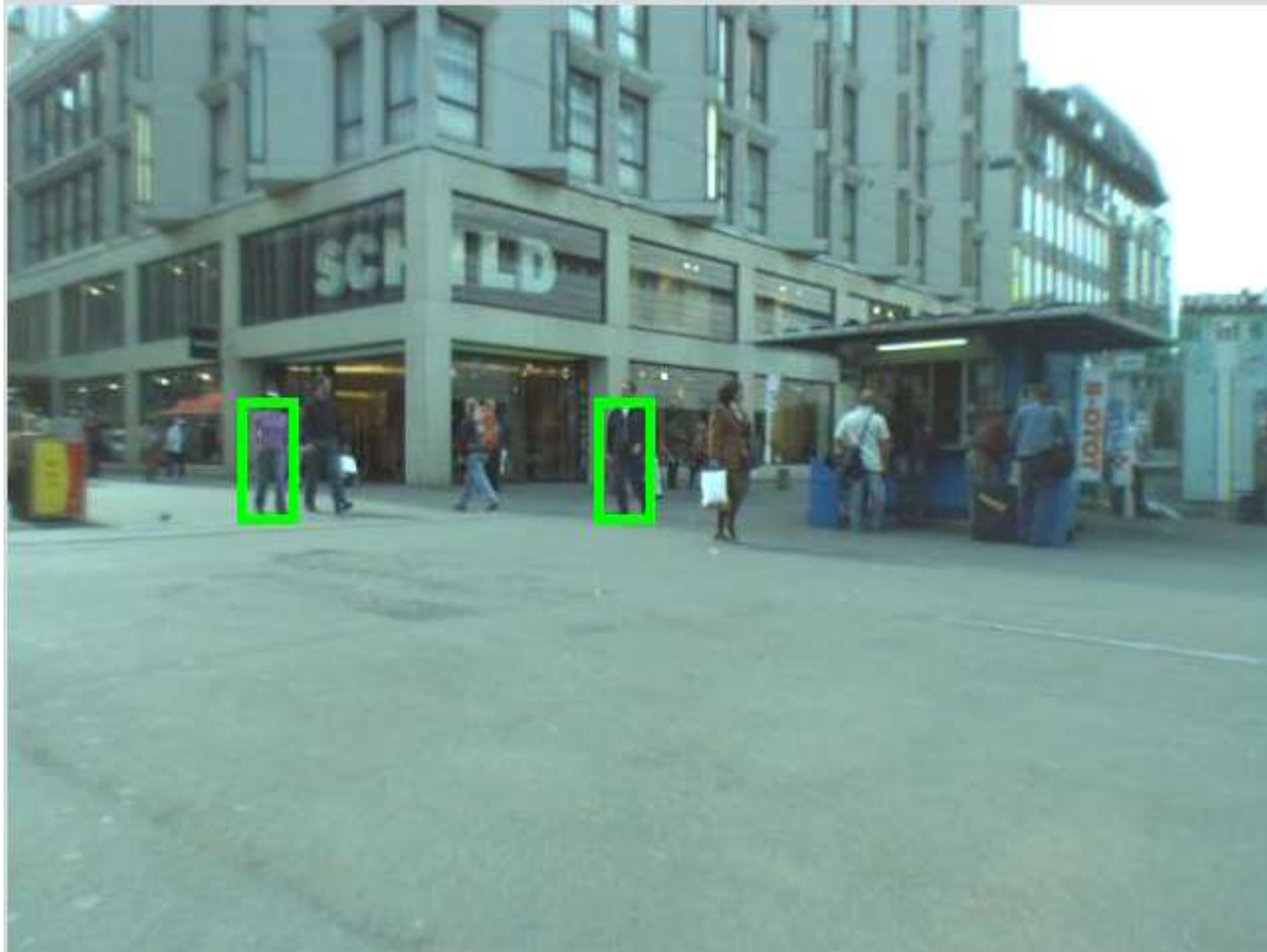
- Batch Mode



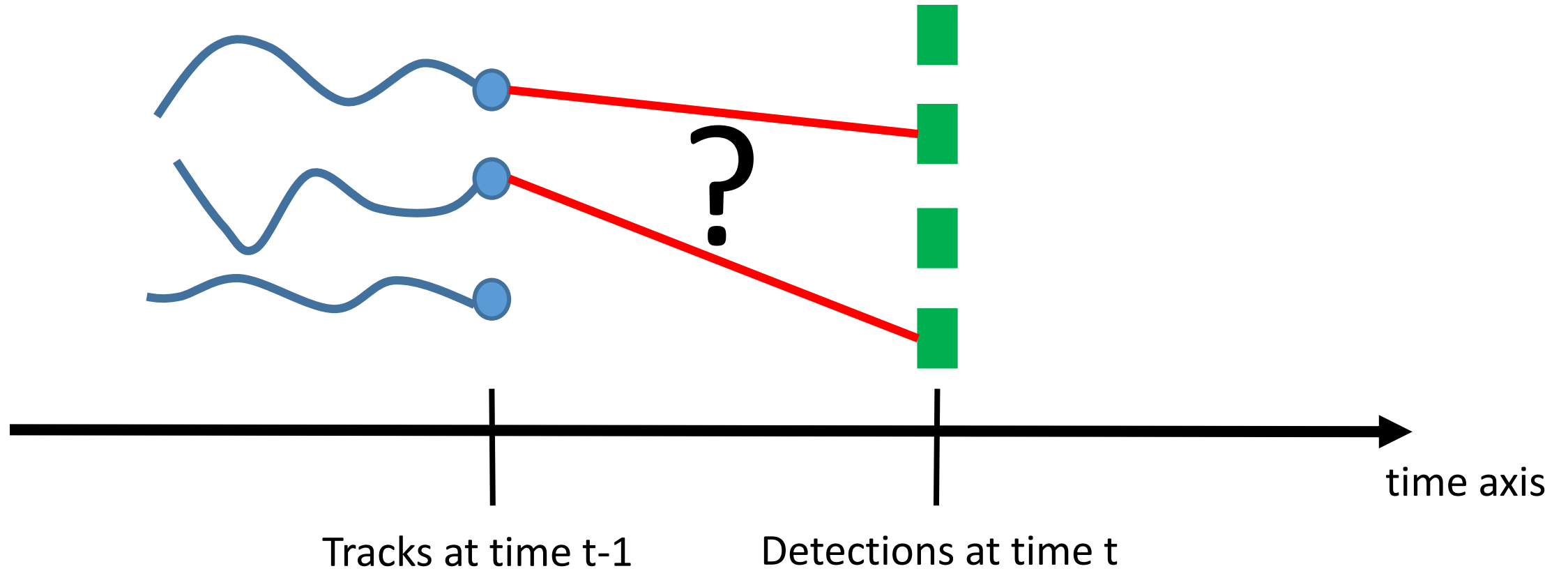
- Online Mode



# Tracking by Detection

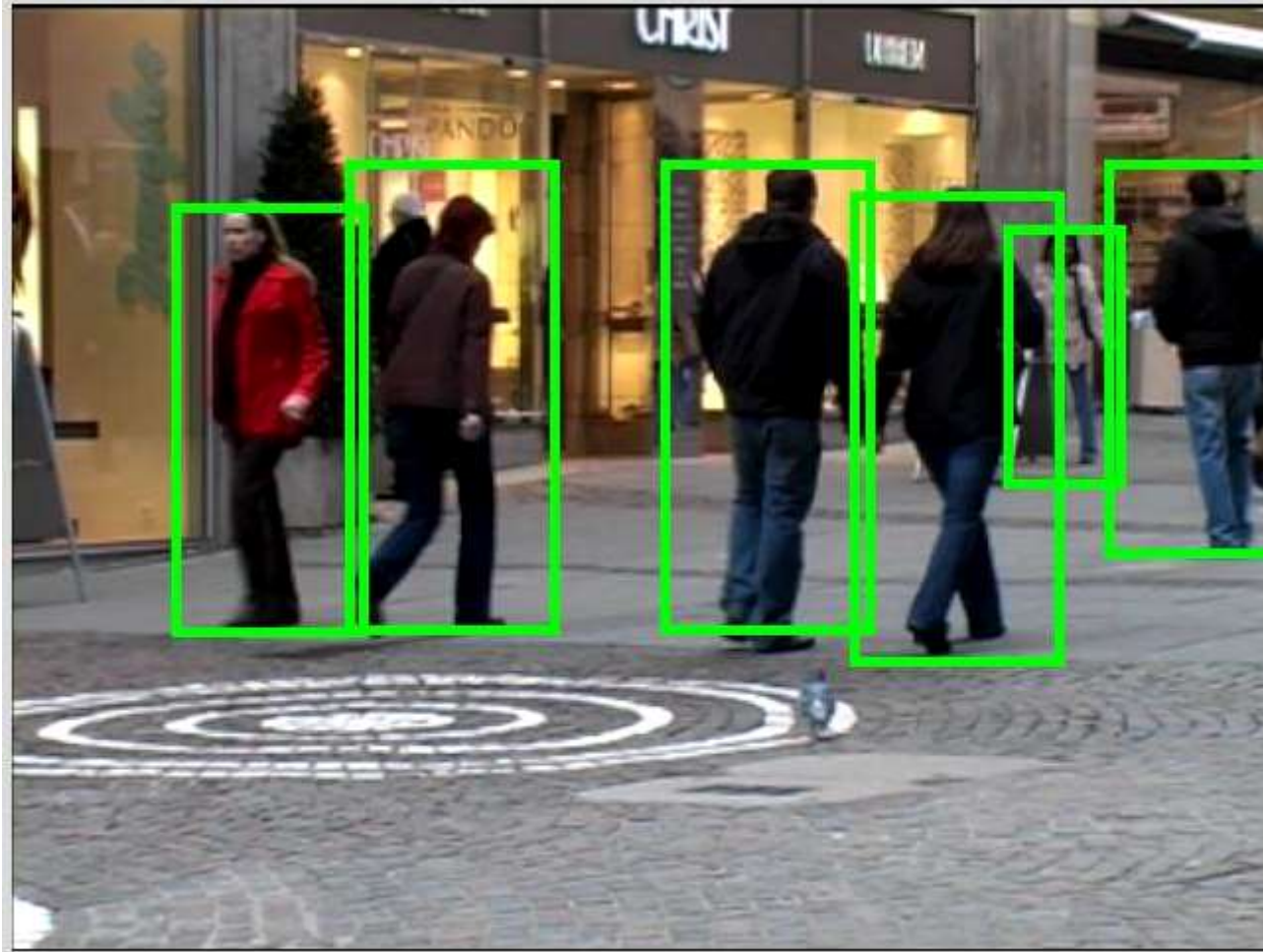


# Data Association





# Challenges



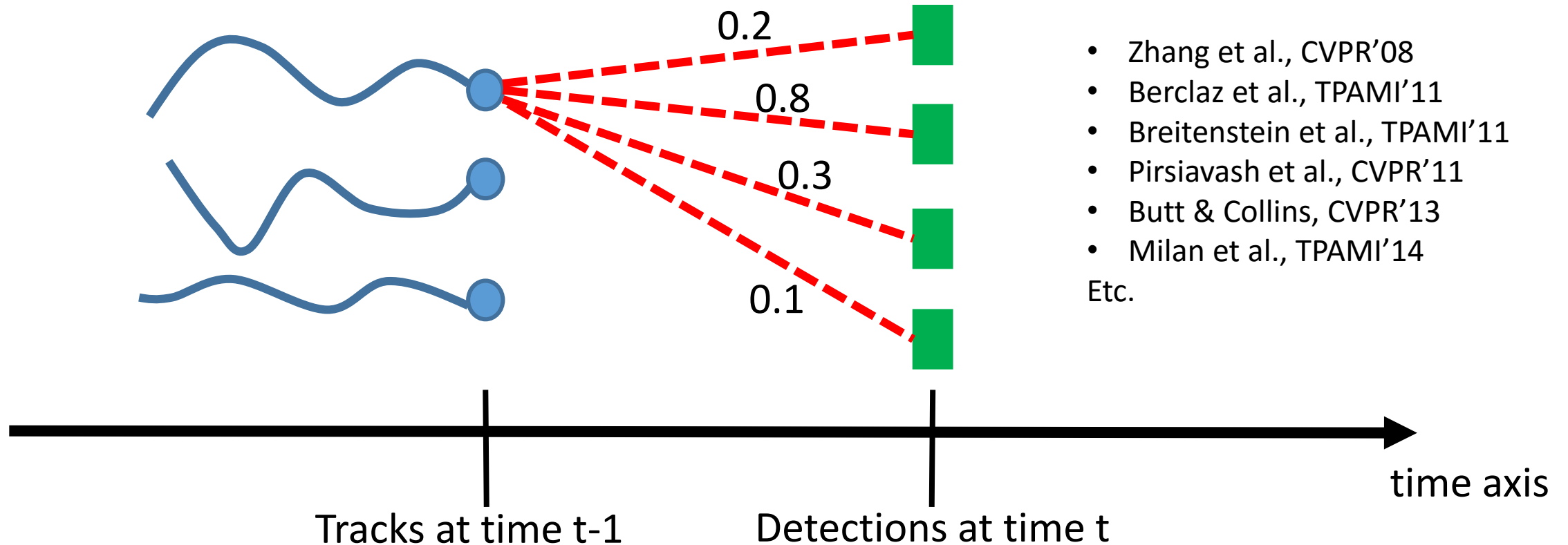
Noisy detection: false alarms and missing detections

# Challenges



Occlusion

# Similarity Function for Data Association

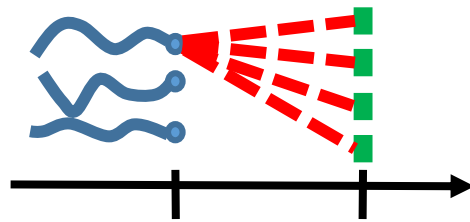


Ours

**Simple** similarity measure + **Powerful** optimization



# Learning to Track



Different features/cues between targets and detections

- Appearance
- Location
- Motion
- Etc.

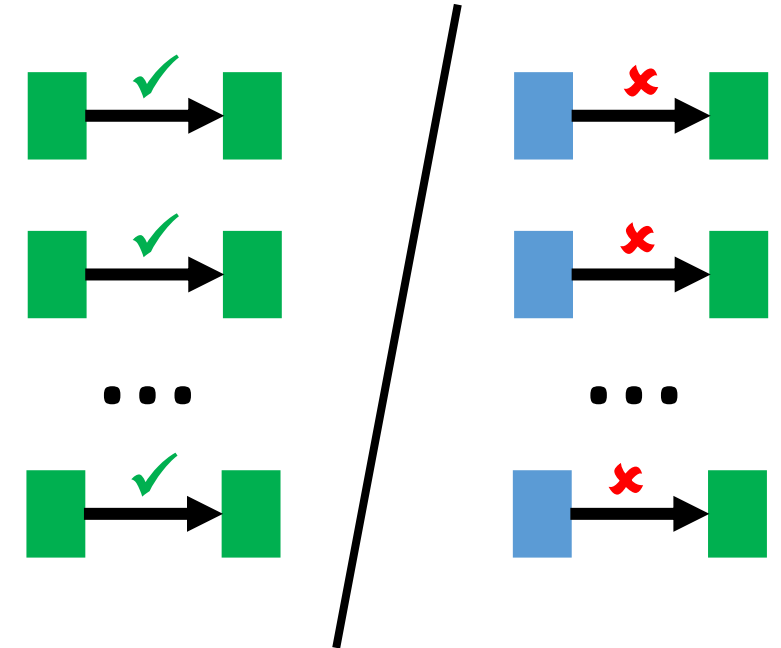
$$\text{Similarity} = w_1 \phi_1(\text{blue wavy line}, \text{green square}) + \dots + w_n \phi_n(\text{blue wavy line}, \text{green square})$$

Weights to combine different cues  
(to be learned)

# Offline-learning vs. Online-learning

# Offline-learning vs. Online-learning

	Offline-learning
Training time	Before Tracking
With supervision	✓
Use history of the target	✗



- Li et al., CVPR'09
  - Kim et al., ACCV'12
- Etc.

# Offline-learning vs. Online-learning

	Offline-learning	Online-learning
Training time	Before Tracking	During Tracking
With supervision	✓	✗
Use history of the target	✗	✓

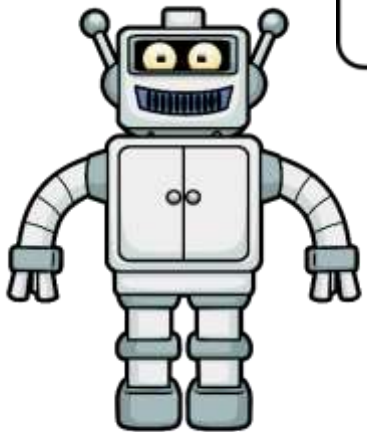


- Song et al., ECCV'08
  - Kuo et al., CVPR'10
  - Bae et al., CVPR'14
- Etc.

