

DeepHuman: 3D Human Reconstruction From a Single Image

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Abstract

We propose DeepHuman, an image-guided volume-to-volume translation CNN for 3D human reconstruction from a single RGB image. To reduce the ambiguities associated with the surface geometry reconstruction, even for the reconstruction of invisible areas, we propose and leverage a dense semantic representation generated from SMPL model as an additional input. One key feature of our network is that it fuses different scales of image features into the 3D space through volumetric feature transformation, which helps to recover accurate surface geometry. The visible surface details are further refined through a normal refinement network, which can be concatenated with the volume generation network using our proposed volumetric normal projection layer. We also contribute THuman, a 3D real-world human model dataset containing about 7000 models. The network is trained using training data generated from the dataset. Overall, due to the specific design of our network and the diversity in our dataset, our method enables 3D human model estimation given only a single image and outperforms state-of-the-art approaches.

1. Introduction

Image-based reconstruction of a human body is an important research topic for VR/AR content creation [7], image and video editing and re-enactment [19, 43], holoportation [40] and virtual dressing [42]. To perform full-body 3D reconstruction, currently available methods require the fusion of multiview images [8, 25, 20] or multiple temporal images [3, 2, 1] of the target. Recovering a human model from a single RGB image remains a challenging task that has so far attracted little attention. Using only a single image, available human parsing studies have covered popular topics starting from 2D pose detection [41, 6, 39], advancing to 3D pose detection [33, 44, 64], and finally expanding to body shape capture [27] using a human statistic template such as SMPL [32]. However, the statistic template can capture only the shape and pose of a minimally clothed body and lack the ability to represent a 3D human model under a normal clothing layer. Although the most recent work,

Figure 1: Given only a single RGB image, our method automatically reconstructs the surface geometry of clothed human body.

BodyNet[52], has pioneered research towards this goal, it only generates nearly undressed body reconstruction results with occasionally broken body parts. We believe that 3D human reconstruction under normal clothing from a single image, which needs to be further studied, will soon be the next hot research topic.

Technically, human reconstruction from a single RGB image is extremely challenging, not only because of the requirement to predict the shape of invisible parts but also due to the need for the geometry recovery for visible surface. Therefore, a method capable of accomplishing such a task should meet two requirements: first, the degrees of freedom of the output space should be constrained to avoid unreasonable artifacts (e.g., broken body parts) in invisible areas; second, the method should be able to efficiently extract geometric information from the input image, such as clothing styles and wrinkles, and fuse them into the 3D space.

In this paper, we propose DeepHuman, a deep learning-based framework aiming to address these challenges. Specifically, to provide a reasonable initialization for the network and constrain the degrees of freedom of the output space, we propose to leverage parametric body models by generating a 3D semantic volume and a corresponding 2D semantic map as a dense representation after estimating the shape and pose parameters of a parametric body template (e.g., SMPL[32]) for the input image. Note that the requirement of inferring a corresponding SMPL model for an image is not strict; rather, several accurate methods are available for SMPL prediction from a single image[5, 27]. The

input image and the semantic volume map are fed into an image-guided volume-to-volume translation CNN for surface reconstruction. To accurately recover surface geometry like the hairstyle or cloth contours to the maximum possible extent, we propose a multi-scale volumetric feature transformation so that those different scales of image guidance information can be fused into the 3D volumes. Finally, we introduce a volumetric normal projection layer to further refine and enrich visible surface details according to the input image. This layer is designed to concatenate the volume generation network and the normal refinement network and enables end-to-end training. In summary, we perform 3D human reconstruction in a coarse-to-fine manner by decomposing this task into three subtasks: a) parametric body estimation from the input image, b) surface reconstruction from the image and the estimated body, and c) visible surface detail refinement according to the image.

