

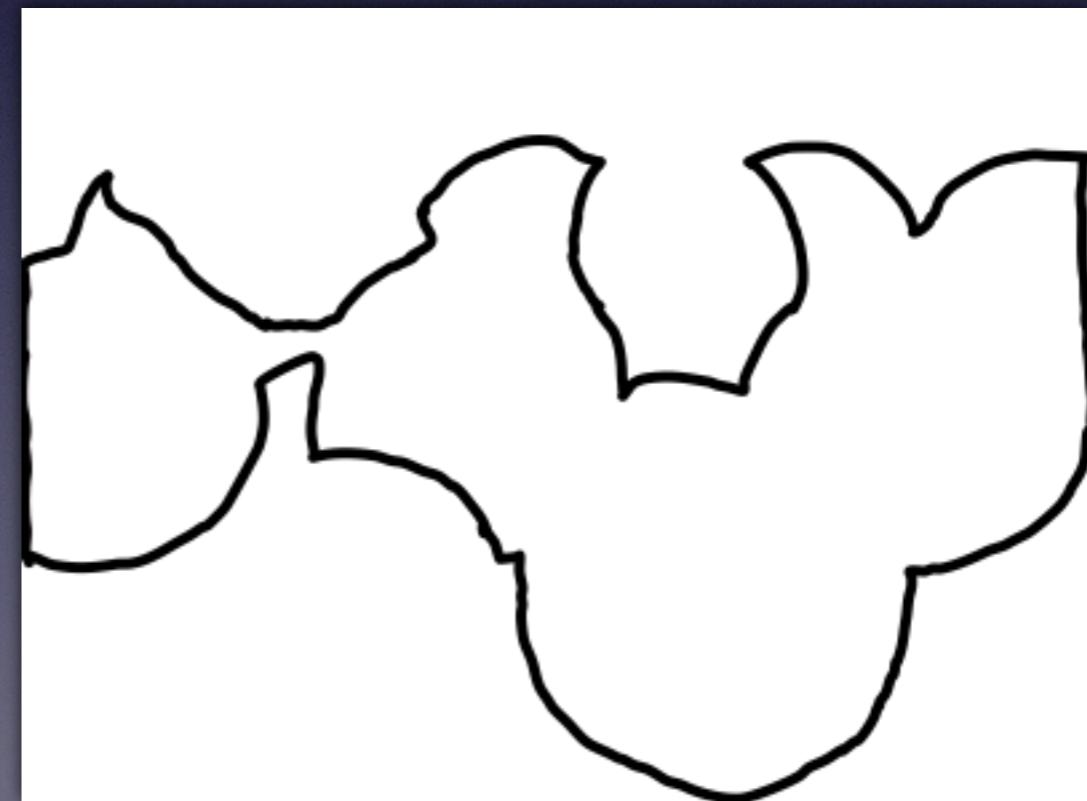
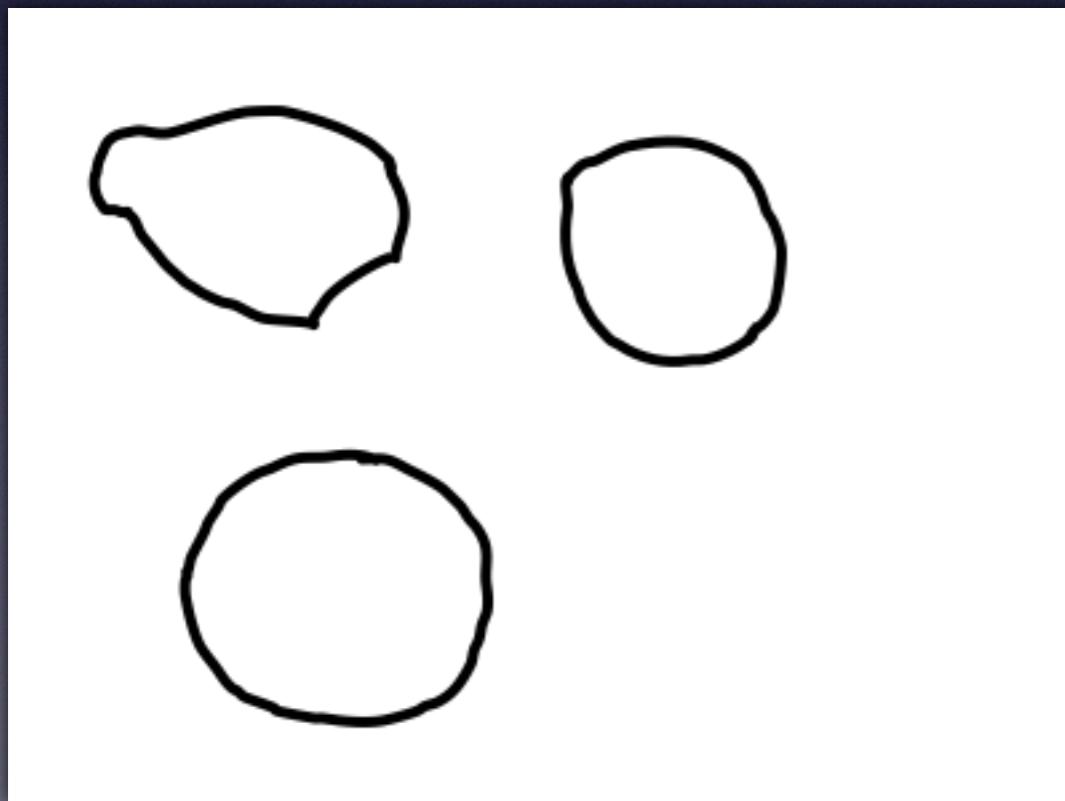
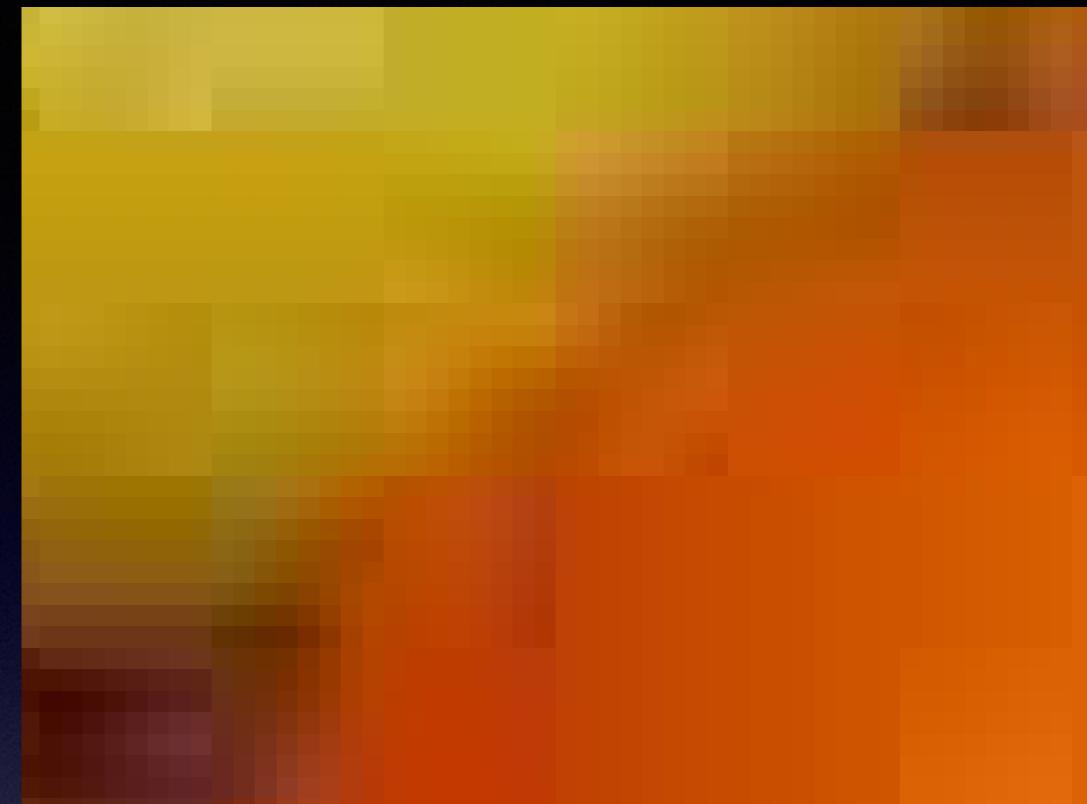
# Statistical Models for Visual Detection and Recognition

