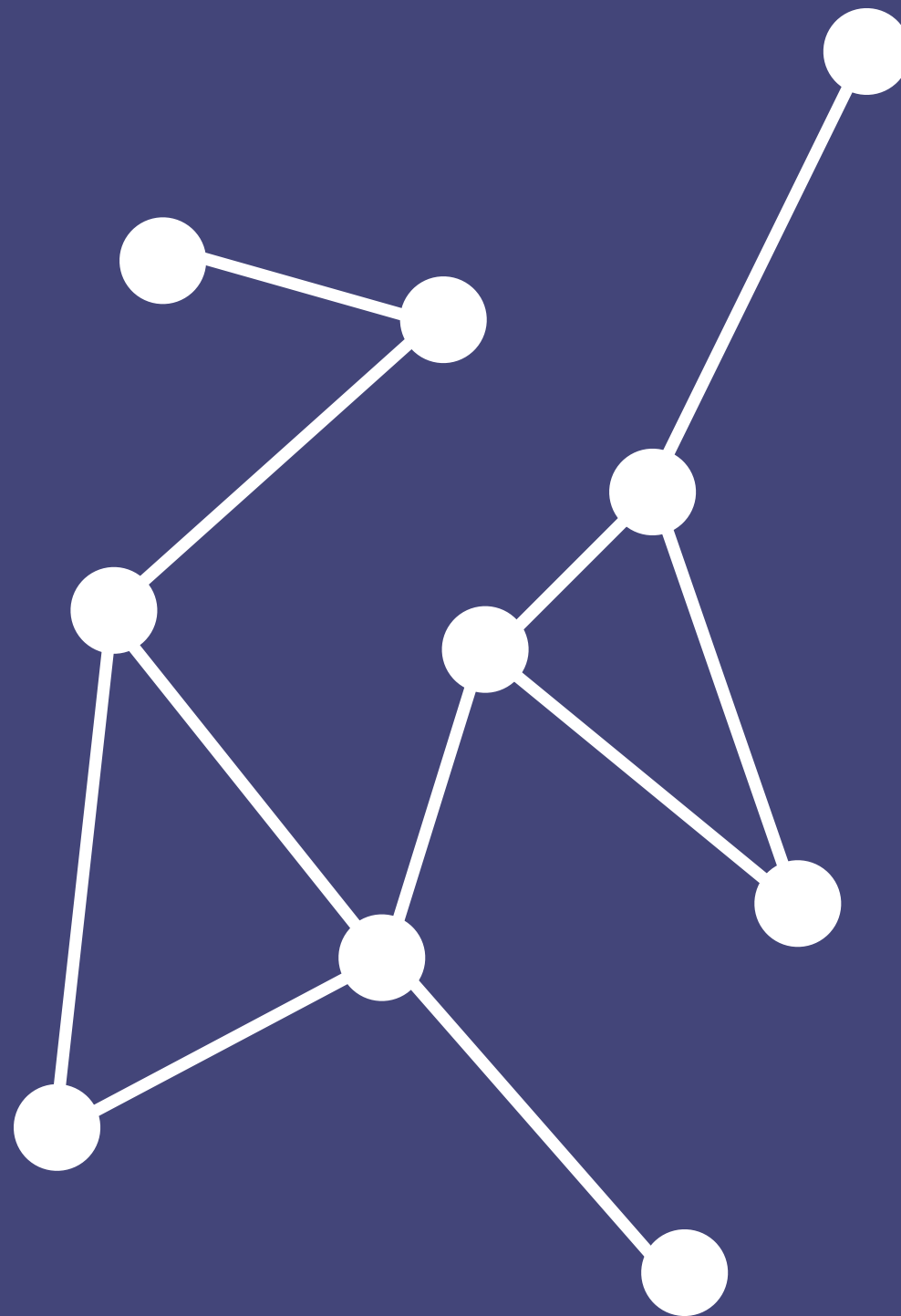


Spatial Temporal Graph Convolutional Networks for Skeleton-Based Action Recognition

A presentation by Faizaan Sakib

Spatial Temporal Graph Convolutional Network (STGCN)

Graph Convolutional Network



$$G = (V, E)$$



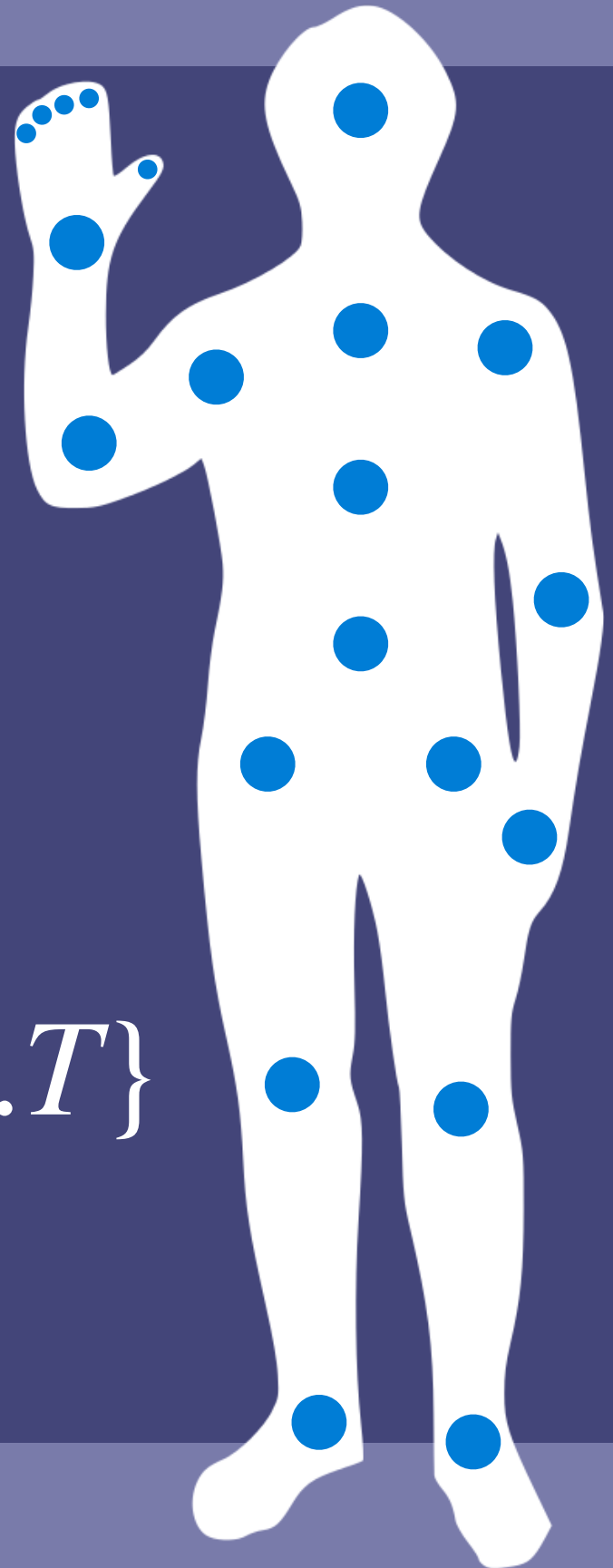
$$G = (V, E)$$



Graph Construction

$$G = (V, E)$$

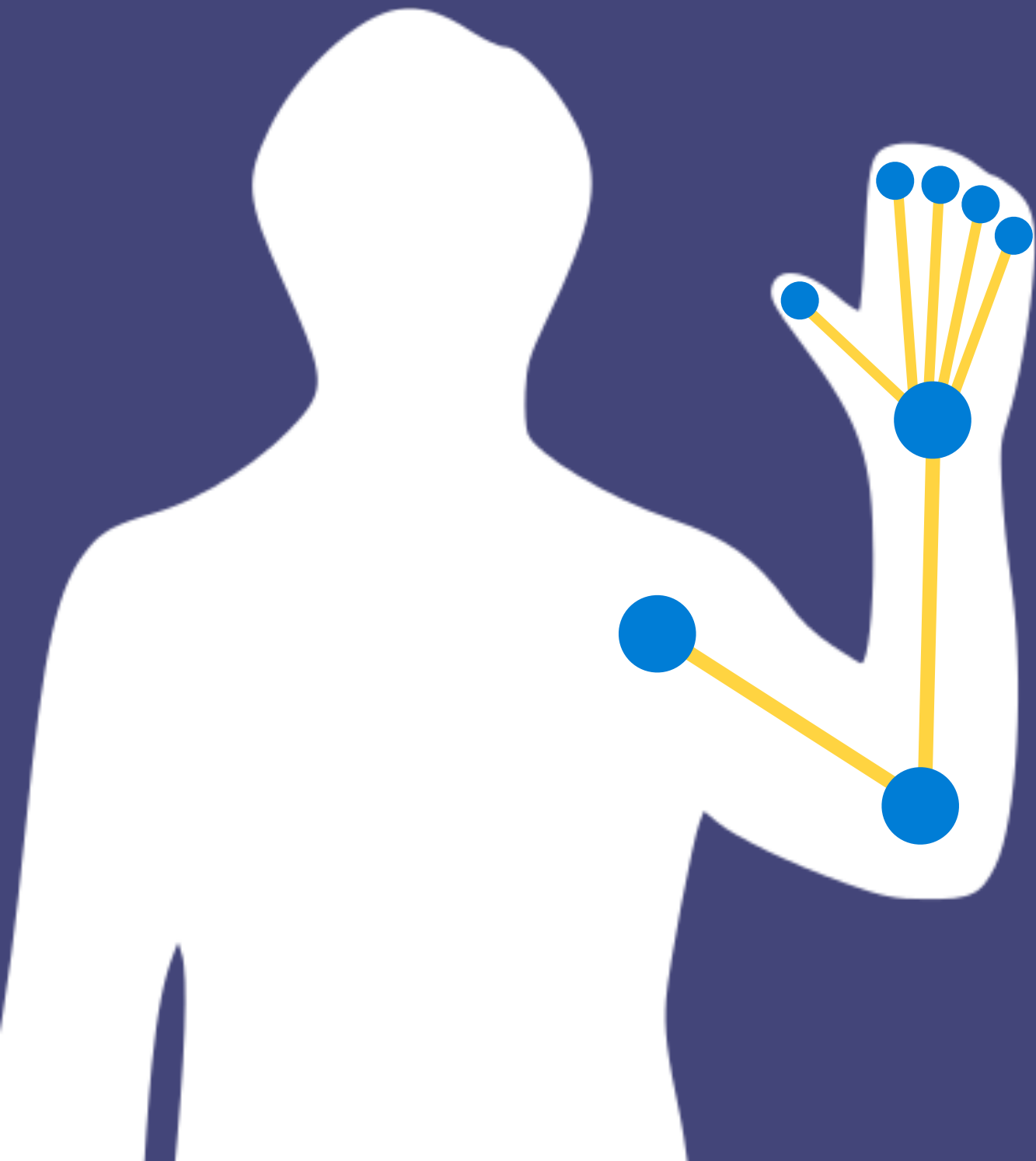
$$V = \{v_{it} \mid i = 1 \dots N, t = 1 \dots T\}$$



$$G = (V, E)$$

“intra-skeleton”

