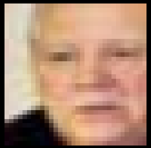
Objects and scenes:

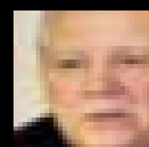
Recognizing Multiple Object Classes

Josef Sivic and Ivan Laptev
http://www.di.ens.fr/~josef
INRIA, WILLOW, ENS/INRIA/CNRS UMR 8548
Laboratoire d’Informatique, Ecole Normale Supérieure, Paris

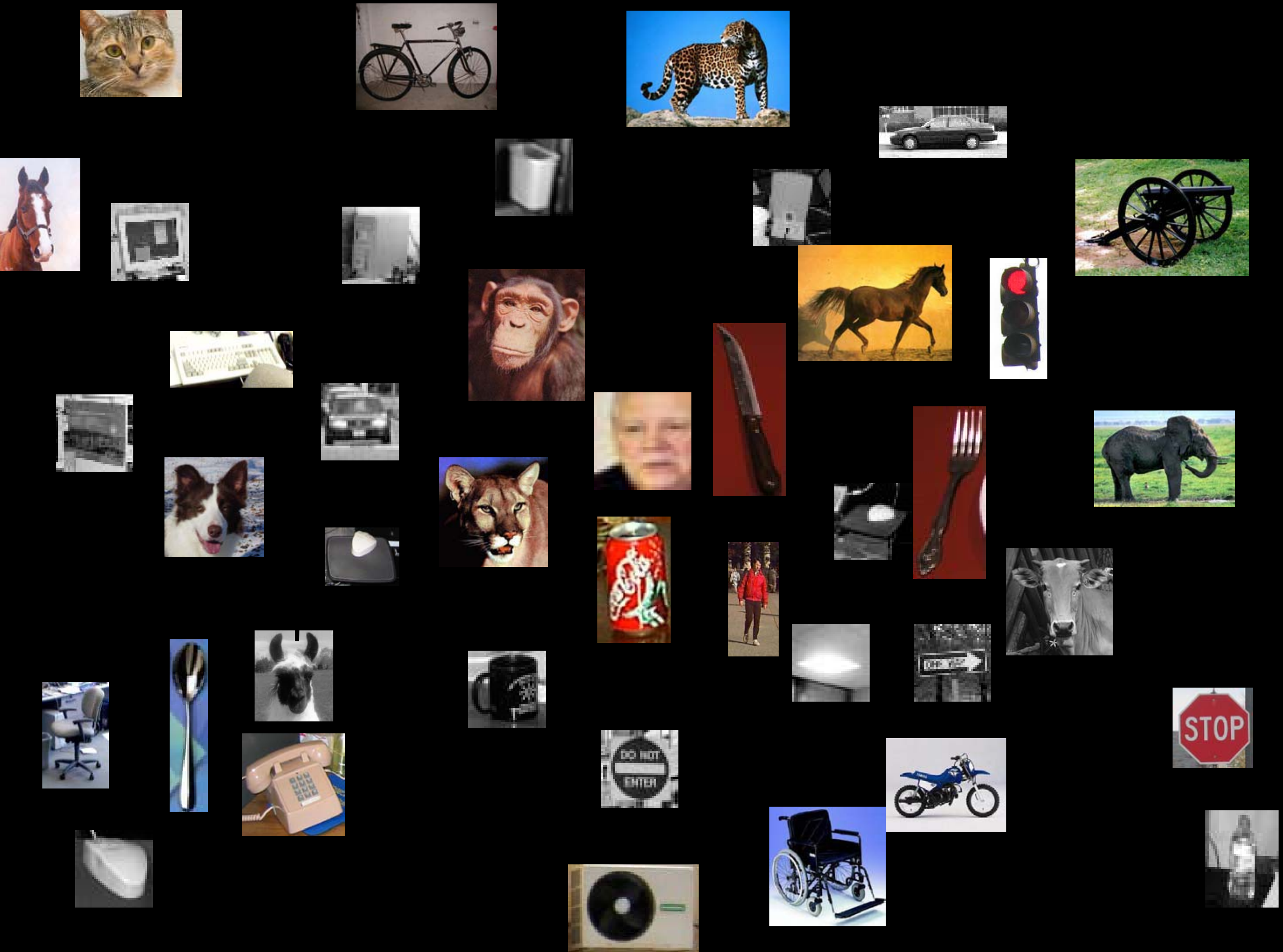
With slides from: A. Torralba, D. Hoiem, D. Ramanan and others.