The available 3D human dataset [53] used for network training in BodyNet [52] is essentially a set of synthesized images textured over SMPL models [32]. No large-scale human 3D dataset with surface geometry under normal clothing is publicly available. To fill in this gap, we present the THuman dataset. We leverage the state-of-the-art DoubleFusion [63] technique for real-time human mesh reconstruction and propose a capture pipeline for fast and efficient capture of outer geometry of human bodies wearing casual clothes with medium-level surface detail and texture. Based on this pipeline, we perform capture and reconstruction of the THuman dataset, which contains about 7000 human meshes with approximately 230 kinds of clothes under randomly sampled poses.

Our network learns from the training corpus synthesized from our THuman dataset. Benefiting from the data diversity of the dataset, the network generalizes well to natural images and provides satisfactory reconstruction given only a single image. We demonstrate improved efficiency and quality compared to current state-of-the-art approaches. We also show the capability and robustness of our method through an extended application on monocular videos.

2. Related Work

Human Models from Multiview Images. Previous studies focused on using multiview images for human model reconstruction [26, 47, 30]. Shape cues like silhouette, stereo and shading cues have been integrated to improve the reconstruction performance [47, 30, 58, 57, 55]. State-of-the-art real-time [11, 10] and extremely high-quality [8] reconstruction results have also been demonstrated with tens or even hundreds of cameras using binocular [12] or multiview stereo matching [13] algorithms. To capture detailed motions of multiple interacting characters, more than six hundred cameras have been used to overcome the occlusion challenges [24, 25]. However, all these systems require complicated environment setups including

camera calibration, synchronization and lighting control.

To reduce the difficulty of system setup, human model reconstruction from extremely sparse camera views has recently been investigated by using CNNs for learning silhouette cues [15] and stereo cues [20]. These systems require about 4 camera views for a coarse-level surface detail capture. Note also that although temporal deformation systems using lightweight camera setups [54, 9, 14] have been developed for dynamic human model reconstruction using skeleton tracking [54, 31] or human mesh template deformation [9], these systems assume a pre-scanned subject-specific human template as a key model for deformation.

Human Models from Temporal Images. To explore low-cost and convenient human model capture, many studies try to capture a human using only a single RGB or RGBD camera by aggregating information from multiple temporal frames. For RGBD images, DynamicFusion [38] breaks the static scene assumption and deforms the non-rigid target for TSDF fusion on a canonical static model. BodyFusion [62] have tried to improve the robustness by adding articulated prior. DoubleFusion [63] introduced a human shape prior into the fusion pipeline and achieved state-of-the-art real-time efficiency, robustness, and loop closure performance for efficient human model reconstruction even in cases of fast motions. There are also offline methods for global registration of multiple RGBD images to obtain a full-body model [29]. To reconstruct a human body using a single-view RGB camera, methods have been proposed for rotating the camera while the target remains as static as possible [65], or keeping the camera static while the target rotates [3, 2, 1]. Recently, human performance capture that can reconstruct dynamic human models using only a single RGB camera has been proposed [59, 18]; however, similar to the multicamera scenario [54, 9, 14], such approaches require a pre-scanned human model as input.

Human Parsing from a Single Image. Parsing human from a single image has recently been a popular topic in computer vision. The research can be categorized into sparse 2D parsing (2D skeleton estimation) [6, 39], sparse 3D parsing (3D skeleton estimation) [33, 44, 64, 48, 50, 35, 61], dense 2D parsing [17] and dense 3D parsing (shape and pose estimation). Dense 3D parsing from a single image has attracted substantial interest recently because of the emergence of human statistical models like SCAPE [4] and SMPL [32]. For example, by fitting the SCAPE or SMPL model to the detected 2D skeleton and other shape cues of an image [5, 28], or by regressing [27, 49, 51] the SMPL model using CNNs, the shape and pose parameters can be automatically obtained from a single image.