$$E_S = \{v_{it}v_{jt} \mid (i,j) \in H\}$$

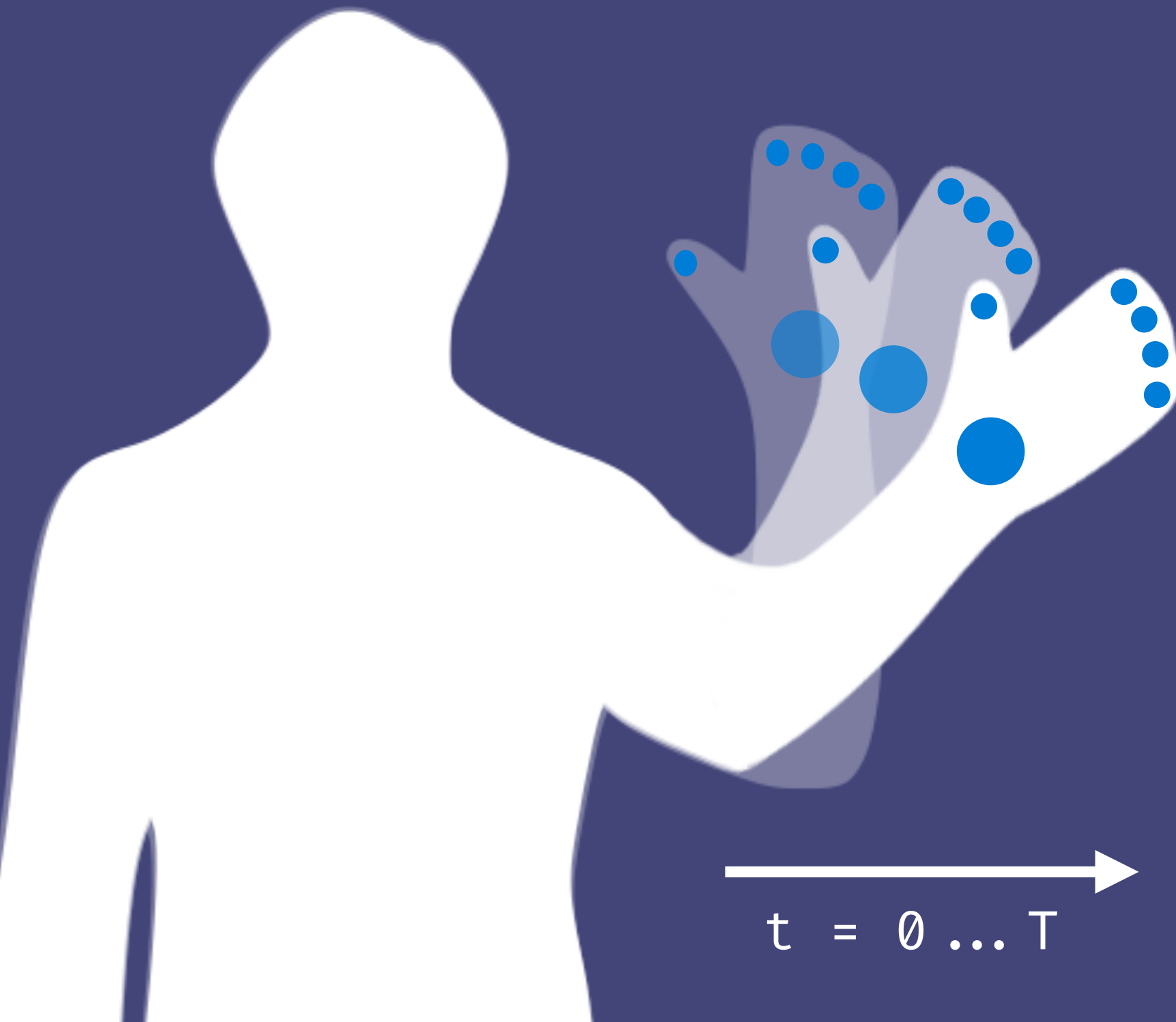


Spatial

Temporal

“intra-frame”

$$E_F = \{v_{it}v_{i(t+1)}\}$$



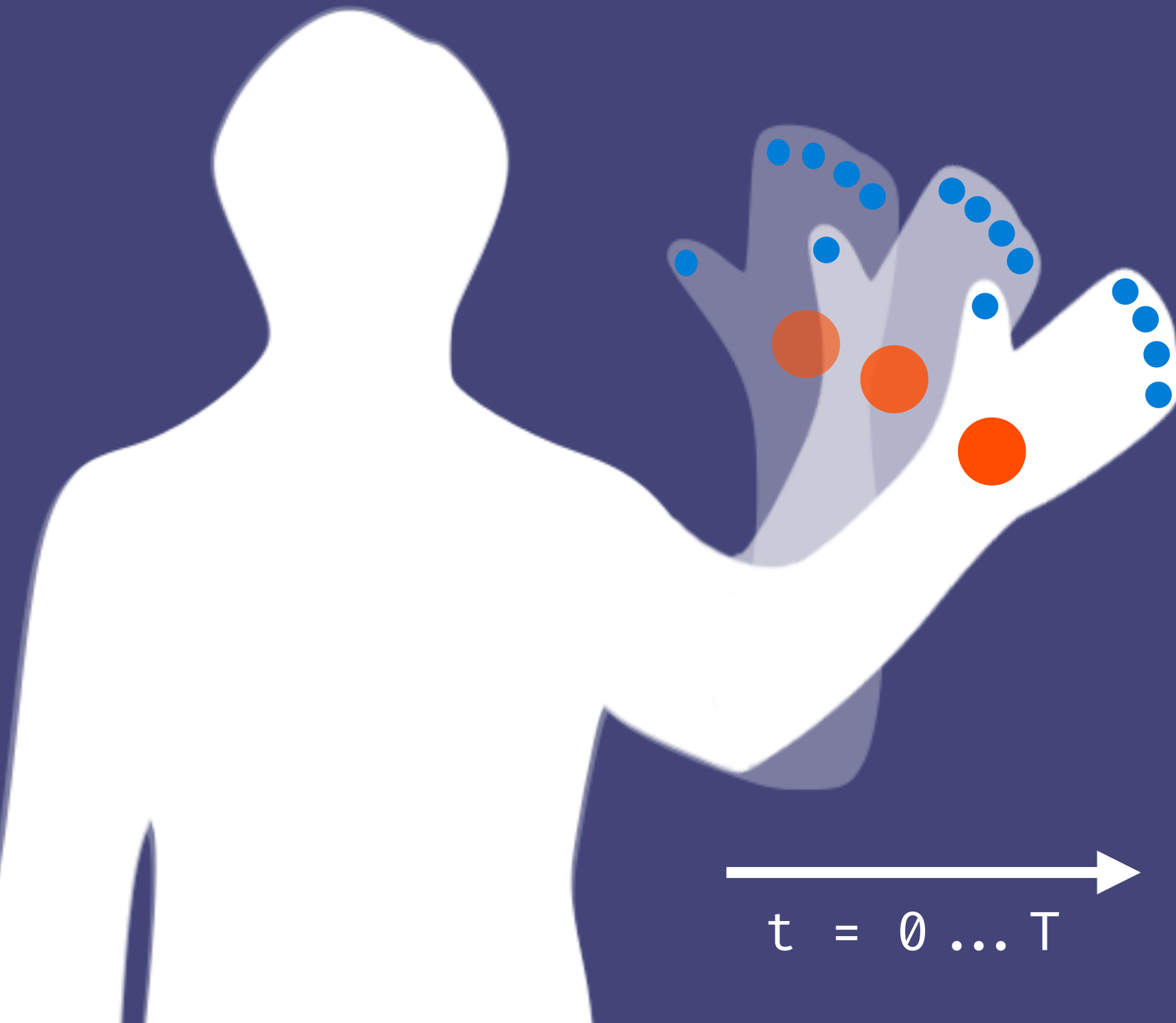
$t = 0 \dots T$

Spatial

Temporal

“intra-frame”

$$E_F = \{v_{it}v_{i(t+1)}\}$$

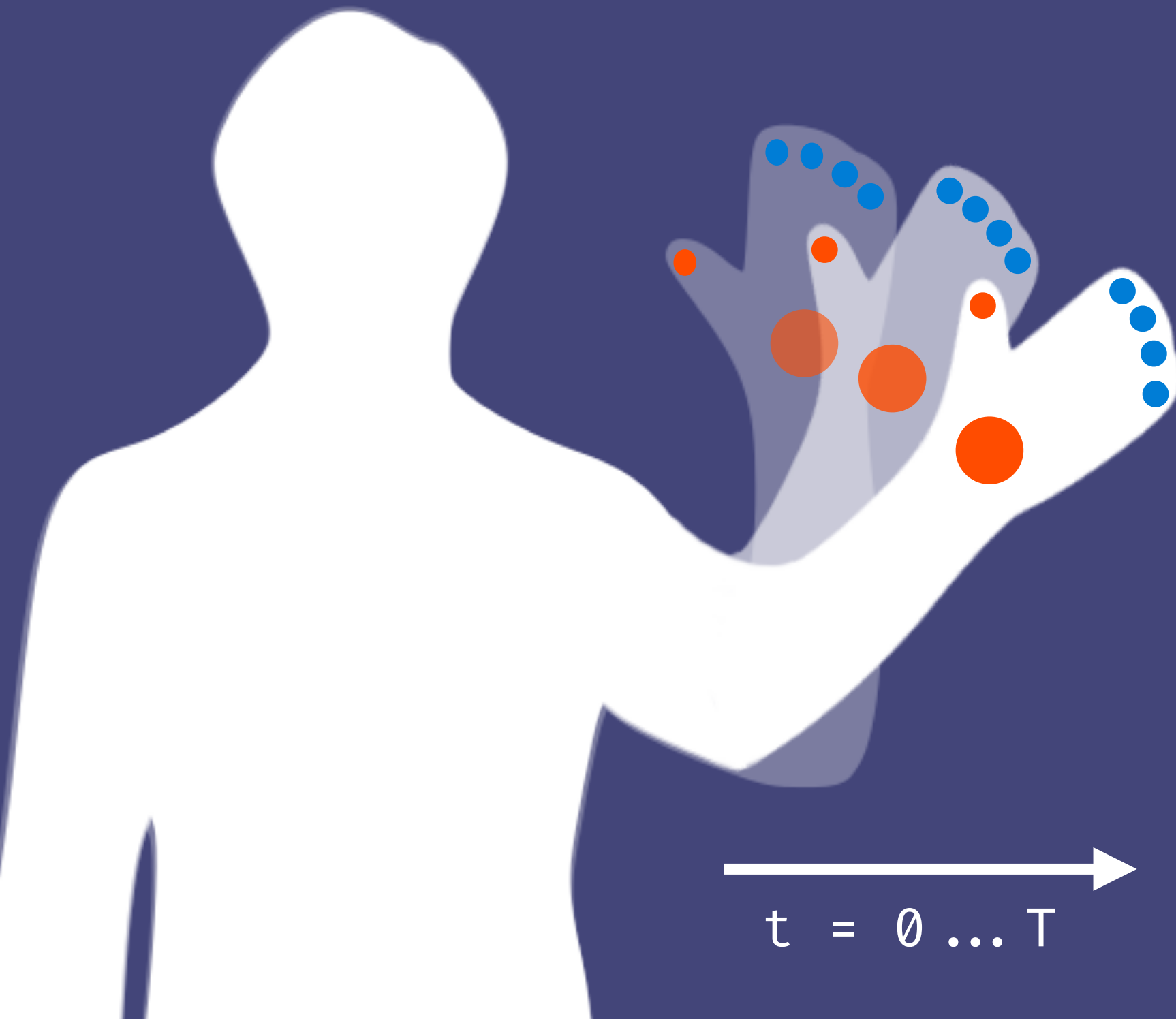


Spatial

Temporal

“intra-frame”

