GPU Implementations of Object Detection using HOG Features and Deformable Models

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Visione-based object detection using camera sensors is an essential piece of perception for autonomous vehicles. Various combinations of features and models can be applied to increase the quality and the speed of object detection. A well-known approach uses histograms of oriented gradients (HOG) with deformable models to detect a car in an image [14]. A major challenge of this approach can be found in computational cost introducing a real-time constraint relevant to the real world. In this paper, we present an implementation technique using graphics processing units (GPUs) to accelerate computations of scoring similarity of the input image and the pre-defined models. Our implementation considers the entire program structure as well as the specific algorithm for practical use. We apply the presented technique to the real-world vehicle detection program and demonstrate that our implementation using commodity GPUs can achieve speedups of 1.5x to 3x in frame-rate over sequential and multithreaded implementations using traditional CPUs.

Index Terms—**GPGPU; Computer Vision; Object Detection**

I. INTRODUCTION

Grand challenges of cyber-physical systems (CPS) include a high computational cost of understanding the physical world. Object detection is one of compute-intensive tasks for CPS. For example, an autonomous vehicle needs to detect and track other vehicles by itself. Current autonomous driving technologies [6], [13], [21] tend to rely on active sensors such as GPS, RADAR, and LIDAR [11], [19] together with very accurate pre-configured maps, but the use of passive camera sensors is becoming more practical due to recent advances in computer vision [2]–[4]: vision-based object detection can be applied for various ranges and orientations. In particular, histograms of oriented gradients (HOG) [2] features provide reliable high-level representations of an image underlying many state-of-the-art object detection algorithms [3], [5], [18], [20], [22]. However, a major concern of HOG-based object detection remains in computational cost.

Previous work on the implementation of HOG-based object detection are limited to either hardware implementations [7], [8], [12] or specific parts of HOG algorithms [1], [17]. There is even no quantitative investigation of what implementation issues could prevent HOG-based object detection from being deployed in real-world applications. Given recent innovations in commodity hardware technology such as multicores and

graphics processing units (GPUs), it is worth exploring if the current state of the arts meets computational requirements of cutting-edge object detection implementations.

Contribution: This paper presents GPU implementations of HOG-based object detection in consideration of real-world applications using deformable part models [3]. While this is a popular vision-based object detection approach, what remains an open question is a genelized programming technique and a quantification of performance characteristics for practical use. We begin with an analysis of traditional CPU implementations to find fundamental performance bottlenecks of HOG-based object detection. This analysis reasons about our approach to GPU implementations where we parallelize compute-intensive blocks of the object detection program using the GPU step by step to minimize its makespan. The experimental results obtained from a real-world car detection program using a commodity GPU show that the GPU outperforms the CPU by 1.5x to 3x in frame-rate, while another 2x improvement would be needed at least to deploy in the real world.

Organization: The rest of this paper is organized as follows. Section II describes the assumption behind this paper. Section III presents an analysis of HOG-based object detection and our GPU implementation technique. Section IV evaluates the performance benefit of our technique over traditional CPU implementations. This paper concludes in Section V.

II. ASSUMPTION

We consider the system composed of a multicore CPU and commodity GPU. They communicate with each other via the PCIe bus. We use CUDA [15] for GPU programming, whose development environment can be downloaded from NVIDIA's website [16]. Input images are loaded from pre-captured JPEG files, since we focus on a high computational cost of image processing. Systemized coordinations of computations and I/O devices are outside the scope of this paper. The use of multiple GPUs is also not in consideration.

We follow the object detection method presented by Felzen-szwalb *et. al.* [3], where objects are represented by HOG features [2] and the detectors is composed of a "root" filter plus a set of "parts" filters that allow visual appearance to be modeled at multiple scales. This is one of the most recognized approach to object detection. See [3] for the detail.

Object detection often requires a machine learning phase to construct the object models. We assume that this learning

phase has already been done a priori and the object models are stored in the system. Particularly we restrict our attention to vehicle detection in this paper, utilizing the vehicle models provided by prior work [14]. Although these models achieve a high detection rate, the computational cost of scoring similarity of an imput image and the models using HOG features is very expensive. Specifically they include 2 root filters and 12 part filters, each of which needs to be scored against 32 resized images. The scoring could be conducted for every squire of a few pixels independently. In consequence, there are approximately 10 million computational blocks for a single high-definition image, while the frame-rate needs to meet 10 to 20 frames per second (FPS) for practical use. This data-parallel compute-intensive nature of HOG-based object detection motivates the use of GPUs in this paper.