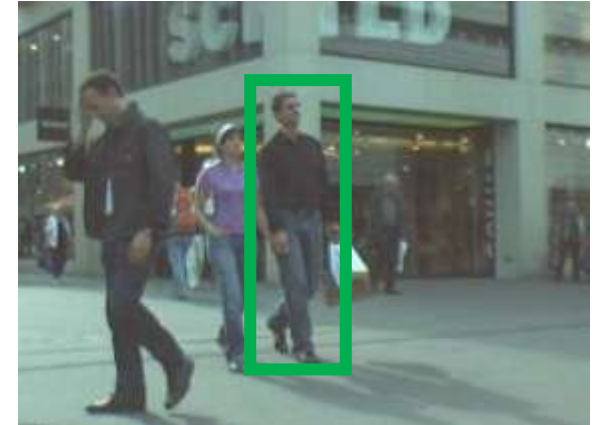
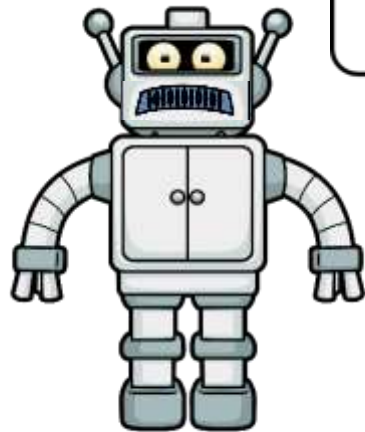
# Our Solution: Tracking by Decision Making



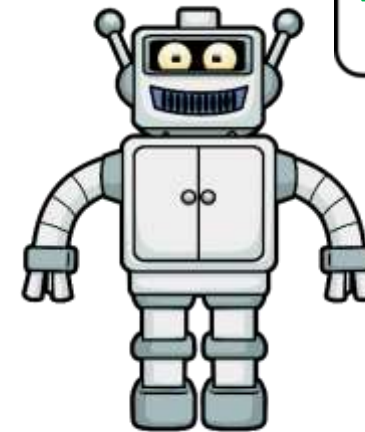
The target is  
tracked



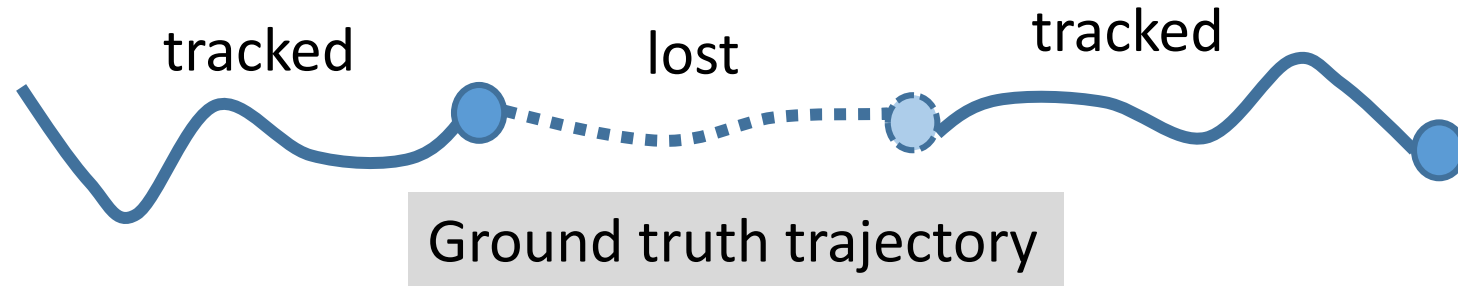
The target is  
occluded



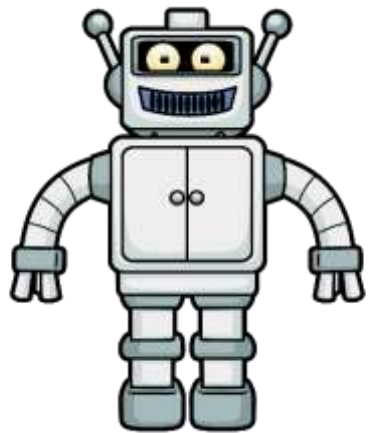
The target is  
tracked again



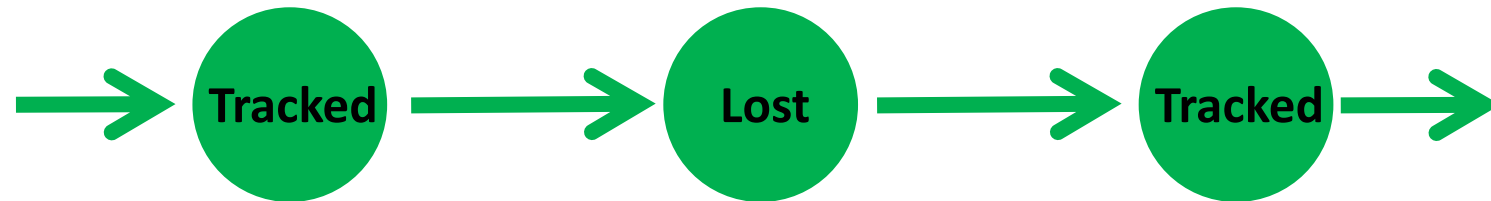
# Inverse Reinforcement Learning



Supervision



Markov  
Decision  
Process  
(MDP)



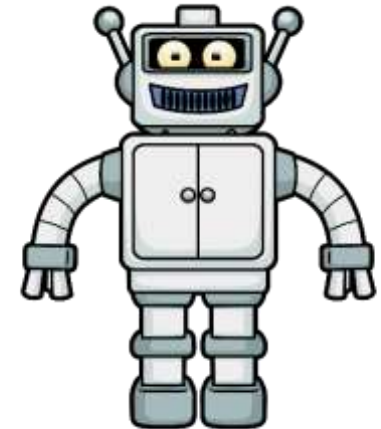


# Comparison between Different Learning Strategies

	Offline-learning	Online-learning
Training time	Before Tracking	During Tracking
With supervision	✓	✗
Use history of the target	✗	✓

# Comparison between Different Learning Strategies

	Offline-learning	Online-learning	Ours
Training time	Before Tracking	During Tracking	Before Tracking
With supervision	✓	✗	✓
Use history of the target	✗	✓	✓



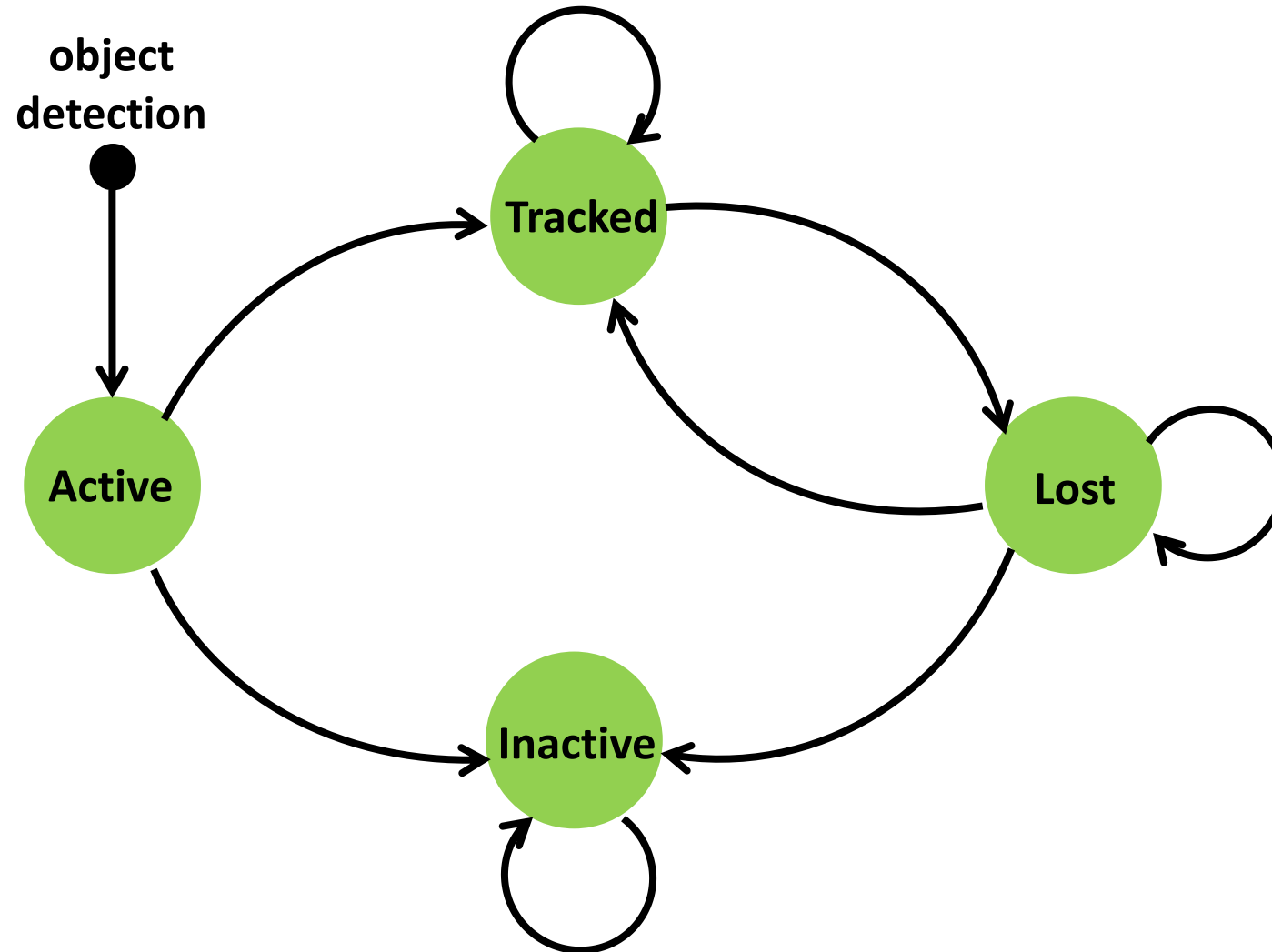
# Outline

- Markov Decision Process (MDP) for a Single Target
- Online Multi-Object Tracking with MDPs
- Experiments
- Conclusion

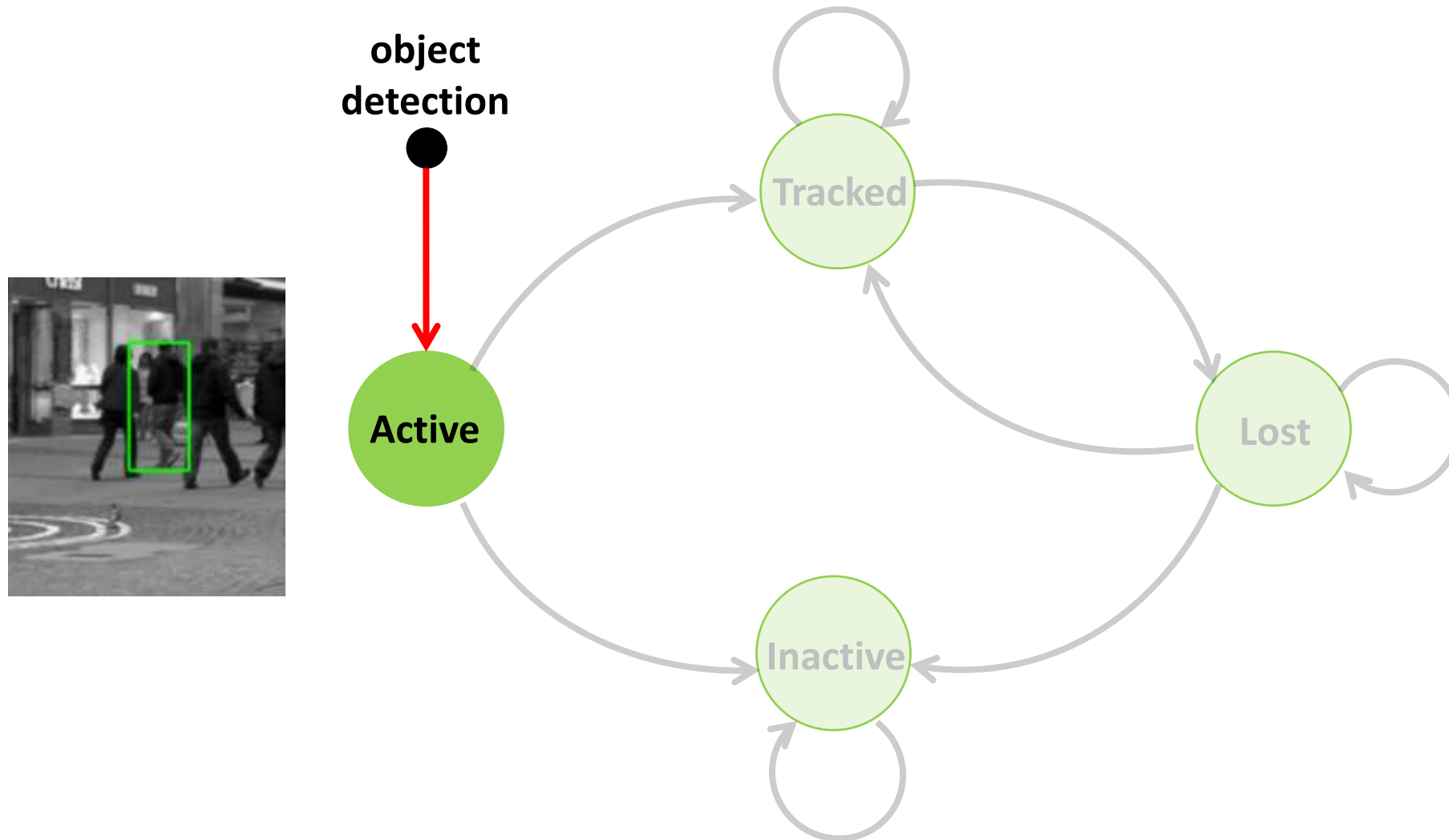
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# Markov Decision Process for a Single Target

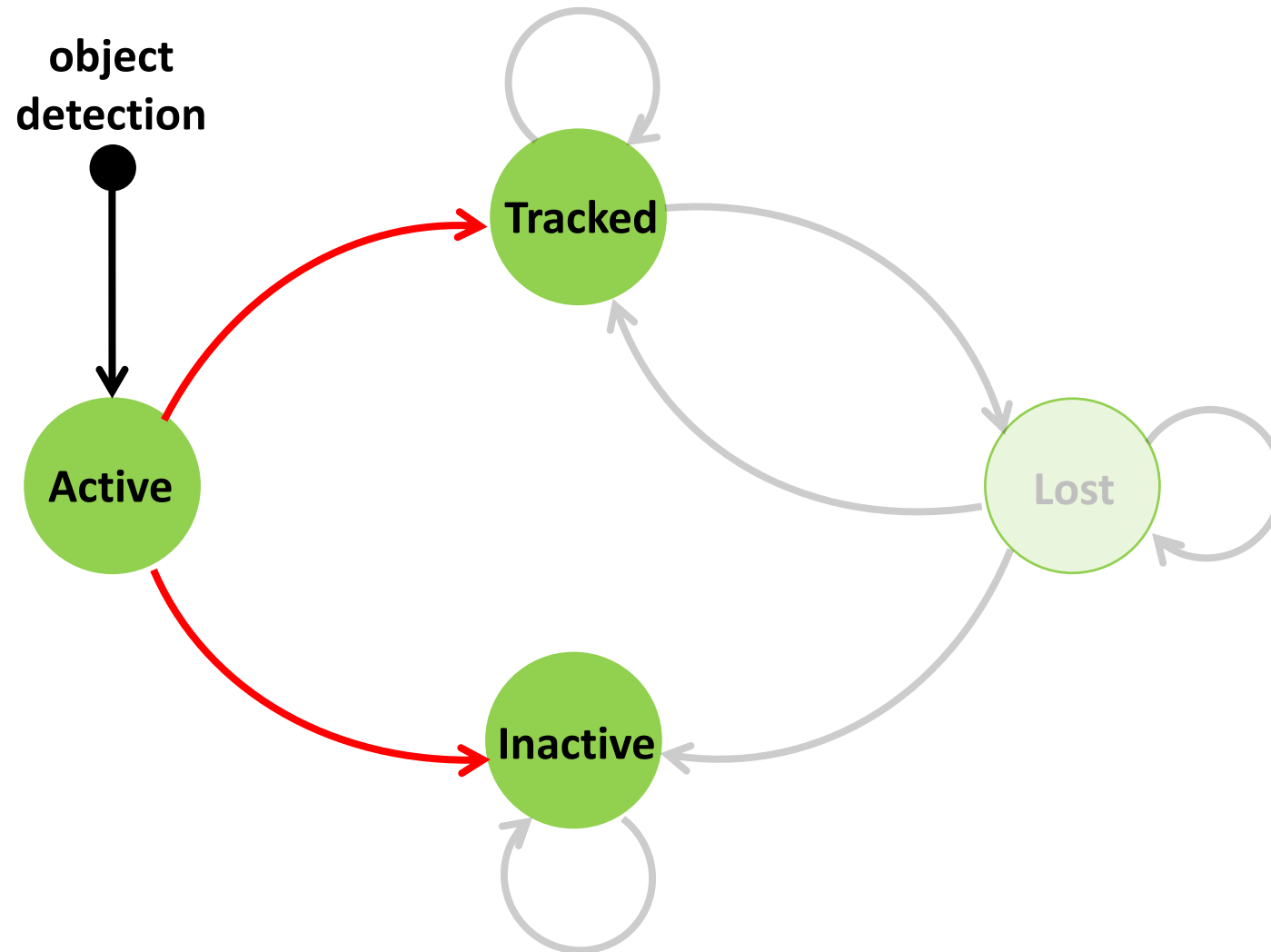


# Markov Decision Process for a Single Target

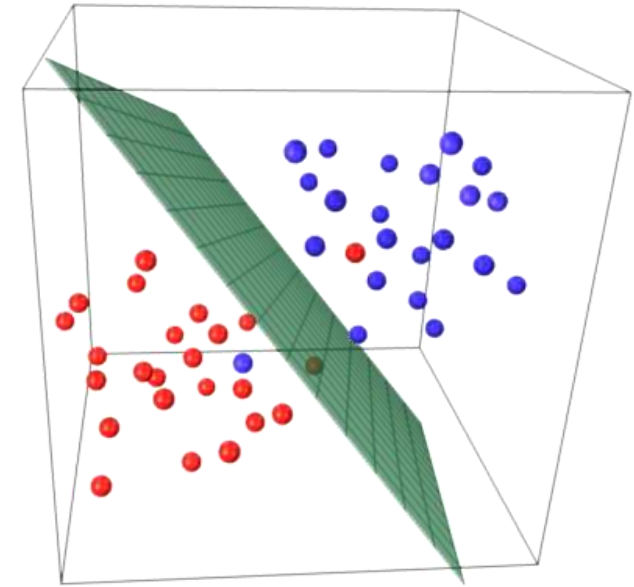
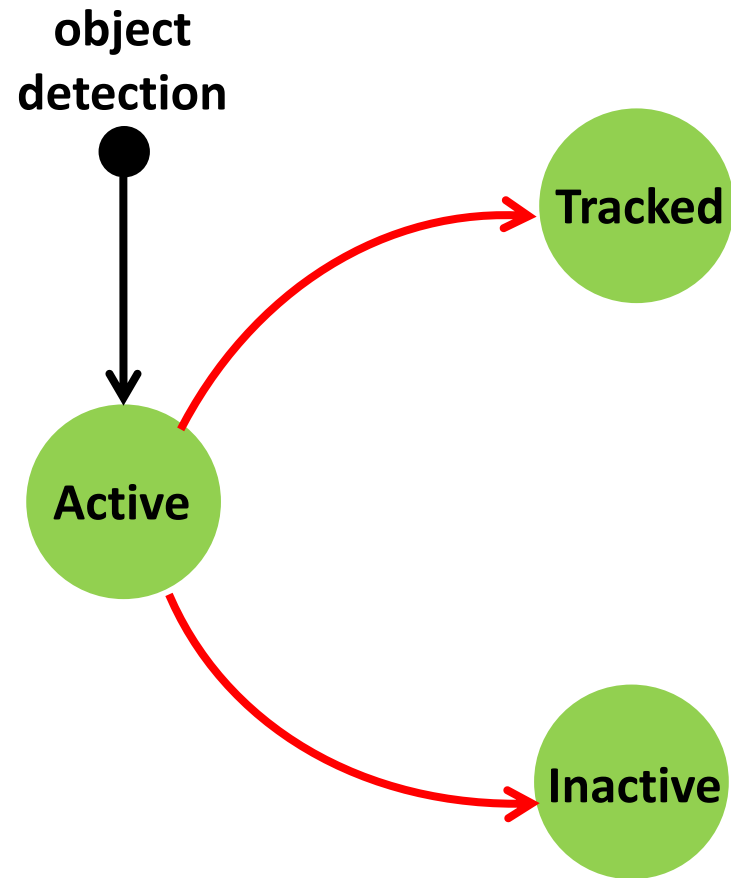




