Tracking Library for the Web

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Outline

1 Introduction

2 Basic concepts
- Web
- Visual tracking
- Visual tracking on the web

3 Tracking library for the web

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Motivation

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- Phones and notebooks devices have embedded web browser
- Entertainment solutions are gaining space on the web
- Vision is an accurate and low-cost solution

Problem definition

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- Video processing requires high computational complexity
- JavaScript is a language interpreted by all web browsers
- Interpreted languages have limited computational power

Objectives

- Facilitate user interaction with the web browser

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- Accelerate the use of visual tracking in commercial products

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- Facilitate user interaction with the web browser
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- Implement a cross-platform tracking library for the web

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The beginning of the web

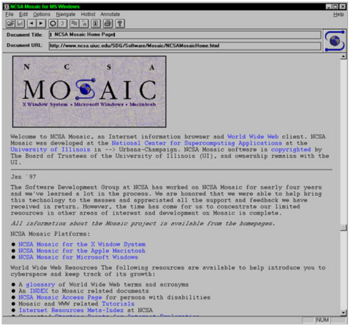

Figure : Mosaic is the web browser credited with popularizing the World Wide Web.

The beginning of the web

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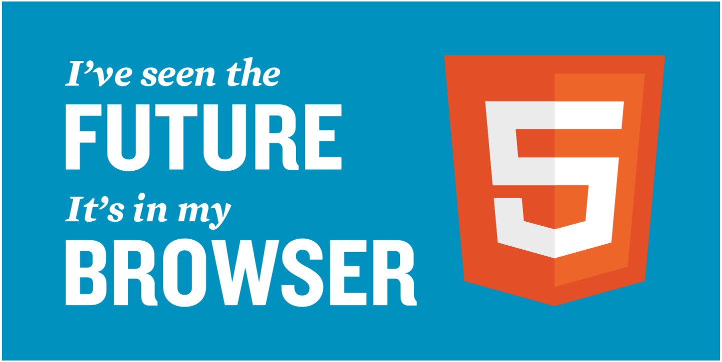
- In 1994, the World Wide Web Consortium (W3C) was founded
- Companies were able to contribute to the W3C specifications
- Today's web is a result of the ongoing efforts of an open web

The modern web



The modern web

- Contributions transformed the web in a growing universe

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- Contributions transformed the web in a growing universe
- Videos, audio, photos, interactive content, 3D graphics
- Processed by the Graphics Processing Unit (GPU)
- Without requiring any third-party plugins installation

Browser technologies

Browser architecture

Figure : Web browsers running on different devices.

Browser architecture

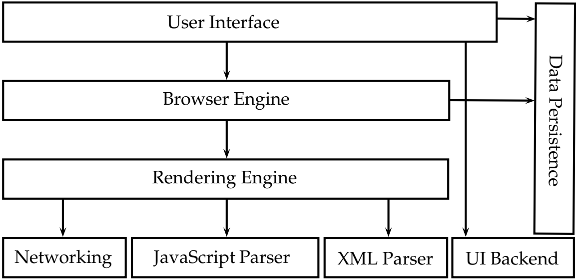


Figure : Reference architecture for web browsers.

Visual tracking

Tracking an object in a video sequence means continuously identifying its location when either the object or the camera are moving.

Figure : Example of an accurate object tracking robust to occlusion.

Visual tracking

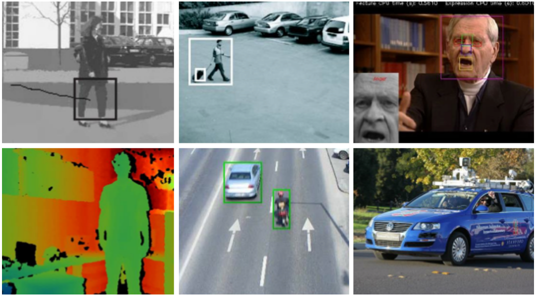
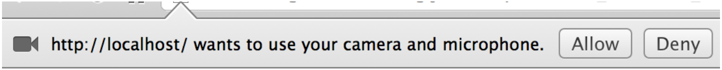


Figure : Computer vision applications: motion-based recognition (top left); automated surveillance (top center); video indexing (top right); human-computer interaction (bottom left); traffic monitoring (bottom center); vehicle navigation (bottom right).

