Hand-Gesture Based Actuation Using 3D Convolutional Neural Networks

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Abstract

With the increase in the applications of VR/AR, 3D hand gestures are increasingly being used as actuation input. Consequently, hand pose estimation is an active field of interest today. In this work we aim to contribute to optimization of existing 3D hand pose estimation models that use depth camera. This work focuses on the algorithms and techniques to minimize latency for real time applications while improving accuracy. This would offer a low-cost neural network-based counterpart to existing systems which mainly use RGB camera (s).

Introduction*[[1]](#footnote-1)*

In recent years after the introduction of cheaper depth cameras such as Intel RealSense, Kinect. Challenges for pose estimation tending towards many solutions and real-time 3D hand pose estimation has instigated a lot of research attention in recent years (Huang, 2001). In 1994 the first efforts to tackle the problems were made (James M. Rehg, 1994). There are many applications such as action recognition, gesture recognition, and sign language interpretation. Till the challenge is to achieve accurate and robust hand pose estimation with unmarked visual inputs, variation in hand poses, similar fingers in the depth visual inputs.

Many recent works focused on Convolution Neural Networks (CNN) (Ge L, 2019) for the 3D hand pose estimation and achieved good performance results as large datasets are readily available. Many researchers used these methods that feed the depth images to 2D CNNs that produce 3D joints (James M. Rehg, 1994). This method is not effective to achieve the real-time level of latency, as 2D CNNs are not sufficient for 3D hand pose estimation due to the lack of spatial information in three dimensions. The results from the 2D CNNs setup are inaccurate which can be made better by applying multi-view 2D CNNs which do not fully utilize the 3D spatial information from depth images. Improving the performance from multiple view 2D CNNs increases model complexity and latency. The 3D CNN based hand pose estimation approach is much effective because 3D CNN fully utilizes the three-dimensional nature of depth images. The work in (Ge L, 2019) used 3D CNNs which capture the 3D spatial structure from the segmented data extracted from the depth images, from which a 3D point cloud of the hand is encoded as 3D volumes storing the Accurate Truncated Signed Distance Function (TSDF). The output is in 3D volumetric representation by applying the dimensionality reduction techniques (PCA), 3D joint locations in the camera’s coordinates can be obtained.

Related Work

**Existing 2D CNN methods.** Regression of 3D hand features using 2D convolutional neural network is a very active area of research. The work in (Jonathan Tompson, 2014) uses an encoder-decoder network which estimates 2D location using direct and latent heat maps and 3D locations using vector representations. Images of hands are fed to the encoder-decoder network, which produces heat maps and features separately, which are then concatenated.

**Existing deep learning methods.** More recently, the AlexNet (Markus Oberweger, 2020) showed much better results, and deep learning is more and more involved as it produces accurate results and is simpler to implement. But for real time consideration it does not work due to its huge latency and demanding compute capability.

**Existing 3D CNN methods.** For real time applications 3D convolutional neural networks look more promising (Ge L, 2019). Due to the nature of 3D CNNs to better represent 3D features, the network can be much simpler and smaller, thus resulting in reduced latency.

Experimental Setup

We implement the experimental pipeline of Liuhao Ge (Ge L, 2019). The publicly available hand pose dataset (Jonathan Tompson, 2014) is used in this work. The depth images from the NYU dataset were converted to accurate Truncated Signed Distance Function (TSDF) based volumes within axis-aligned bounding boxes (Ge L, 2019). Neural Networks with 3D convolution filters were used to train on these volumes. 14 Hand joints were selected for regression from the Neural Network (Ge L, 2019). The points representing 14 Hand Joints were normalized between zero and unity. The 42 3D features representing 14 Hand joint locations were reduced to 30 feature vector space using PCA as the most optimal number of features described in (Ge L, 2019). The shallow plain network in (Ge L, 2019) was implemented and modified in a way to produce better results. SGD optimizer performed best with a learning rate of 0.01 initially, and then it was divided by 10 after every 5 epochs. Both models were trained for 15 epochs with 3500 steps per epoch and a batch size of 16. The loss function was Mean Absolute Error. 10 percent of the data was used as a validation split. The lower Feature Representation of the 14 joints as the output of the neural network used fully connected layer(s) to reconstruct the 3D joint features.