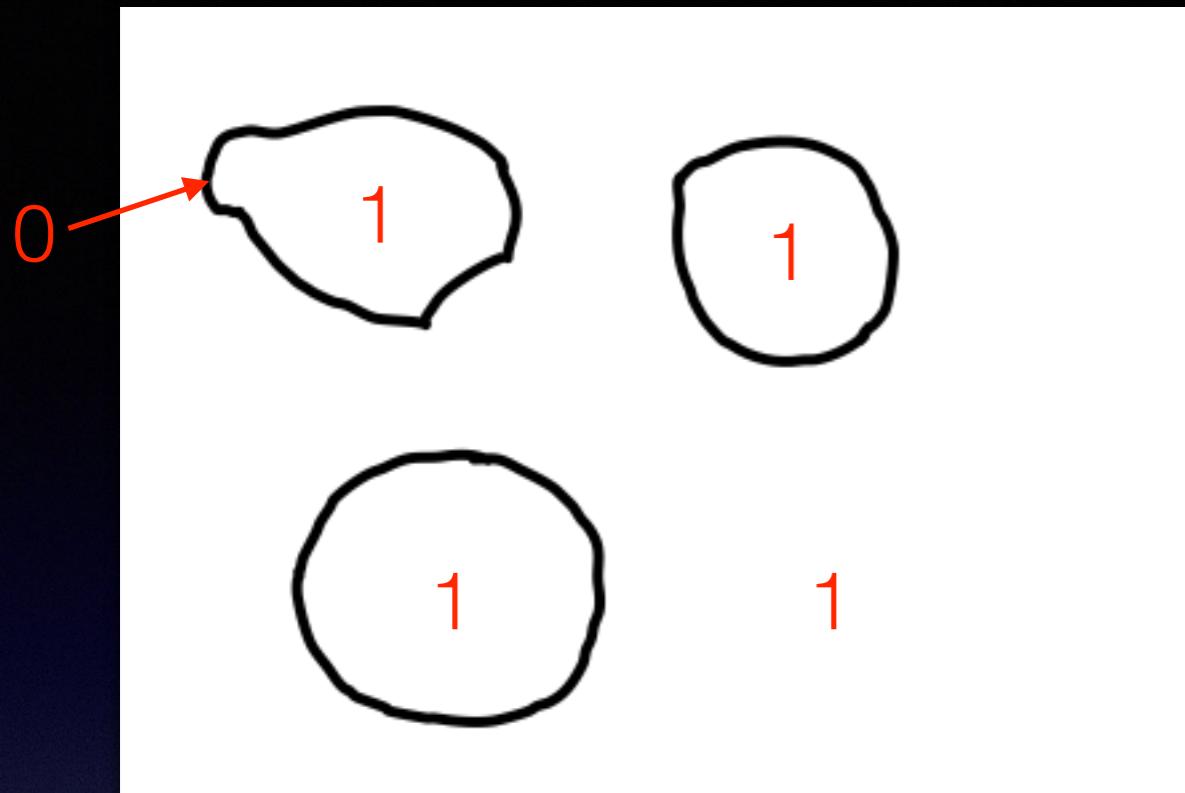
COMPSCI 527

Today: (discrete probabilities)

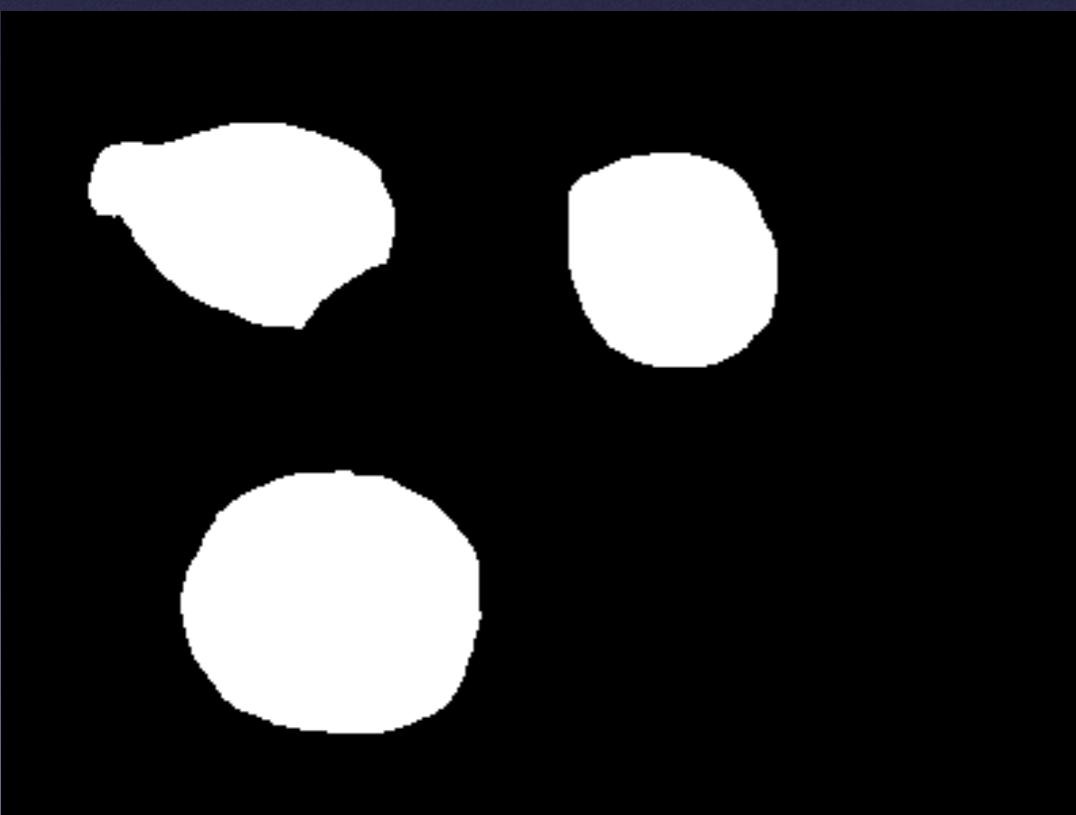
- Color features and Matlab
- Joint and conditional probabilities
- Bayes's theorem and the Bayes classifier



