
Visual motion disambiguation via contextual feedback control

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Abstract

This lab rotation considered the affect of contextual feedback from the visual area MT to the primary visual cortex V1. Due to the aperture effect the movement of the presented square stimulus is ambiguous except at its edges. A model formulated to disambiguate the movement of each pixel considers three stages within each model area. The first stage architecture is dominated by modulatory feedback from the higher stage, whereas the second stage realizes an integration in space by an isotropic gaussian filter. Finally stage three normalizes estimations to emphasize unambiguous signals.

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1 Introction

In a natrual environment the visual system deals with disambiguating moving stimuli. This process involves area V1 and MT of the dorsal stream, see Figure 1.

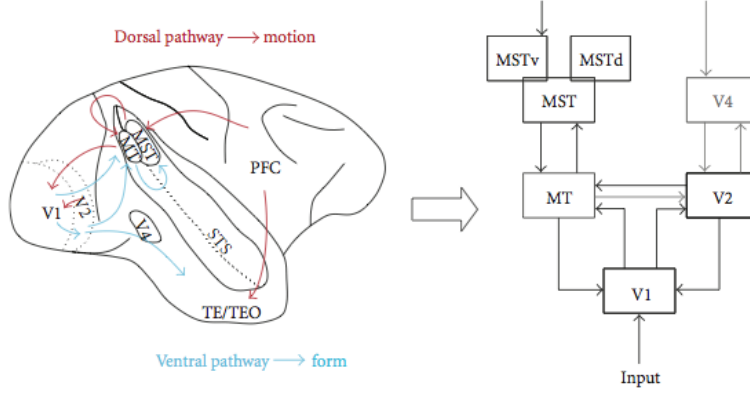


Figure 1: The Dorsal pathway for motion processing. The location of involved brain areas are shown in the left part whereas a structural processing scheme is displayed on the right side.

The input to model area V1 is considered to be the output of a local measure of motion, which is realized by the Reichard detector [?]. It delivers a movement orthogonal to an extended edge, which is known as the aperture problem. This can be resolved for localized image features, such as edges, but remains otherwise. Due to the small receptive field of single neurons a e.g. horizontal edge which is moving in a 45 degree angle seems to move upward instead. Such an initial detection of motion can be contradicting within one object and remains to be resolved within following areas V1 and MT.

This disambiguation step is further subcategorized in six stages, three within the primary visual cortex and three in MT. Stages of both model areas are equal in their architecture.

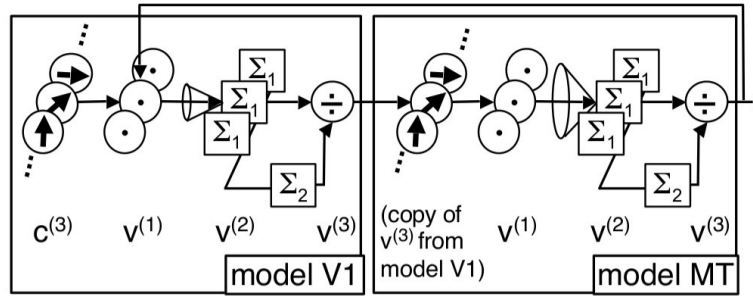


Figure 2: Overview of the model architecture including three stages within area V1 and MT. Feedback stage $v^{(1)}$ is the output of area MT in V1 and zero in area MT, since no higher stages are considered to feed back to area MT. Stage $v^{(2)}$ consists of an integration with isotropic gaussian kernels in space realized by a convolution with the signal from $v^{(1)}$. $v^{(3)}$ is the lateral shunting inhibition stage where unambiguous signals get amplified and ambiguous ones get weakened.

In order to solve the aperture problem this architecture involves feedforward and modulatory feedback, which provides a prediction mechanism and is realized via a recurrent loop, see Figure 2.

However, in V1 the feed forward signal from the Reichardt detector receives, as a first modulatory impact, feedback from area MT. The resulting activity can then be interpreted as a measure of degree of match between the feedback and input at the next time step. Therefore, if the prediction of area MT matches the new input, the resulting activation will be maximal. The purpose of this step is to provide activations in V1 that match the expectations of the system

Further the resulting signal is sharpened by squaring it and then feed forward to the step of spatial integration. Here the signal from the previous step is convoluted with a two dimensional spatial gaussian. This serves the aim that motion information from neighbouring pixels are smoothened which can be compared to the vector average of the individual motion vectors. Here the model ensures integration of the surround into the motion information of each pixel which is then feed forward to the final model area.

Here a normalization of movement direction estimations is realized by ????