$$E_F = \{v_{it}v_{i(t+1)}\}$$

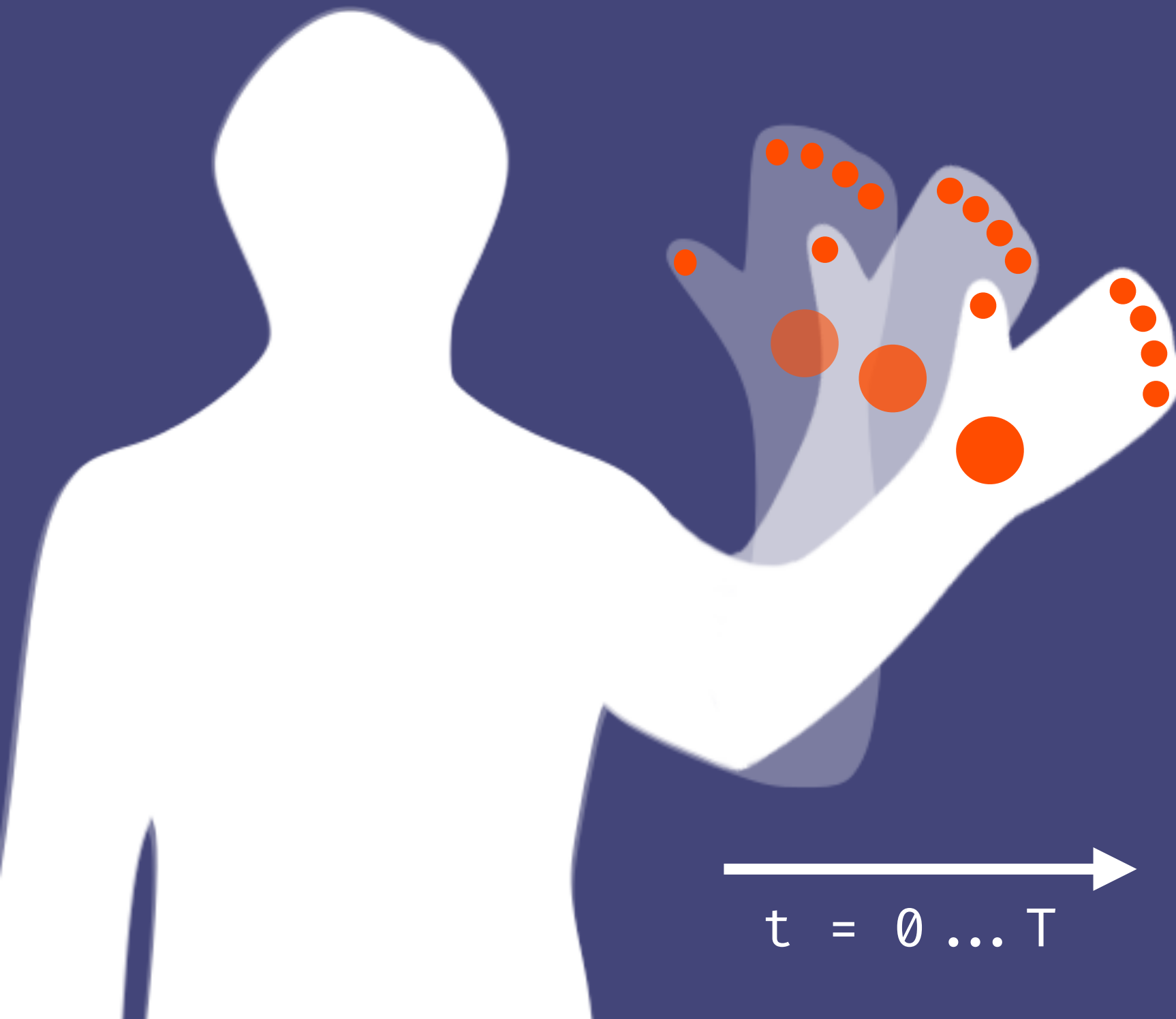


Spatial

Temporal

“intra-frame”

$$E_F = \{v_{it}v_{i(t+1)}\}$$



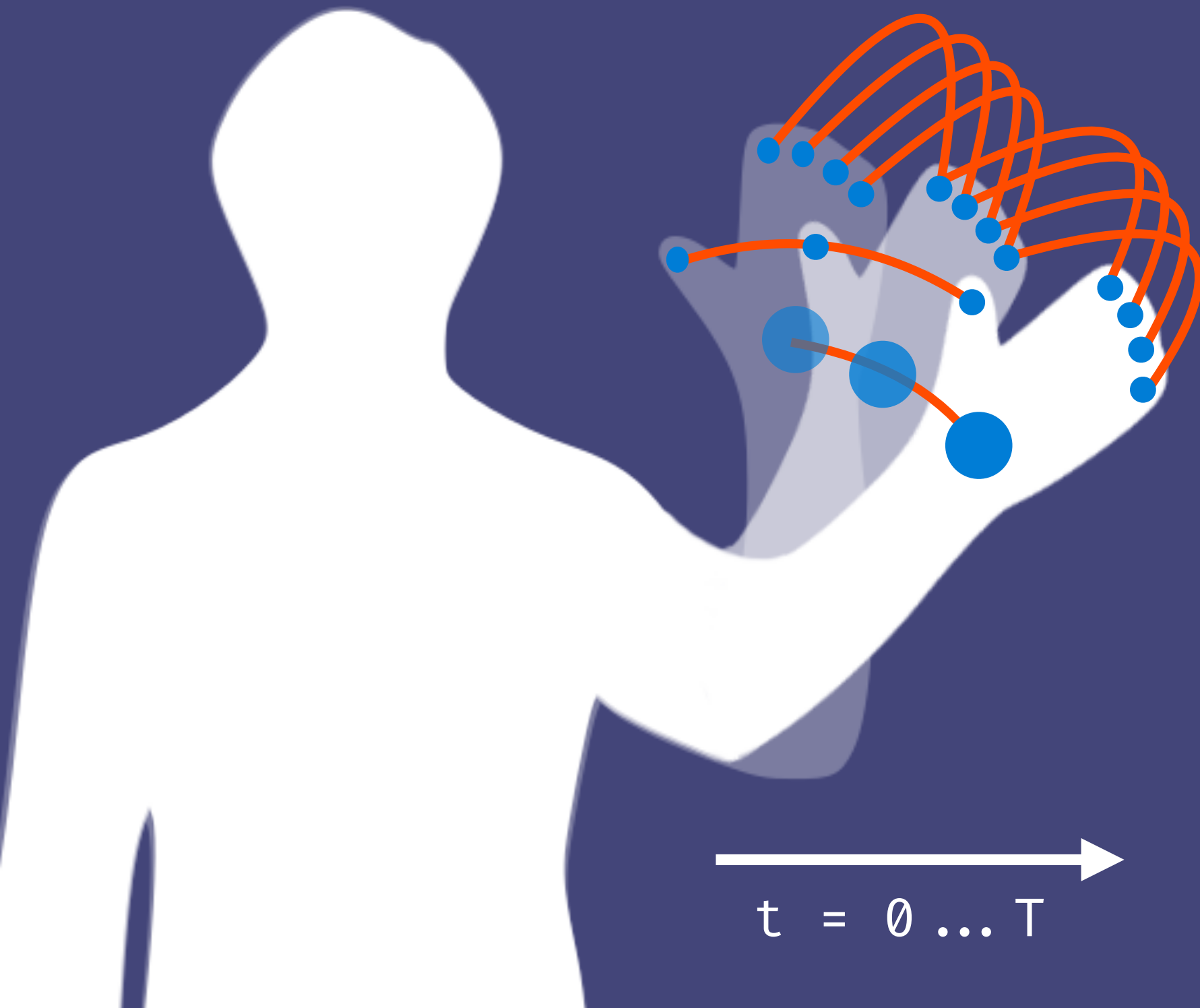
$t = 0 \dots T$

Spatial

Temporal

“intra-frame”

$$E_F = \{v_{it}v_{i(t+1)}\}$$



Spatial

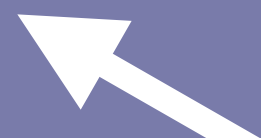
Temporal

Before
STGCNs

class = waving



softmax



CNN

singular RGB frame



CNN

consecutive multi-frame of
optical flow



input video

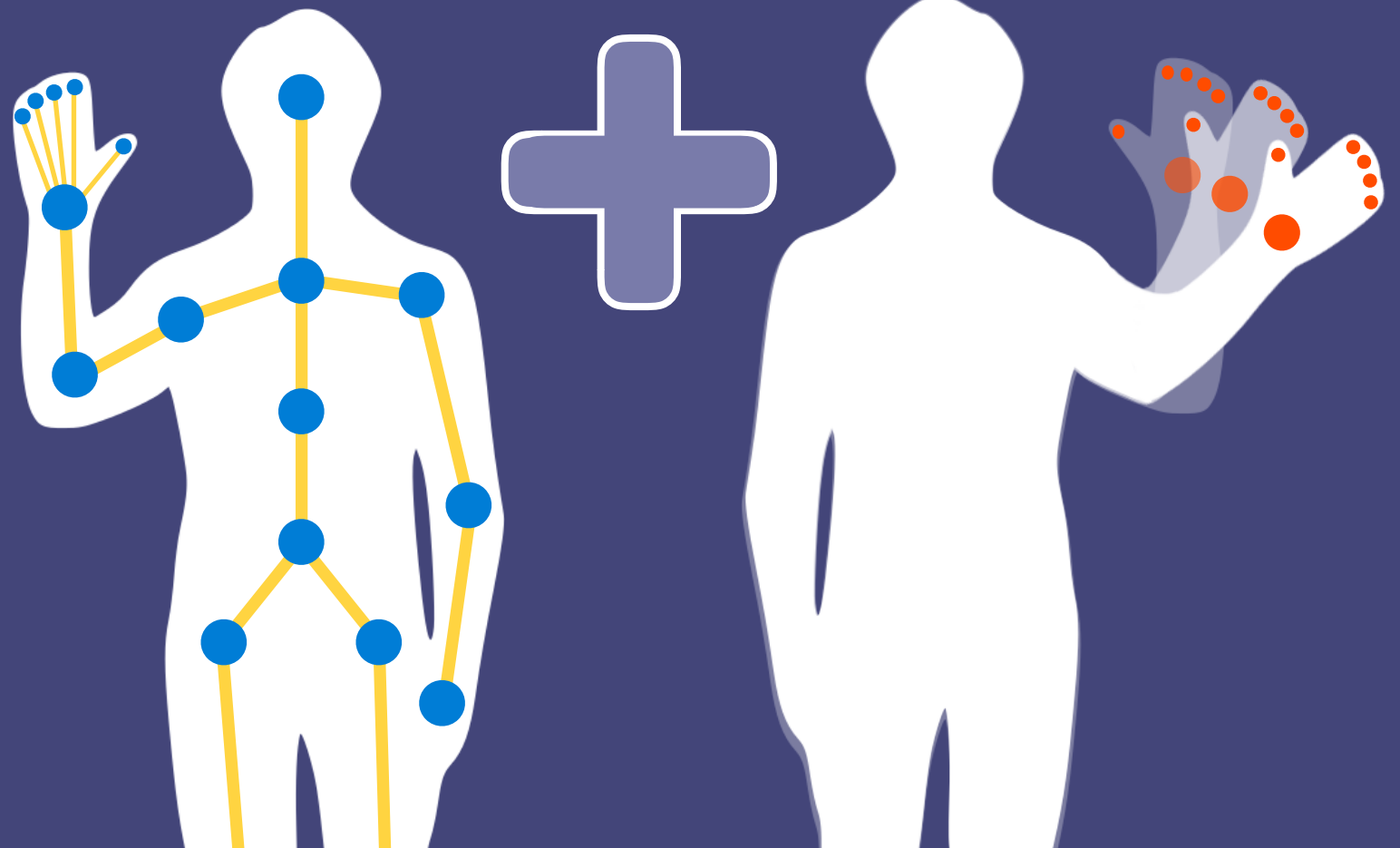
class = waving

softmax

STGCN

~9 layers

Pose
estimation
(e.g. OpenPose)