Visual tracking workflow on the web

1. Request user web-cam access



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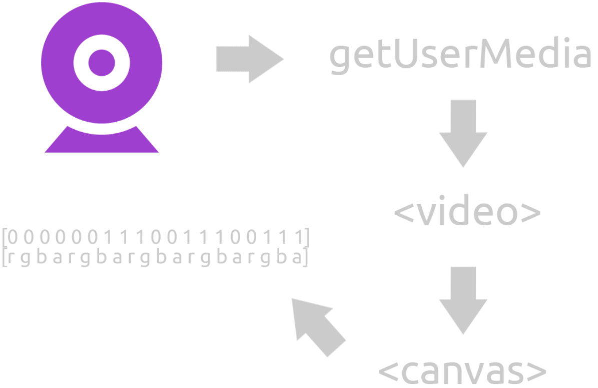

2. Capture web-cam stream

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<script>
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    // Stream captured
  }, onFail);
</script>
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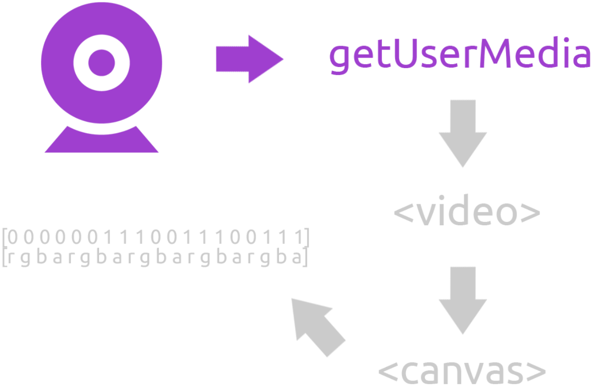

3. Reproduce web-cam stream into the video

Figure : Video and audio HTML5 elements.

3. Reproduce web-cam stream into the video

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<video autoplay></video>
<script>
  var video = document.querySelector('video');
  navigator.getUserMedia({video: true}, function(localMediaStream) {
      video.src = window.URL.createObjectURL(localMediaStream);
      video.onloadedmetadata = function(e) { alert('Ready to go.') };
  }, onFail);
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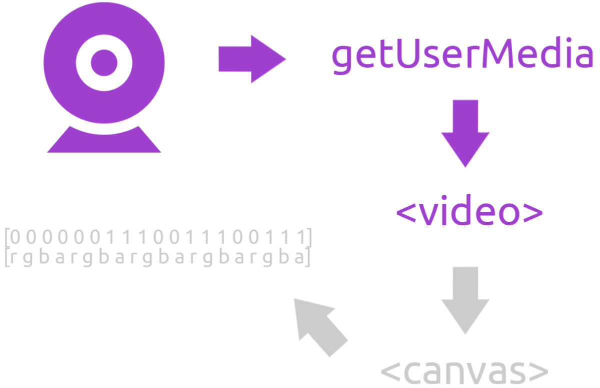

4. Process video data using canvas

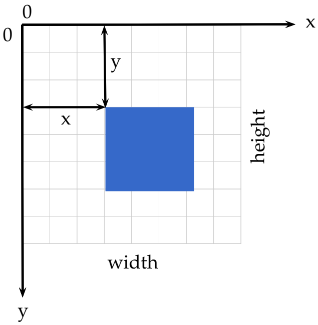

Figure : The canvas element.