2 Theory of Model Stages

2.1 Input Stage

As a stimulus a black square on a white background was used, which moves in the direction of 45° with a step size of Δt .

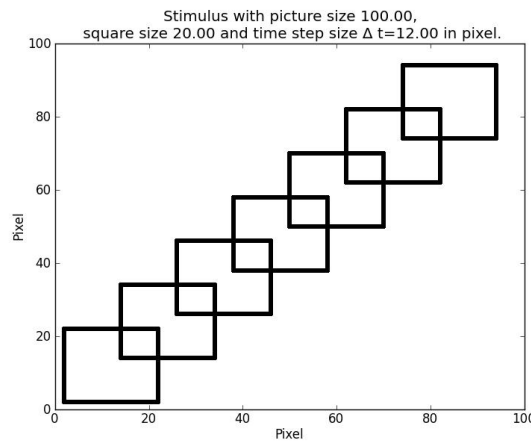


Figure 3: Black square stimulus moving in the direction of 45°

. Each time step Δt is represented as a single square at a certain position. For illustration reasons in this figure all time steps are presented together.

As described above the input to model area V1 is the output of the Reichardt detector. In this lab rotation the Reichardt detector was not implemented as such but its output was created manually instead.

More explicit this means that for each pixel a population code was build to mimic the Reichardt detector output. This was done by choosing 8 neurons which are individually tuned, in a gaussian fashion, to a certain angle in space. The neuronal tuning curves were chosen to equally divide the entire space (360°) and can be seen in figure 4

For each direction in space one can now write an eight dimensional vector, where the rows correspond to the individual neuron with its activation for the chosen direction in space (see figure 4).

Due to the aperture problem we assume vertical vectors for horizontal stimulus edges and horizontal vectors for vertical edges. The three pixels which form the stimulus corners indicate the correct

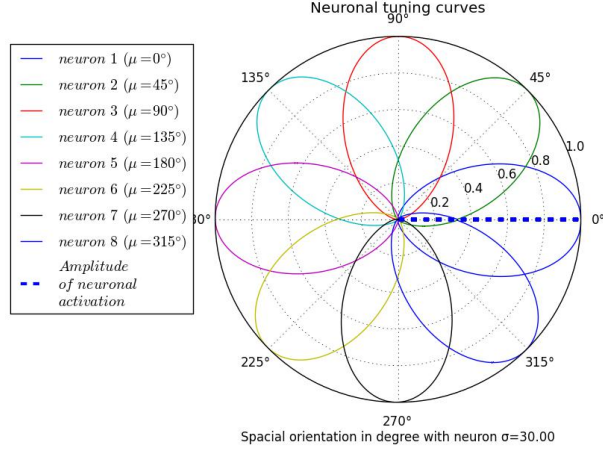


Figure 4: Gaussian tuning curves in space of 8 different neurons with a maximal Amplitude of 1.

direction of 45° .

In order to plot such a vector for each pixel (x, y) , the neuronal activation from the population code needs to be translated. This can be done by mutiping the eight dimensional vector containing the activation of the single neurons $(A(n))$ with its basis:

$$V = (A(1), A(2), \dots, A(8)) \cdot \begin{pmatrix} (0 & 1) \\ (1 & 1) \\ \vdots \\ (-1 & 1) \end{pmatrix} \quad (1)$$

To get the endpoints of the vector for the considered pixel, we sum each column of (1):

$$(\Delta x, \Delta y) = \left(\sum_{n=1}^8 V(n, 1), \sum_{n=1}^8 V(n, 2) \right) \quad (2)$$

Connecting the considered pixel (x, y) with $(\Delta x, \Delta y)$ of quation (2) draws the desired vector. Repeating this procedure for all pixels gives us the final input to the model (figure 5).

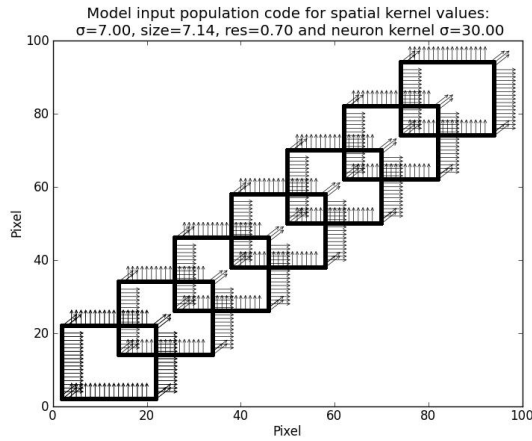


Figure 5: Input population codes with visualized vectors indicating the motion direction per pixel. One square represents one input per time step, moving in 45° .