Graph Convolution

kernel

2	1	1
0	0	2
1	2	0



image

2	1	2	0	2
1	3	2	2	1
1	2	1	0	3
2	0	0	1	0
0	1	1	3	1

kernel

2	1	1
0	0	2
1	2	0

image

2	1	2	0	2
1	3	2	2	1
1	2	1	0	3
2	0	0	1	0
0	1	1	3	1

kernel

2	1	1
0	0	2
1	2	0



image

2	1	2	0	2
1	3	2	2	1
1	2	1	0	3
2	0	0	1	0
0	1	1	3	1

image

kernel

2	1	1
0	0	2
1	2	0



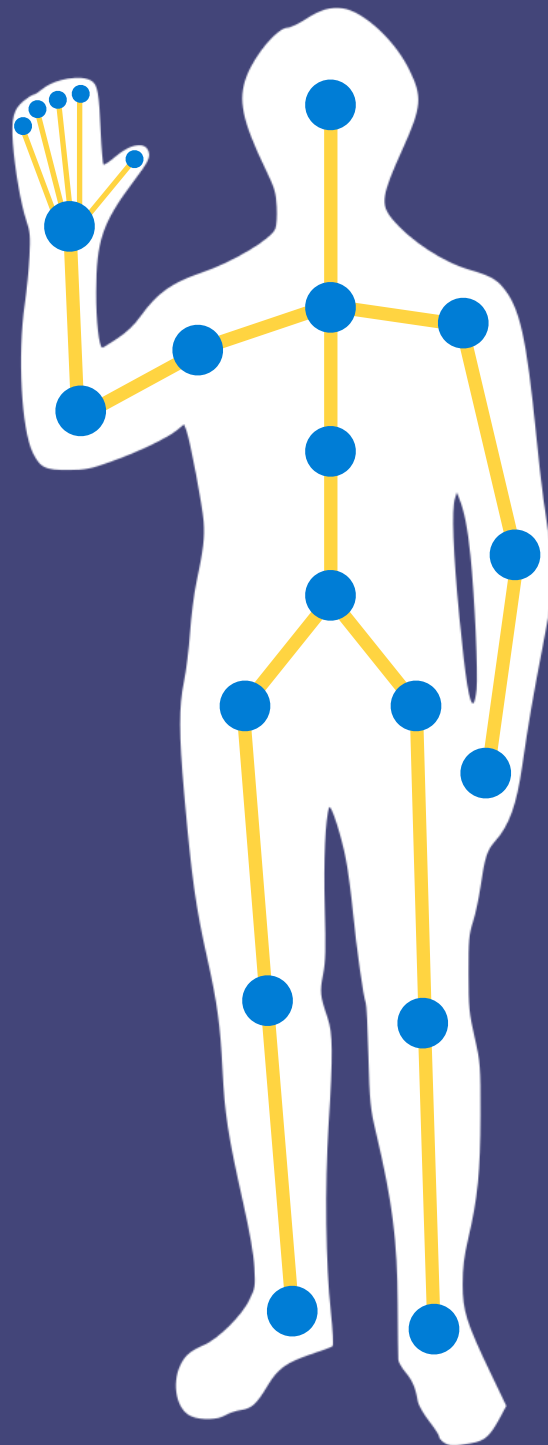
2	1	2	0	2
1	3	2	2	1
1	2	1	0	3
2	0	0	1	0
0	1	1	3	1