Network Architecture

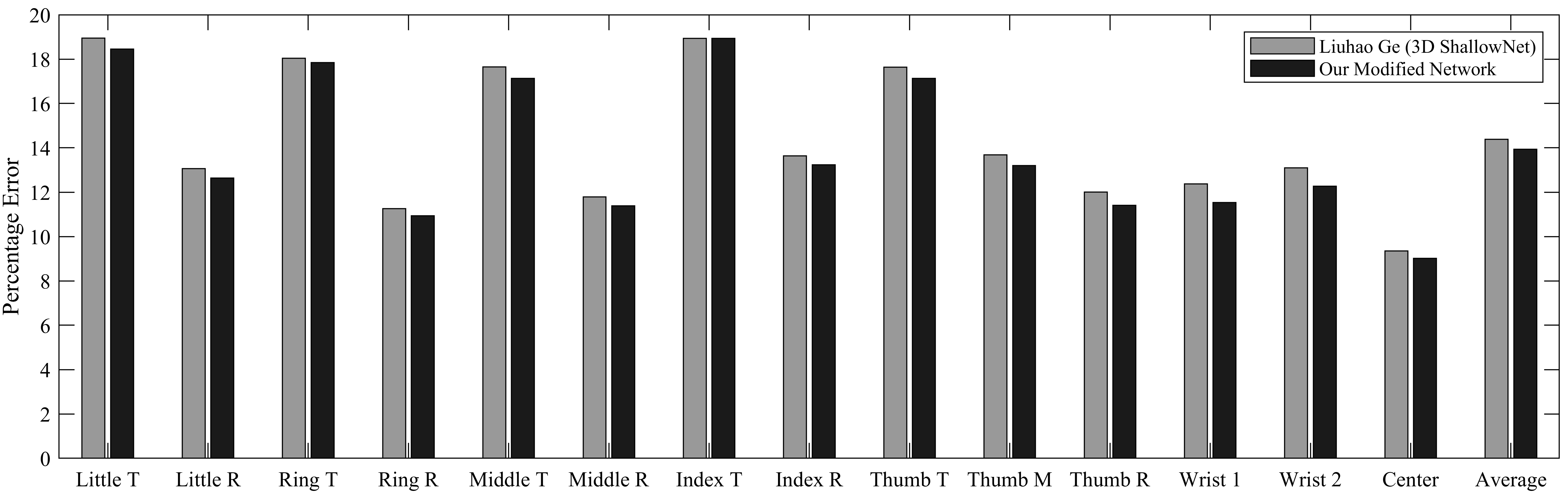
The original shallow network and our modified 3D CNN model, both take a volume input of voxels containing accurate TSDF. The network output is a tensor containing a lower-dimensional embedding of 30 features that are passed through a neural network to transform these lower dimension embeddings to 42, 3D joint location. It is better to predict the 3D spaces by using the lower dimension embedding rather than absolute spaces (Hengkai Guo, 2017).

Figure 1: Mean percentage error of each joint on hand. The error of both original shallow network (gray) and our modified network (black) representing the accuracy of 3D CNN approach. (T: Tip, R: Root, M: Middle)

Results & Evaluation

Figure 1 shows the percentage mean error of shallow network in (Ge L, 2019) and our modified network. It was observed that our proposed modification performed better.

There is a trade-off by increasing parameters of neural network accuracy may increase at the cost of increased latency, Hence the FPS in real-time drops. This work focused on modifying shallow network (Ge L, 2019) with the same filters for achieving the same latency. A divide and conquer strategy was adopted. At each layer N number Convolution 3D of Filters were converted to (N/2) 5x5x5 and (N/2) 3x3x3 filters. This enables the neural network to capture more diverse filters and perform better. The modified network achieved a lower elbow point during training shown in figure 2. The mean percentage error by calculating the Euclidean distance from ground truth to the predicted 42 features for NYU test data using the same neural network at output of our modified and original shallow network for achieving 3D points from lower embedding space are shown in figure 1. The average prediction time of shallow plain and our modified on Nvidia GTX 1050 was 60 ms and 49 ms, respectively.

Discussion

The result illustrates the advantage of using different filters at each layer. By using the same number of filters, approximately the same latency is achieved. In the future, a different volumetric representation of the depth images is to be used for the neural network to perform better. 3D architectures having similar basic structures to GoogleNet and EfficientNet will be implemented. A better dimensionality reduction technique will be adopted to exploit better relationships between points. PCA works optimally if correlations are linear, and it cannot handle non-linear data.

Diagram

Description automatically generatedA picture containing table

Description automatically generatedHyperparameter Optimization

Hyperparameters are the variables in the neural network which determine the network structure and how the network is going to be trained ( number of hidden layers, number of neuron, learning rate, Batch size, Optimizer ). They are set before the training process. Hyperparameter optimization can be done by manually search, random search, grid search, surrogate function. Manual search is a subjective process. In random search the probability of getting optimal parameters is inversely proportional to size of the search space. Grid search requires a large computation cost and time. Surrogate is the only objective process using mathematical calculations to exploit the best parameters in search space.

Search Space

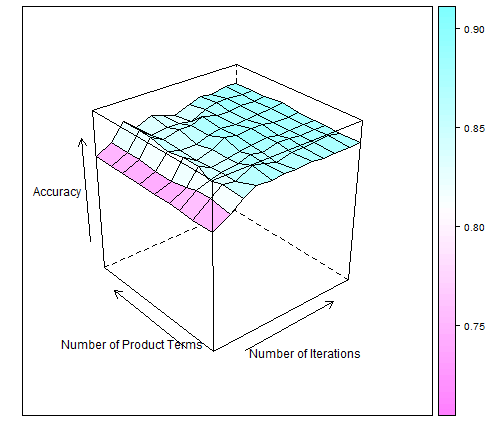
The search space for the hyperparameters of the model producing 14 points in the 3d space was No of hidden layers from 1 to 5. No of Neurons in each layer were taken between 512-4096 that are multiple of 512. Learning rate between the range 0.01 to 0.000001. Dropout layer was not used because no regularization technique was required due to availability of large dataset.