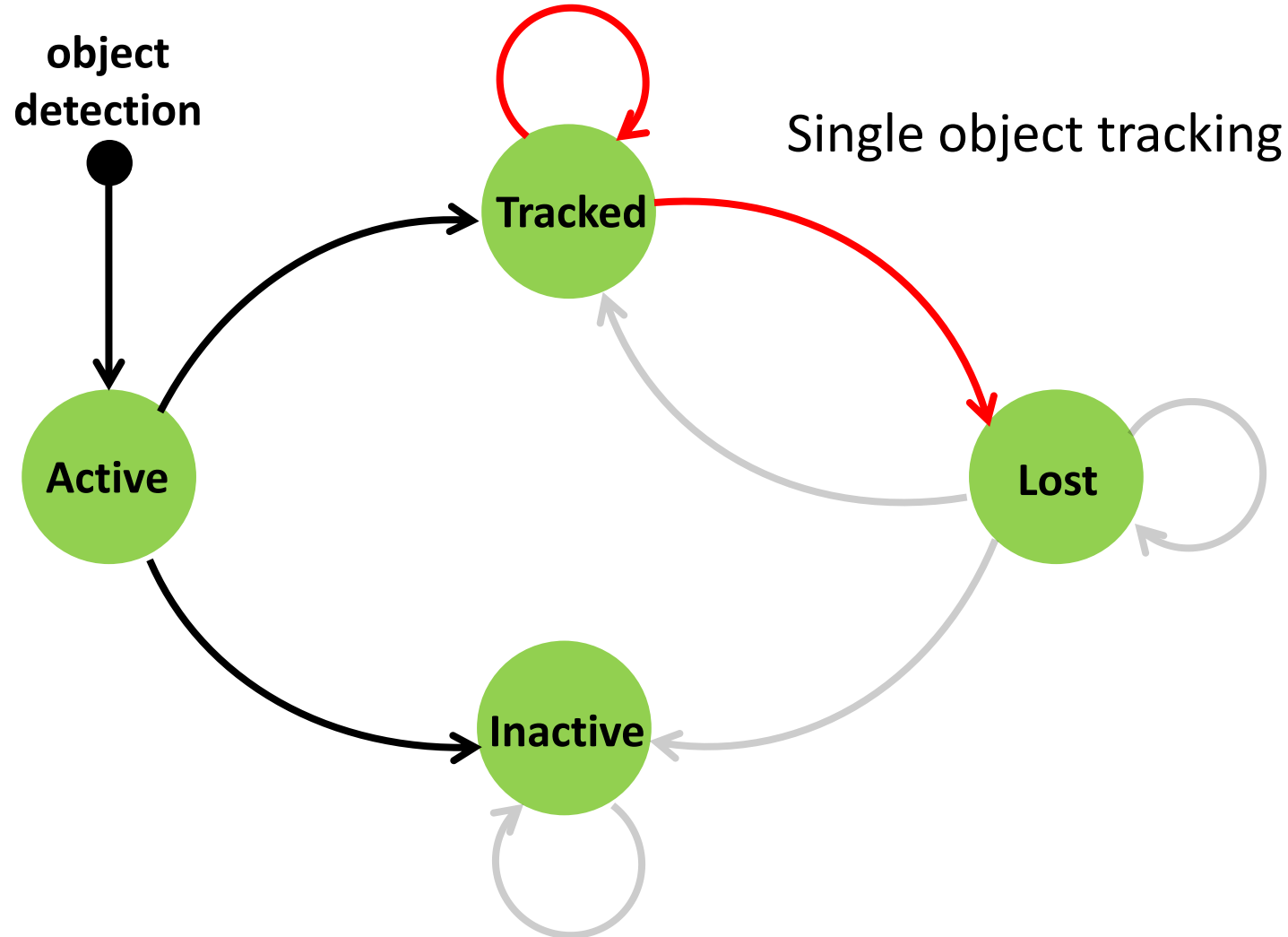
# Markov Decision Process for a Single Target



# Markov Decision Process for a Single Target



# Markov Decision Process for a Single Target



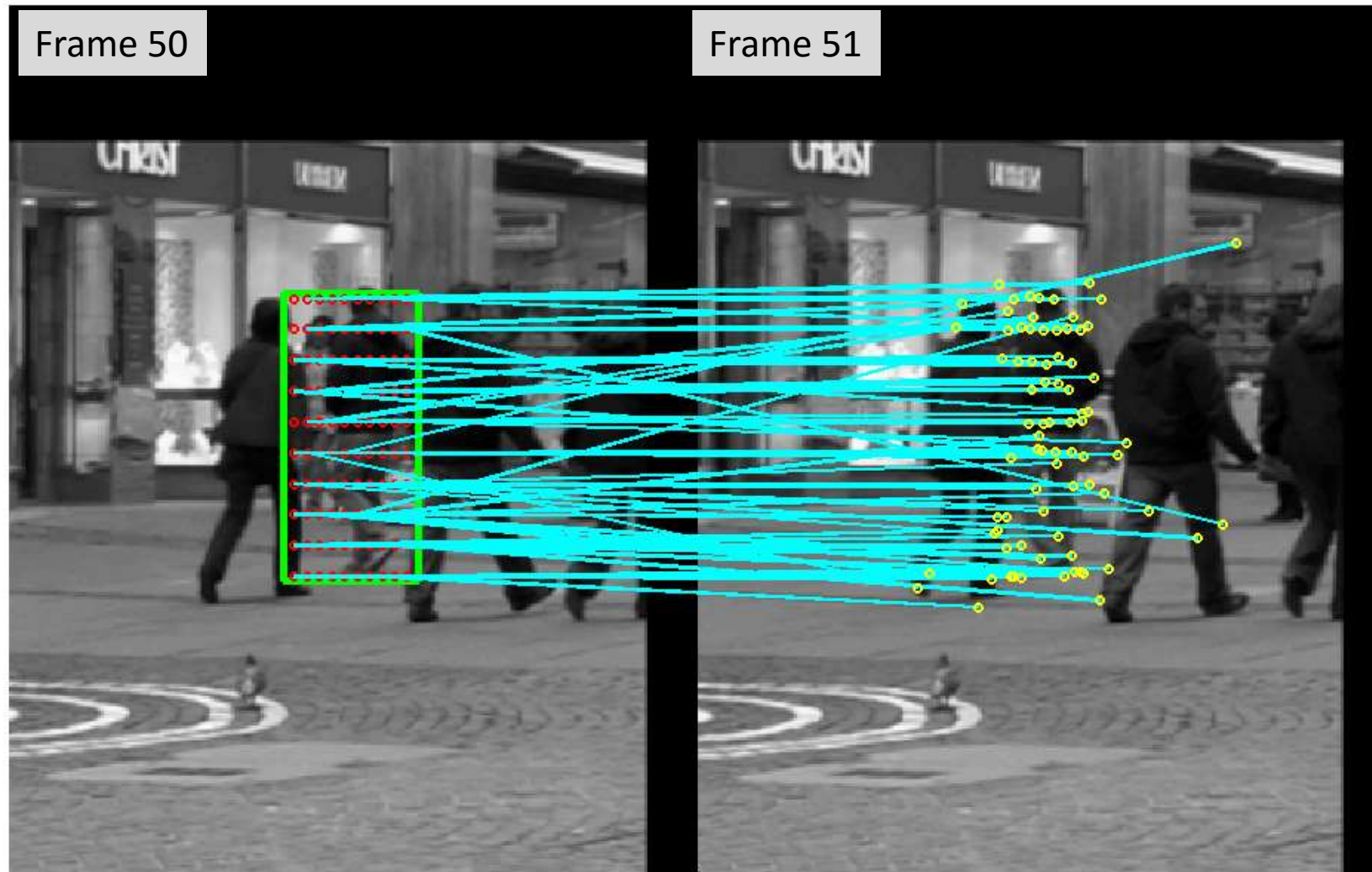
# Template Tracking in Tracked States



# Template Tracking in Tracked States

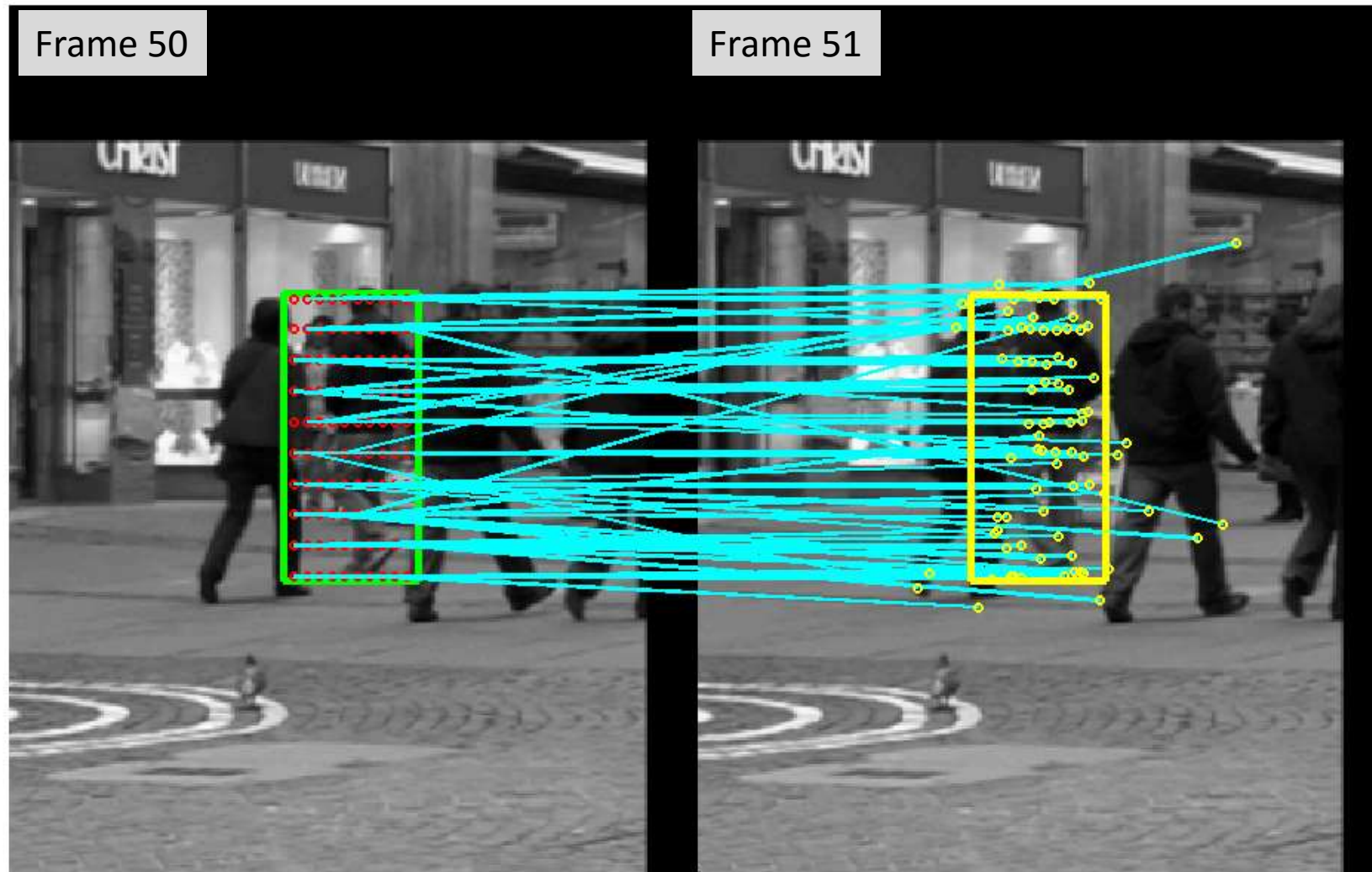


# Template Tracking in Tracked States





# Template Tracking in Tracked States



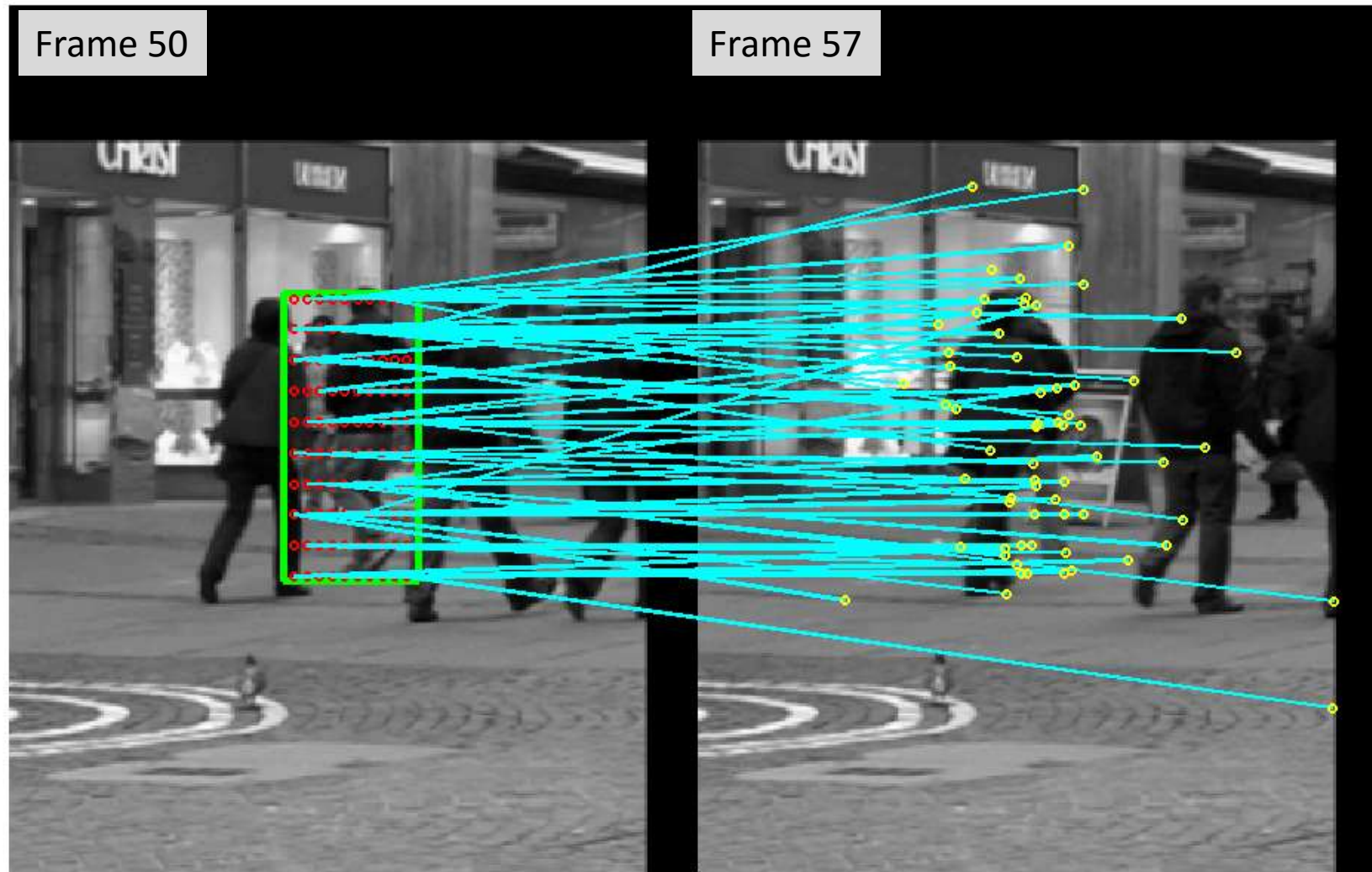
# Template Tracking in Tracked States



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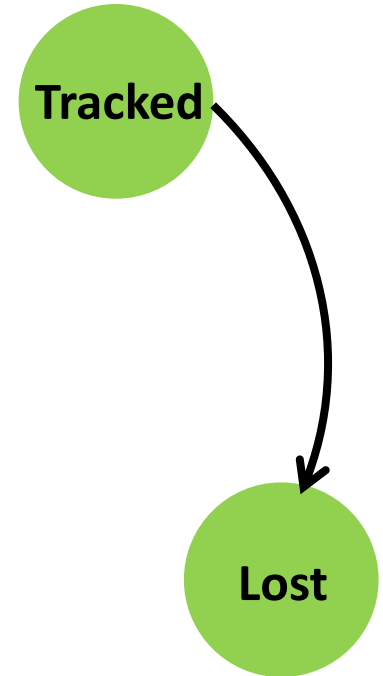
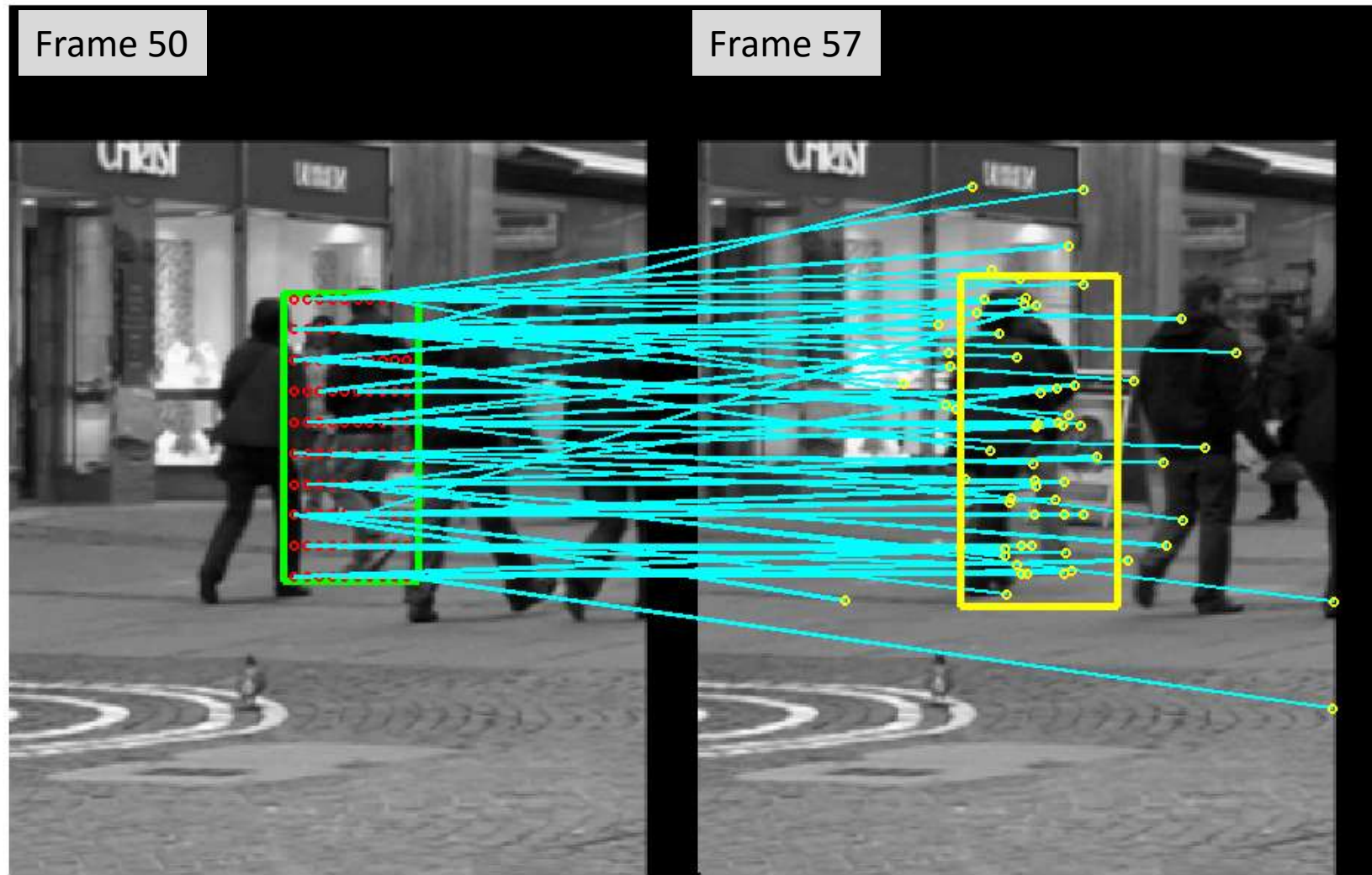