Regarding single-view human model reconstruction, there are only several recent works by Varol et al. [52], Jackson et al. [23] and Natsume et al. [36]. In the first study, the 3D human datasets used for network training lacks geometry details, leading to SMPL-like voxel geometries in their

outputs. The second study shows the ability to output high-quality details, but their training set is highly constrained, leading to difficulty in generalization, e.g., to different human poses. The concurrent work by Natsume et al.[36] predicts multiview 2D silhouettes to reconstruct the 3D model, but their reconstruction results have limited pose variation.

3D Human Body Datasets. Most of the available 3D human datasets are used for 3D pose and skeleton detection. Both HumanEva [46] and Human3.6M [21] contain multi-view human video sequences with ground-truth 3D skeleton annotation obtained from marker-based motion capture systems. Because of the need to wear markers or special suits, both datasets have limited apparel divergence. MPI-INF-3DHP [34] dataset enriches the cloth appearance by using a multiview markerless mocap system. However, all these datasets lack a 3D model of each temporal frame. To meet the requirement of pose and shape reconstruction from a single image, the synthesized SURREAL [53] datasets have been created for this task by rendering SMPL models with different shape and pose parameters under different clothing textures. The “Unite the People” dataset [28] provides real-world human images annotated semi-automatic with 3D SMPL models. These two datasets, in contrasts to our dataset, do not contain surface geometry details.

3. Overview

Given an image of a person in casual clothes, denoted by I , our method aims to reconstruct his/her full-body 3D surface with plausible geometrical details. Directly recovering a surface model of the subject from the image is very challenging because of depth ambiguities, body self-occlusions and the high degree of freedom of the output space. Therefore, we perform 3D human reconstruction in a coarse-to-fine manner. Our method starts from parametric body estimation, then performs full-body surface reconstruction and finally refines the details on the visible areas of the surface.

We exploit the state-of-the-art methods HMR[27] and SMPLify[5] to estimate a SMPL model from I ; see the supplementary document for more details. To feed the SMPL estimation into the CNN, we predefine a semantic code (a 3-dimensional vector) for each vertex on SMPL according to its spatial coordinate at rest pose. Given the SMPL estimation, we render the semantic code onto the image plane to obtain a semantic map M_s and generate a semantic volume V_s by first voxelizing the SMPL model into the voxel grid and then propagating the semantic codes into the occupied voxels. Our dense semantic representation has three advantages: (1) it encodes information about both the shape and the pose of the body and thus provides a reasonable initialization for the network and constrain the degrees of freedom of the output space; (2) it provides clues about the corresponding relationship between 3D voxels and 2D image pixels; (3) it is easy to be incorporated into neural networks. More details are presented in the supplementary document.

Figure 2: Network architecture. Our network is mainly composed of an image feature encoder (orange), a volume-to-volume translation network (blue & green) and a normal refinement network (yellow).

For the surface geometry reconstruction, we adopt an occupancy volume to represent the surface[52]. Specifically, we define a 3D occupancy voxel grid V_o , where the voxel values inside the surface are set to 1 and others are set to 0. All occupancy volumes have a fixed resolution of $128 \times 192 \times 128$, where the resolution of the y-axis is set to a greater value and it can be automatically adapted to the major axis of the observed human body. To reconstruct V_o from V_s with the assistance of I and M_s , we propose an image-guided volume-to-volume translation network (Sec.4.1), in which we use multiscale volumetric feature transformation (Sec.4.1.1) to fuse 2D image guidance information into a 3D volume. Accordingly, the network will take advantage of knowledge from both the 2D image and the 3D volume.

Due to resolution limitations, a voxel grid always fails to capture fine details such as clothing wrinkles. To further enrich and refine the geometrical details on the visible part of the surface, we propose to directly project a 2D normal map N from V_o (Sec.4.1.2) and refine it with a U-net (Sec.4.1). In other words, we encode the geometrical details of the visible surface using 2D normal maps and consequently lower the memory requirement.

To train the network with supervision, we contribute THuman, a real-world 3D human model dataset (Sec.5). We synthesize the training corpus from the dataset. Once the network is trained, it can predict an occupancy volume and a normal map of the visible surface given an image of a person and the corresponding SMPL estimation. We obtain the final reconstruction result by first extracting a triangular polygon mesh from the occupancy volume using the Marching Cube algorithm and then refining the mesh according to the normal map using the method in [37].