4. Process video data using canvas

- Introduced as a new element on HTML5

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- Introduced as a new element on HTML5
- Resolution-dependent bitmap canvas
- Two-dimensional grid, computer graphics coordinate system
- Can render images, video frames or shapes

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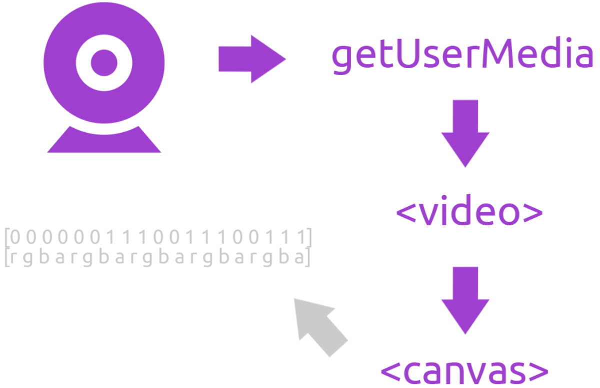

5. Access canvas data using JavaScript typed arrays

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- Browsers needed a quick way to manipulate raw binary data
- Typed data structures were added to JavaScript
- JavaScript-typed arrays access raw binary more efficiently

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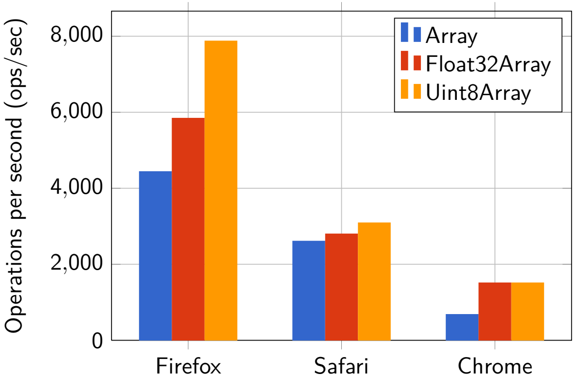
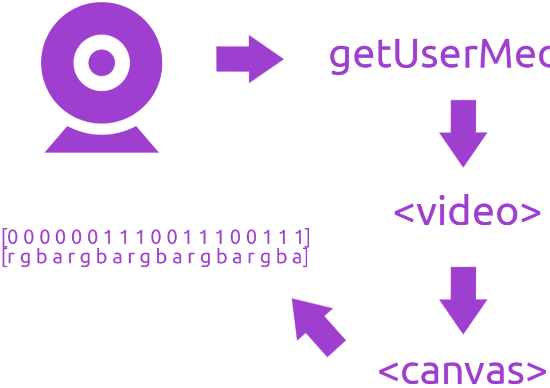


Figure : Regular *vs* typed arrays performance benchmark.

5. Access canvas data using JavaScript typed arrays



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- Canvas raw binary data can be accessed from JavaScript
- Canvas array of pixels, is in row-major order
- Consider the 2×3 array $\begin{bmatrix} 1 & 2 & 3 \\ 4 & 5 & 6 \end{bmatrix}$, in row-major order it is laid out contiguously in linear memory as $\begin{bmatrix} 1 & 2 & 3 & 4 & 5 & 6 \end{bmatrix}$.

What is the relation between typed arrays and canvas?

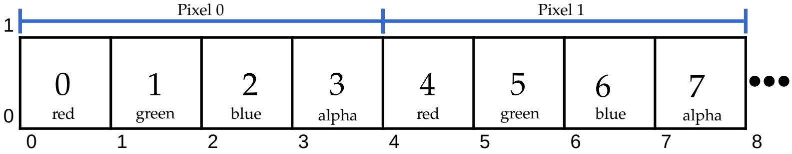

Figure : The canvas image data array of pixels.