# Template Tracking in Tracked States

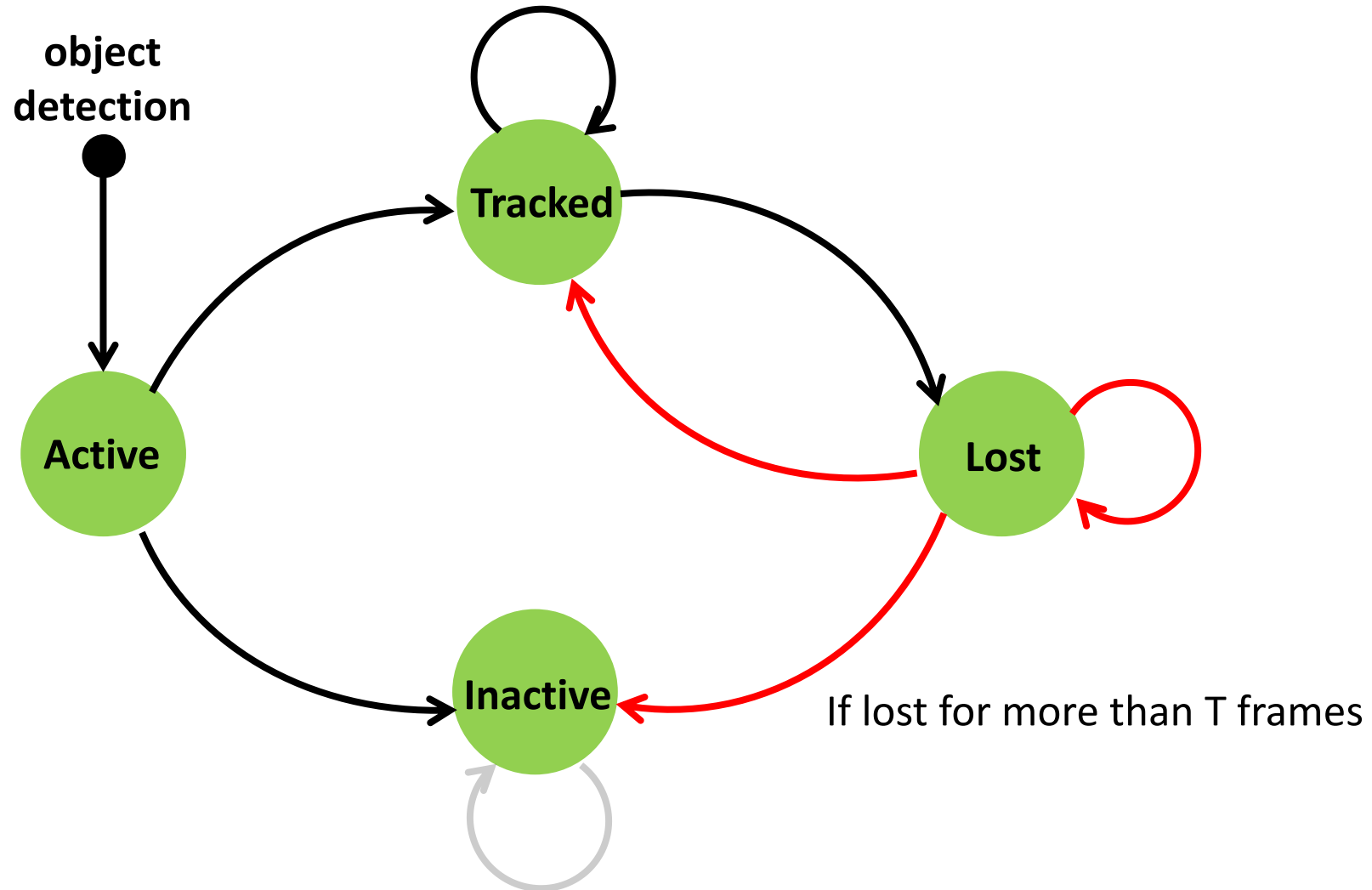




# Template Tracking in Tracked States

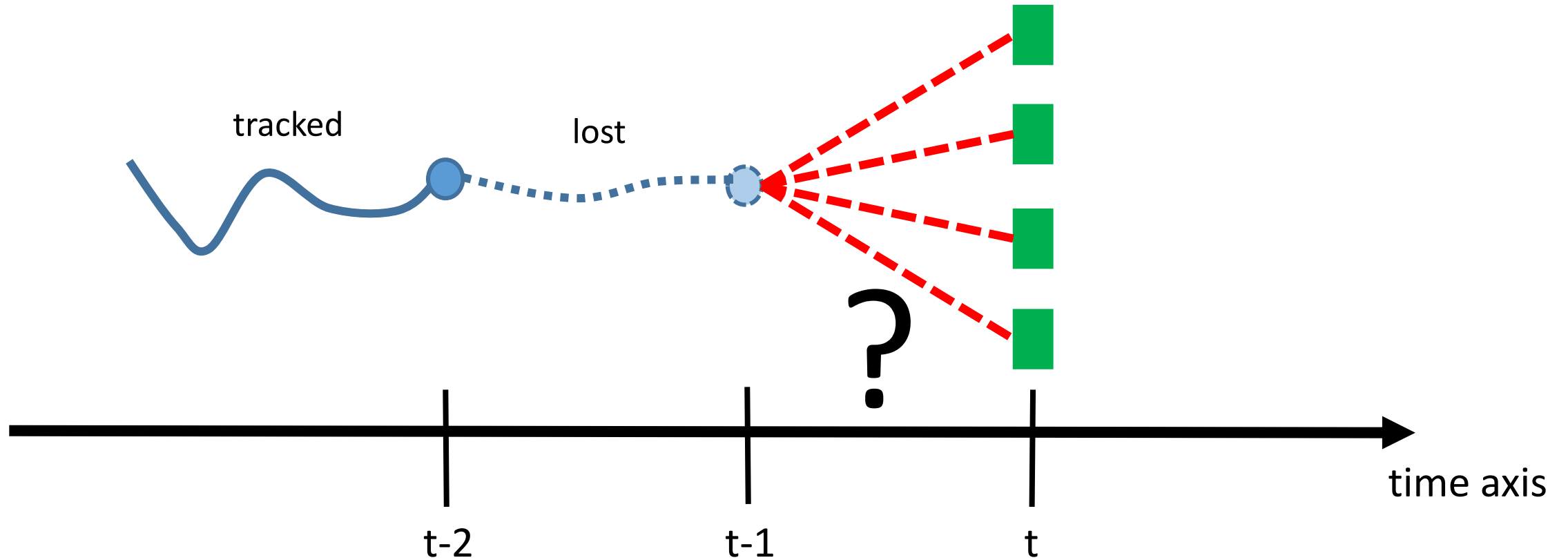


# Markov Decision Process for a Single Target





# Data Association in Lost States



# Learning the Similarity Function

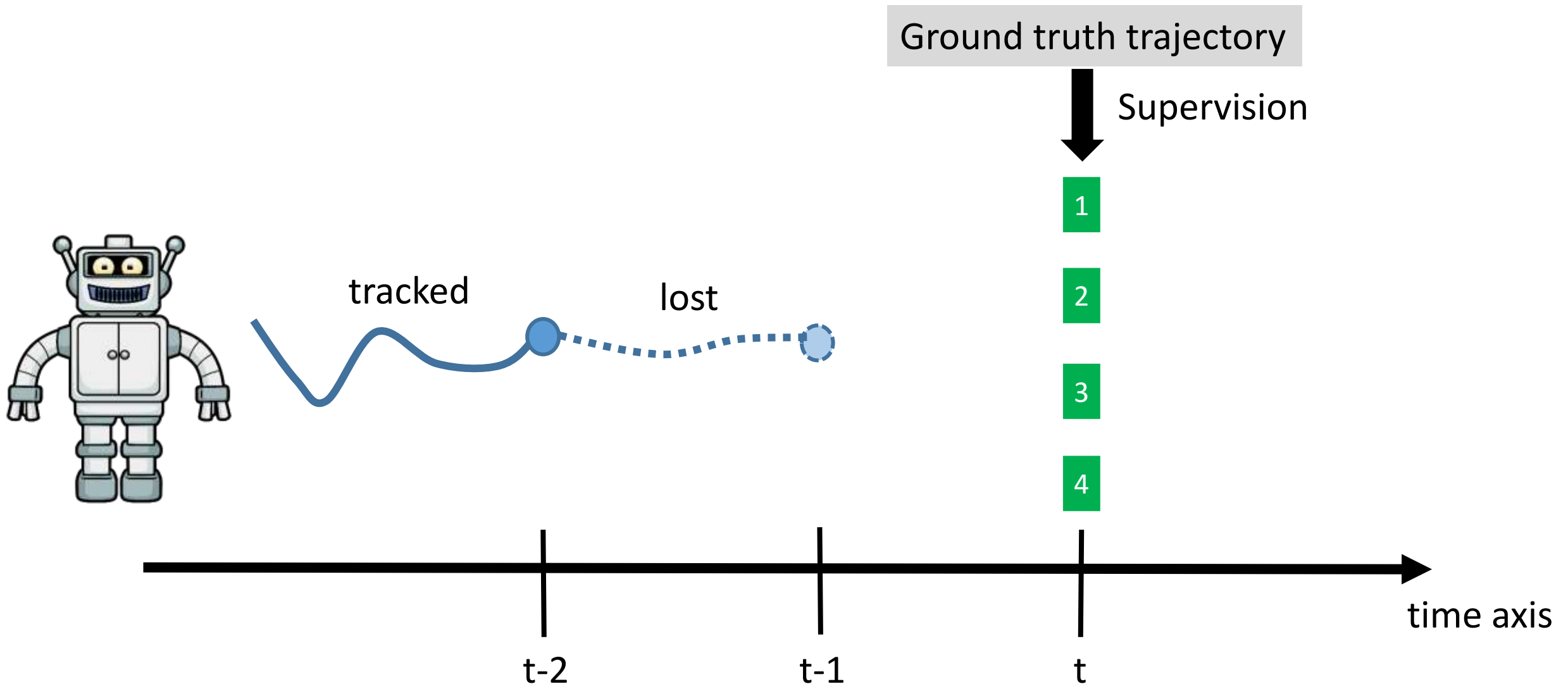
$$\text{Similarity} = w_1 \phi_1(\text{car}, \text{green}) + \dots + w_n \phi_n(\text{car}, \text{green}) + b$$

Inverse reinforcement learning: tracking objects in training videos!

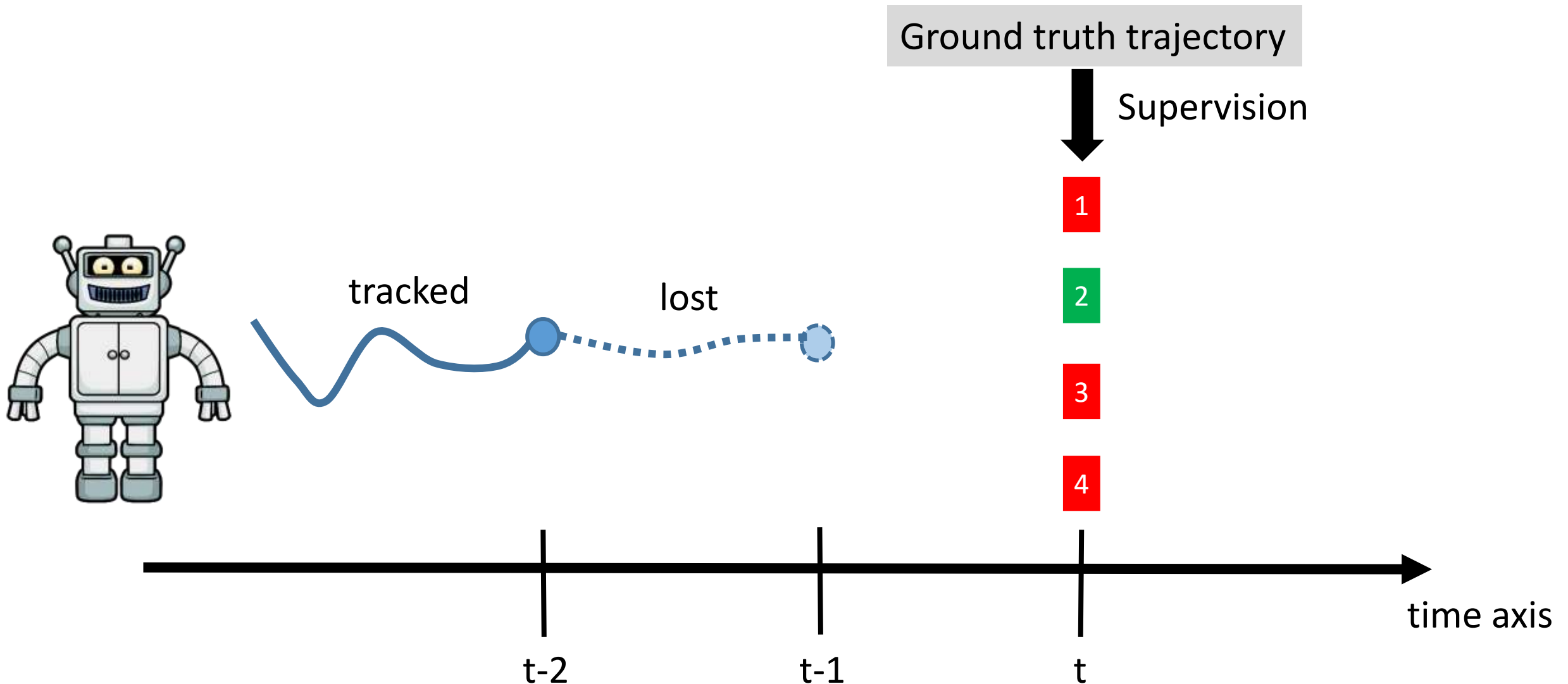
$(\text{car}, 1)$   
 $(\text{car}, 2)$   
...  
 $(\text{car}, M)$   
Hard positive examples

$(\text{car}, 1)$   
 $(\text{car}, 2)$   
...  
 $(\text{car}, N)$   
Hard negative examples