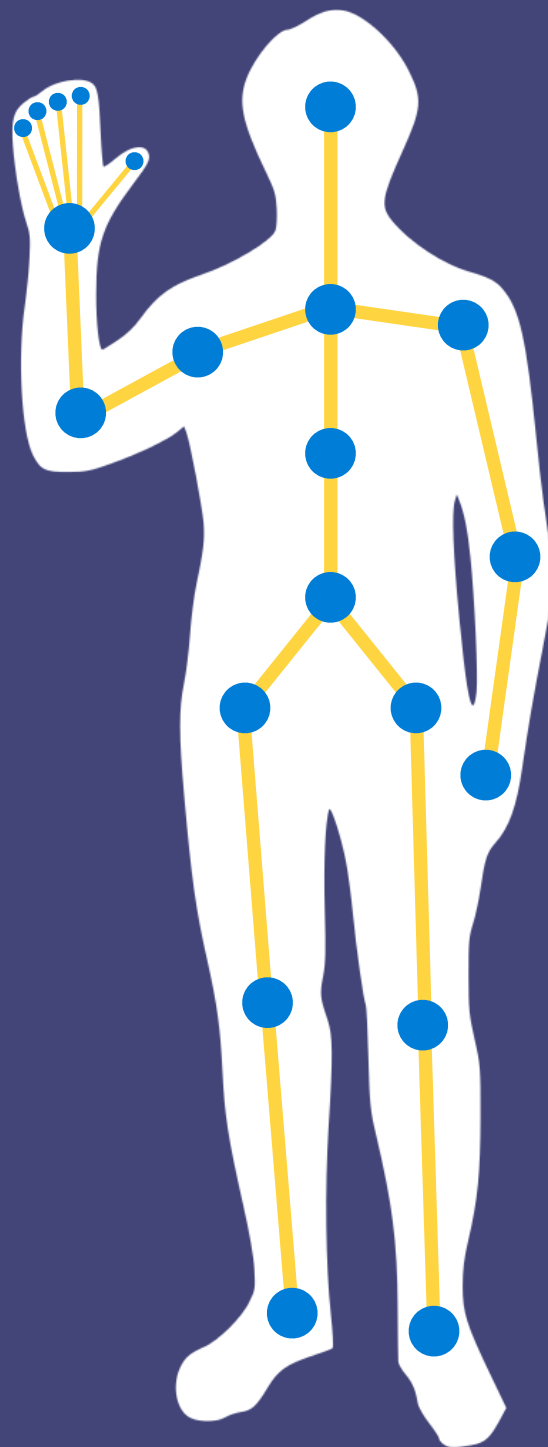
output

2	1	1
0	0	2
1	2	0

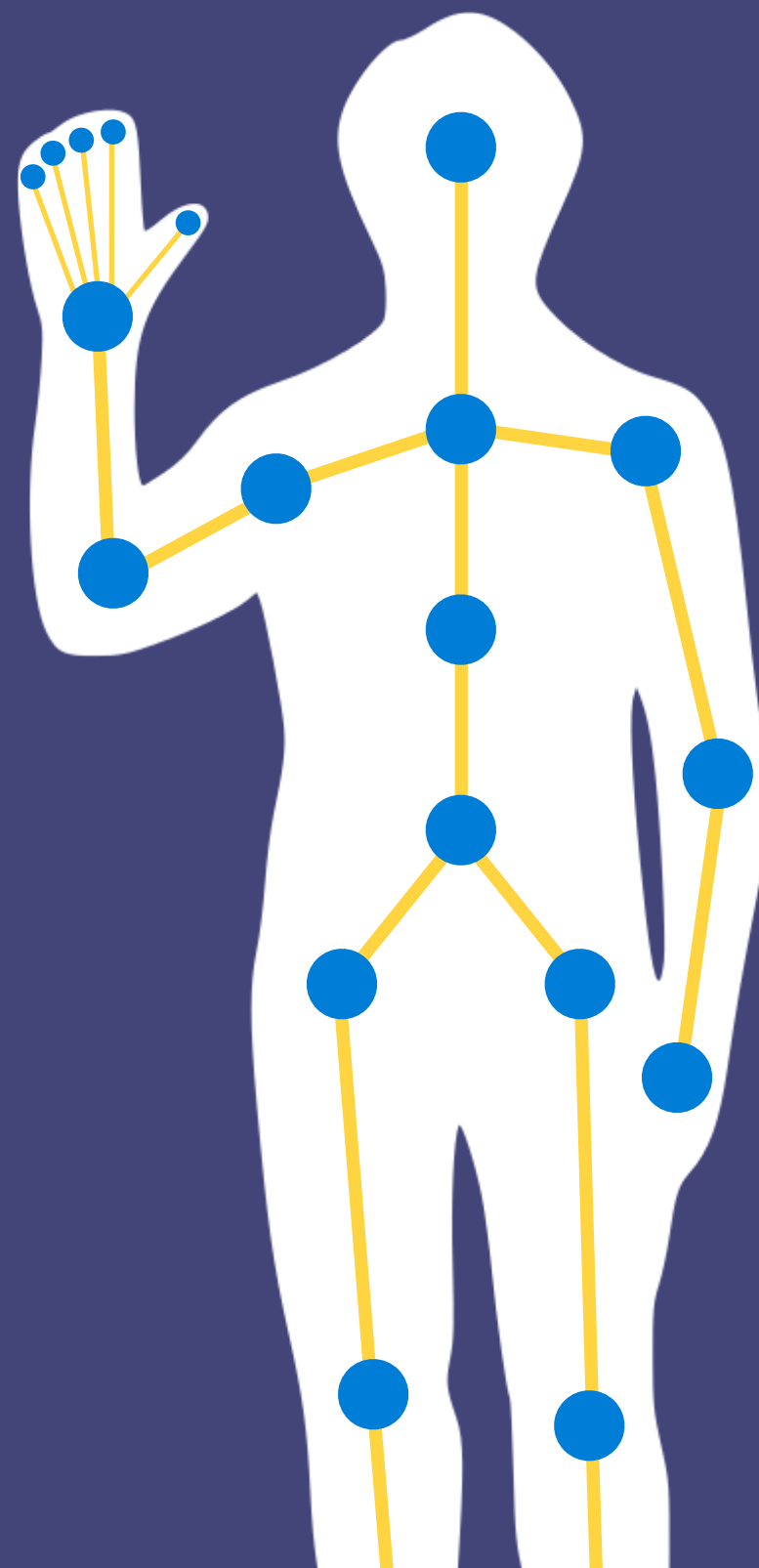
2	1	1
0	0	2
1	2	0



2	1	1
0	0	2
1	2	0



Spatial Convolution

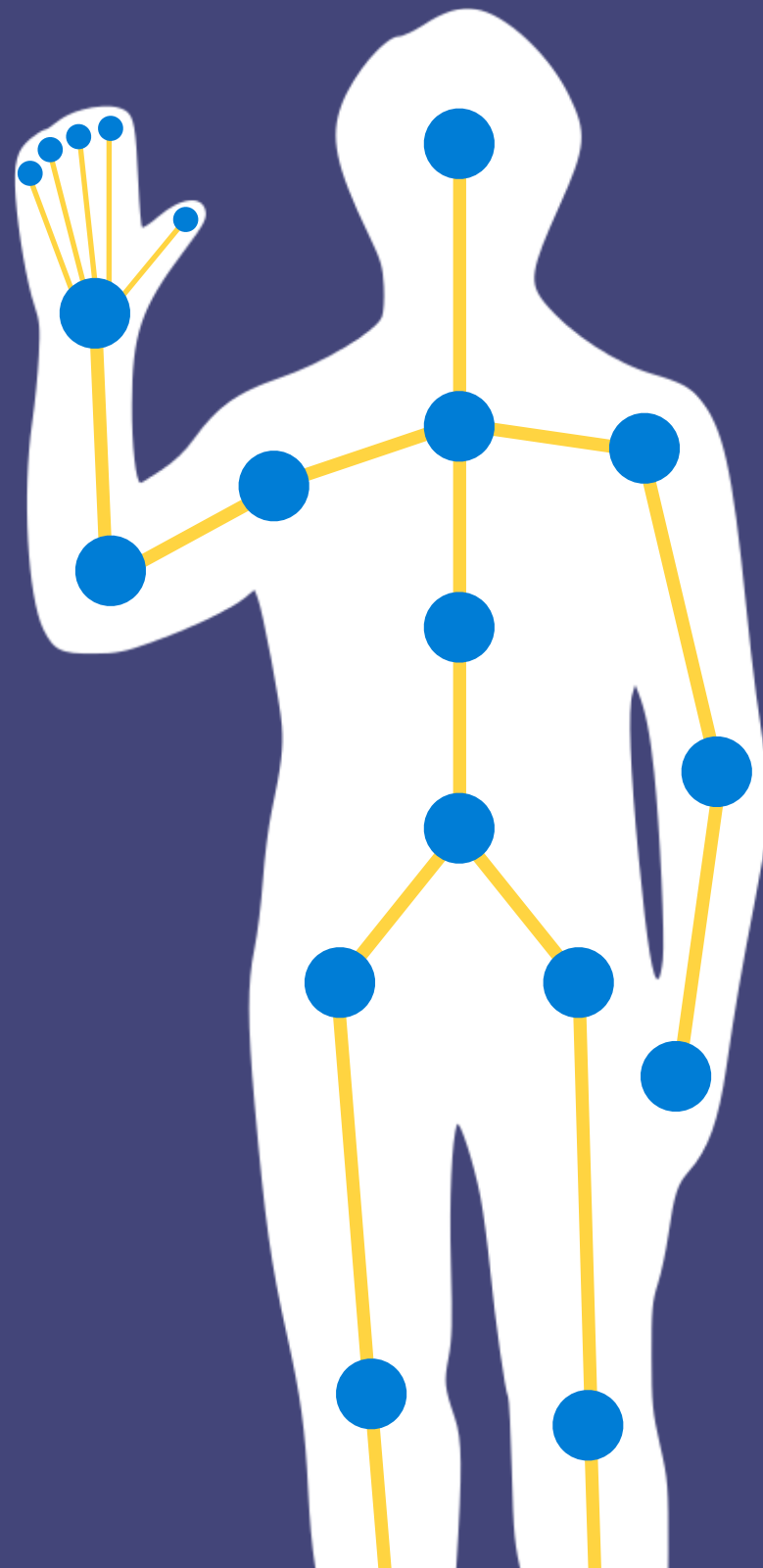


Spatial Configuration Partitioning

Root Node

Centripetal

Centrifugal



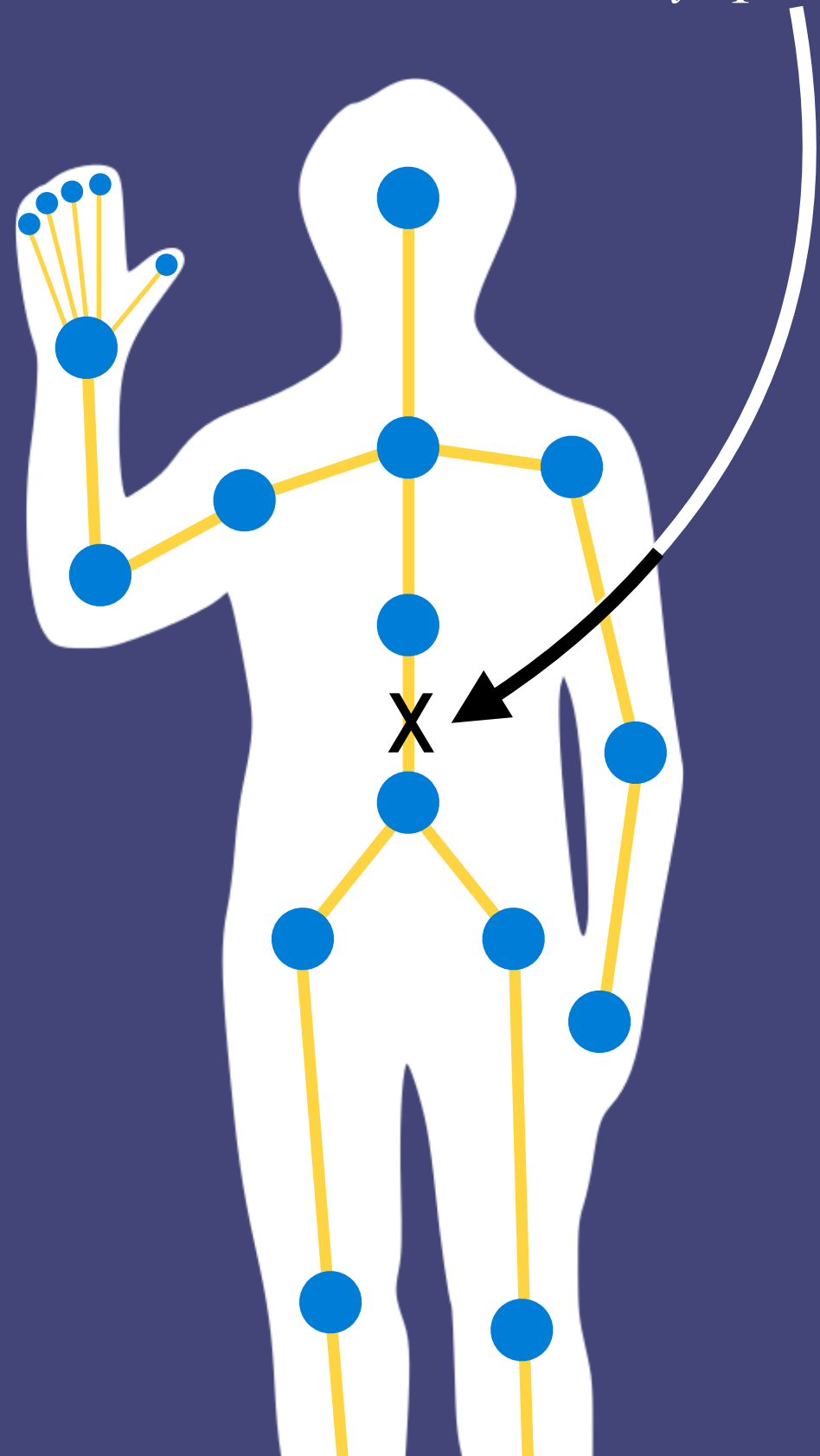
Spatial Configuration Partitioning

Root Node

Centripetal

Centrifugal

