WK3 Report

Replication of Deepfake Representation with Multilinear Regression

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Data (video frames) Preprocessing

Step 1: Vectorizing video frames

Step 2: Finding eigenfaces of each class

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Step 1: Vectorizing video frames

- It is preferable to vectorize an image and treat it as a single observation rather than a collection of independent column/row observations
- By vectorizing an image, the authors treat an image as a point in high dimensional pixel space and calculate all possible combinations of pixel statistics
- e.g. n is amount of colors and r is amount of pixels. 300x300 full RGB color image? (255^3)^(300^2)
- img.shape(): img[0] is height, img[1] is width, img[2] is channels

Step 2: Finding eigenfaces of each frame

- A. Eigenfaces are eigenvectors(**B**) when the images are human faces
- B. The eigenfaces represent a basis set of all faces used to construct the covariance matrix (for dimensionality reduction ⇒ the eigenfaces are equal to basis vectors of PCA decomposition)

$$\mathbf{D}_{\text{real}} = \mathbf{U}_{\text{real}} \mathbf{\Sigma}_{\text{real}} \mathbf{V}_{\text{real}}^{\text{T}} = \mathbf{B}_{\text{real}} \mathbf{V}_{\text{real}}^{\text{T}}$$
(11)

$$\mathbf{D}_{\text{fake}} = \mathbf{U}_{\text{fake}} \mathbf{\Sigma}_{\text{fake}} \mathbf{V}_{\text{fake}}^{\text{T}} = \mathbf{B}_{\text{fake}} \mathbf{V}_{\text{fake}}^{\text{T}}$$
(12)

Where B_{real} and B_{fake} are basis matrices and V_{real} and V_{fake} are the normalized coefficient matrices of the corresponding classes.

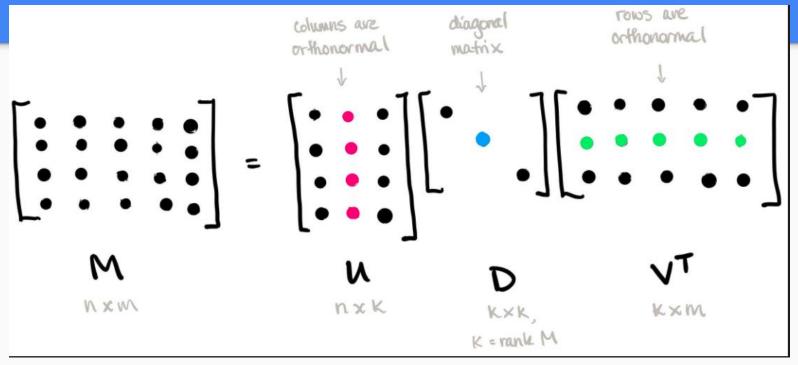
Step 2: Finding eigenfaces of each frame

C. The classification could be achieved by comparing how different faces are represented by the basis set of the corresponding class. That is, B (fake or real basis matrices).

D. create two separate metrices: B_real, B_fake

Singular Value Decomposition (SVD)





PC: https://www.math3ma.com/archive/september-2020

Principal Components Analysis (PCA)

Rewriting equation 1 in conventional linear algebra, the Principal Components Analysis (PCA) is:

$$\mathbf{D} = \underbrace{\mathbf{U}}_{\text{Basis Coefficient}} \underbrace{\mathbf{\Sigma}\mathbf{V}^{\text{T}}}_{\text{(3)}}$$

The same as:

$$\mathbf{B}_{\text{real}} \mathbf{V}_{\text{real}}^{\mathbf{I}}$$
$$= \mathbf{B}_{\text{fake}} \mathbf{V}_{\text{fake}}^{\mathbf{T}}$$