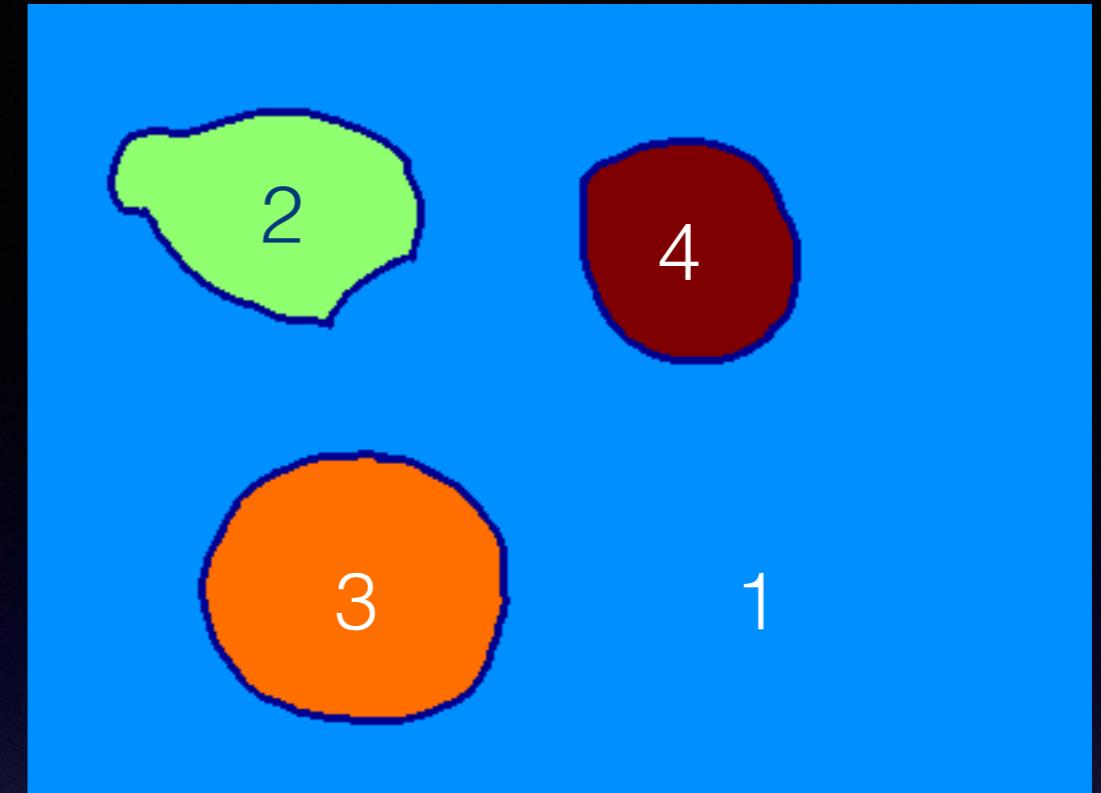




trace



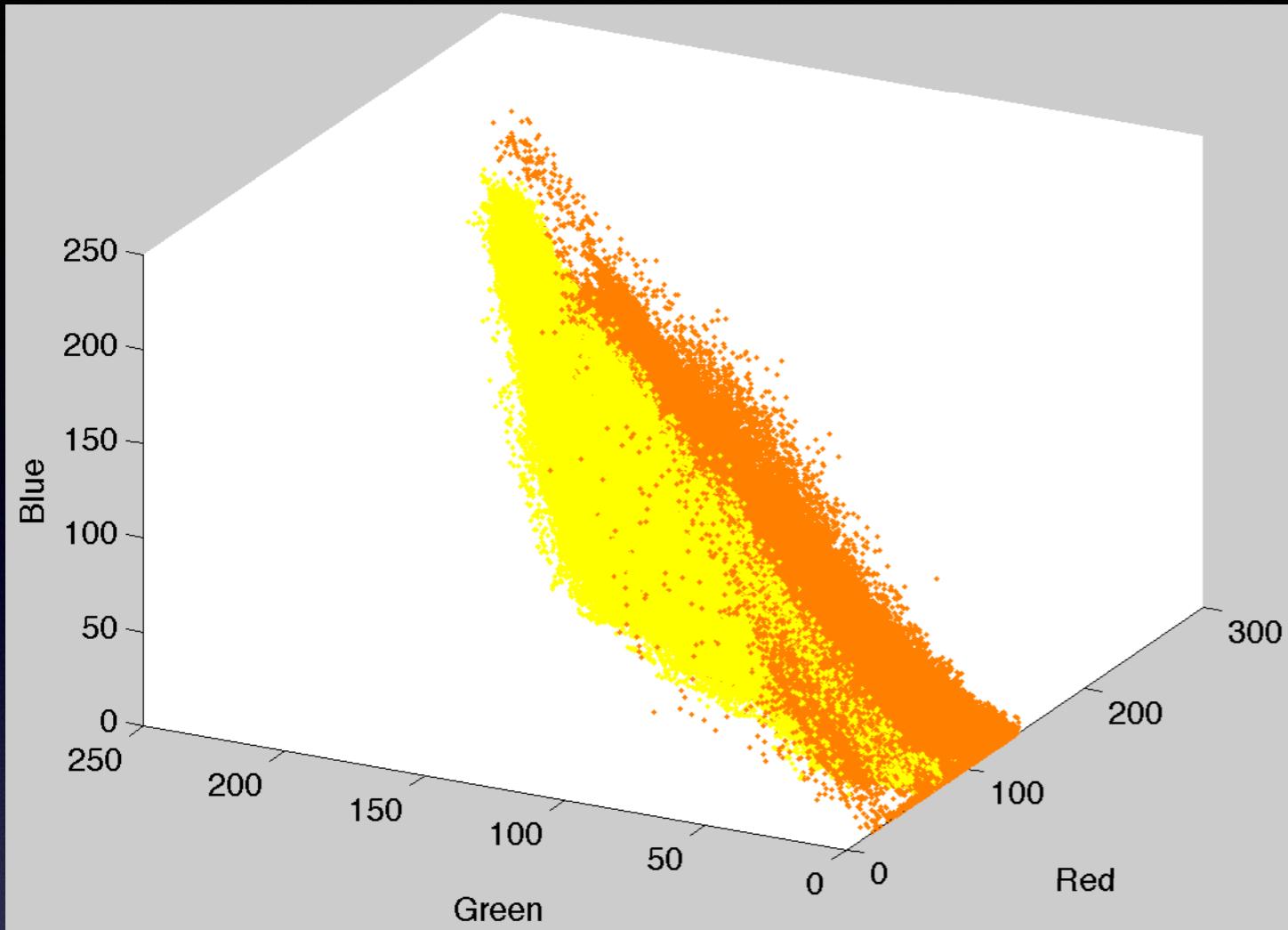
mask



CC

```
% Connected components
cc = bwlabel(trace);
mask = cc==2 | cc==3 | cc==4;
red = img(:, :, 1);
green = img(:, :, 2);
blue = img(:, :, 3);
rgb = [red(mask), ...
        green(mask), blue(mask)];
```