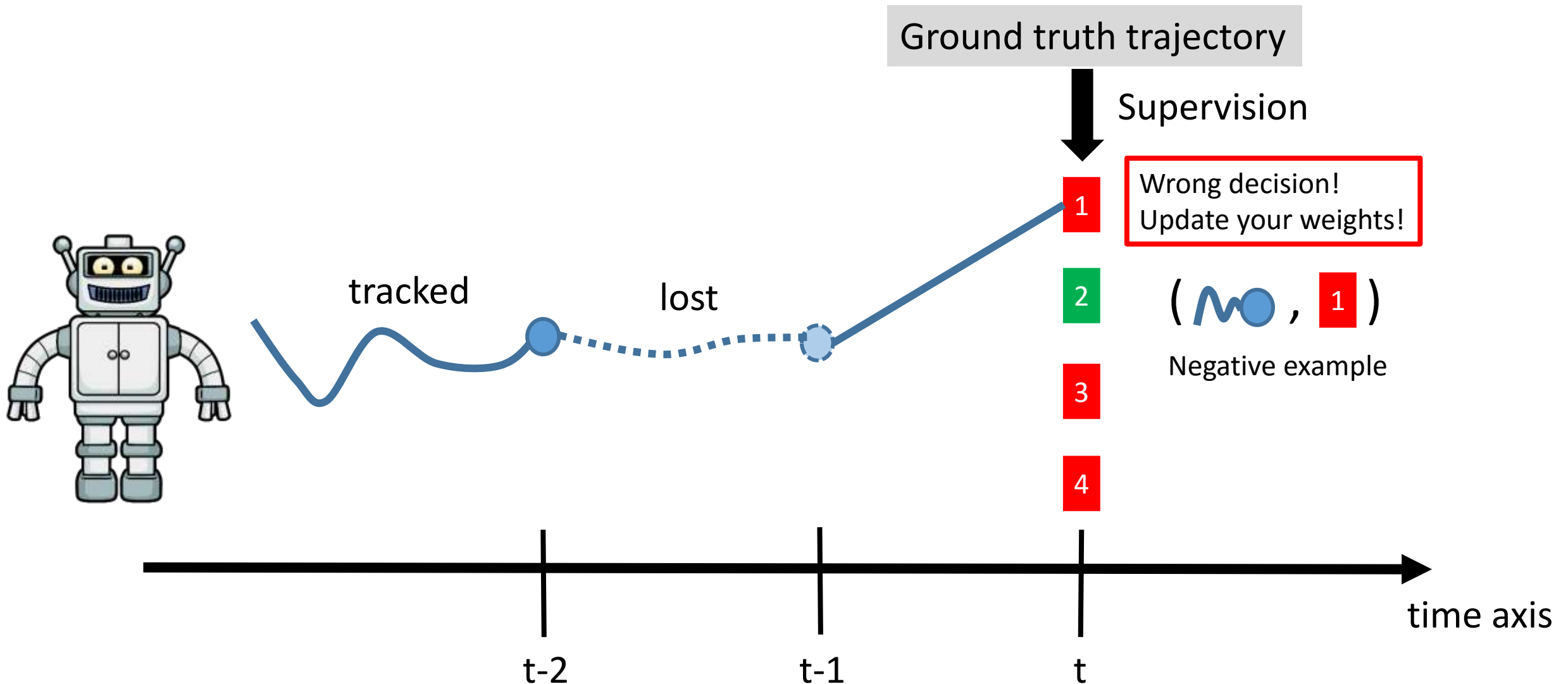
# Inverse Reinforcement Learning



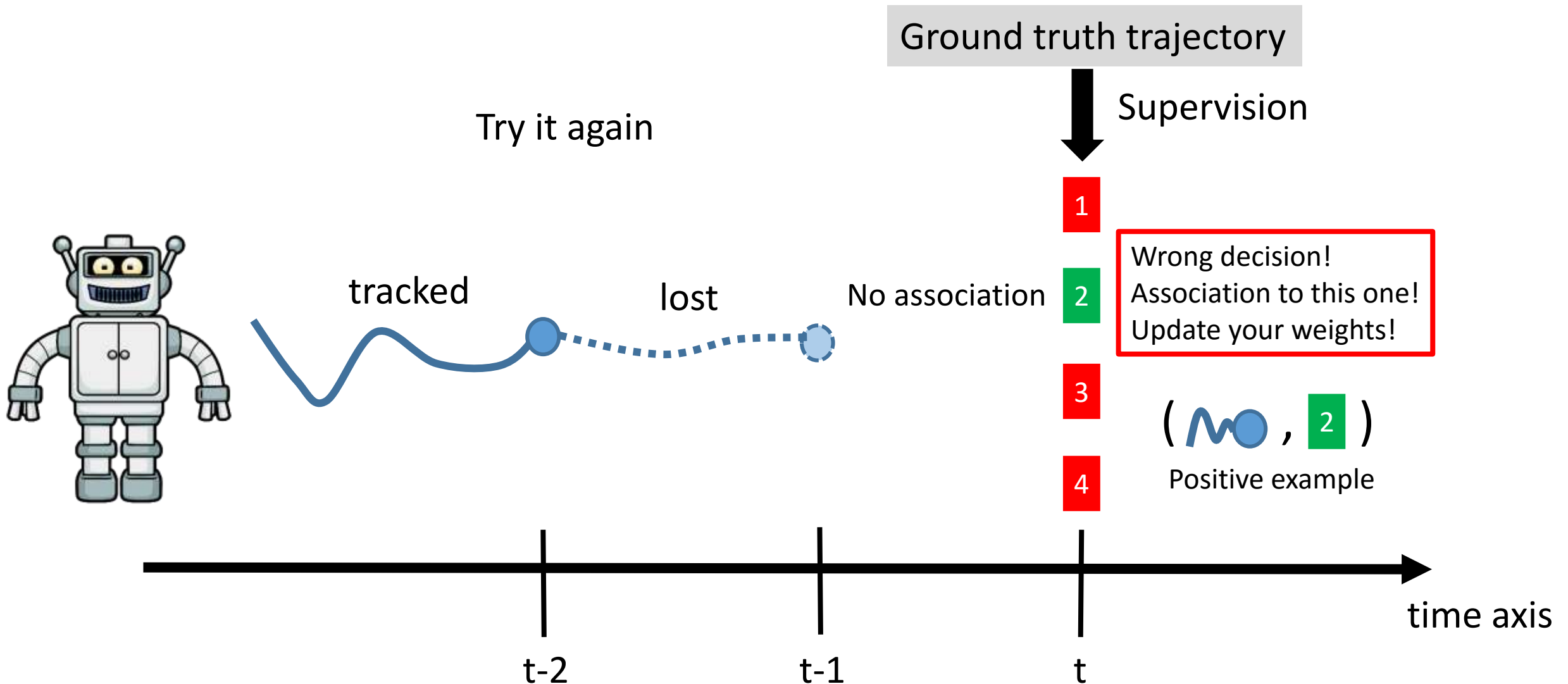
# Inverse Reinforcement Learning



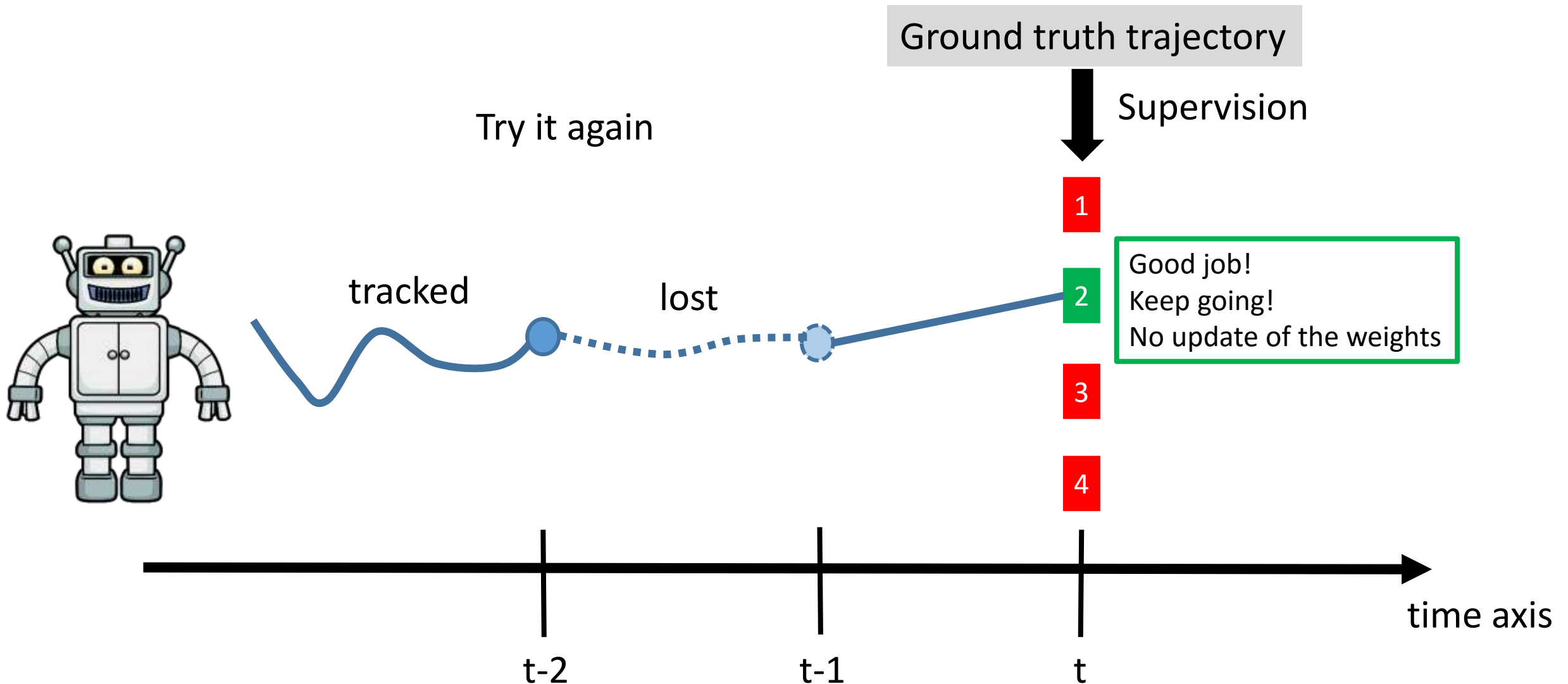
# Inverse Reinforcement Learning



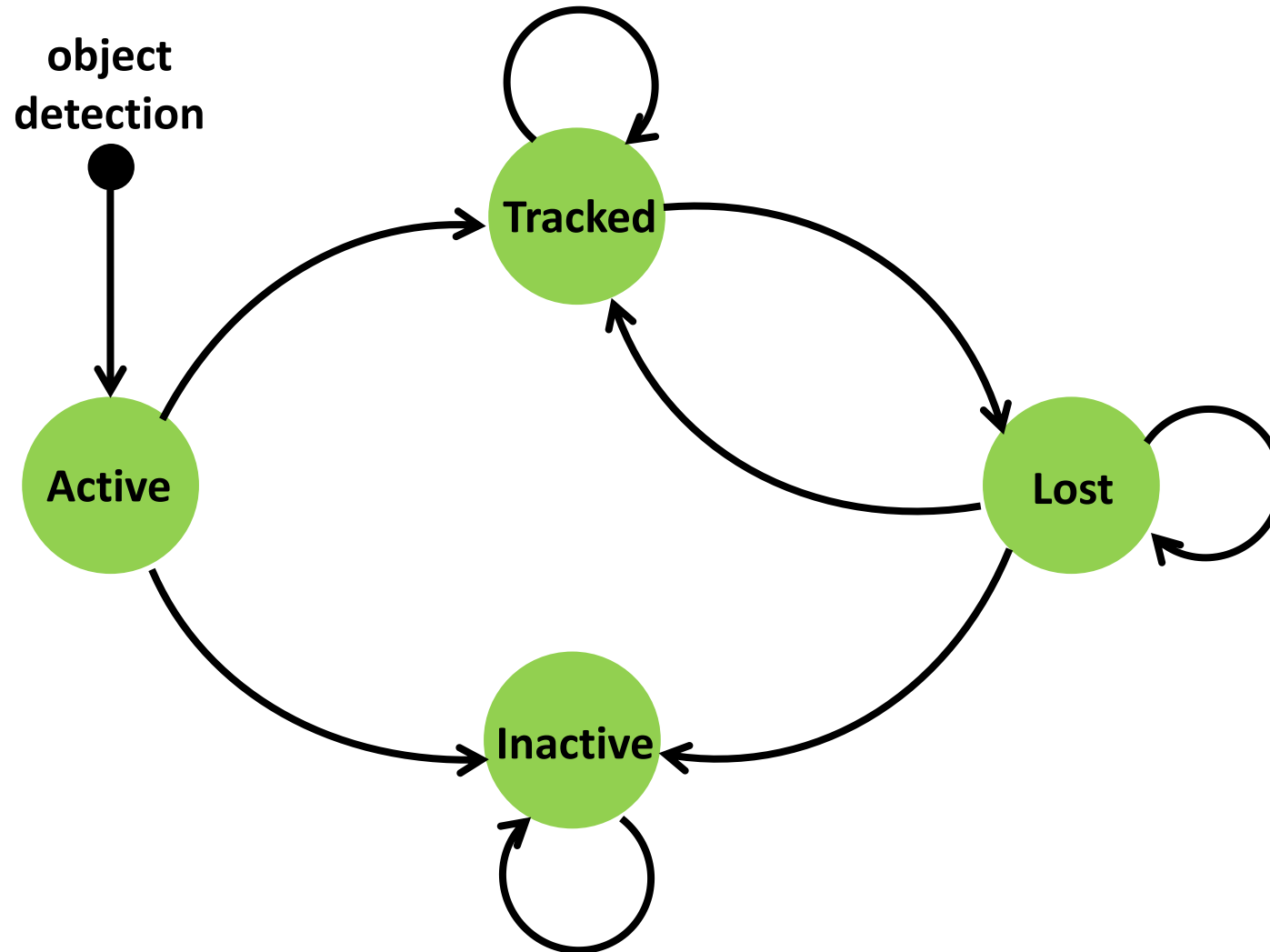
# Inverse Reinforcement Learning



# Inverse Reinforcement Learning



# Markov Decision Process for a Single Target

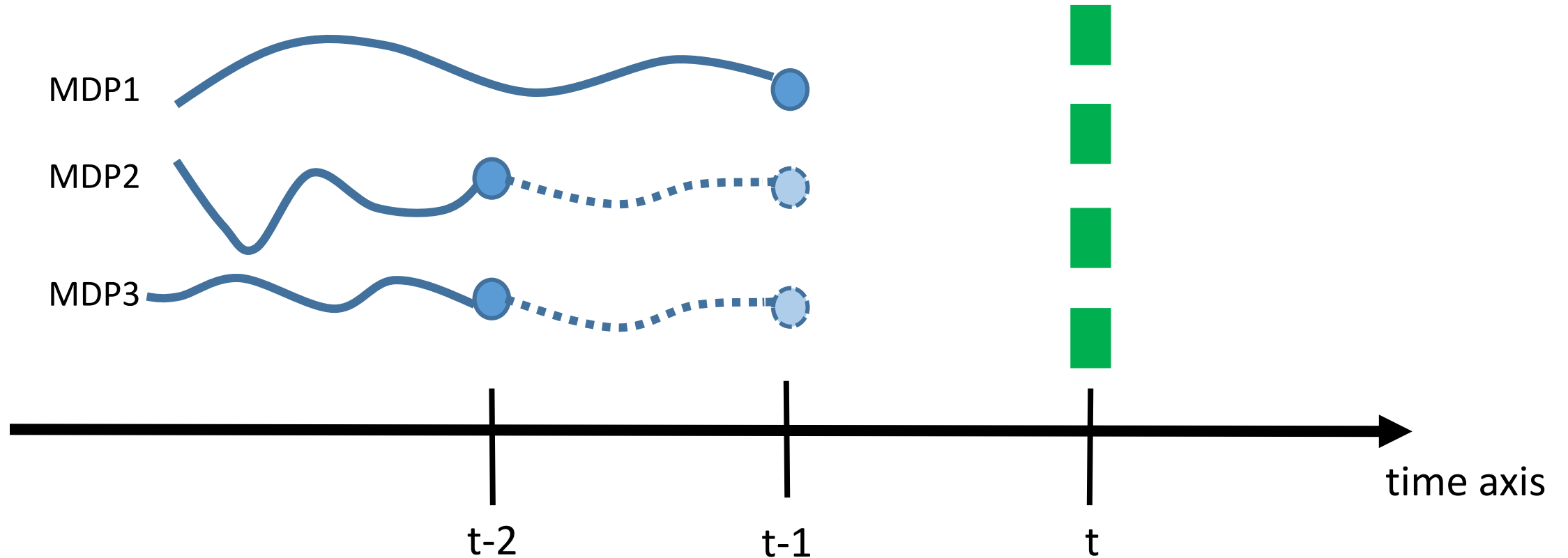




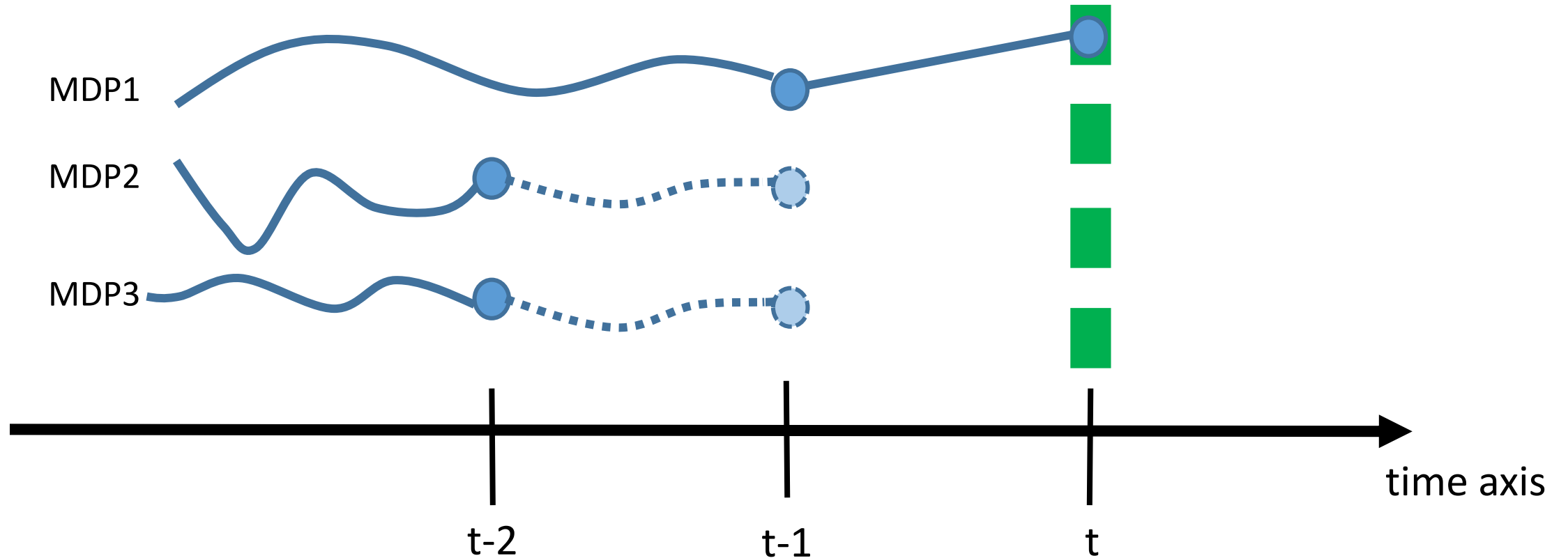
# Outline

- Markov Decision Process (MDP) for a Single Target
- **Online Multi-Object Tracking with MDPs**
- Experiments
- Conclusion

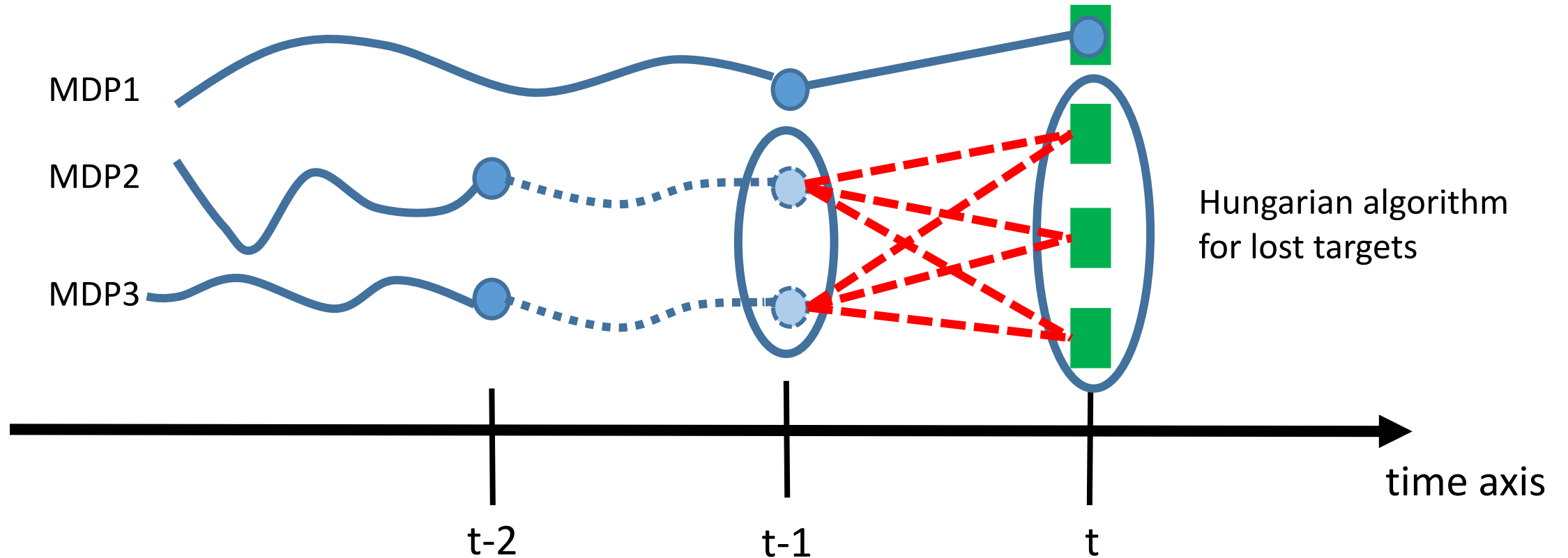
# Ensemble MDPs for Online Multi-Object Tracking



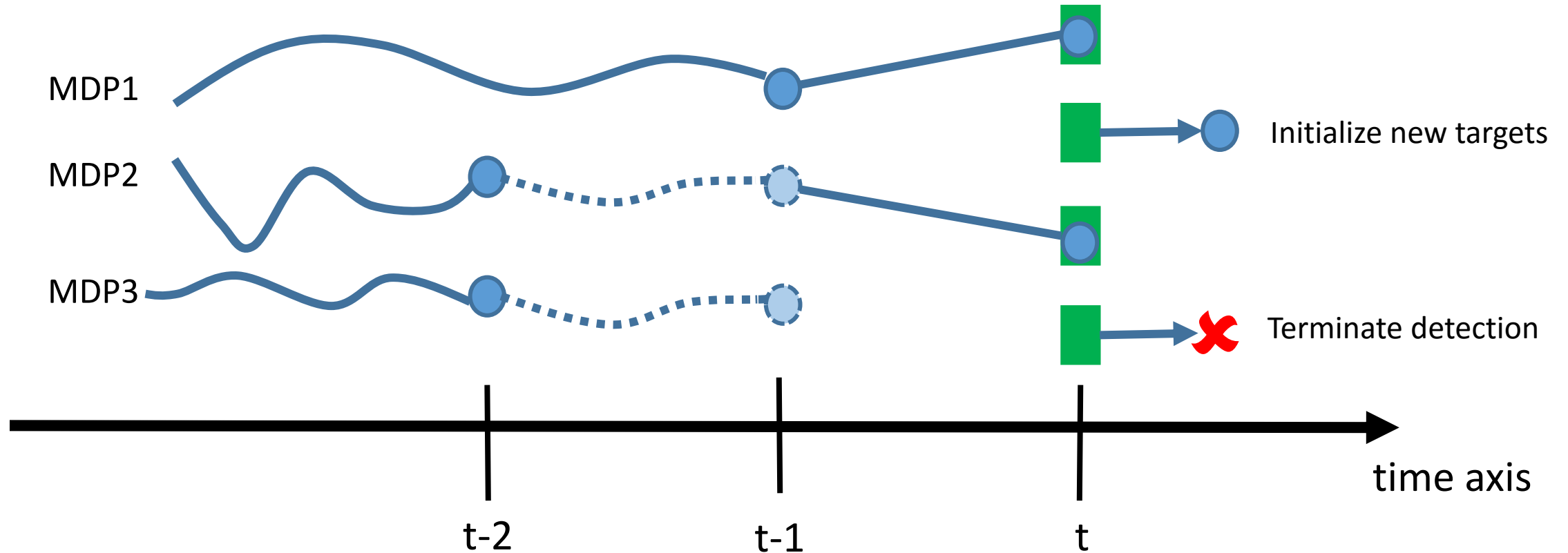
# Step 1: Process tracked targets



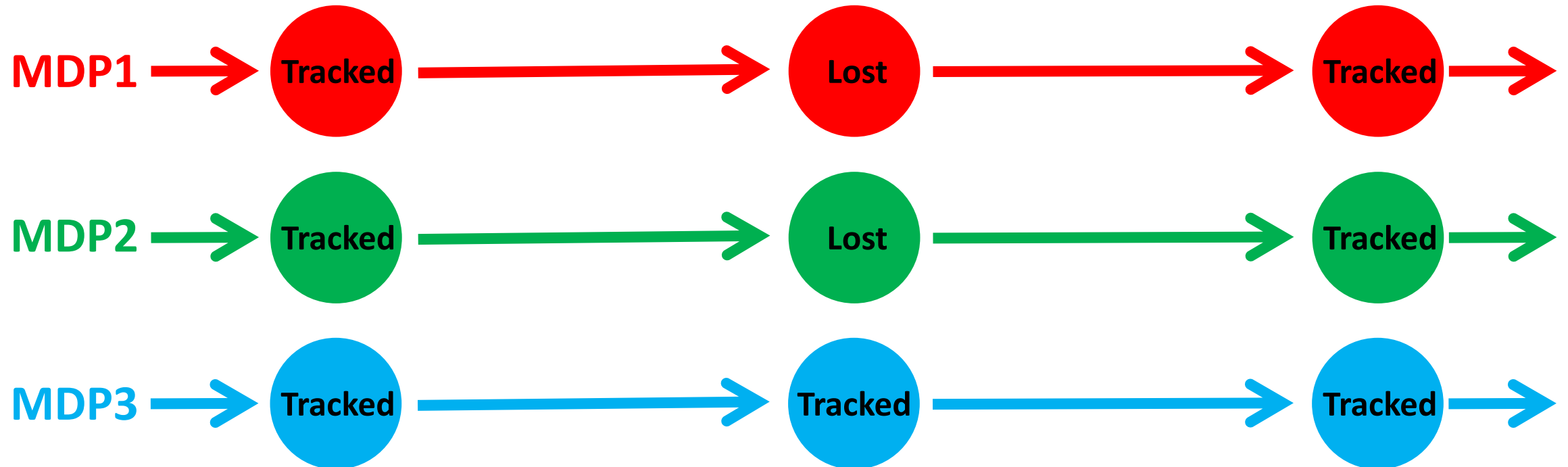
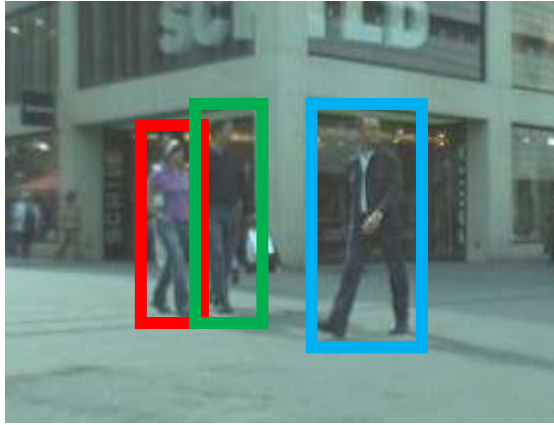
## Step 2: Process lost targets



# Step 3: Initialize new targets



# Online Multi-Object Tracking with MDPs



# Outline

- Markov Decision Process (MDP) for a Single Target
- Online Multi-Object Tracking with MDPs
- **Experiments**
- Conclusion

# Experiments: Dataset

- Multiple Object Tracking Benchmark [1]
  - 11 training sequences
  - 11 test sequences
  - Object detections from the ACF detector [2]



[1] L. Leal-Taixé, A. Milan, I. Reid, S. Roth, and K. Schindler. MOTChallenge 2015: Towards a Benchmark for Multi-Target Tracking. arXiv:1504.01942 [cs], 2015.