Multiclass object detection

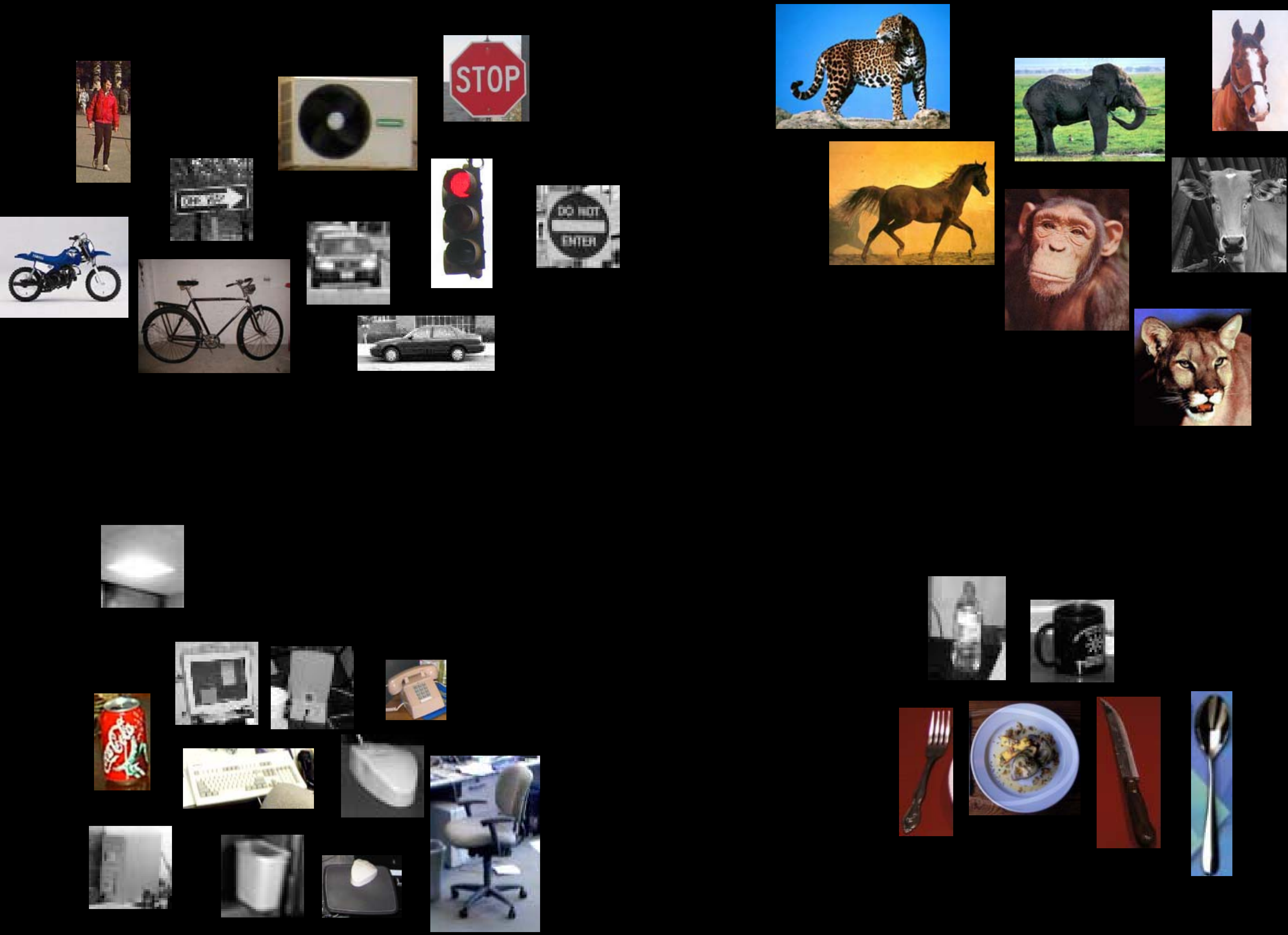




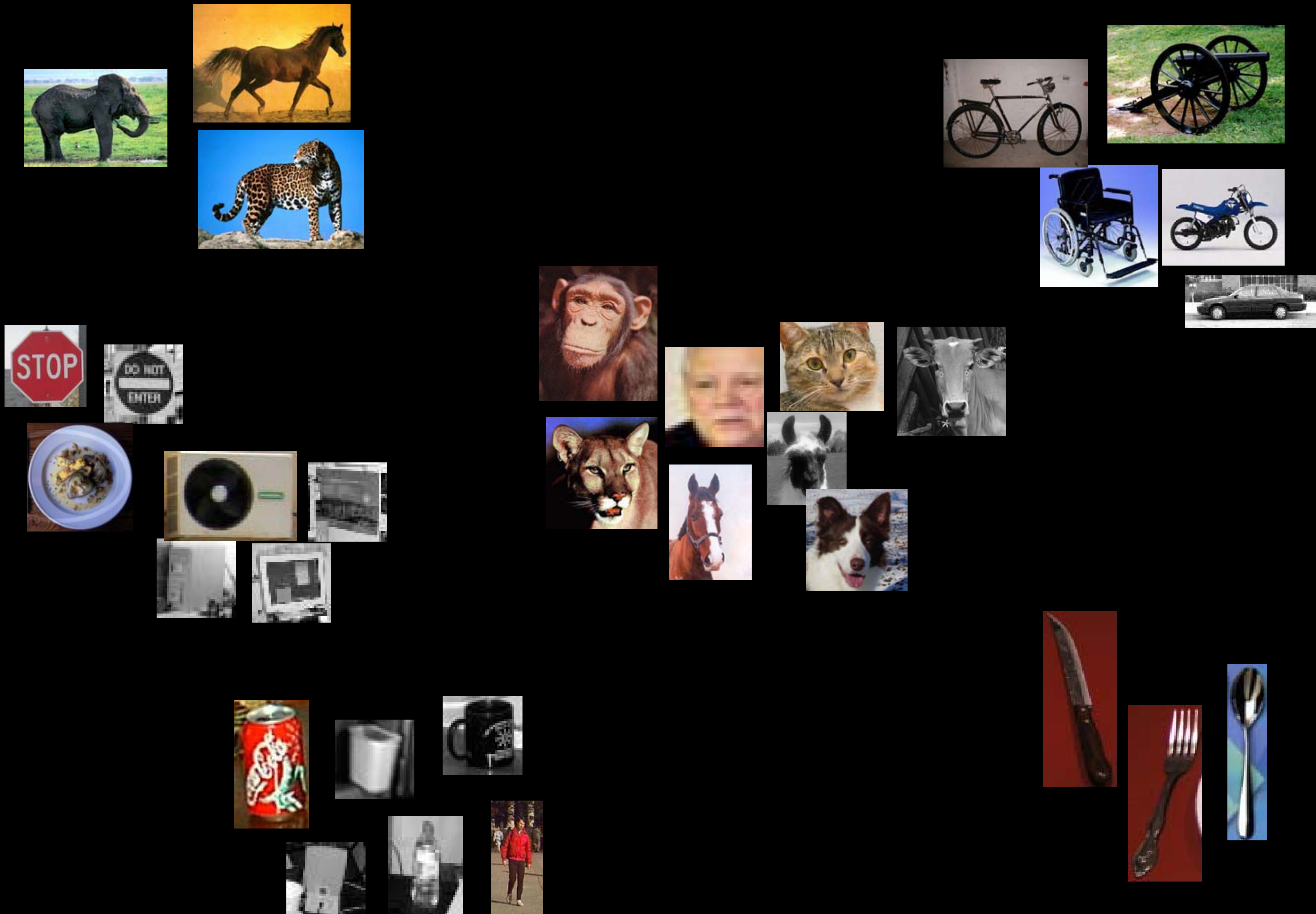

STOP


DO NOT
ENTER
STOP

Context: objects appear in configurations