4. Approach

4.1. Network Architecture

Our network consists of 3 components, namely an image encoder G , a volume-to-volume (vol2vol) translation net-

Figure 3: Illustration of volumetric feature transformation (VFT) at level k .

work H and a normal refinement network R , as shown in Fig.2. The image encoder G aims to extract multi-scale 2D feature maps $M_f^{(k)}$ ($k = 1, \dots, K$) from the combination of I and M_s . The vol2vol network is a volumetric U-Net [60], which takes V_s and $M_f^{(k)}$ ($k = 1, \dots, K$) as input, and outputs an occupancy volume V_o representing the surface. Our vol2vol network H fuses multi-scale semantic features $M_f^{(k)}$ ($k = 1, \dots, K$) into its encoder through a multi-scale volumetric feature transformer. After generating V_o , a normal refinement U-Net [45] R further refines the normal map N after calculating it directly from V_o through a volume-to-normal projection layer. All operations in the network are differentiable, and therefore, it can be trained or fine-tuned in an end-to-end manner. Implementation details are presented in the supplementary document.

4.1.1 Multi-scale Volumetric Feature Transformer

In this work, we extend the Spatial Feature Transformer (SFT) layer [56] to handle 2D-3D data pairs in the multi-scale feature pyramid, and propose multi-scale Volumetric Feature Transformer (VFT). SFT was first used in [56] to perform image super-resolution conditioned on semantic categorical priors to avoid the regression-to-the-mean problem. A SFT layer learns to output a modulation parameter pair (γ, θ) based on the input priors. Then transformation on the feature map F is carried out as: $SFT(F) = F + \gamma \odot \theta$, where \odot is Hadamard product.

In our network, at each level k , a feature volume $V_f^{(k)}$ (blue cubes in Fig.2) and a feature map $M_f^{(k)}$ (orange squares in Fig.2) are provided by previous encoding layers. Similar to [56], we first map the feature map $M_f^{(k)}$ to modulation parameters (γ_k, θ_k) through convolution+activation layers (see the second row of Fig.3). Note that the operation in $SFT(\cdot)$ cannot be applied directly on $V_f^{(k)}$ and $M_f^{(k)}$ because of dimension inconsistency ($V_f^{(k)}$ has a z -axis while (γ_k, θ_k) doesn't.) Therefore, we slice the feature volume along the z -axis into a series of feature slices, each of which has a thickness of 1 along the z -axis. Then we apply the same element-wise affine transformation to each feature z -

Figure 4: Illustration of differentiable depth projection.

slice independently:

$$VFT(V_f^{(k)}(z_i)) = \gamma_k V_f^{(k)}(z_i) + \theta_k \quad (1)$$

where $V_f^{(k)}(z_i)$ is the feature slice on plane $z = z_i$, $z_i = 1, 2, \dots, Z$ and Z is the maximal z -axis coordinate. The output of a VFT layer is the re-combination of transformed feature slices. Fig.3 is an illustration of VFT.

The superiority of VFT is three-fold. First, compared to converting feature volumes/maps into latent codes and concatenating them at the network bottleneck, it preserves the shape primitiveness of image/volume feature and thus encodes more local information. Second, it is efficient. Using VFT, feature fusion can be achieved in a single pass of affine transformation, without requiring extra convolutions or full connection. Third, it is flexible. VFT can be performed on either the original image/volume or downsampled feature maps/volumes, making it possible to fuse different scales of features and enabling much deeper feature transfer.

In order to integrate image features to the maximum possible extent, we perform volumetric feature transformation on the multi-scale feature pyramid; see the blue arrows/lines in Fig.2 for illustration. We only perform VFT in the encoder part of our vol2vol network; however, the transformation information can be propagated to the decoder through skip-connections. As discussed in Sec.6.3, the multi-scale feature transformation helps recover more accurate surface geometry compared to directly concatenating latent variables at the network bottleneck.