↑  
n x 3 array of pixel values

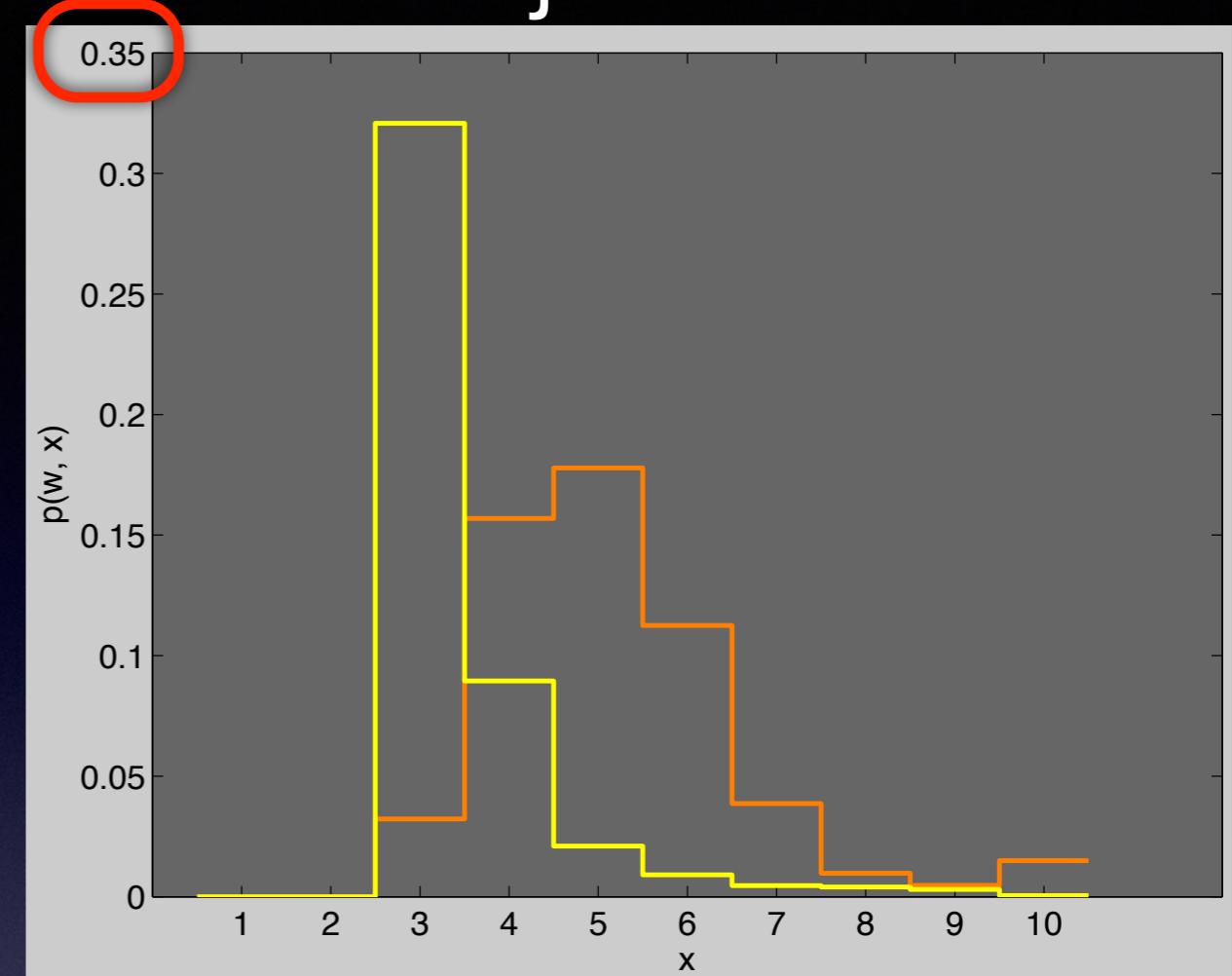
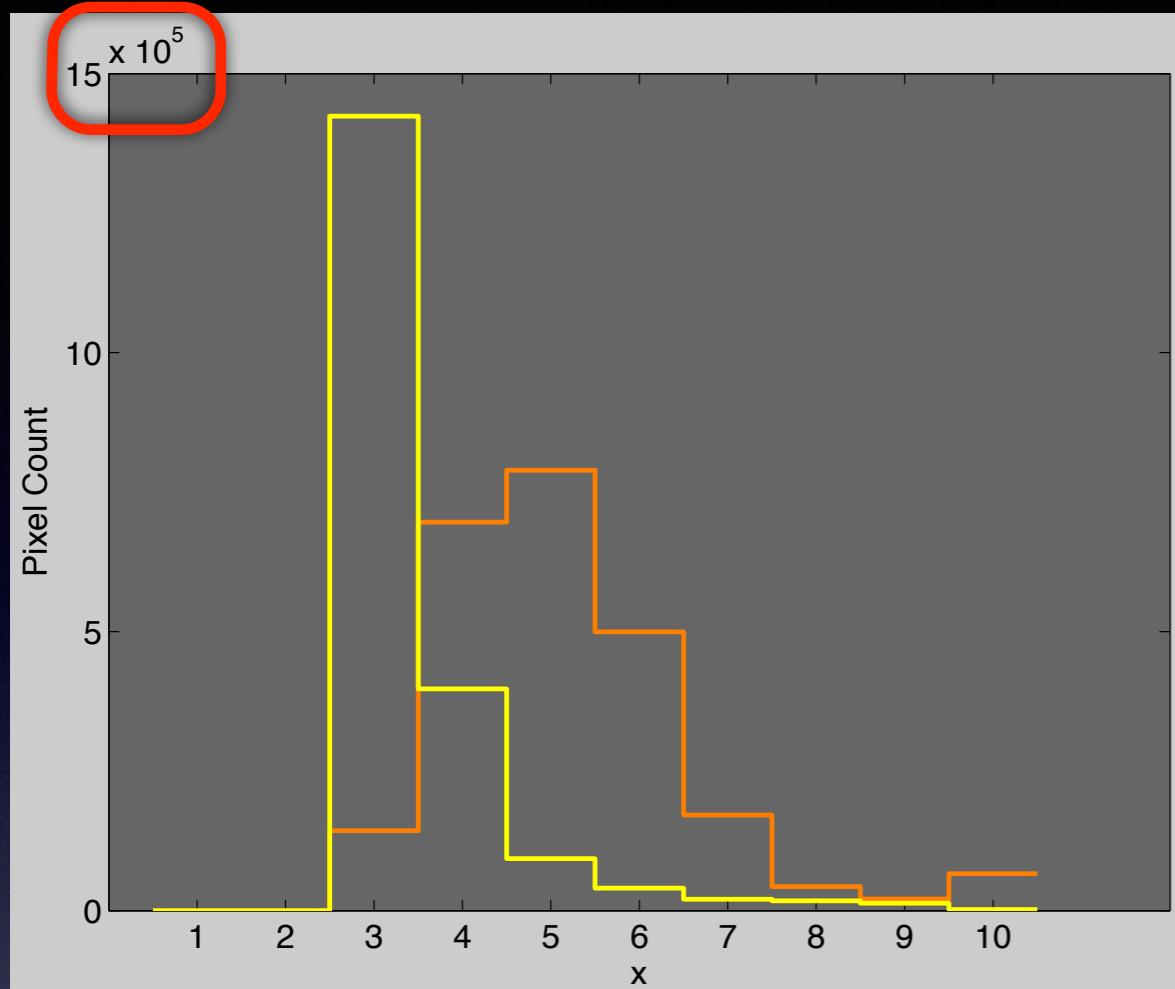


- Brightness does not matter
  - Yellow  $\propto [1 1 0]$
  - Orange  $\propto [1 0.5 0]$
  - Blue does not matter

$$c = \frac{R - G}{R + G + B}$$

```
function c = colorToScalar(rgb)
rgb = double(rgb);
denom = sum(rgb, 2);
nz = denom ~= 0;
rgb(nz, :) = rgb(nz, :) ./ (denom(nz) * ones(1, 3));
c = rgb(:, 1) - rgb(:, 2);
```