[2] P. Dollár, R. Appel, S. Belongie, and P. Perona. Fast feature pyramids for object detection. TPAMI, 36(8):1532–1545, 2014.

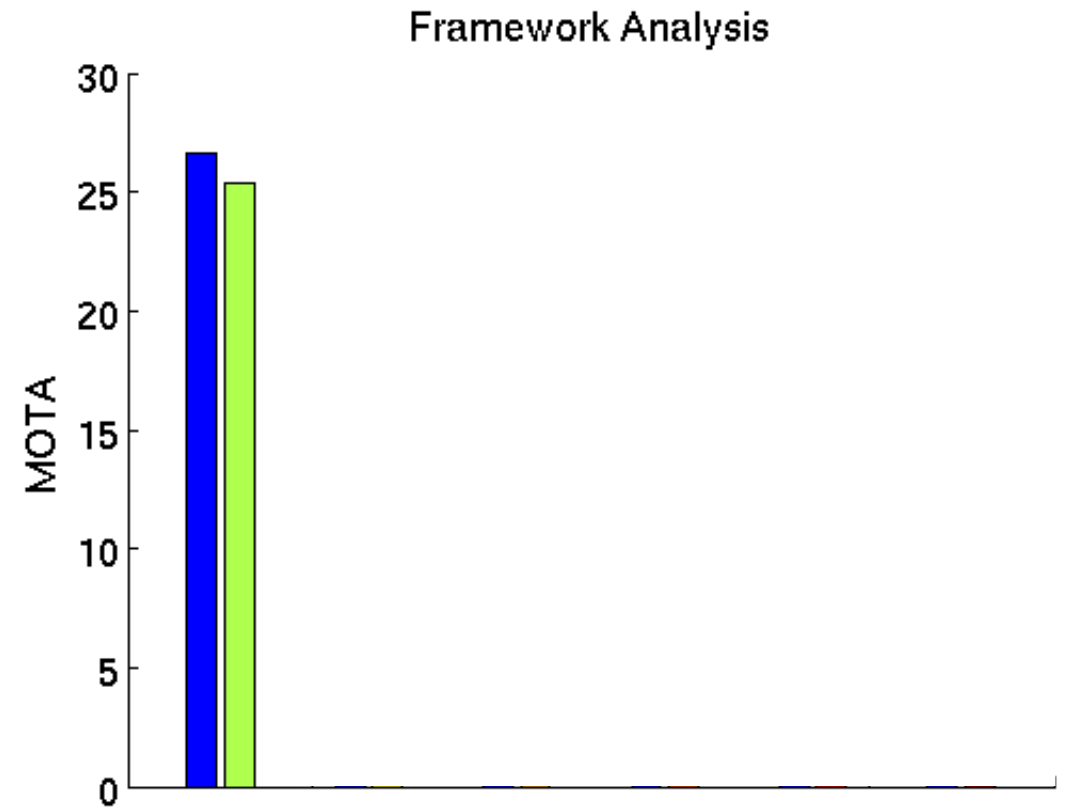
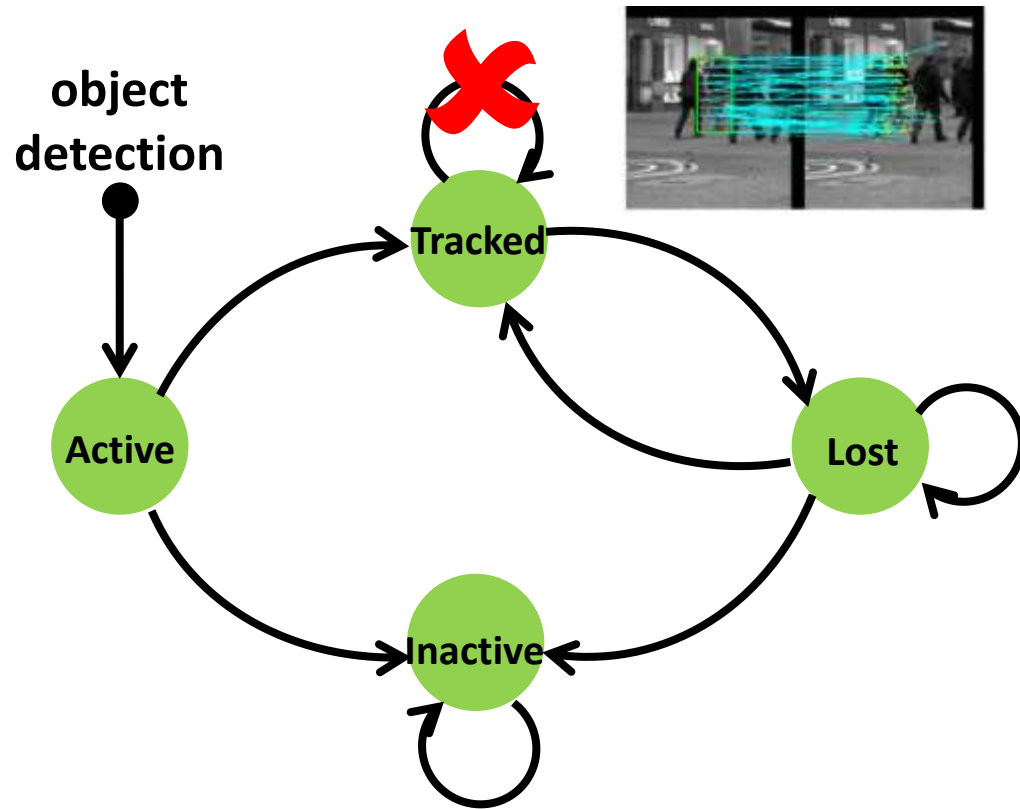


# Experiments: Analysis on Validation Set

- Contribution of different components

# Experiments: Analysis on Validation Set

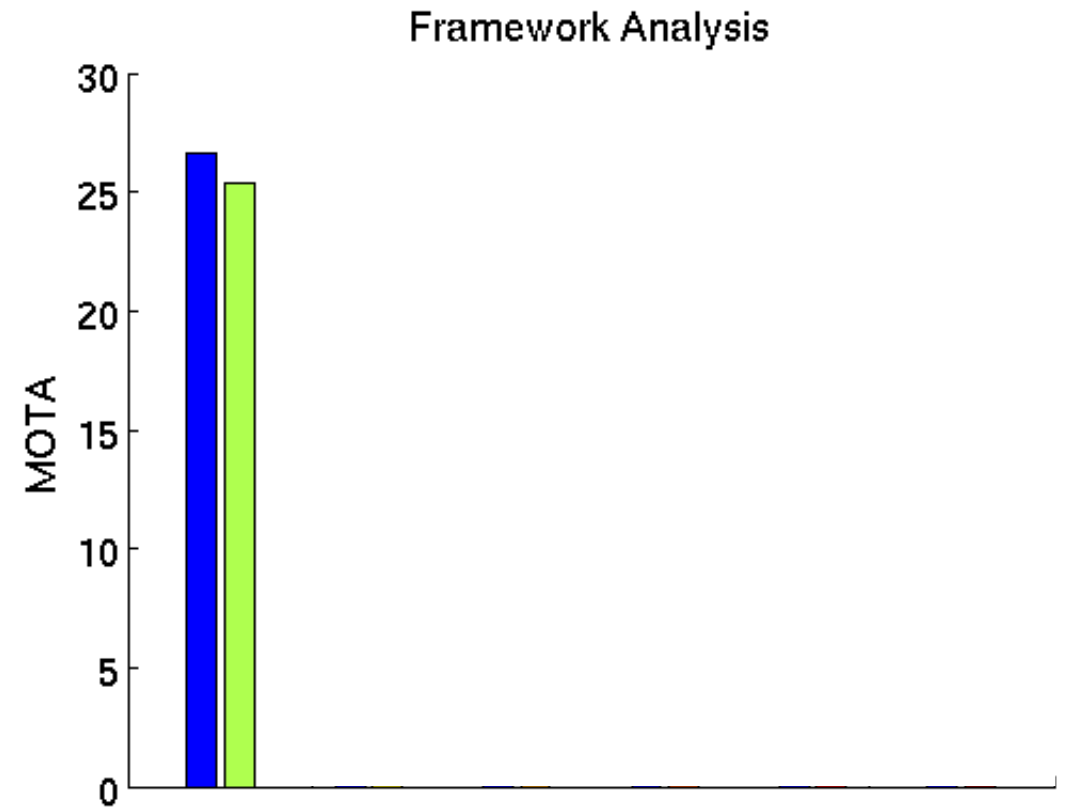
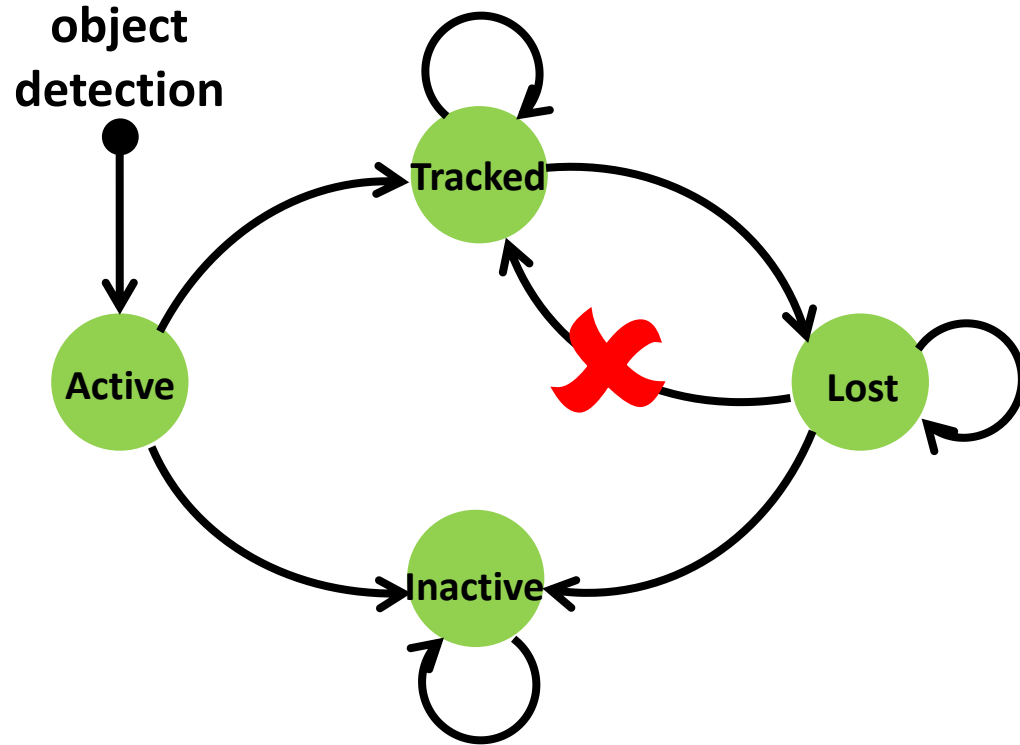
- Contribution of different components



**MOTA:** multiple object tracking accuracy

# Experiments: Analysis on Validation Set

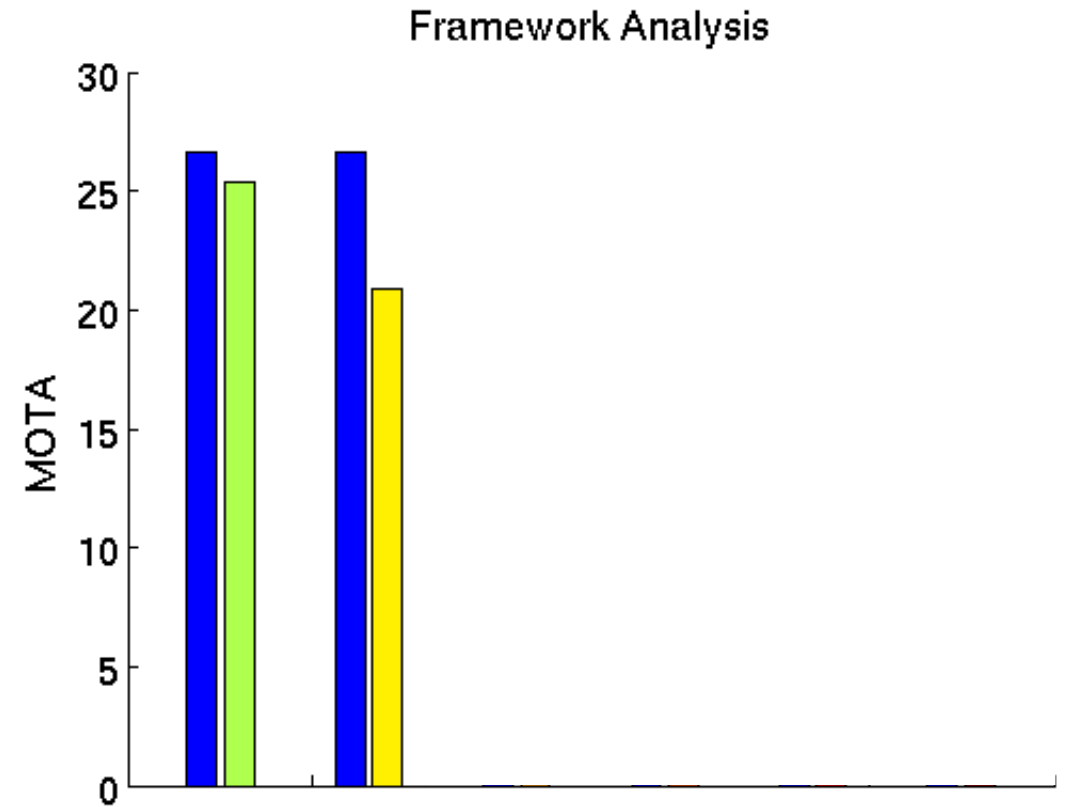
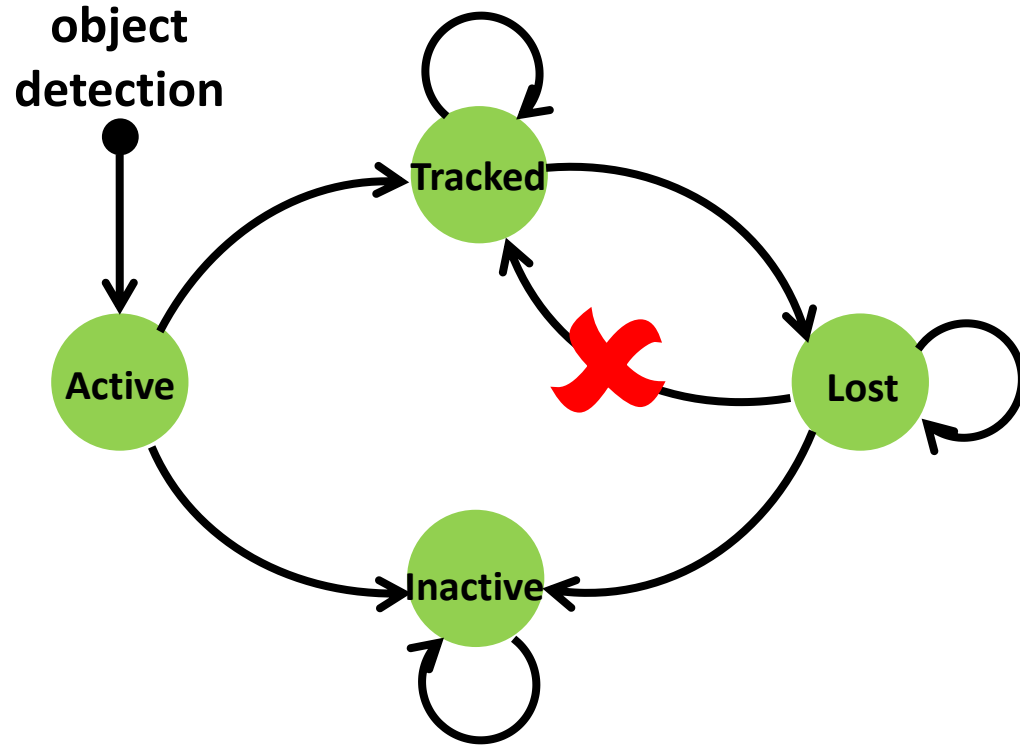
- Contribution of different components