The CPU implementation of HOG-based vehicle detection has already been developed in prior work [14]. It leverages the POSIX *pthread* to parallelize the scoring per filter on a multicore CPU. While we use this multicore implementation for a performance comparison as it is, we also serialize it to execute on a single core so that we can compare our GPU implementation to two variants of the CPU implementation.

III. GPU Implementation

This paper presents GPU implementations of the existing object detection program using a popular computer vision technique [14]. Our contribution is distinguished from prior GPU implementations work [1], [17] in that we analyze the performance characteristics of the object detection program to figure out what part of the program should be accelerated using the GPU and our implementations build on this analysis optimizing performance.

Note that this paper focuses on vehicle detection but the presented GPU implementations and our technical contribution can be applied for other object detection methods using HOG features and deformable models.

A. Basic Understanding

In GPU programming, the GPU code and the input data typically need to be copied from the host to the device memory before we launch a function, *a.k.a.*, a compute kernel, on the GPU. The output data also needs to be copied back from the device to the host memory so that the CPU can read them. Hence the GPU-accelerated computation comes at the expense of the offloading overhead. Another shortcoming of the GPU is its relatively low operating frequency as compared to the CPU due to the presence of a significant number of compute cores. These trade-offs must be addressed to benefit from GPU programming; it is a complex undertaking for programmers to ascertain appropriate computational blocks that can accelerate on the GPU. Nonetheless this massively parallel computing architecture is becoming a trend in the state of the art. Given that GPUs outperform traditional multithreaded and multicore CPUs in peak performance by an order of magnitude [9], it is worth exploring a more efficient way of GPU programming.
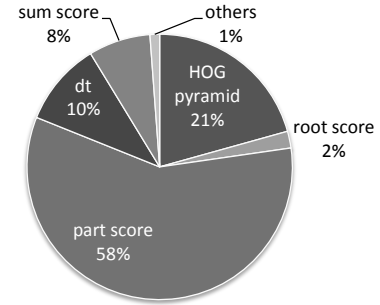

Fig. 1. The breakdown of computation times.

This paper provides a guideline of how to use GPUs in an efficient way for vision-based object detection.

B. Program Analysis

As aforementioned, the usage of the GPU depends highly on the program structure. If the program does not contain data-parallel compute-intensive blocks, the GPU is not effective at all. Therefore it is important to analyze the program prior to coding and implementation. The following is a summary of the program sequence for HOG-based object detection using the deformable models. The detailed procedure and algorithm description are presented in [3], [14].

1) Load an input image.
2) Load the pre-defined object models.
3) Calculate HOG features for all resized variants of the input image, often referred to as a *HOG pyramid*.
4) Calculate similarity scores for every set of the root/part filters and the resized HOG images.
5) Detect an object region based on a summation of the similarity scores.
6) Recognize an object based on the detection result.
7) Output the recognition result.

In order to identify computationally time-consuming blocks of the object detection program, we conducted a preliminary measurement running the original sequential code [14] on a generic Intel Core i7 2700K CPU. The measurement method is straightforward. We find high-level *for* loops (in case that the program is written in the C-like language) by scanning the program structure and make a timestamp for each loop. The result of measurement is shown in Fig. 1. Note that a label "others" represents the computation time excluding the high-level *for* loops. This breakdown of computation times provides us with a hint of how to approach GPU implementations. Specifically an obvious computational bottleneck appears in the calculation of similarity scores against the part filters, which corresponds to partly "Step 4)" in the above program sequence. This block dominates 58% of the total time. On the

resized input picture (# N)

generate

score array

filter (# M)