4.1.2 Volume-to-normal Projection Layer

Our goal is to obtain geometric details (e.g. wrinkles and cloth boundary) on the visible surface of the human model. However, a volume-based representation is unable to capture such fine-grain details due to resolution limitations. Thus, we encode the visible geometrical details on 2D normal maps, which can be directly calculated from the occupancy volume using our differentiable volume-to-normal projection layer. The layer first projects a depth map directly from the occupancy volume, transforms the depth map into a vertex map, and then calculates the normal maps through a series of mathematical operations.

Fig.4 is a 2D illustration explaining how the layer projects depth maps. In Fig.4(a), the blue circle is the model we aim to reconstruct, and the voxels occupied by the circle

are marked in grey. Consider the pixel $p = (x_p, y_p)$ on the image plane as an example. To calculate depth value $D(p)$ of p according to V_o , a straightforward method is to consider a ray along the z -axis and record the occupancy status of all voxels along that ray (Fig.4(b)). Afterwards, we can determine $D(p)$ by finding the nearest occupied voxel. Formally, $D(p)$ is obtained according to

$$D(p) = \inf_z |V_o^{(x_p y_p z)}| = 1 \quad (2)$$

where $V_o^{(x_p y_p z)}$ denotes the value of the voxel at coordinate (x_p, y_p, z) . Although this method is straightforward, it is difficult to incorporate the operation, $\inf\{\cdot\}$ into neural networks due to the complexity of differentiating through it. Therefore, we transform the occupancy volume to a depth volume V_d by applying a transformation f :

$$V_d^{(xyz)} = f(V_o^{(xyz)}) = M(1 - V_o^{(xyz)}) + zV_o^{(xyz)} \quad (3)$$

where M is a sufficiently large constant. Then as illustrated in Fig.4(c), $D(p)$ can be computed as:

$$D(p) = \min_z f(V_d^{(x_p y_p z)}). \quad (4)$$

After depth projection, we transform the depth map to a vertex map M_v by assigning x and y coordinates to depth pixels according to their positions on the images. Then Sobel operators are used to calculate the directional derivative of the vertex map along both the x and y directions: $G_x = S_x M_v$, $G_y = S_y M_v$, where S_x and S_y are Sobel operators. The normal at pixel $p = (x_p, y_p)$ can be calculated as:

$$N^{(x_p y_p)} = G_x(p) \times G_y(p), \quad (5)$$

where \times denotes cross product. Finally, N is up-sampled by a factor of 2 and further refined by a U-Net.

4.2. Loss Functions

Our loss functions used to train the network consist of reconstruction errors for the 3D occupancy field and 2D silhouette, as well as the reconstruction loss for normal map refinement. We use extended Binary Cross-Entropy (BCE) loss for the reconstruction of occupancy volume [22]:

$$L_v = -\frac{1}{\hat{V}_o} \sum_{x,y,z} \hat{V}_o^{(xyz)} \log V_o^{(xyz)} + (1 - \hat{V}_o) \sum_{x,y,z} (1 - V_o^{(xyz)}) \log (1 - V_o^{(xyz)}) \quad (6)$$

where \hat{V}_o is the ground-truth occupancy volume corresponding to V_o , $V_o^{(xyz)}$ and $\hat{V}_o^{(xyz)}$ are voxels in the respective volumes at coordinate (x, y, z) , and \hat{V}_o is a weight

used to balance the loss contributions of occupied and unoccupied voxels. Similar to [52], we use a multi-view re-projection loss on the silhouette as additional regularization:

$$L_{FS} = -\frac{1}{\hat{S}_{fv}} \sum_{x,y} \hat{S}_{fv}^{(xy)} \log S_{fv}^{(xy)} + (1 - \hat{S}_{fv}^{(xy)}) \log (1 - S_{fv}^{(xy)}) \quad (7)$$