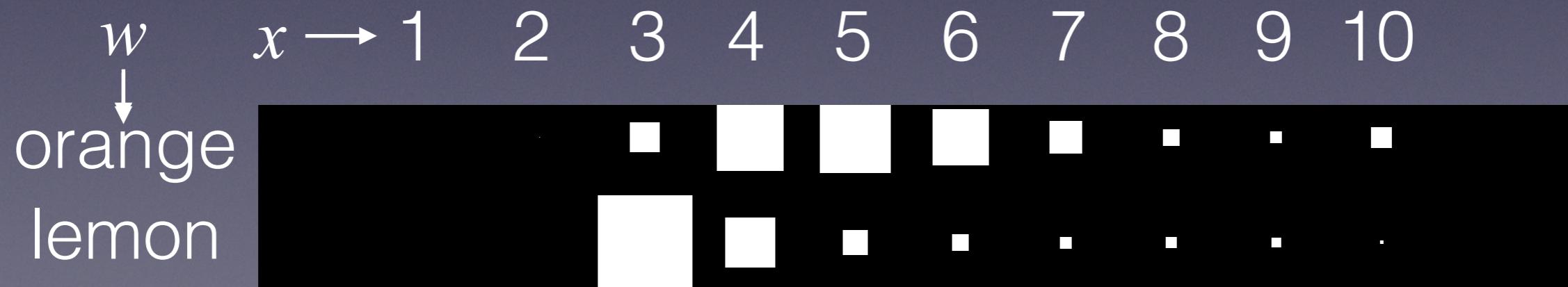
# joint



Data *feature*:  $x = \text{bin}(c)$

World *state*:  $w = \{O, L\}$

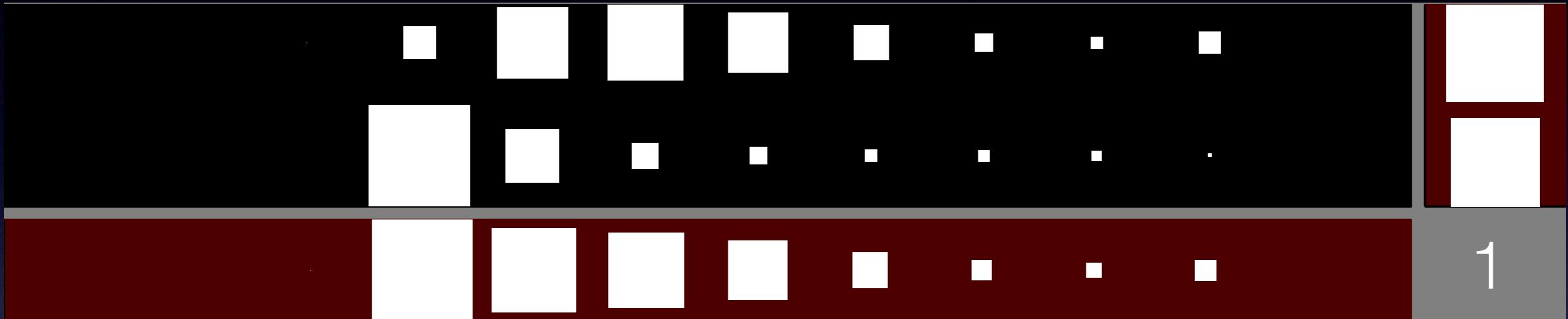
$$\sum_w \sum_x p(w, x) = 1$$



# marginals

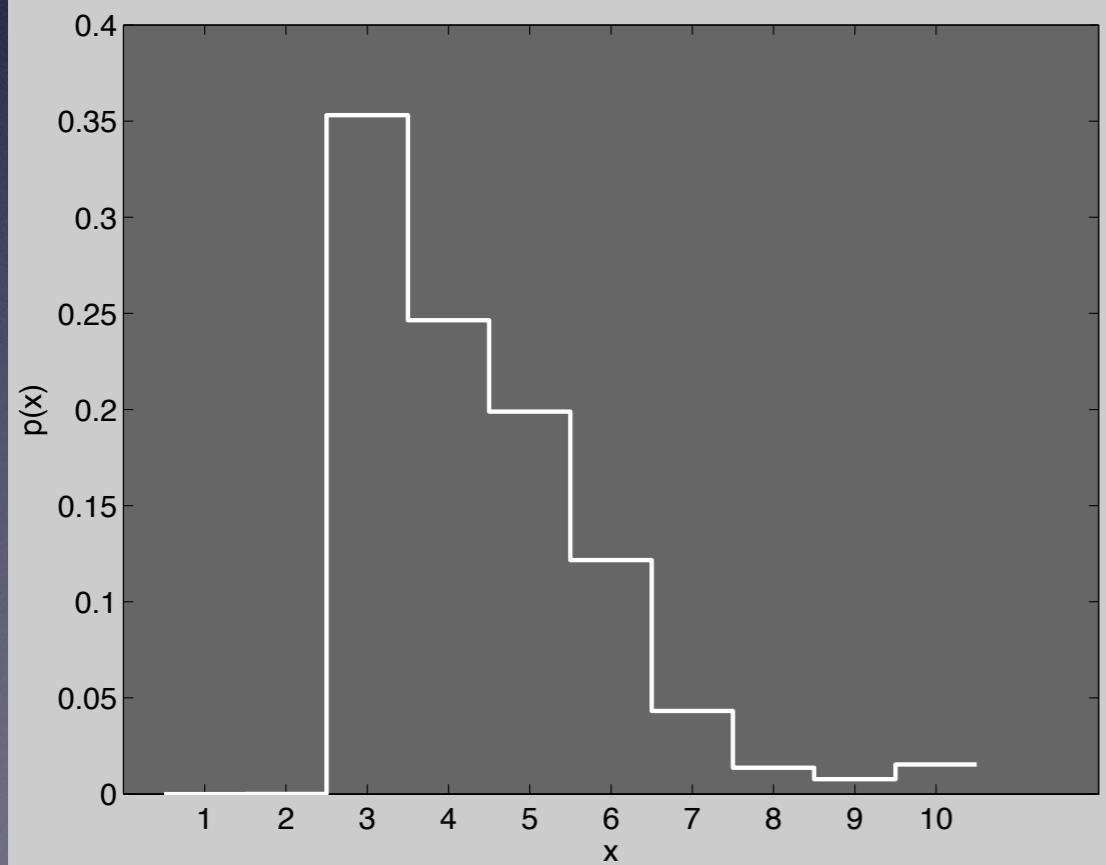
$x$   $\longrightarrow$

$w$



$$p(w) = \sum p(w, x)$$

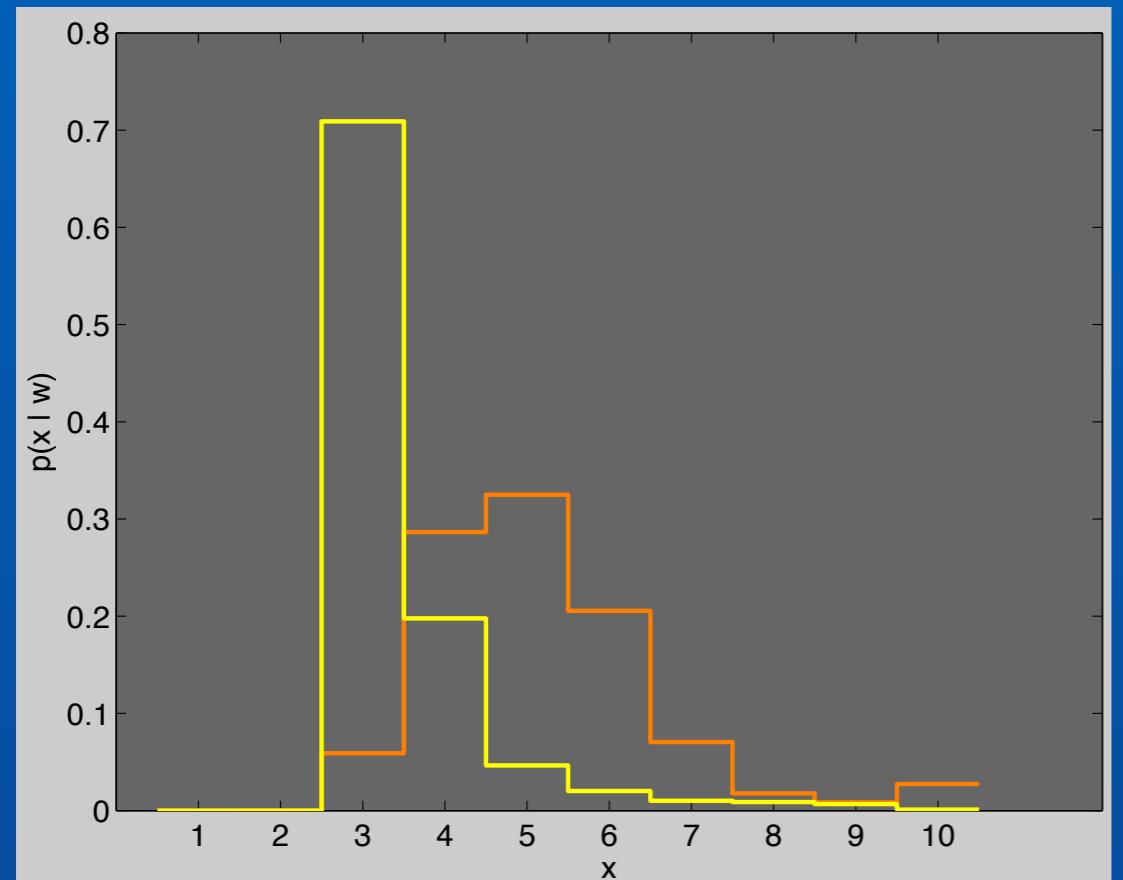
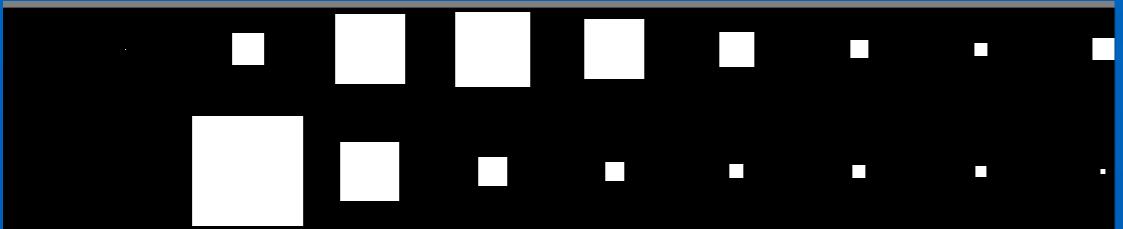
$x$