N

max_height

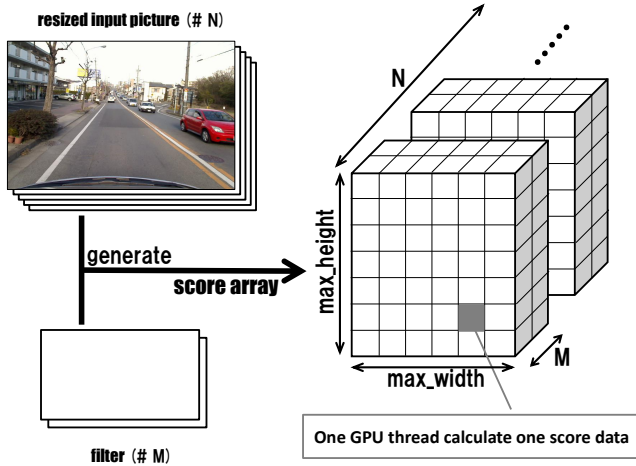max_width

M

One GPU thread calculate one score data

Fig. 2. The number of compute threads and their block shape.

other hand, the calculation of HOG features corresponding "Step 3)" spends 21% of the total time, while the detection and recognition of the object, *i.e.*, "Step 5)" and "Step 6)", contribute to 10% and 8% of the total time respectively.

Our analysis conducted herein implies that even a simple time measurement highlighting only the program structure without awareness of the program context is helpful enough to understand computational bottlenecks of the program. In our case, it turned out that the most portion of the total time is spent in the *for* loops, which means that this program contains a very high degree of parallelism and could be accelerated on the GPU.

C. Implementation Approach

We parallelize all the high-level *for* loops of the program using the GPU. According to the measurement result in Fig. 1, the scoring of the root filters is a minor factor (2%) of the total time, but its program structure is almost identical to that of the part filters and they adhere to continuous blocks. Hence we include it to the GPU code. In the rest of this section, we focus on the implementation of the scoring of these filters, which is the most dominant part of the program, due to a space constraint.

Fig. 2 illustrates a conceptual structure and flow of our GPU implementation. We have 32 resized pictures to be able to detect different sizes of the object, *i.e.*, N is 32. We also have 2 root filters and 12 part filters to be able to detect different shapes or angles of the object, *i.e.*, M is 2 or 12. A minimum piece of the similarity score for a HOG representation and an object model can be calculated for each pixel of the filtered area independently. This area could be larger than a squire of 100 pixels (equivalent to max_width × max_height) for a 640 × 480 size of an image when using the trained data obtained from previous work [14]. Therefore the number of producible compute threads could be an order of millions in this setup. We shape these threads by blocks and grids

for CUDA as shown in Fig. 2 where each block size is max_width × max_height × M and each grid size is N. This shape is considered for ease of programming and a different shape may further improve performance but such a fine-grained performance tuning is outside the scope of this paper.

D. GPU Programming

Once computational blocks of the program to be parallelized are determined, we can focus on the program structure rather than the context to implement the program using the GPU.

IV. EVALUATION

10 pictures and success rate is 95 to 99%.

V. CONCLUSION

In this paper, we have presented GPU implementations of HOG-based object detection and their performance evaluation. Unlike preceding work that highly stressed on performance improvements, our implementations are based on an analysis of performance bottlenecks posed due to an introduction of the deformable models in HOG-based object detection. This approach ensures that the GPU truly accelerates approapriate computational blocks. Our evaluation using a commodity GPU showed that our GPU implementation can speed up the existing HOG-based vehicle detection program tailored to the deformable models by 1.5x to 3x over traditional CPU implementations. Given that this performance improvement is obtained from the entire program runtime rather than particular algorithm parts of the program, our contribution is useful and significant for real-world applications of vision-based object detection.

To the best of our knowledge, this is the first piece of work that made a *tight* coordination of object detection and parallel computing – a core challenge of CPS. Specifically we showed that a measured and structured way of GPU programming is efficient for the object detection program and quantified the impact of GPUs in performance. Our conclusion is that GPUs are promising to meet the required performance of vision-based object detection in the real world.

In future work, we plan to complement this work with systemized coordinations of computations and I/O devices. Since real-world applications require camera sensors to obtain input images while GPUs are compute devices off the host computer, the data I/O latency could become a bottleneck upon data buses. In this scenario, we need enhanced system support such as zero-copy approaches [10] to minimize the data latency raised between camera sensors and GPUs. We also plan to augment our GPU implementations using multiple GPUs in order to meet the real-time and real-fast requirement of real-world CPS applications.

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