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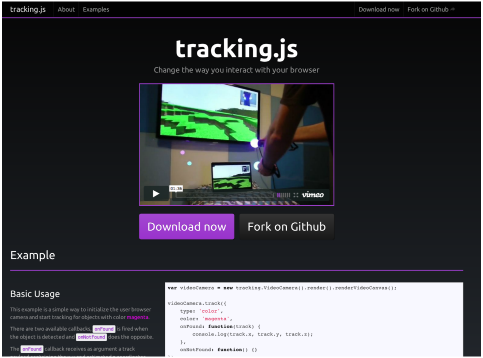
tracking.js


tracking.js
About
Examples
Download now
Fork on Github
tracking.js
Change the way you interact with your browser
01:36
vimeo
Download now
Fork on Github
Example
Basic Usage
This example is a simple way to initialize the user browser camera and start tracking for objects with color magenta.
There are two available callbacks, onFound is fired when the object is detected and onNotFound does the opposite.
The onFound callback receives as argument a track
var videoCamera = new tracking.VideoCamera().render().renderVideoCanvas();
videoCamera.track({
type: 'color',
color: 'magenta',
onFound: function(track) {
console.log(track.x, track.y, track.z);
},
onNotFound: function() {}

tracking.js

Tracking library for the web

Common infrastructure to develop visual tracking applications and to accelerate the use of those techniques on the web in commercial products.

Related work

- FLARToolKit: a port of ARToolKit marker tracking library to ActionScript

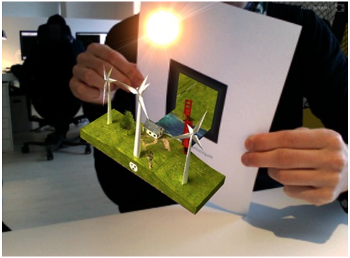


Figure : Marker based AR for the web using FLARToolKit.

Related work

- JSARToolkit: is a JavaScript port of FLARToolKit

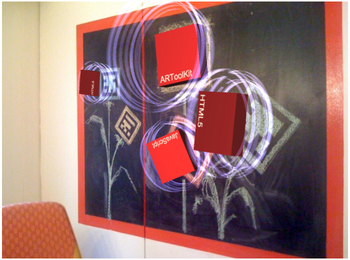


Figure : Marker-based AR for the web using JSARToolKit.

Related work

- Unifeye Viewer: a robust markerless tracking solution for the web to ActionScript

Figure : Markerless example of image projected over a magazine cover.

Flash vs HTML5

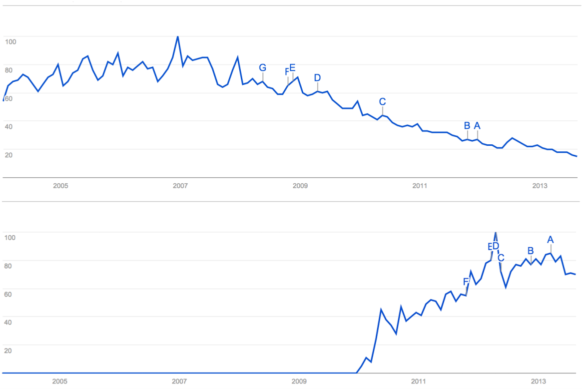


Figure : Google trends results for "flash games" on the top, and for "html5 games" on the bottom.

Library features

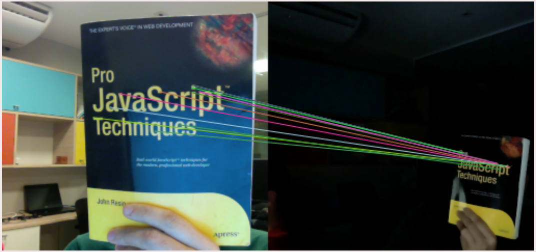
1. Color tracking

Library features

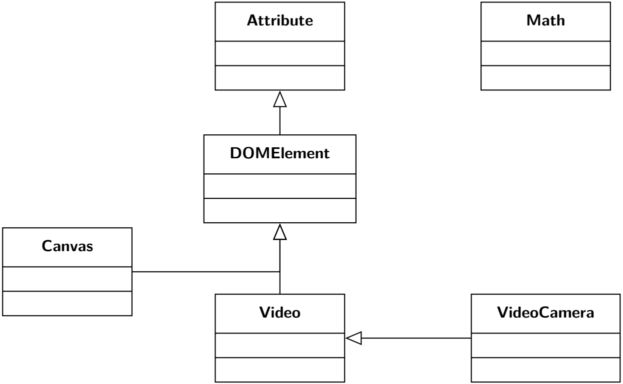
2. Rapid object detection (Viola Jones)