**MOTA:** multiple object tracking accuracy

# Experiments: Analysis on Validation Set

- Contribution of different components

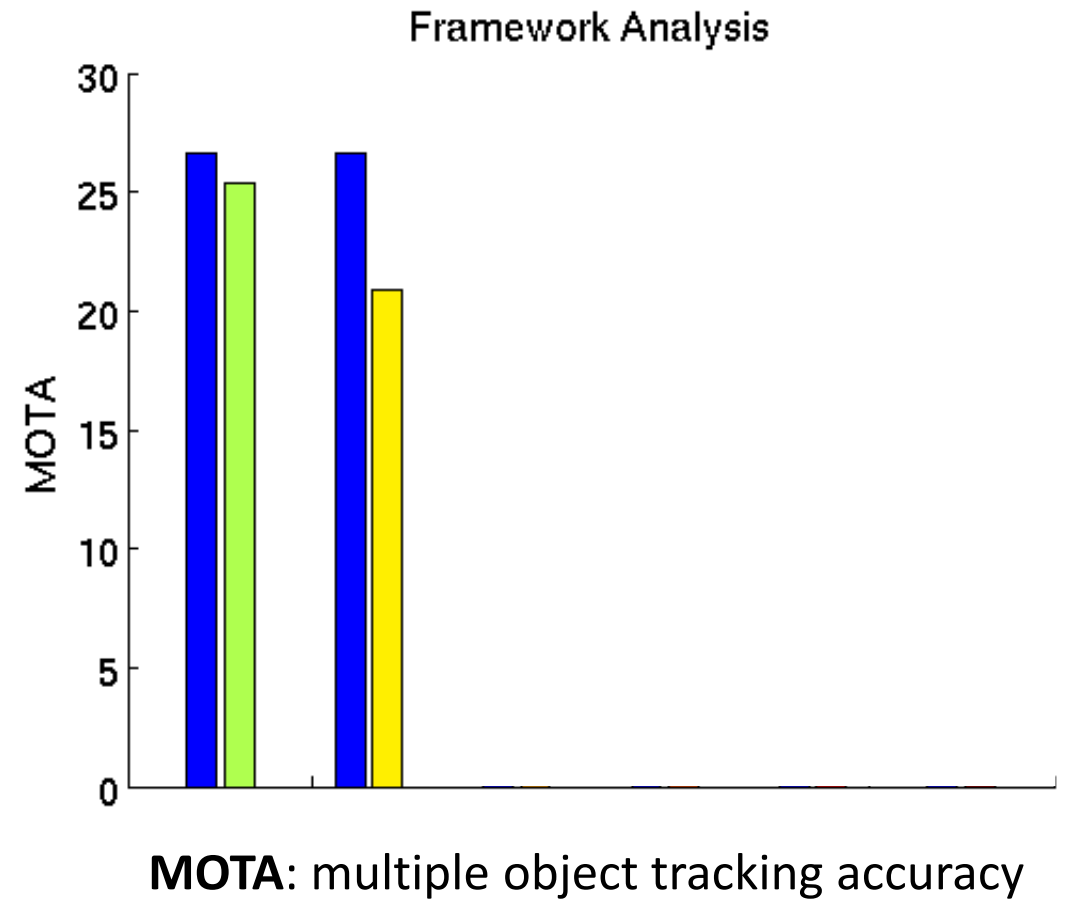


**MOTA:** multiple object tracking accuracy

# Experiments: Analysis on Validation Set

- Contribution of different components

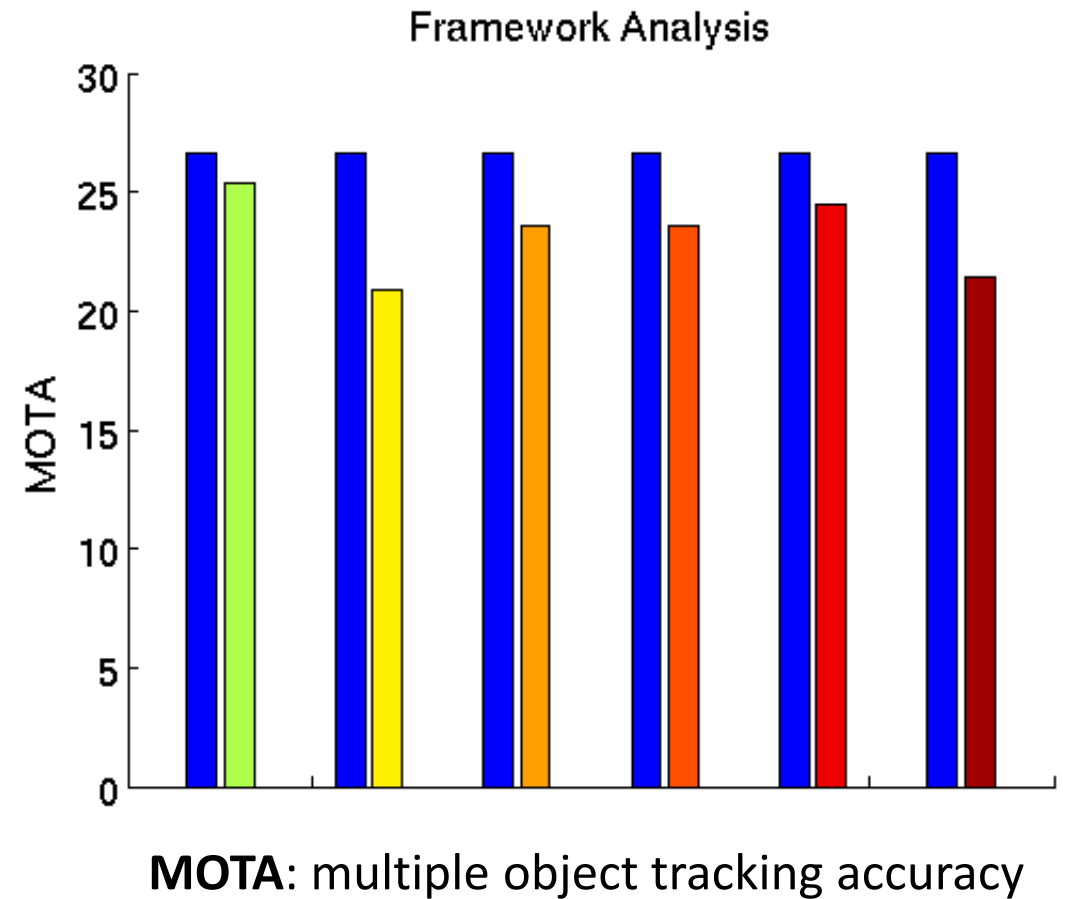
$$\begin{aligned} \text{Similarity} = & w_1 \phi_1(\text{blue wavy line}, \text{green square}) \\ & + \\ & \vdots \\ & + \\ & w_n \phi_n(\text{blue wavy line}, \text{green square}) \\ & + \\ & b \end{aligned}$$



# Experiments: Analysis on Validation Set

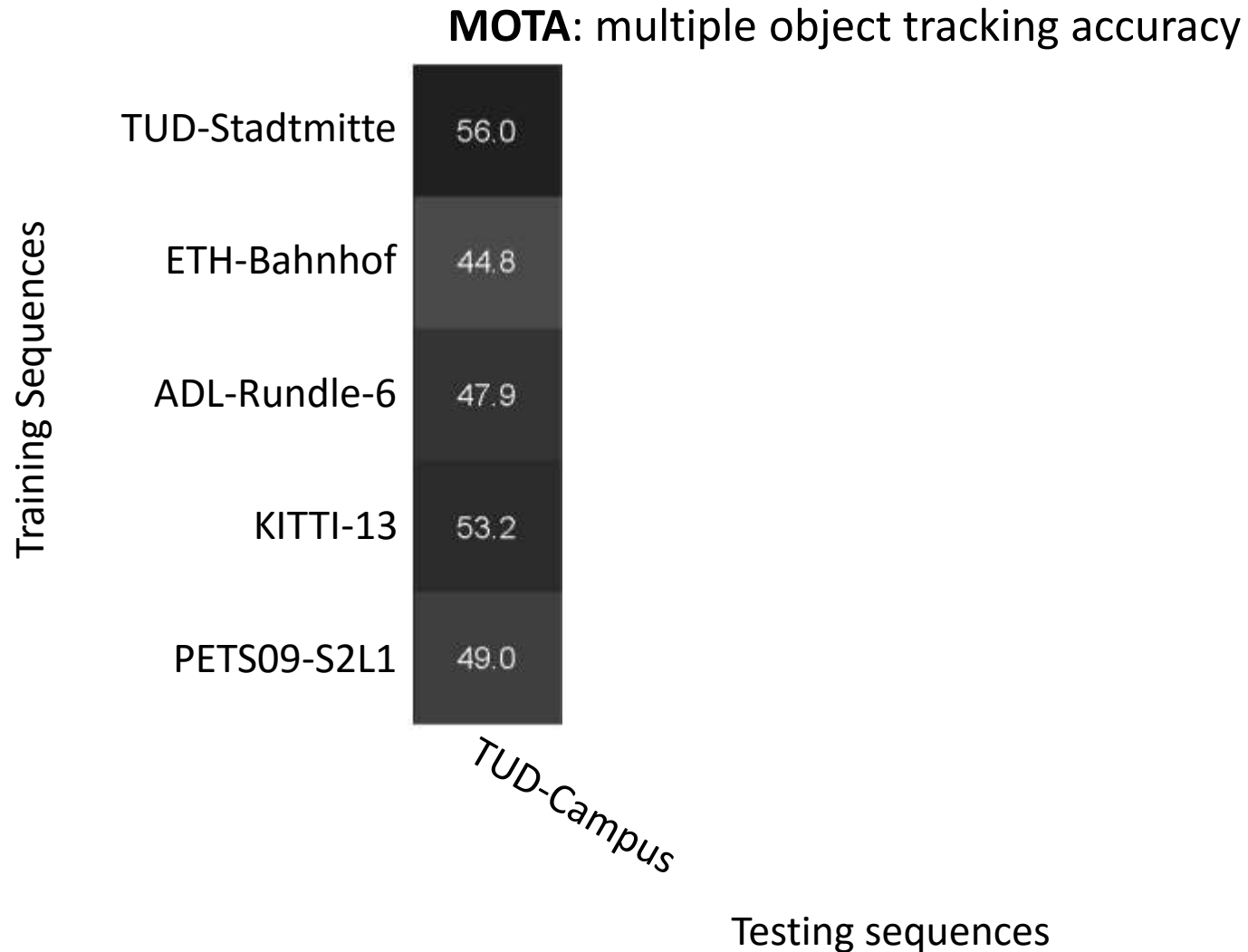
- Contribution of different components

$$\begin{aligned} \text{Similarity} = & w_1 \phi_1(\text{blue wavy line}, \text{green square}) \\ & + \\ & \vdots \\ & + \\ & w_n \phi_n(\text{blue wavy line}, \text{green square}) \\ & + \\ & b \end{aligned}$$



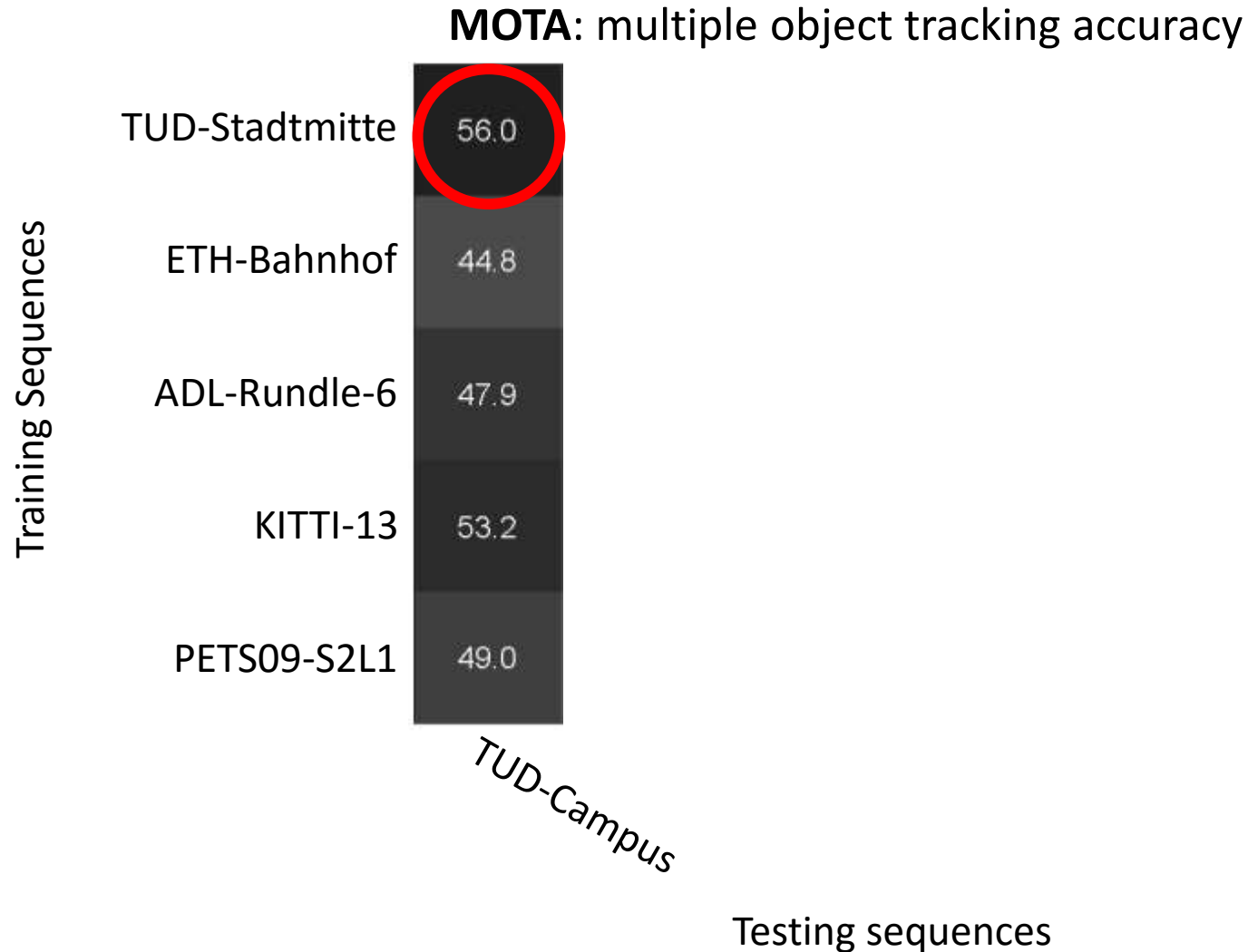
# Experiments: Analysis on Validation Set

- Cross-domain tracking



# Experiments: Analysis on Validation Set

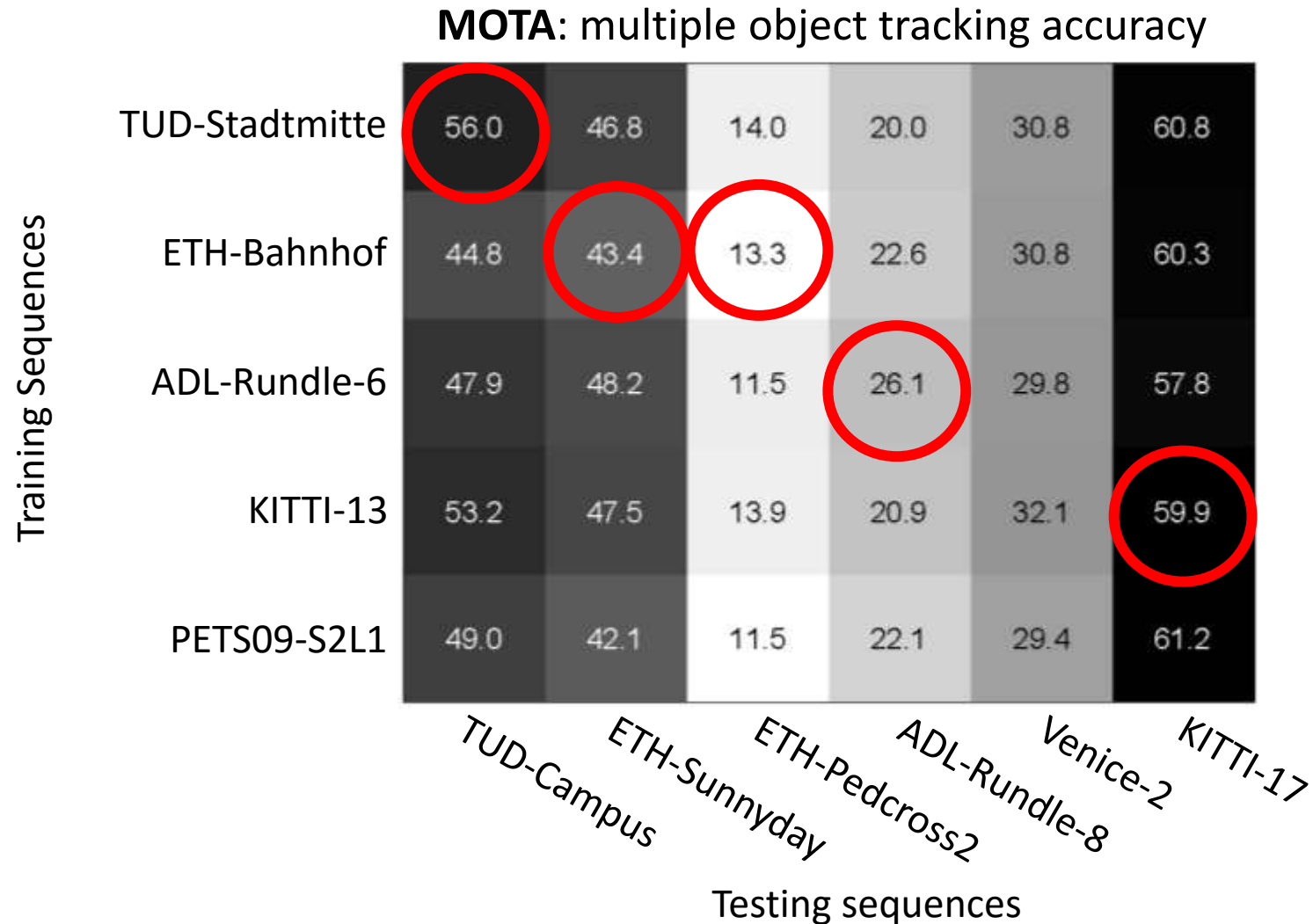
- Cross-domain tracking





# Experiments: Analysis on Validation Set

- Cross-domain tracking



# Experiments: Evaluation on Test Set

Tracker	Tracking	Learning	MOTA
DP_NMS [1]	Batch	N/A	14.5
TC_ODAL [2]	Online	Online	15.1
TBD [3]	Batch	Offline	15.9
SMOT [4]	Batch	N/A	18.2
RMOT [5]	Online	N/A	18.6
CEM [6]	Online	N/A	19.3
SegTrack [7]	Batch	Offline	22.5
MotiCon [8]	Batch	Offline	23.1
<b>MDP (Ours)</b>	Online	Online	<b>30.3</b>