where L_{FS} denotes the front-view silhouette re-projection loss, S_{fv} is the silhouette re-projection of V_o , \hat{S}_{fv} is the corresponding ground-truth silhouette, and $S_{fv}^{(xy)}$ and $\hat{S}_{fv}^{(xy)}$ denote their respective pixel values at coordinate (x, y) . Assuming a weak-perspective camera, we can easily obtain $S_{fv}^{(xy)}$ through orthogonal projection [52]: $S_{fv}^{(xy)} = \max_z V_o^{(xyz)}$. The side-view re-projection loss L_{SS} is defined similarly.

For normal map refinement, we use the cosine distance to measure the difference between predicted normal maps and the corresponding ground truth:

$$L_N = \frac{1}{\hat{N}} \sum_{x,y} 1 - \frac{\langle N^{(xy)}, \hat{N}^{(xy)} \rangle}{|N^{(xy)}| \cdot |\hat{N}^{(xy)}|} \quad (8)$$

where $N^{(xy)}$ is the refined normal map produced by the normal refiner, $\hat{N}^{(xy)}$ is the ground-truth map, and similarly $N^{(xy)}$ and $\hat{N}^{(xy)}$ denote their respective pixel values at coordinate (x, y) .

Therefore, the combined loss is

$$L = L_v + F_S L_{FS} + S_S L_{SS} + N L_N. \quad (9)$$

5. THuman: 3D Real-world Human Dataset

Collecting rich 3D human surface model with texture containing casual clothing, various human body shapes and natural poses has been a time-consuming and laborious task as it always relies on either expensive laser scanners or sophisticated multiview systems in a controlled environment. Fortunately, this task becomes easier with the recently introduced DoubleFusion[63], a real-time human performance capture system using a single depth camera. Based on DoubleFusion, we develop a method to capture a 3D human mesh models, and collect a 3D real-world human mesh dataset called ‘‘THuman’’. THuman has about 7000 data items; each item contains a textured surface mesh, a RGBD image from the Kinect sensor, and an accompanying well-aligned SMPL model. More details about the capture system and the dataset are presented in the supplementary document.

In this work, we only use the textured surface mesh and the accompanied SMPL model to generate training data. The training corpus are synthesized in the following steps: for each model in our dataset, we first render 4 color images from 4 random viewpoints using a method similar to

Method	HMR	BodyNet	Ours
Averaged 3D IOU	41.4%	38.7%	45.7%

Table 1: Quantitative comparison using 3D IOU score.

[53]; after that, we generate the corresponding semantic maps and volumes, occupancy volumes as well as normal maps. By enumerating all the models in our dataset, we finally synthesize 28K images for network training.

6. Experiments

6.1. Results

We demonstrate our approach with various human images in Fig.5. The input images are natural images sampled from the LIP dataset[16]. As shown in Fig.5 our approach is able to reconstruct both the 3D human models and surface details like cloth wrinkles, belts and the hem of a dress. In Fig.6 we show an extended application on 3D human performance capture from a single-view RGB video. It should be noted that the reconstruction results are generated by applying our method on each the video frame independently, without any temporal smoothness involved. The results demonstrate the ability of our method to tackle various human poses and its robust performance. Please see the supplemental materials and video for more results.

6.2. Comparison

In Fig.5 and Fig.7, we **qualitatively** compare our work against three state-of-the-art deep learning based approaches for single view 3D human reconstruction: HMR[27], BodyNet[52] and SiCloPe[36]. As shown in Fig.5, our method is able to achieve much more detailed reconstruction than HMR and BodyNet (See Fig.5(a-f)) and more robust performance than BodyNet when some body parts are occluded (See Fig.5(b,g,h)). In Fig.7 we show that SiCloPe fails on some challenging poses and produces inaccurate reconstruction on other common poses. Overall, our method makes a better balance between generality and accuracy thanks to the coarse-to-fine algorithm design.