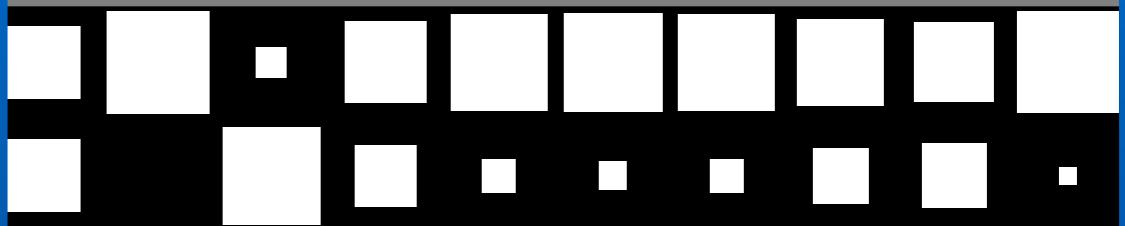
$$p(x) = \sum_w p(w, x)$$

$w$

# conditionals



$$p(x | w) = \frac{p(w, x)}{p(w)}$$



$$p(w | x) = \frac{p(w, x)}{p(x)}$$

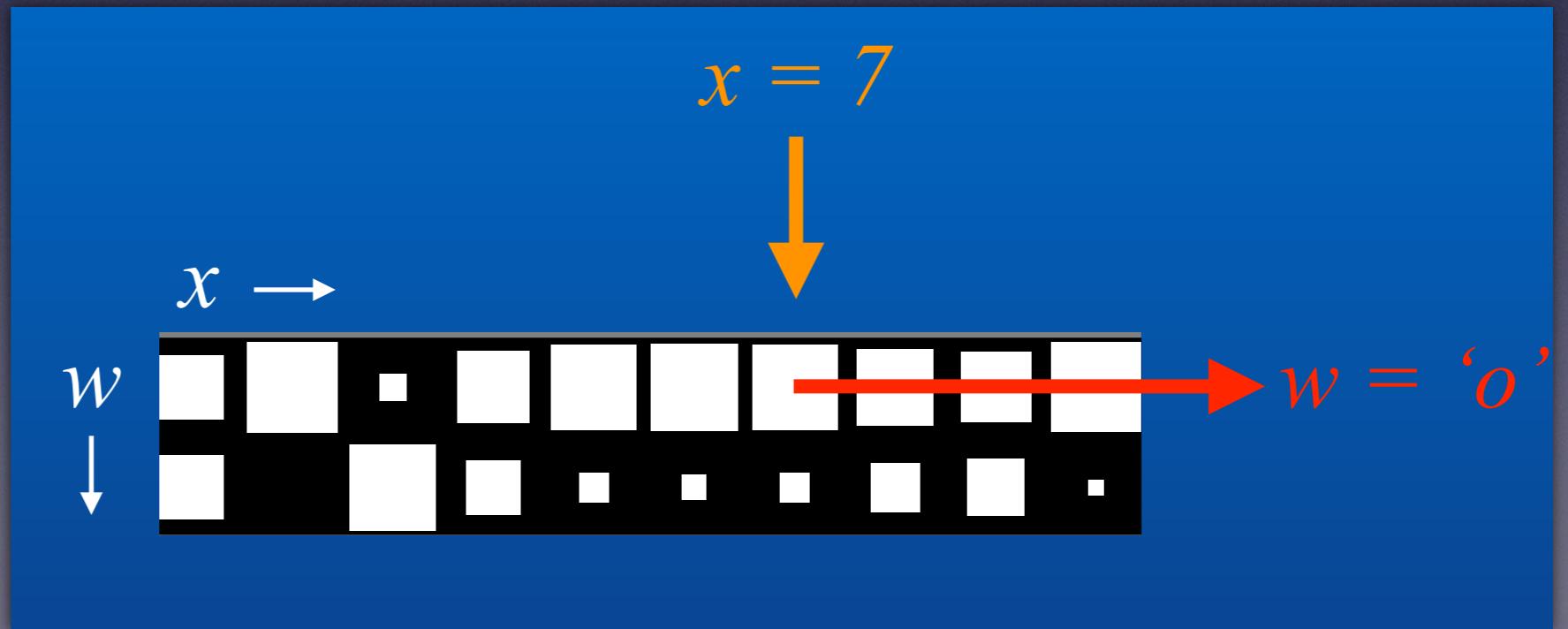
↑  
10 of these ( $b = 1, \dots 10$ )

← 2 of these ( $f = 1, 2$ )

# The Bayes Classifier

- $w = f(x)$ : given an image observation  $x$ , find the world state  $w$
- we have  $p(w|x)$
- $f(x) = \arg \max_w p(w|x)$