**MOTA:** multiple object tracking accuracy

[1] Pirsiavash et al., CVPR' 11

[2] Bae et al., CVPR'14

[3] Geiger et al., TPAMI'14

[4] Dicle et al., ICCV'13

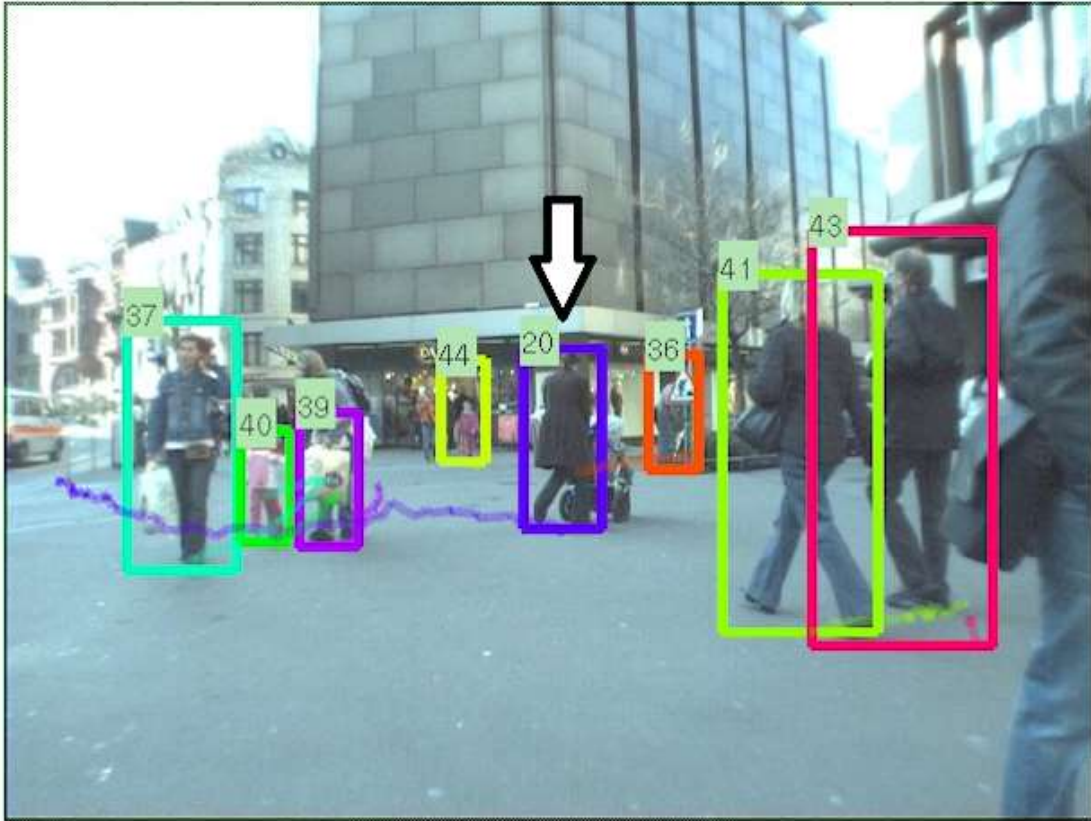
[5] Yoon et al., WACV'15

[6] Milan et al., TPAMI'14

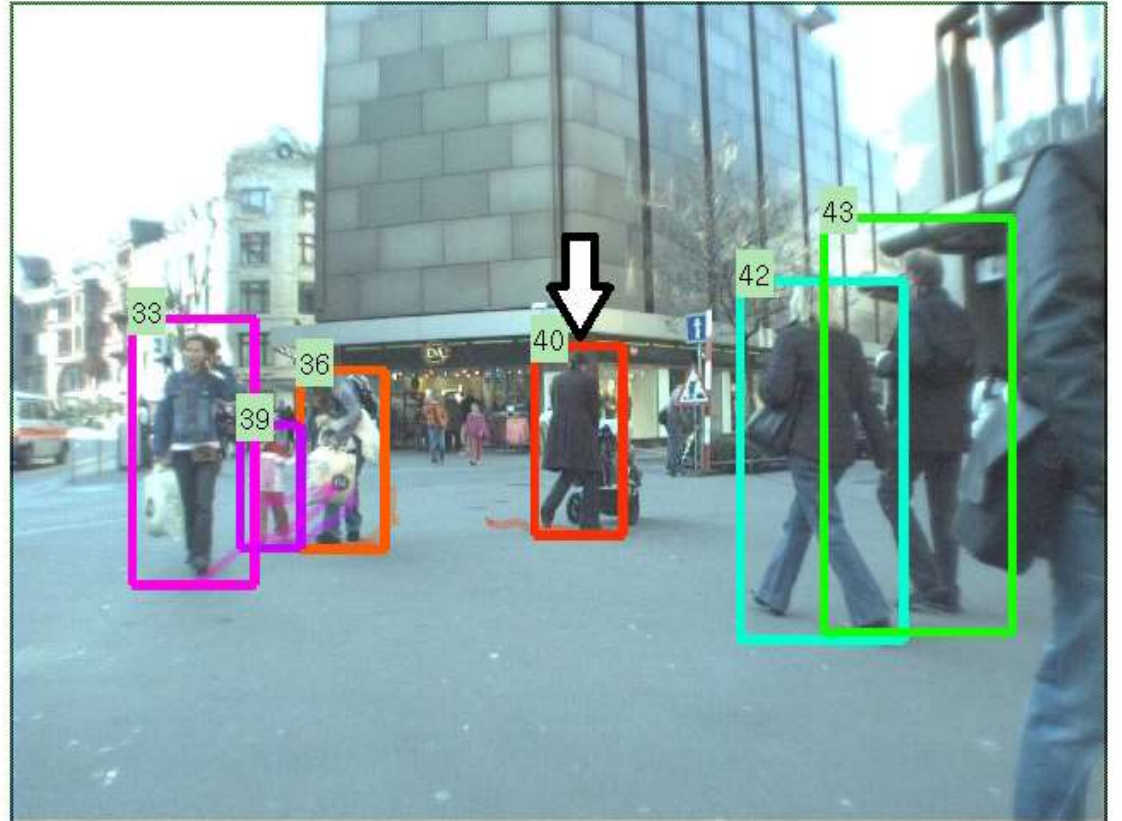
[7] Milan et al., CVPR'15

[8] Leal-Taixé et al., CVPR'14

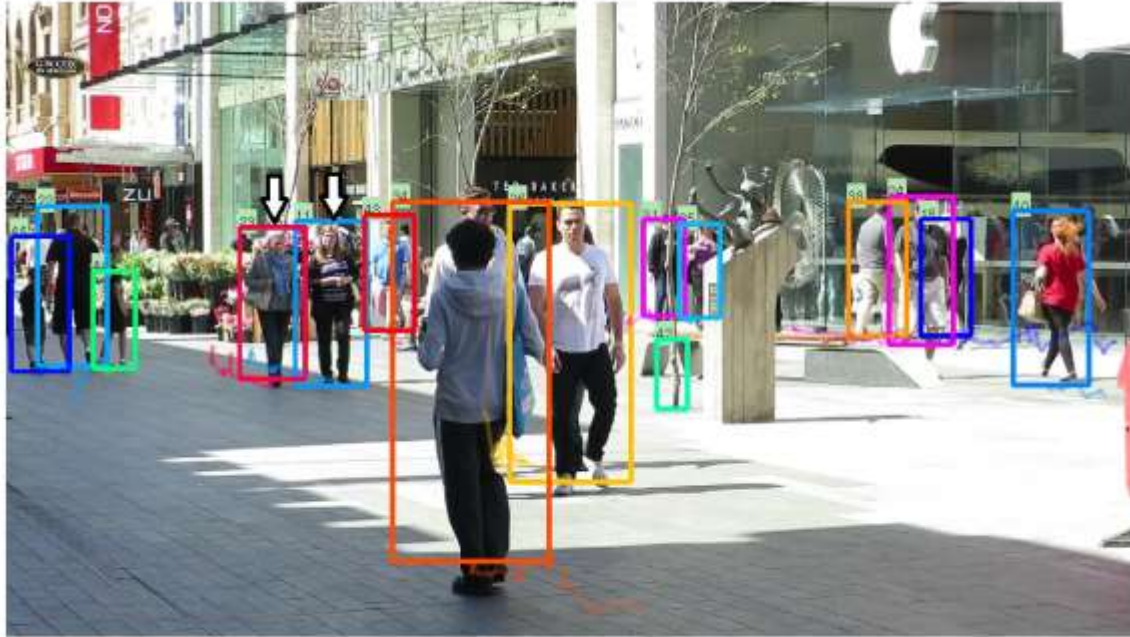
# Tracking Results



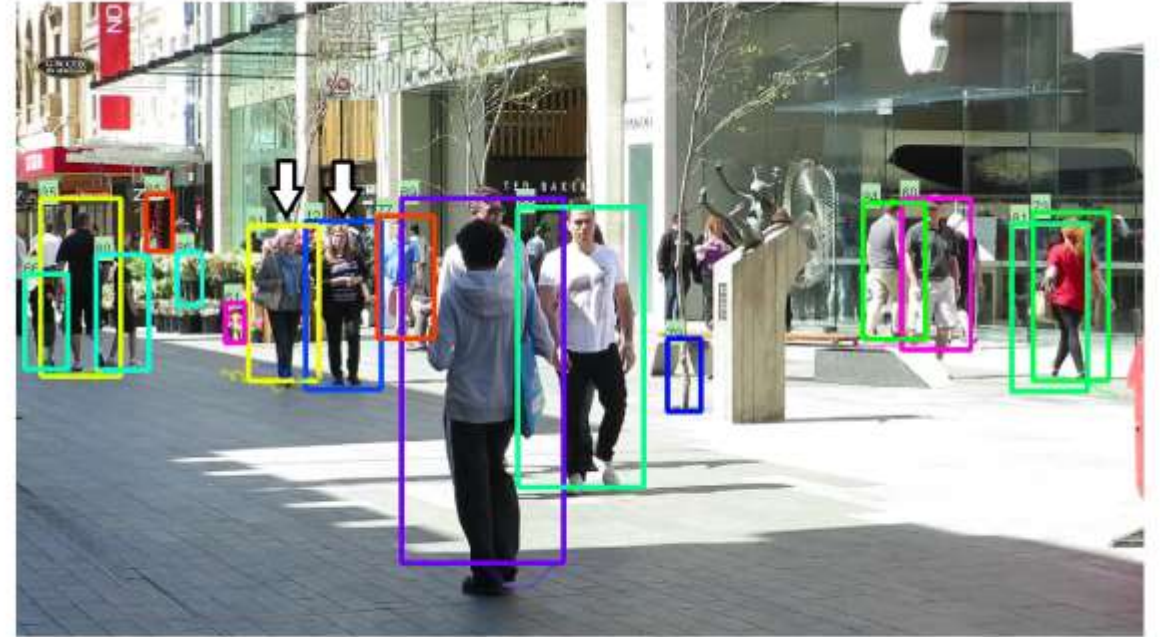
MDP [Ours]



MotiCon [Leal-Taixé et al., CVPR'14]

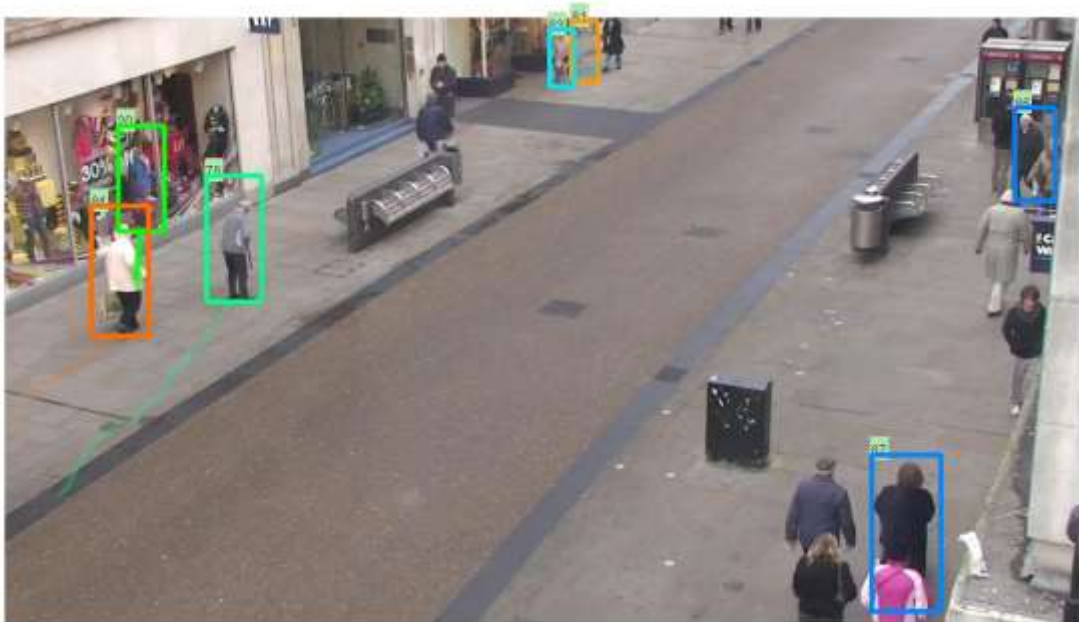


MDP [Ours]



MotiCon [Leal-Taixé et al., CVPR'14]





MDP [Ours]



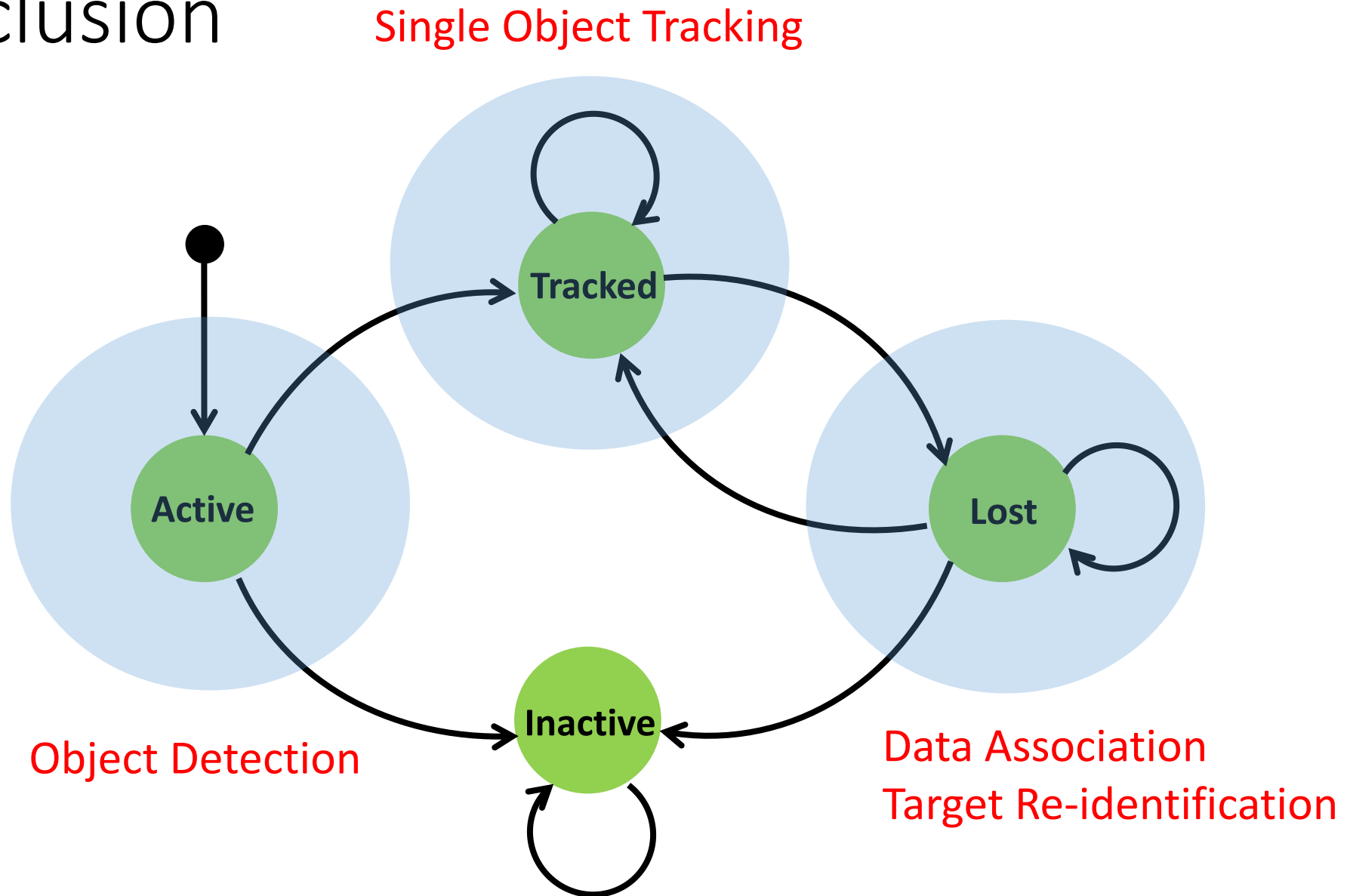
MotiCon [Leal-Taixé et al., CVPR'14]

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# Conclusion



# Code



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112 commits 1 branch 0 releases 1 contributor

Branch: master MDP\_Tracking / +

Yu Xiang make video 1 to N Latest commit 744796b on Oct 6

3rd_party	hungarian	7 months ago
qsub	qsub	8 months ago
.gitignore	remove files	2 months ago
LICENSE	Initial commit	10 months ago
LICENSE_TLD	add TLD license	2 months ago
LK.m	clean up	8 months ago
LK_associate.m	add comments	2 months ago
LK_crop_image_box.m	add comments	2 months ago
LK_initialize.m	add comments	2 months ago

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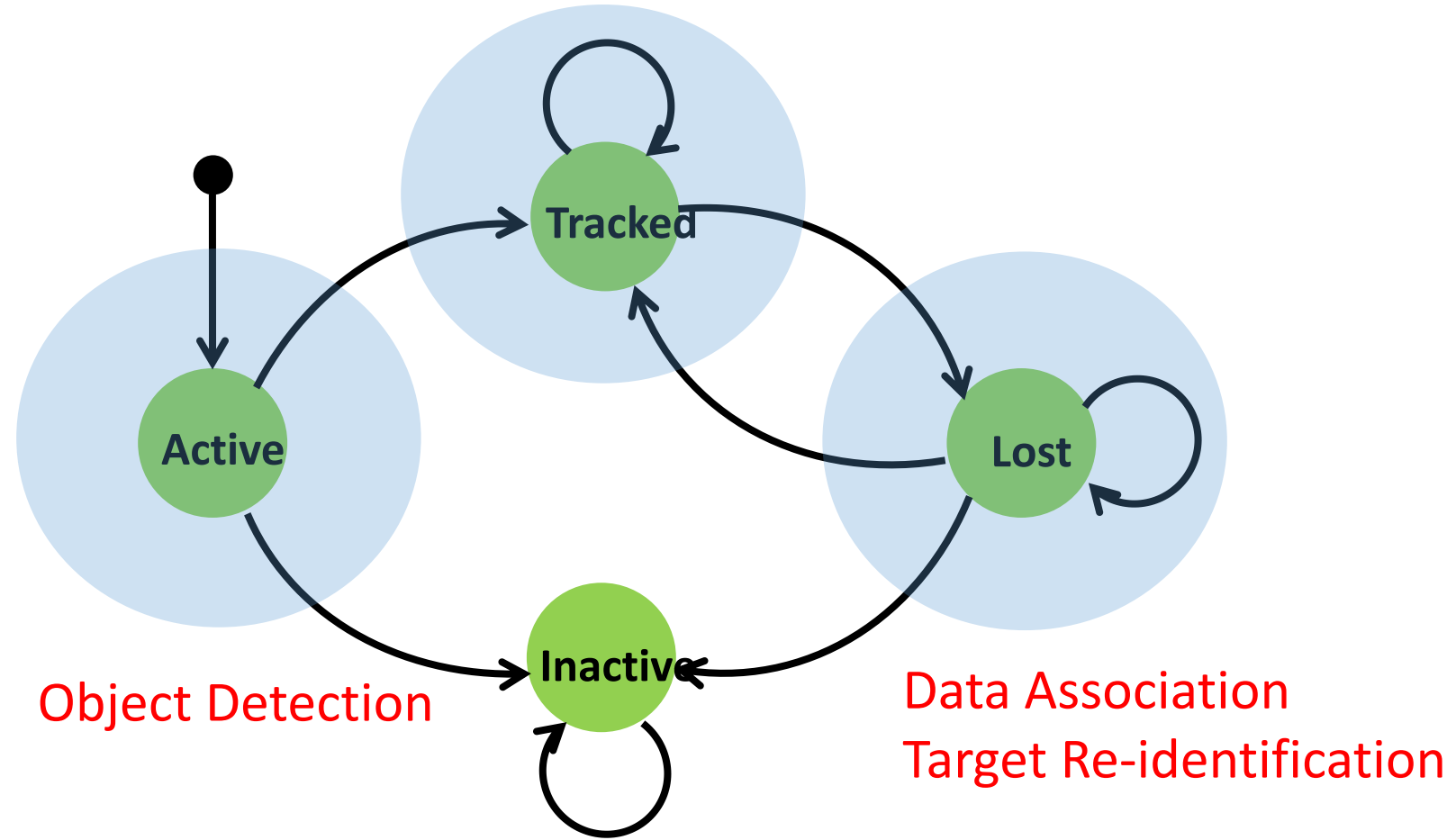


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## Single Object Tracking



# Thank you!