$$\text{Centre of Gravity: } \frac{1}{N} \sum_{i=1}^N v_{it}$$



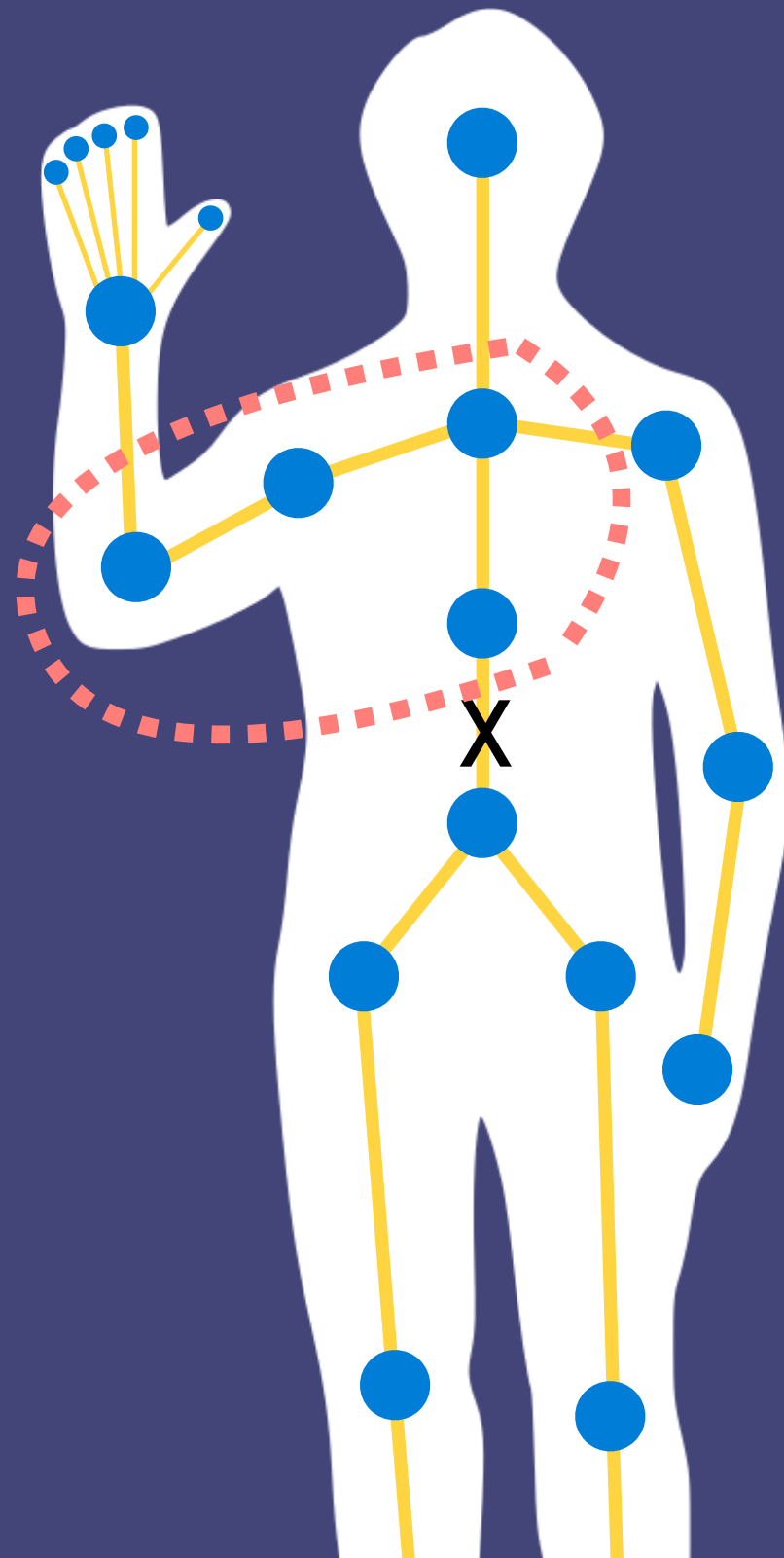
Spatial Configuration Partitioning

Root Node

Centripetal

Centrifugal

$$\text{Centre of Gravity: } \frac{1}{N} \sum_{i=1}^N v_{it}$$

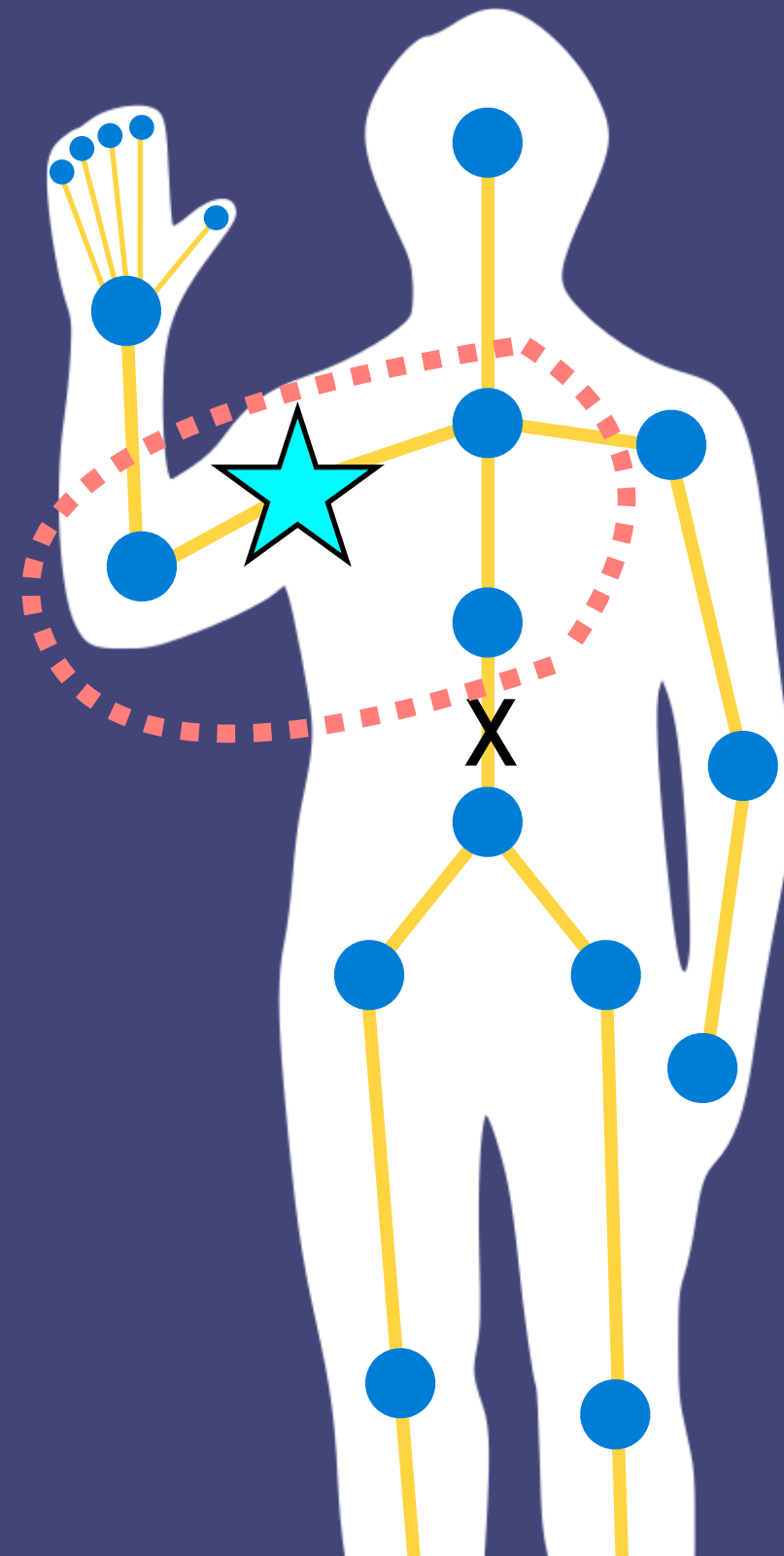


Spatial Configuration Partitioning

Root Node

Centripetal

Centrifugal

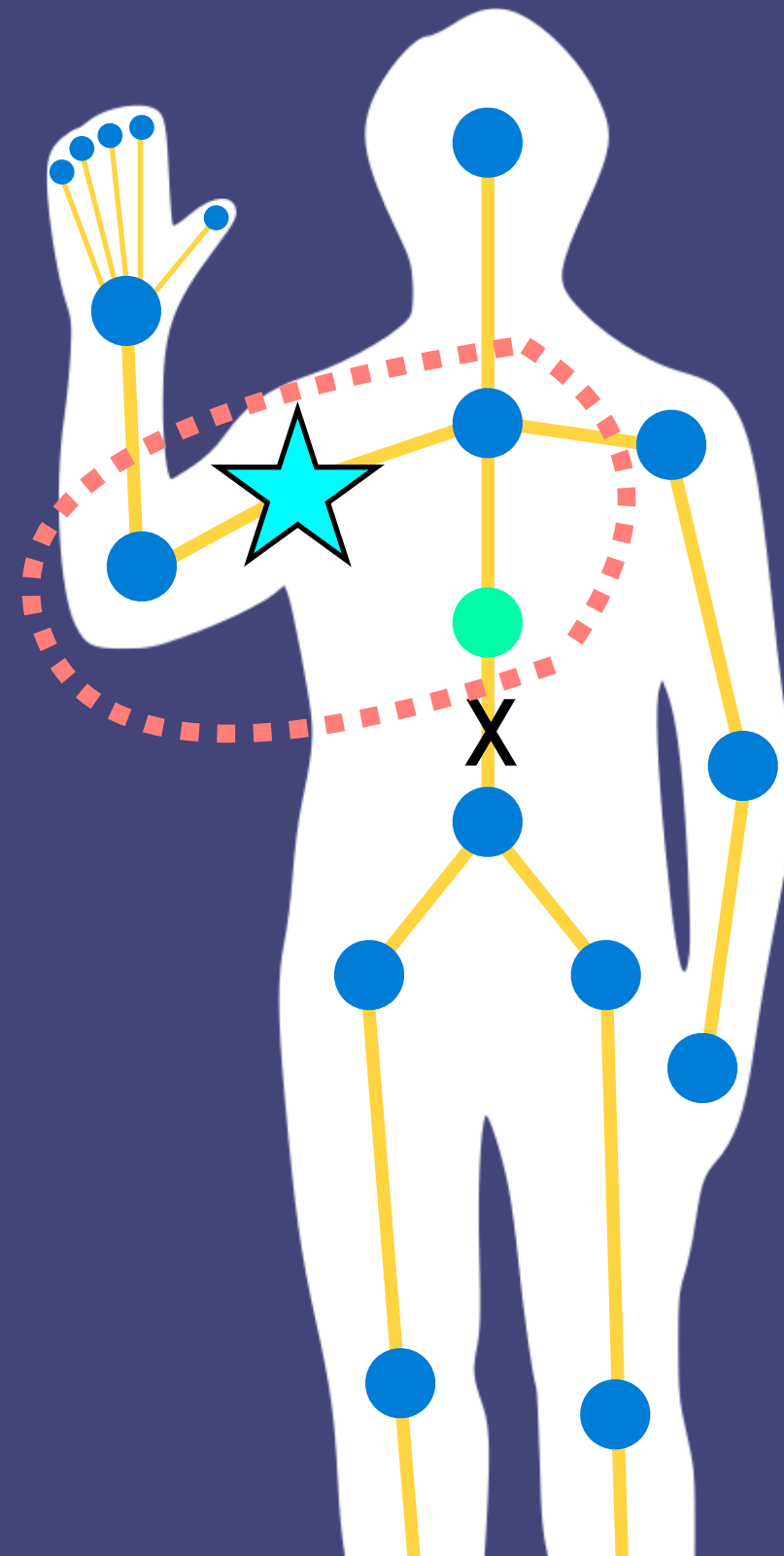


Spatial Configuration Partitioning

Root Node