Library features

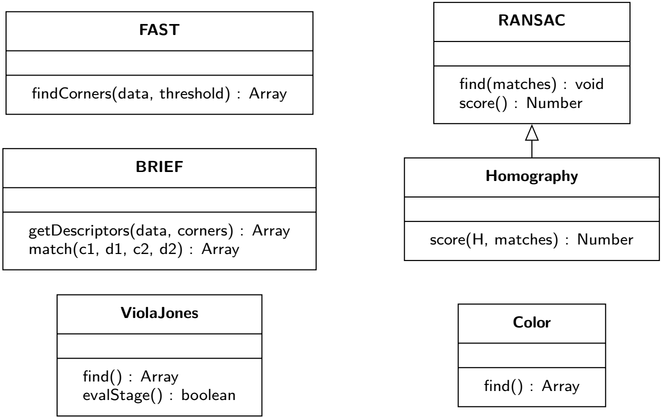
3. Markerless tracking algorithm



Library modules - Base classes



Library modules - Visual tracking classes



Color tracking algorithm

Figure : © http://www.flickr.com/photos/laynecom/8674644879/

Color tracking algorithm - Color difference evaluation

$$\|C_1 - C_2\| = \sqrt{(C_{1,R} - C_{2,R})^2 + (C_{1,G} - C_{2,G})^2 + (C_{1,B} - C_{2,B})^2}$$

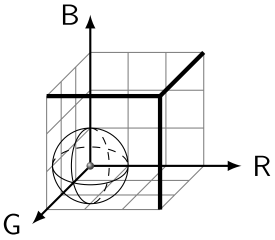
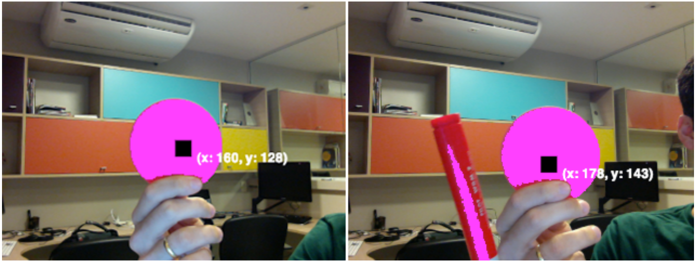
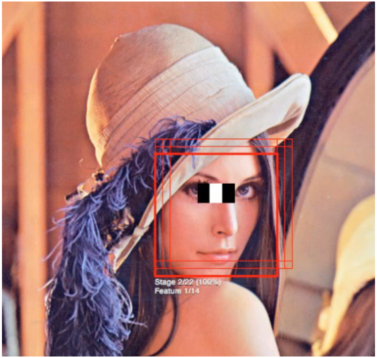


Figure : Color neighborhood represented in a RGB orthogonal three-dimensional color space.

Color tracking algorithm - Color blob detection



Rapid object detection (Viola Jones)



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- A training phase is required
- A scanning detector is what makes the detection

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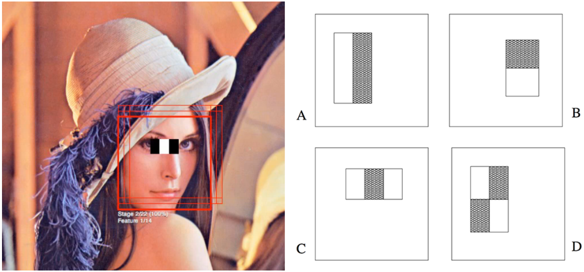

Figure : Images are classified based on the value of rectangle features.