The **quantitative** comparison against HMR[27] and BodyNet[52] is conducted on the testing set of our synthetic data, and the results are presented in Tab.1. As shown by the numerical results, our method achieves the most accurate reconstruction among all the approaches. BodyNet occasionally produces broken bodies and consequently gets the lowest score. Please see the supplementary document for more details and more comparisons.

6.3. Ablation Study

6.3.1 Semantic Volume/Map Representation

Baseline. An alternative representation to our semantic volume/map is body joint heat volumes/maps that are used in BodyNet[52]. A joint heat map is a multi-channel 2D image where in each channel a Gaussian with fixed variance

Representation	IOU score (%)
Joints Heat Map/Volume	74.16
Semantic Map/Volume	79.14

Table 2: Numerical evaluation of semantic volume/map representation.

is centered at the image location of the corresponding joint. By extending the notion of 2D heat maps to 3D, we can also define the heat volumes for body joints. In order to evaluate our semantic volume/map representation, we implement a baseline network that takes body joints' heat maps and heat volumes as input and has the identical structure to the network presented in Sec.4. In this experiment we generate input semantic volumes/maps and joint heat volumes/maps from the ground-truth SMPL model to eliminate the impact of inaccurate SMPL estimation.

Results. Fig.8 shows the experimental results. We can see that compared to sparse joints, a network taking dense semantic maps/volumes as input is able to learn to reconstruct the 3D model more accurately. In Tab.2, we also test these two methods on the testing portion of our synthetic dataset and measure the reconstruction error using the IoU score of the network output and the ground-truth volume. The numerical results also show that taking dense semantic maps/volumes as input helps the network achieve higher reconstruction accuracy. We think that it is because our semantic volume/map representation encodes information about the body shape and pose jointly and provides a good initialization for the volumetric reconstruction network.

6.3.2 Multi-scale Volumetric Feature Transformation

Baseline. To evaluate our multi-scale VFT component, we implement 3 baseline networks: Baseline (A) only performs VFT at the finest scale, while Baseline (B) at the coarsest scale; different from the original network and Baseline (A)(B), Baseline (C) first encodes input images/volumes into latent codes, concatenates the latent code of the image with that of the volume and then feeds the concatenation into the volume decoder.

Results. Fig.9 shows the reconstruction loss for different fusing methods. Here we found that by using multi-scale VFT, the network outperforms the baseline method in terms of the reconstruction of the model boundaries (see the second plot in Fig.9). The same conclusion can be drawn from the visual comparison shown in Fig.10. Using coarsest VFT (Baseline (B)) or latent code concatenation (Baseline (C)) results into over-smooth reconstruction of the girl's head due to the lack of higher-scale information (see the last two results in Fig.9). The result generated by Baseline (A) is much more accurate but contain noises. With the proposed multi-scale VFT component, our network is able to reconstruct the hair bun of the girl (the blue circle in Fig.10).

Figure 5: Reconstruction results on natural images. In each panel, the input images are presented in the left column, while last five columns show the results of HMR[27] (in orange), BodyNet[52] (in green) and our method (in blue). For BodyNet and our method we render the results from two views, i.e., the input camera view and a side view.

Figure 6: 3D reconstruction from monocular videos using our method. The reconstruction results are generated by applying our method on each individual video frame independently. The last three video clips come from the dataset of MonoPerfCap[59].

6.3.3 Normal Refinement

Baseline. To evaluate our normal refinement module, we implement a baseline network by removing the volume-to-normal projection layer and the normal refinement U-Net as well from the original network.

Results. The evaluation experiment is conducted using

our synthetic dataset and the results are shown in Tab.3 and Fig.11. In Tab.3 we present the prediction error of surface normal with and without normal refinement. This numeric comparison shows that the normal refinement network properly refines the surface normal based on the input image. We can also observe that surface details are enhanced and enriched after normal refinement in Fig.11.