Centripetal

Centrifugal

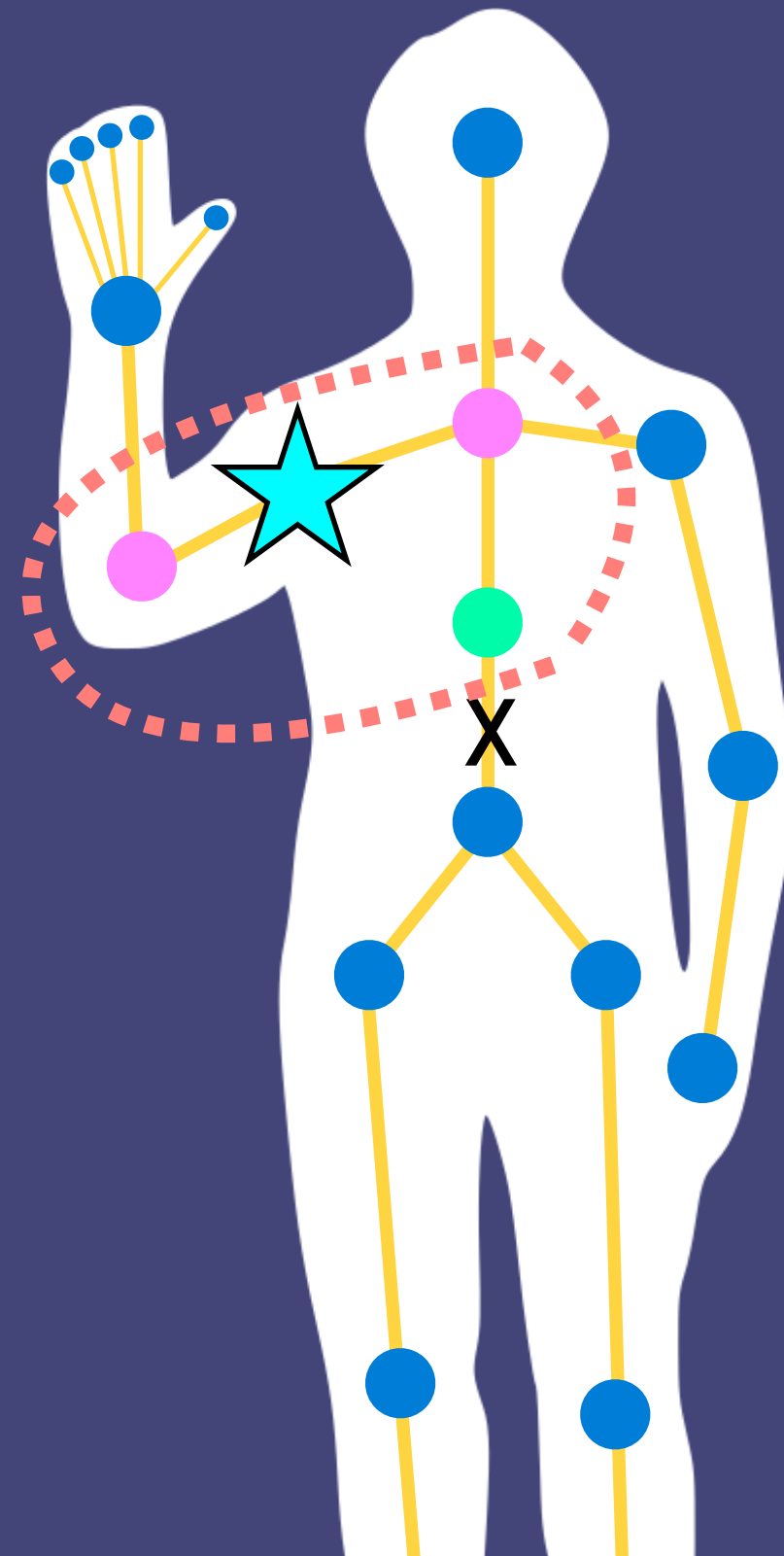


Spatial Configuration Partitioning

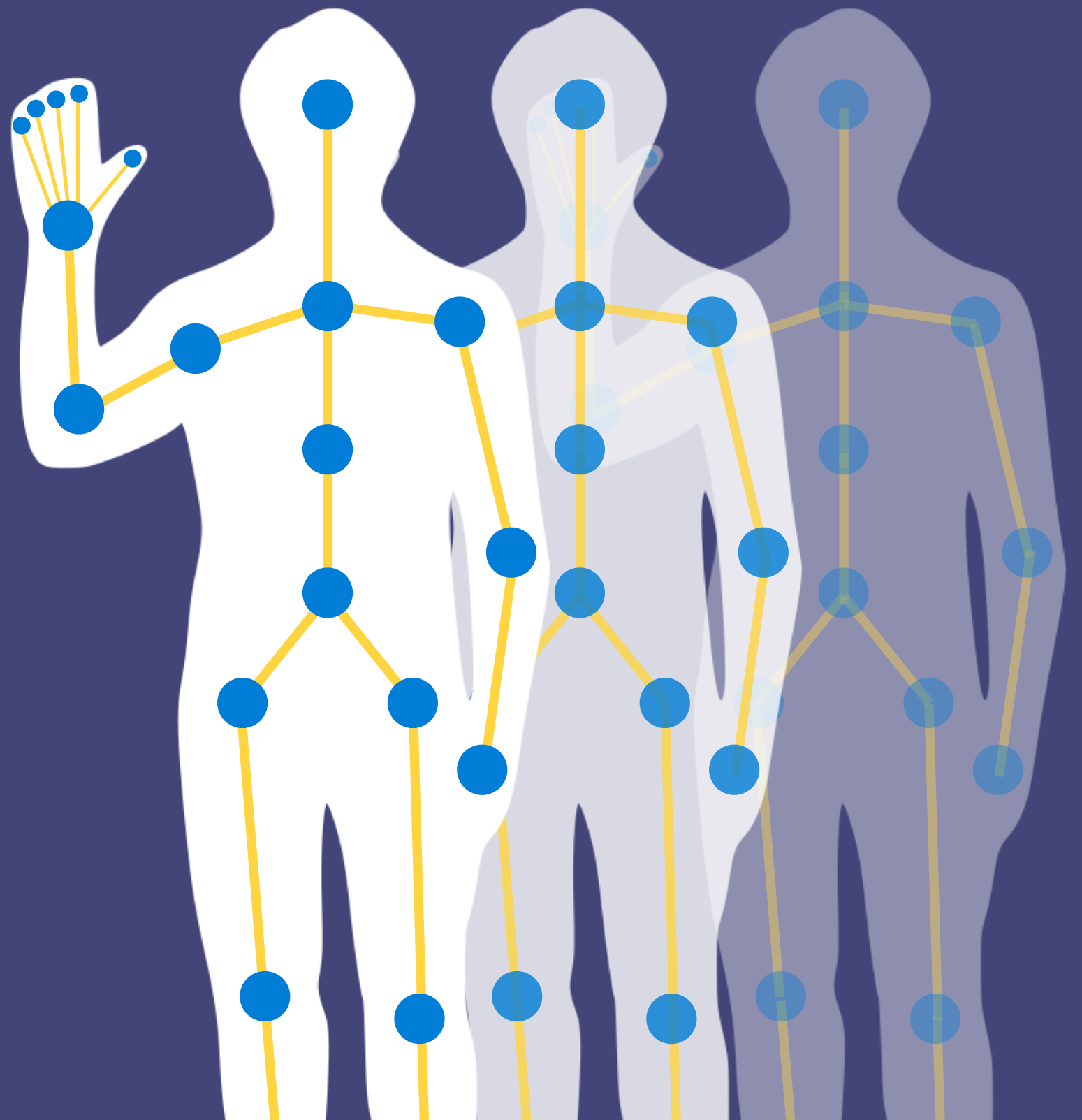
Root Node

Centripetal

Centrifugal

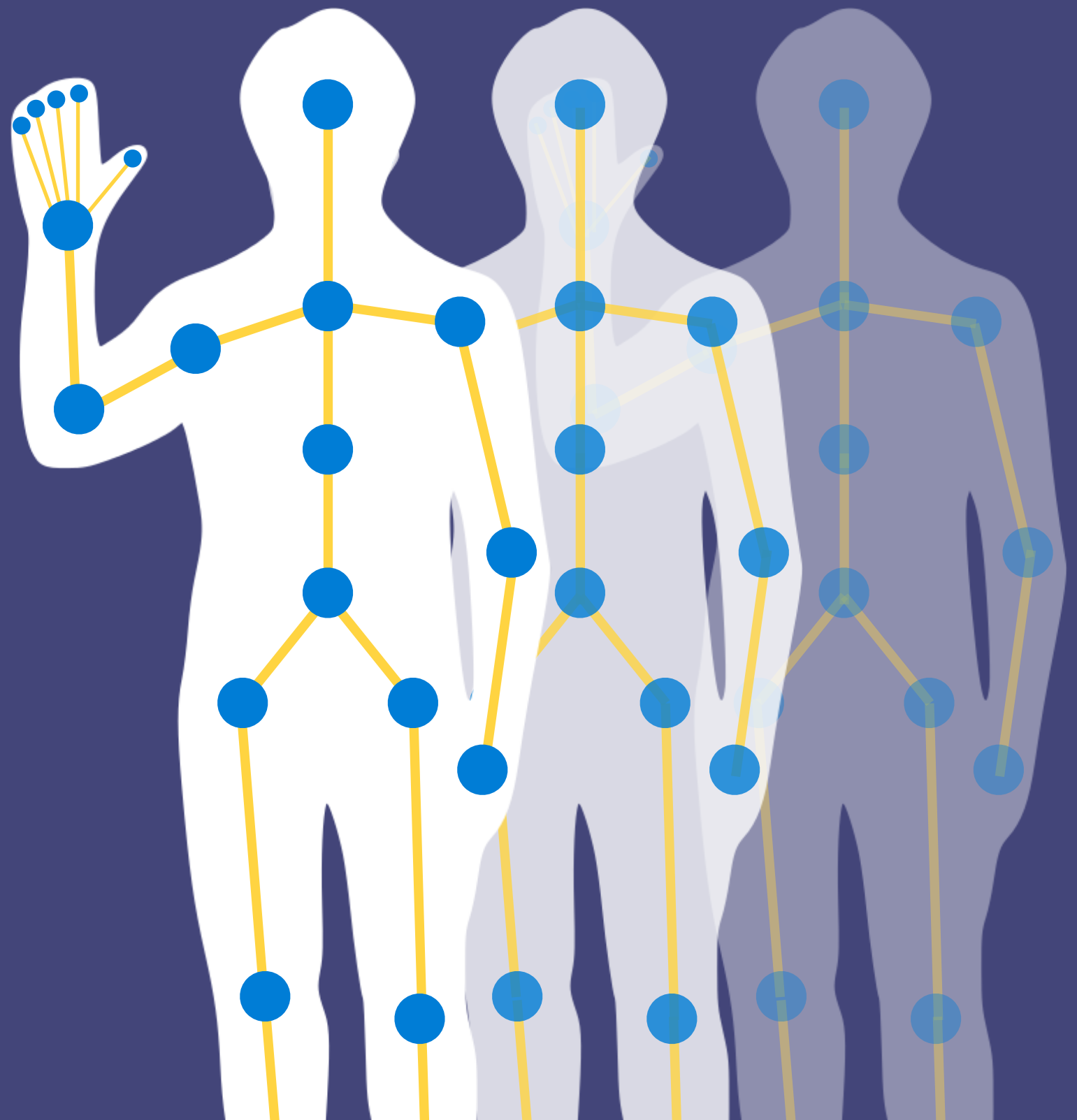


Temporal Convolution



Temporal Convolution

Temporal Kernel Size Γ



Performance

NTU-RGB+D

Kinetics

ST-GCN

C-CNN + MLTN

Temporal Conv

ST-LSTM + TS

PA-LSTM

Deep-LSTM

H-RNN

Lie Group