Rapid object detection (Viola Jones)

Integral Image

Rectangle features can be computed very rapidly using an intermediate representation for the image which we call the integral image.

The integral image at location x, y contains the sum of the pixels above and to the left of x, y, inclusive

$$ii(x, y) = \sum_{x' \leq x, y' \leq y} i(x', y')$$

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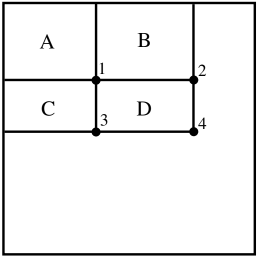

Figure : The sum of the pixels within rectangle D can be computed with four array references. The value of the integral image at location 1 is the sum of the pixels in rectangle A. The value at location 2 is $A + B$, at location 3 is $A + C$ and at location 4 is $A + B + C + D$.

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Scanning detector algorithm

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6. Once the tree is done, group the overlapping rectangles
7. Find the best rectangle of each the group (merging phase)

Rapid object detection (Viola Jones)

Optimized merging phase

Rectangles are used partitioned into a disjoint set data structure. On this work it was replaced by an alternative called Minimum Neighbor Area Grouping.

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Optimized merging phase

Rectangles are used partitioned into a disjoint set data structure. On this work it was replaced by an alternative called Minimum Neighbor Area Grouping.

Minimum Neighbor Area Grouping

Simple loop trough the possible rectangles comparing the current rectangle with all other not yet compared. If their area overlaps by $\eta = 0.5$ the smallest rectangle of the set is selected.

Feature detector (FAST)

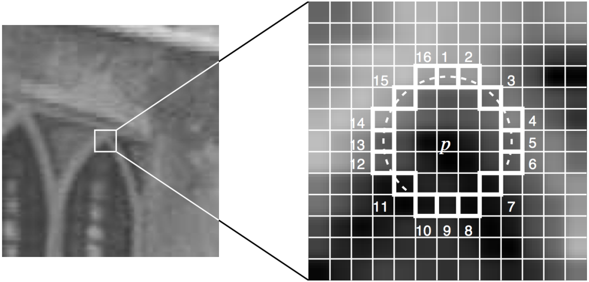
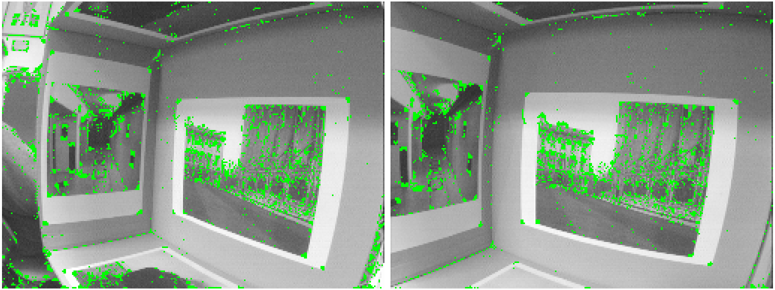
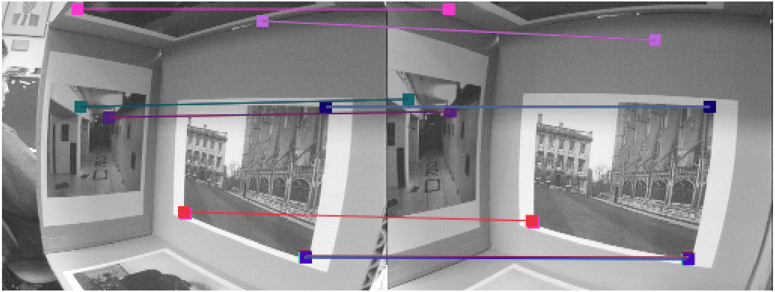


Figure : Point segment test corner detection in an image patch.