Figure 7: Comparison against SiCloPe[36]. Blue: our results; Green: results by SiCloPe.

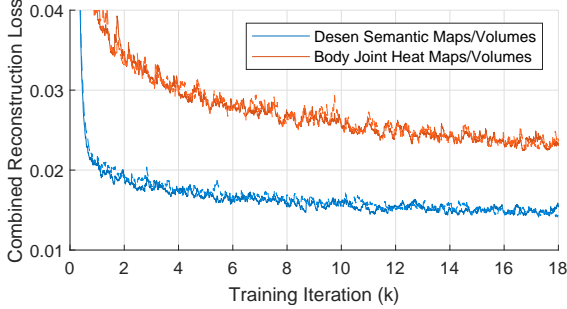


Figure 8: Evaluation of semantic volume/map representation. We evaluate two different inputs for the image-guided vol2vol network, and show the combined reconstruction losses ($L_V + F_S L_{FS} + S_S L_{SS}$). Solid lines show training error and dashed lines show validation error (they almost overlap with each other).

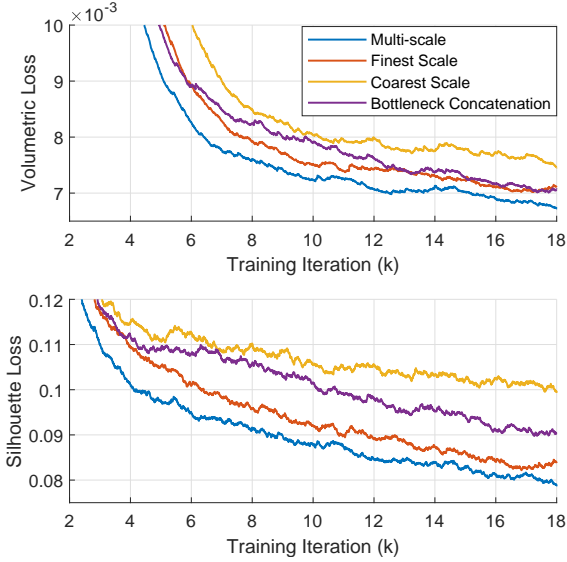


Figure 9: Evaluation of multi-scale volumetric feature transformation (VFT). We evaluate several ways to fuse 2D features into 3D volumes, and show the volumetric loss (L_V) and the silhouette loss ($L_{FS} + L_{SS}$) in the figure. For clarity we do not show the validation loss.

7. Discussion

Limitations. Our method relies on HMR and SMPLify to estimate a SMPL model for the input image. As a result,

Figure 10: Visual evaluation of multi-scale VFT. From left to right: input image, head reconstruction result by our method, baseline(A), baseline(B) and baseline(C).

Error Metric	Cosine Distance	2-norm
Without Refinement	0.0941	0.336
With Refinement	0.0583	0.262

Table 3: Numerical normal errors with/without normal refinement.

(a) (b) (c)

Figure 11: Qualitative evaluation of normal refinement. (a) Reference image and the ground-truth normal. (b) Surface normal and error map without normal refinement. (c) Refined normal and the corresponding error map.

we cannot give an accurate reconstruction if the SMPL estimation is erroneous. Additionally, the reconstruction of invisible areas is over-smoothed; using a generative adversarial network may force the network to learn to add realistic details to these areas. Due to the limited resolution of the depth maps, DoubleFusion is unable to reconstruct hand geometry and thus all hands are clenched in the THuman dataset. Consequently, our method also fails to recover fine-scale details such as facial expression and hands' shape. This issue can be addressed using methods that focus on face/hand reconstruction.

Conclusion. In this paper, we have presented a deep-learning based framework to reconstruct a 3D human model from a single image. Based on the three-stage task decomposition, the dense semantic representation, the proposed network design and the 3D real-world human dataset, our method is able to estimate a plausible geometry of the target in the input image. We believe both our dataset and network will enable convenient VR/AR content creation and inspire many further researches on 3D vision for humans.

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