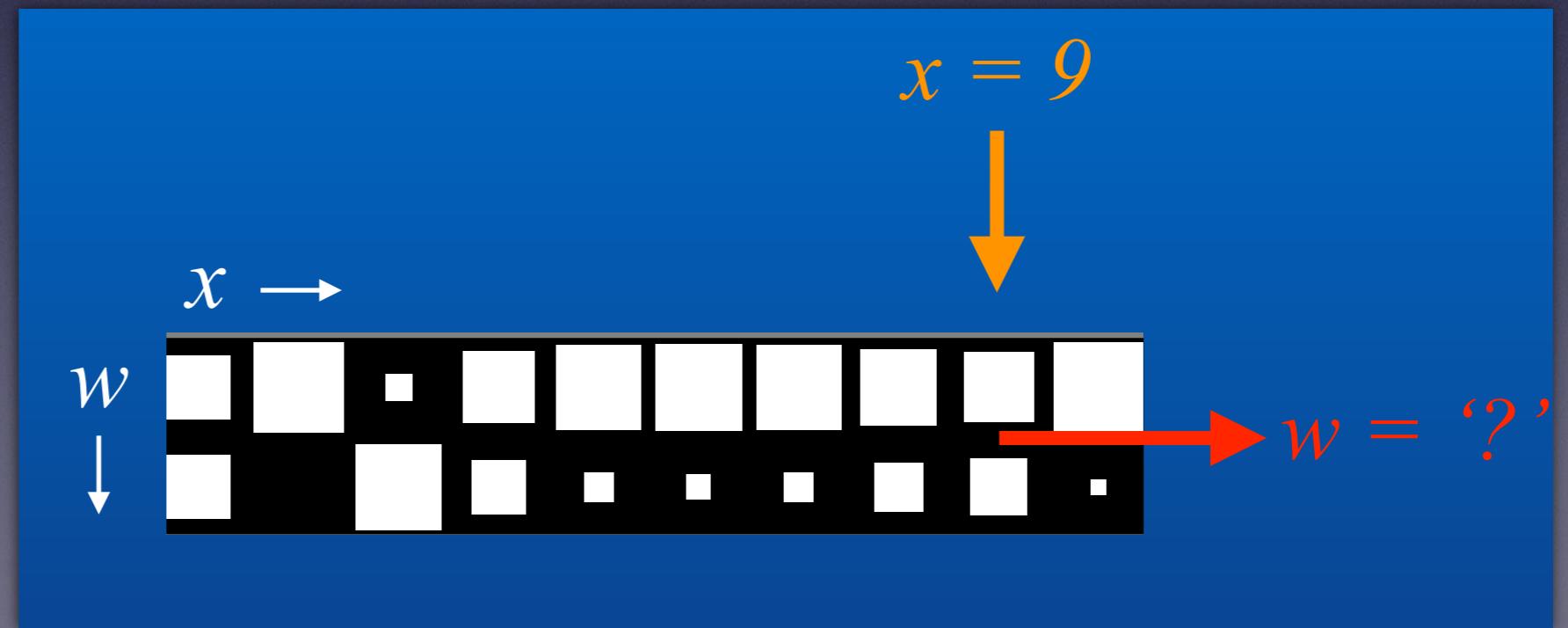
$$p(w | x) = \frac{p(w, x)}{p(x)}$$



# Classifier with Confidence

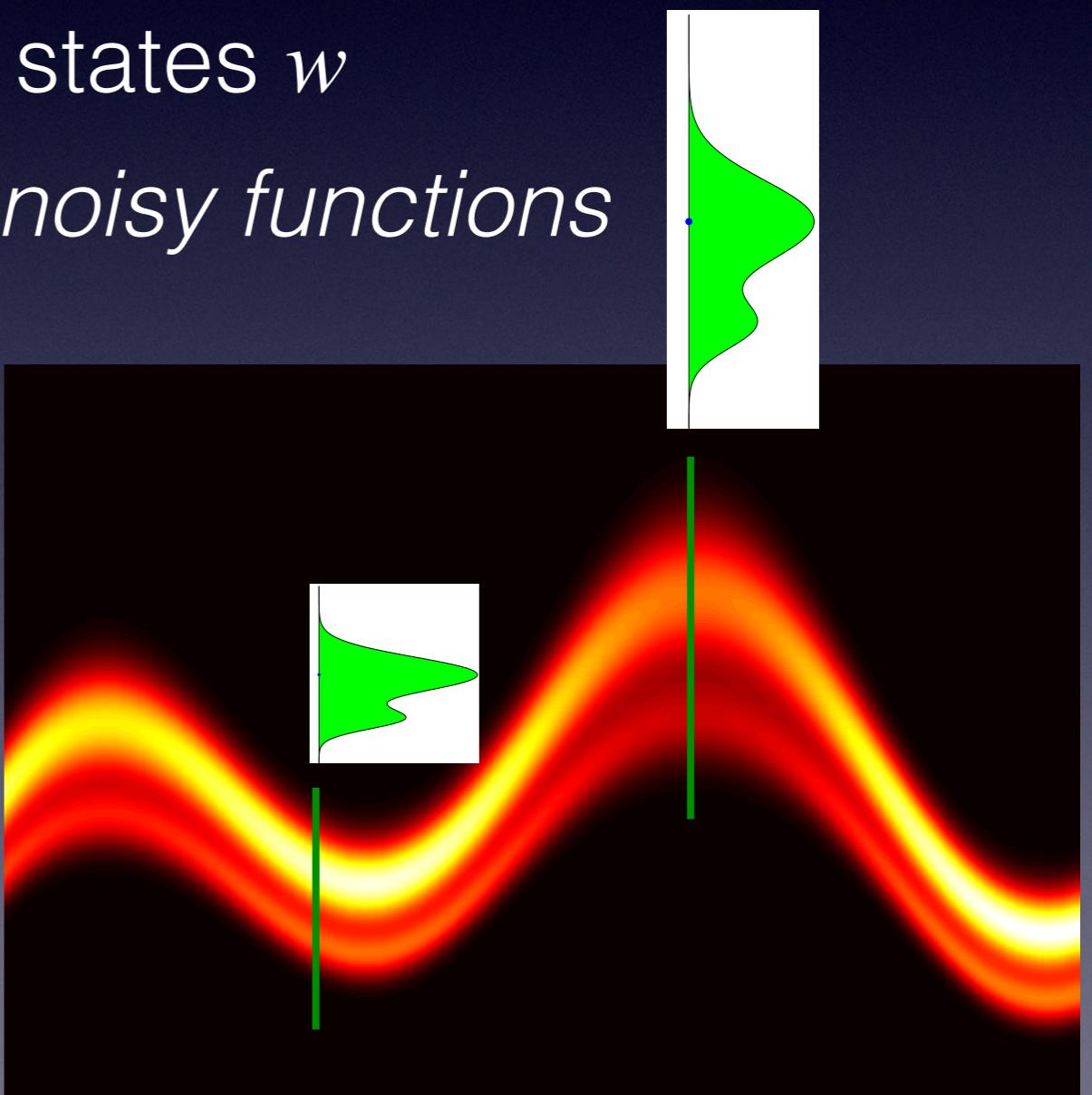
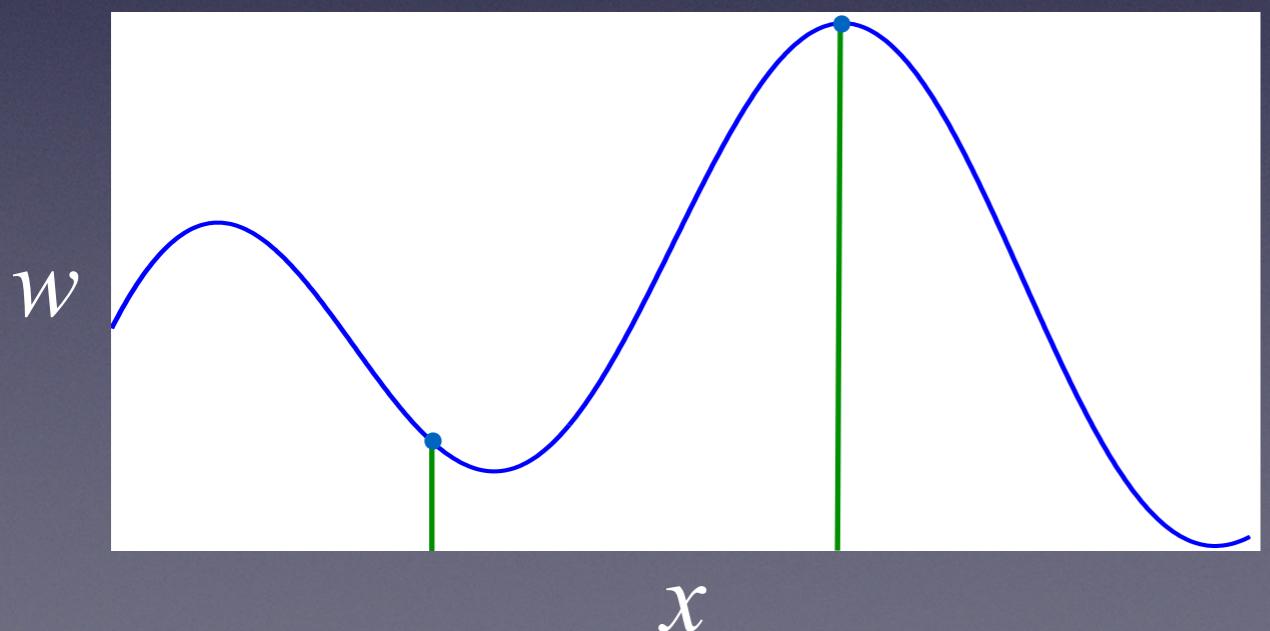
- $f(x) = \arg \max_w p(w|x)$  [Bayes classifier]
- confidence: some function of  $p(w|x)$ : maybe  $c(x) = 2 [p(f(x)|x) - 1/2]$  for the binary case
- can say “don’t know” if  $c$  is too small