Feature detector (FAST)



Feature extractor (BRIEF)



Feature extractor (BRIEF)

To generate the binary strings it is defined the test τ on patch $\mathbf{p}$ of size $\mathbf{S} \times \mathbf{S}$ as:

$$\tau(\mathbf{p}; x, y) := \begin{cases} 1 & \text{if} \quad \mathbf{p(x)} < \mathbf{p(y)}, \\ 0 & \text{otherwise} \end{cases}$$

Feature extractor (BRIEF)

The n_d-dimensional bit-string is our BRIEF descriptor for each keypoint:

$$f_{n_d}(\mathbf{p}) := \sum_{1 \leq i \leq n_d} 2^{i-1} \tau(\mathbf{p}; x, y).$$

In this work $n_d = 128$ was used. The number of bytes required to store the descriptor can be calculated by $k = n_d/8$.

Feature extractor (BRIEF)

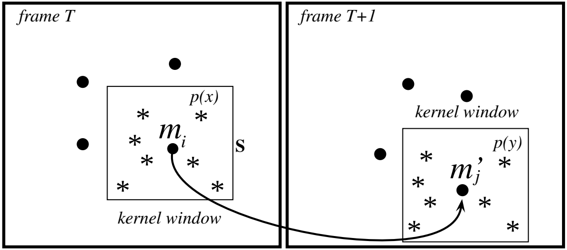


Figure : BRIEF feature extractor.

Feature extractor (BRIEF)

The weighted Hamming distance is computed by:

$$WHam(x, y) = \sum_{i=1}^{n} w_i(b_i(x) \otimes b_i(y))$$

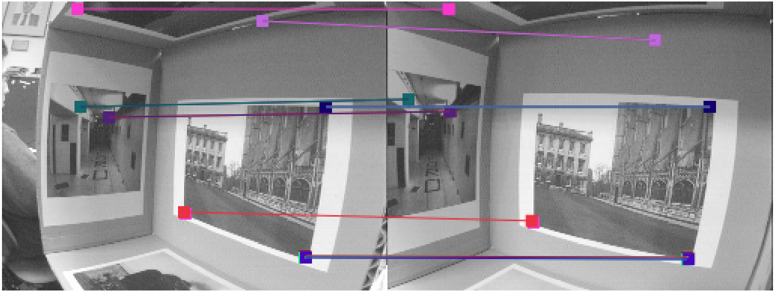
$$b_1 = 0000000001...$$

$$b_2 = 0000000011...$$

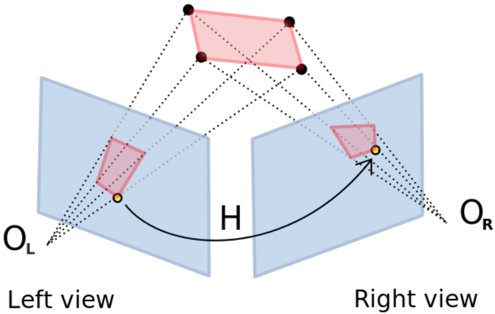
$$b_1 \otimes b_2 = 0000000010...$$

$$WHam = 1$$

Feature extractor (BRIEF)



Homography estimation



Random sample consensus (RANSAC)

RANSAC (Random Sample Consensus) is an iterative method to estimate parameters of a mathematical model from a set of observed data which contains outliers. It is the most commonly used robust estimation method for homographies.

Homography estimation

Homography is a mapping from $P^2 \rightarrow P^2$ which is a projectivity if and only if there exists a non-singular 3×3 matrix H such that for any point in P^2 represented by vector **x** it is true that its mapped point equals $H\mathbf{x}$

$$c \begin{pmatrix} u \\ v \\ 1 \end{pmatrix} = H \begin{pmatrix} x \\ y \\ 1 \end{pmatrix}, \quad H = \begin{pmatrix} h1 & h2 & h3 \\ h4 & h5 & h6 \\ h7 & h8 & h9 \end{pmatrix},$$

where c is any non-zero constant, $(\ u\ v\ 1\ )^T$ represents **x'**, $(\ x\ y\ 1\ )^T$ represents **x**