NTU-RGB+D

Kinetics

Two-Stream: RGB + Flow

ST-GCN

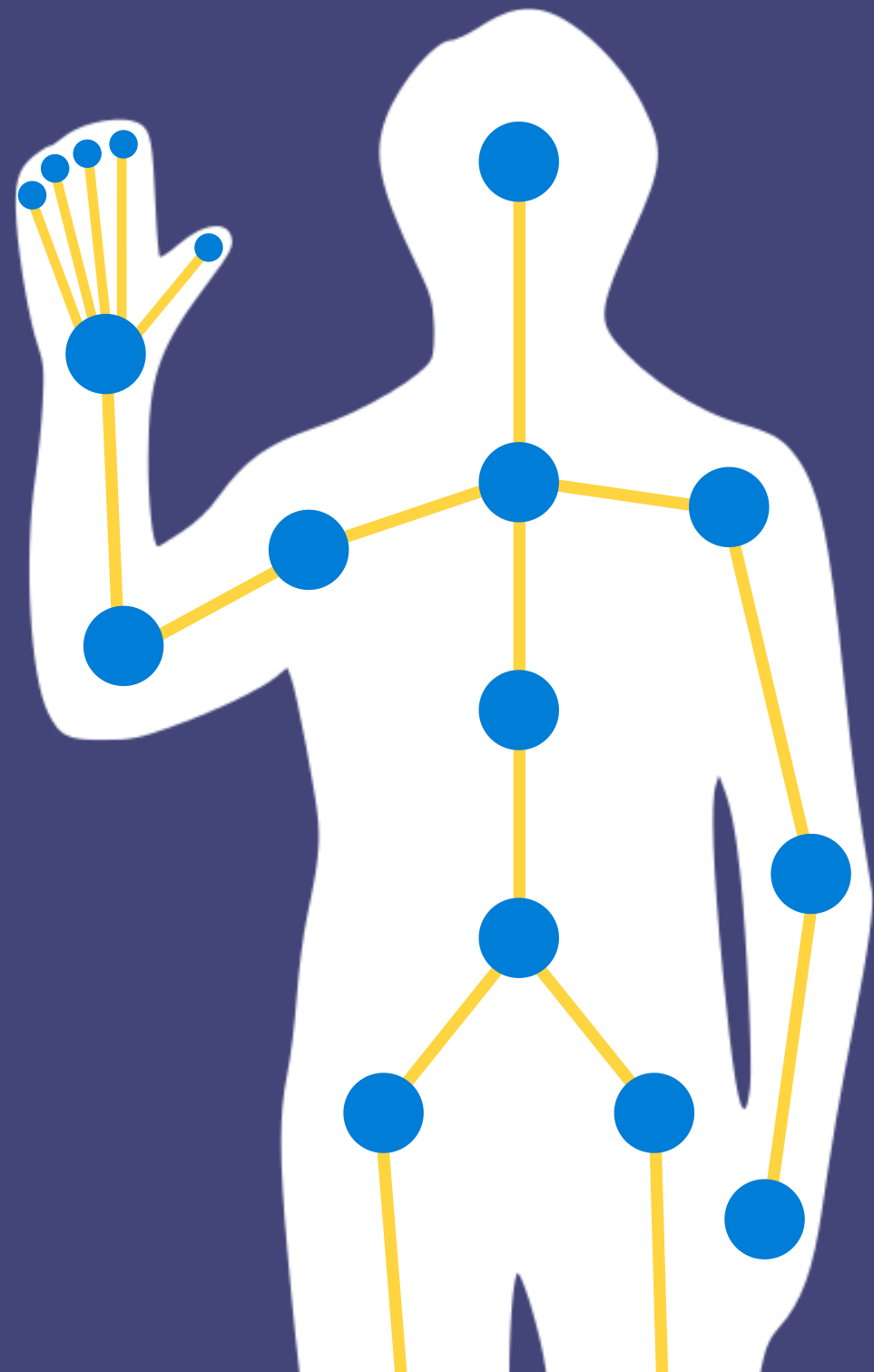
Temporal Conv

Deep LSTM

VideoDarwin

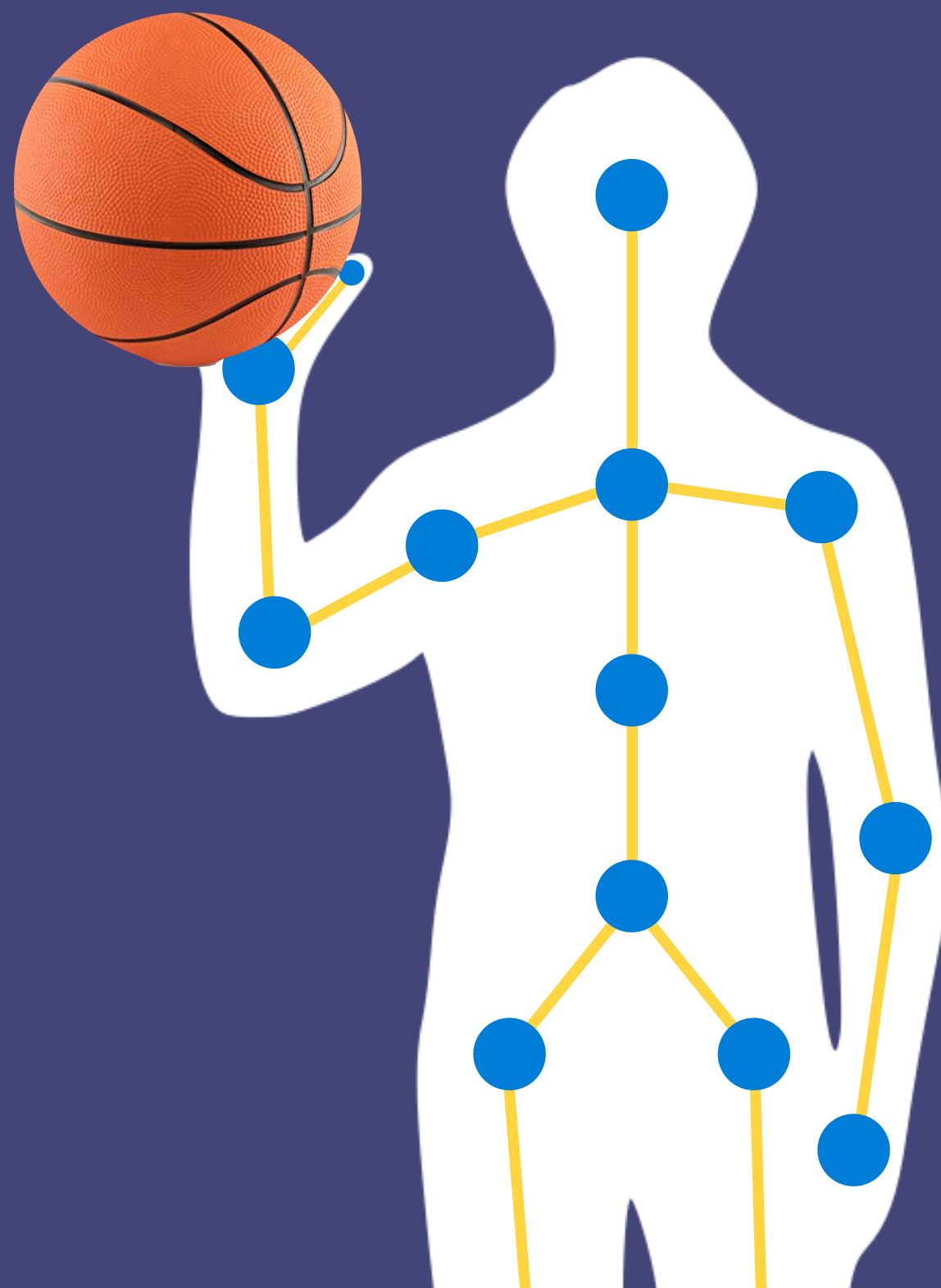
Heterogeneous Graphs

Depth of Model



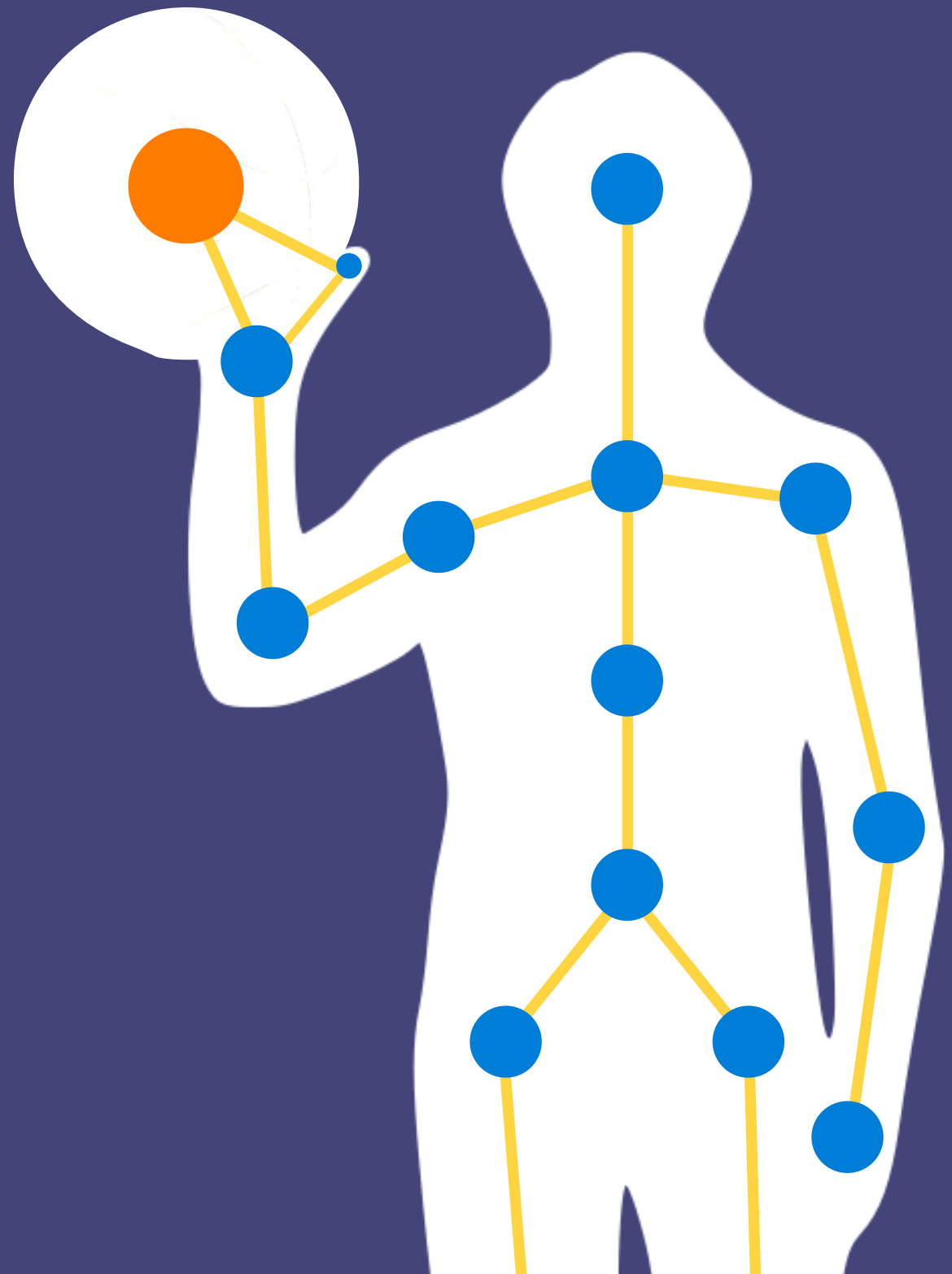
Heterogeneous Graphs

Depth of Model



Heterogeneous Graphs

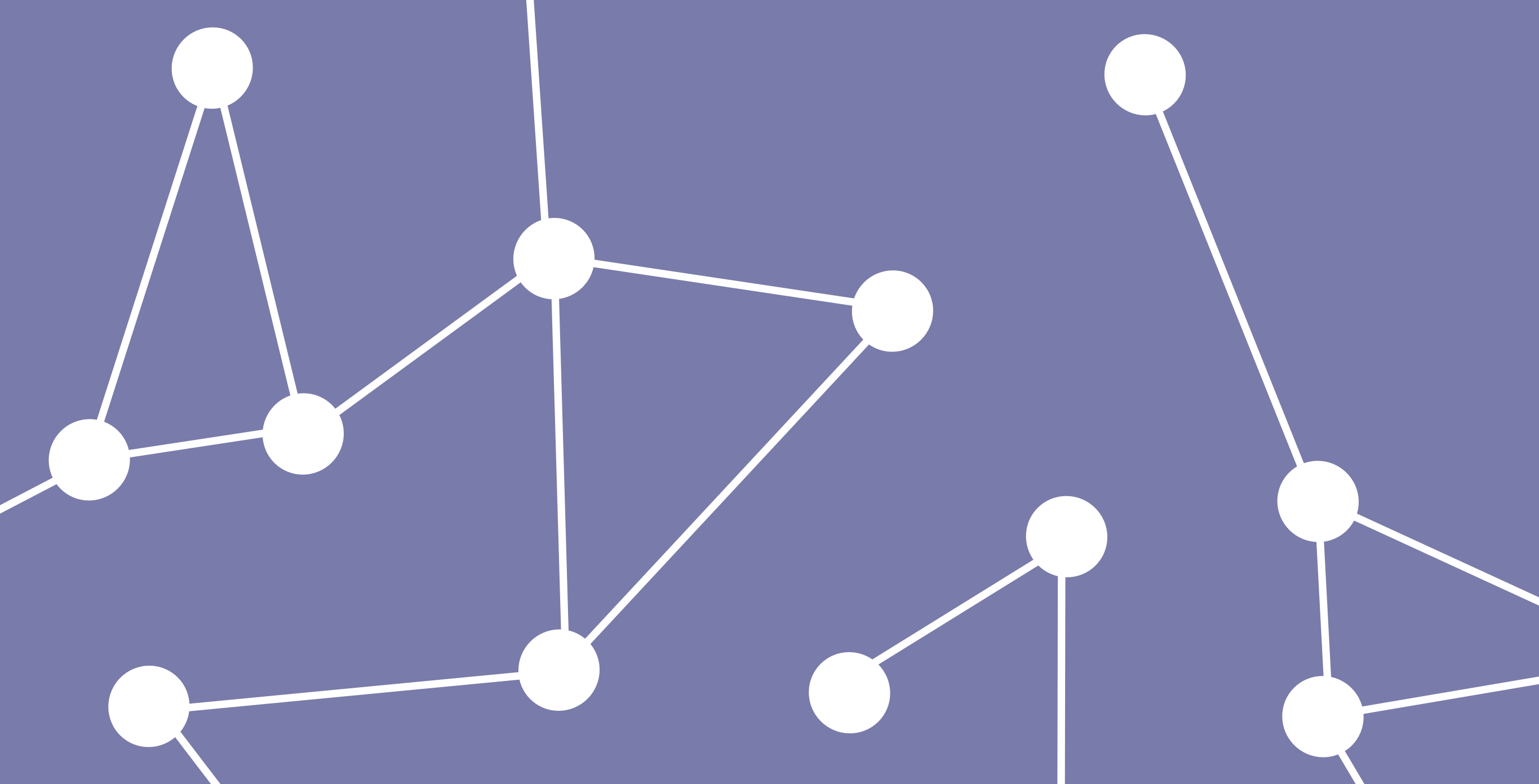
Depth of Model



Heterogeneous
Graphs

Depth of Model





Thank you