$$p(w | x) = \frac{p(w, x)}{p(x)}$$

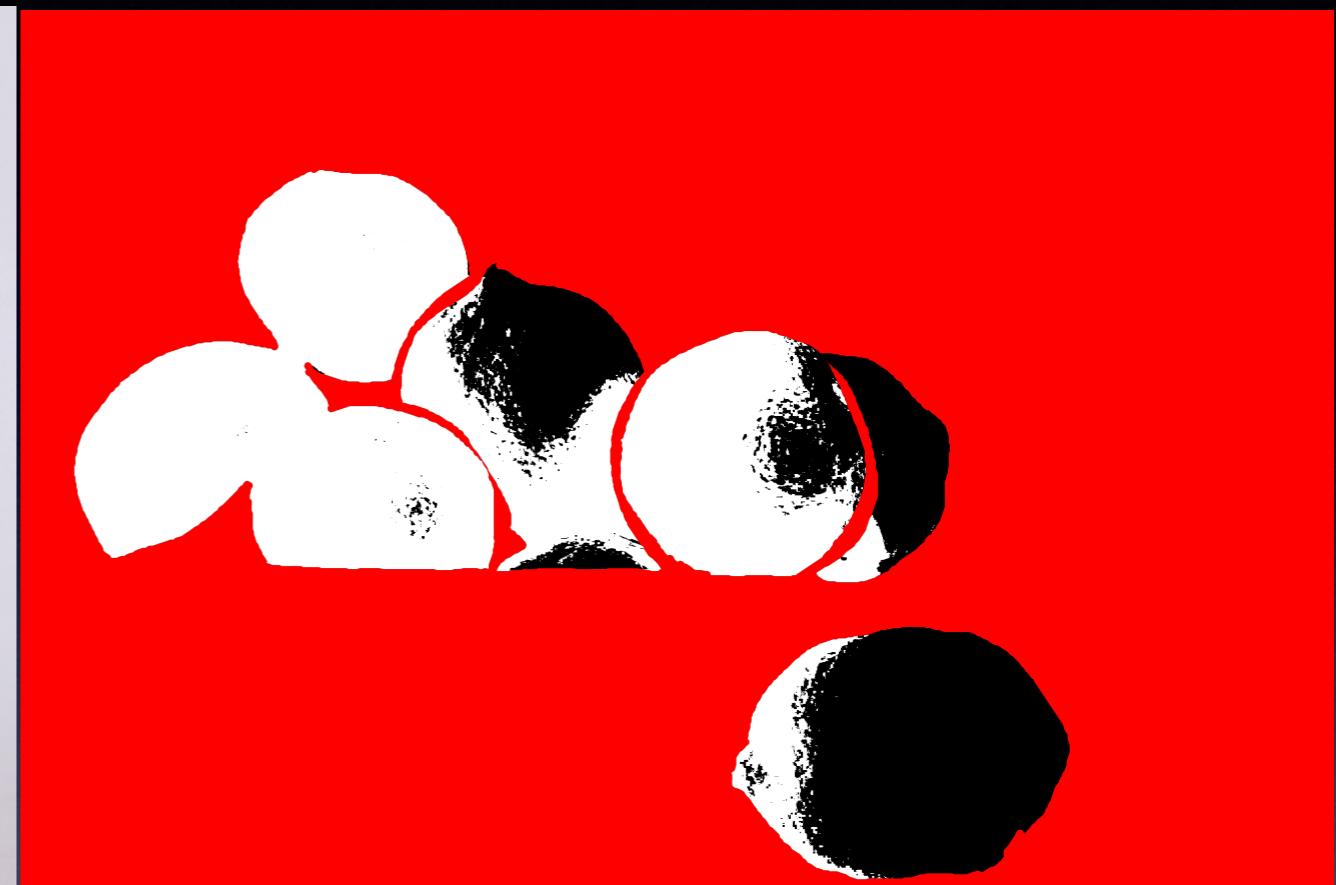


# Noisy Functions

- $f(x)$  is a function that maps each image observation  $x$  to a world state  $w$
- $p(w|x)$  is a function that maps each image observation  $x$  to a distribution over world states  $w$
- conditional probabilities are *noisy functions*



# oranges?



~oranges == lemons?

not really a binary problem!

how well can we possibly do?

# Bayes Error Rate

$p(w|x)$



$$f(x) = \arg \max_w p(w|x)$$

$p(w, x)$



$$e = 1 - \sum_x p(f(x), x) = \mathbf{0.164}$$

# Cheating Big Time!



training set

test set

Need:  $\text{training set} \cap \text{test set} = \emptyset$

# Discrete Bayes's Theorem

[one conditional from the other]

$$p(w, x) = p(w \mid x)p(x) = p(x \mid w)p(w)$$

$$p(x \mid w) = \frac{p(w \mid x)p(x)}{p(w)}$$

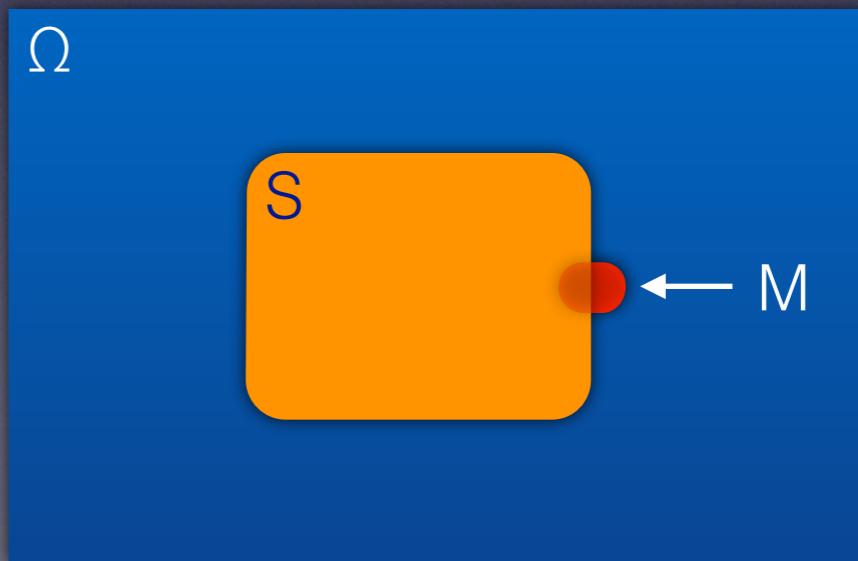
$$p(w \mid x) = \frac{p(x \mid w)p(w)}{p(x)}$$

$$p(x) = \sum_{w'} p(x \mid w')p(w')$$

# Bayes Example

[From Russel and Norvig, *Artificial Intelligence*, Prentice Hall 1995]

- One in 20 people have a stiff neck
- One in 50,000 people have meningitis
- *Half the people with meningitis have a stiff neck*
- If you have a stiff neck, should you worry about meningitis?



$$p(w|x) = \frac{p(x|w)p(w)}{p(x)}$$

Diagram illustrating the components of the Bayesian formula:

- (world) state: Represented by a green arrow pointing to  $p(w|x)$ .
- data: Represented by a green arrow pointing to  $p(x|w)$ .
- likelihood: Represented by an orange arrow pointing to  $p(x|w)$ .
- prior: Represented by an orange arrow pointing to  $p(w)$ .
- posterior: Represented by an orange arrow pointing to  $p(w|x)$ .
- evidence: Represented by an orange arrow pointing to  $p(x)$ .

# Convenient Notation Abuse

$$p(w \mid x) = \frac{p(x \mid w)p(w)}{p(x)}$$

Four functions, one name!

$$p_{W|X}(w, x) = \frac{p_{X|W}(x, w)p_W(w)}{p_X(x)}$$

[Note:  $p(a, b \mid c, d) = p((a, b) \mid (c, d))$ ]

[book uses  $\Pr$  instead of  $p$ ]