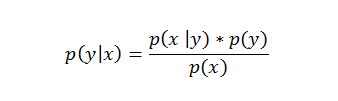
In the search space of the modified network, hyperparameter optimization was applied only on the last two fully connected Dense layers due to expensive computation cost of training the neural network. Hyperparameters were no of neurons in the last two hidden layers, optimizer, learning rate.

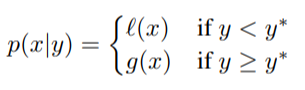
Surrogate Function ( Probability Model )

Surrogate function is the response function or response surface it tends to exploit the search space for the best loss or accuracy. It takes into account previous results and uses probabilistic calculations in order to find future best hyperparameters. The main objective of the surrogate function is to reduce the number the times objective function needs to run. There are many forms of surrogate function including Bayesian optimizations. Figure 3 shows response surface for only two hyperparameters

Figure 2: Showing Architecture of both Modified network and original shallow network

**Tree-structured Parzen Estimator ( TPE )**

The surrogate function used for performing hyperparameter optimization of the both models is TPE. The TPE is a sequential model-based optimization (SMBO) approach. TPE builds a model by applying Bayes rule. The probability for achieving y loss with x parameters is calculated by following equation.

The p(x | y) can be defined piecewise on the basis of the return value from objective function i.e. y. It can defined by following equation.

The above equation makes two different distributions for the hyperparameters. The above equation is for distribution to minimize the objective function. The expected improvement for the next for hyperparameters is proportional to the terms g(x) and l(x). It can be seen in equation below.

In order to maximize the expected improvement, the ration of l(x)/g(x) must increase. The algorithm must choose hyperparameters which fall in l(x) rather then g(x). The TPE estimator returns value for maximum value for the ratio l(x)/g(x). If the surrogate function is optimal it will return hyperparameters to maximize the expected improvement. If the surrogate function will be updated after result of every hyperparameter configuration.

**Drawback of TPE**

Tree-structured Parzen Estimator tends to find the suitable distribution for the hyperparameters. It lacks to exploit the interaction between different hyperparameters, much less then gaussian process between. It will not sample hyperparameters from relative search space if strong relationship exists between them.

**Base Sampler**

This sampling technique brings balance of both the worlds by applying both relative sampling and independent sampling. The relative sampling determines the value of multiple hyperparameters so correlation could be determined between them. The independent sampling determines value of single hyperparameter without considering relationship between other parameters. The relative search space is determined by a method. Before every trail the parameters returned within relative search space are sampled by relative sampler and the rest with independent sampler.

**HPO Experimental Setup**

The neural network producing 14 , 3D joints from lower embedding was trained on input of lower dimensional embedding of 30 values achieved through PCA and output of 14,3D joints.

The NYU dataset was split into 90% training and 10% validation .Objective function trains the neural network for 10 epochs and returns the best loss. Neural network with 1,2,3 and 5 dense layers were given to search space described above with TPE to find the best neural network.

The modified network takes a lot of time to train so for HPO it was trained on subset of data (TSDF) i.e. 16,000 and validation on

Figure 3 : The response surface for only two hyperparameters

![Chart, line chart

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generated](data:image/jpeg;base64,/9j/4AAQSkZJRgABAQEAYABgAAD/4RDsRXhpZgAATU0AKgAAAAgABAE7AAIAAAALAAAISodpAAQAAAABAAAIVpydAAEAAAAWAAAQzuocAAcAAAgMAAAAPgAAAAAc6gAAAAgAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAEFMSSBBUlNMQU4AAAAFkAMAAgAAABQAABCkkAQAAgAAABQAABC4kpEAAgAAAAMwMgAAkpIAAgAAAAMwMgAA6hwABwAACAwAAAiYAAAAABzqAAAACAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAA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Figure 4 : Shows parallel coordinate graph of Hyperparameter optimization of model producing 14, 3D coordinates from lower embedding

5,000 (TSDF). The search space for modified network was described above. The modified network hyperparameter optimization technique produced best results on base sampler rather then TPE , it could be concluded that hyperparameters have a strong dependent relationship among each other. This effect was not visible in the neural network producing 14 joints 3 dimensional embedding, it was due to the small search space both techniques were able to exploit every combination in the small search space. The best architecture for producing embeddings by HPO achieved had two layers, First layer with 2816 nodes and second layer with 2304 nodes with learning rate of 0.000731. The best architecture for the modified network achieved was 4096 neurons in the last two hidden layers with Adamax optimizer and learning rate of 0.00014.

Curriculum Learning

Curriculum learning is defined as training the neural network in such a way that easy samples are given first then gradually the difficulty of the samples is increased. Curriculum learning was used to further improved the modified network. The samples were classified into three categories Easy, Intermediate, Difficult. The classification was done from the previously modified network obtained from HPO by Base Sampler. The Error for classification was MAE. Samples with loss less then 0.05 were classified in easy category. Samples with loss between 0.05 and 0.10 were classified into Intermediate category. Samples with loss above then 0.10 were classified into Difficult category.

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