Generalization: objects share parts

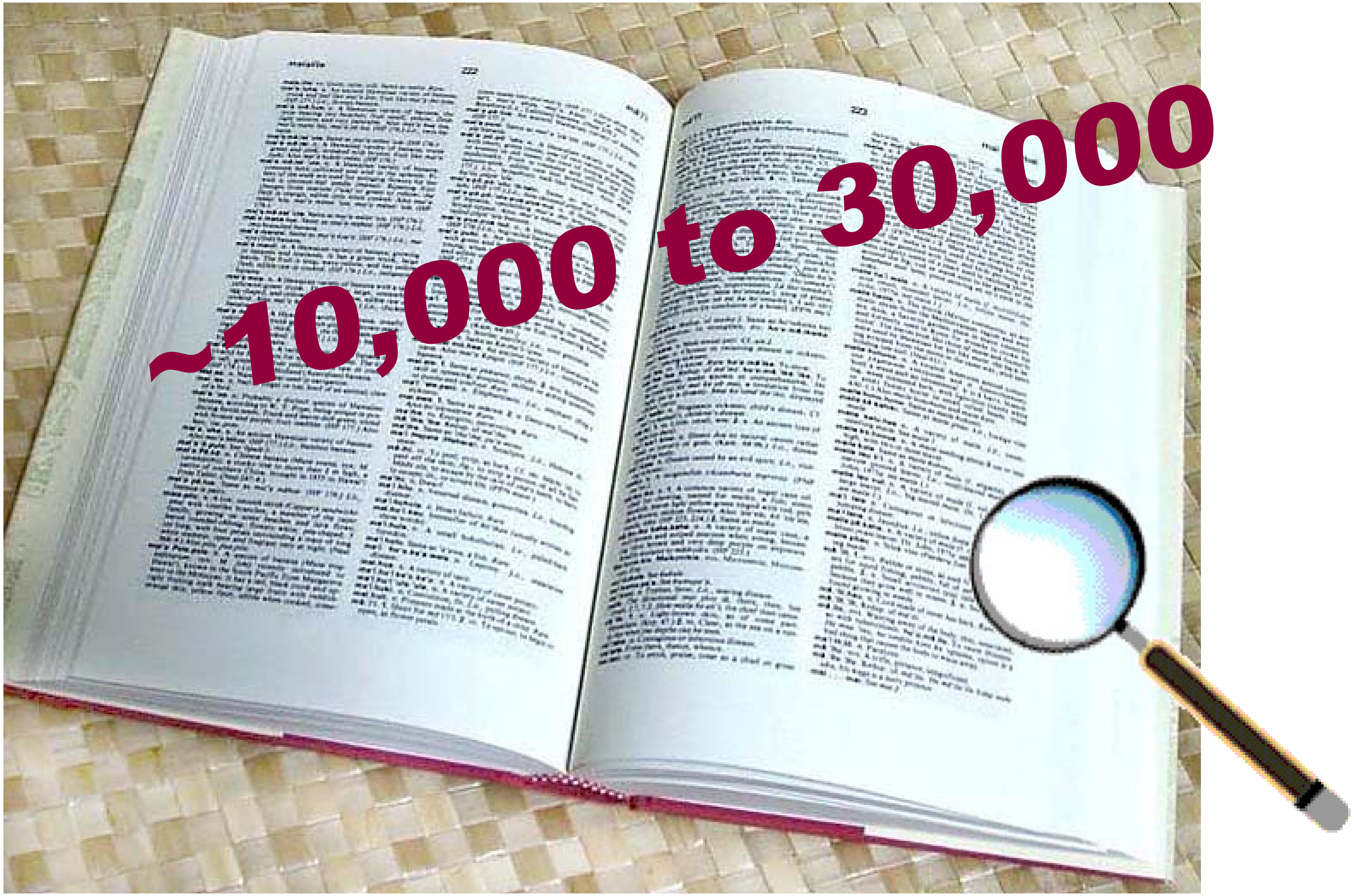


How many categories?

How many categories?

Slide by Aude Oliva

How many object categories are there?



Biederman 1987

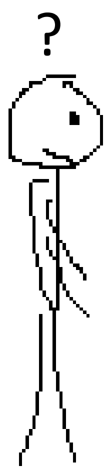
How many categories?

- Probably this question is not even specific enough to have an answer

Which level of categorization is the right one?

Car is an object composed of:

a few doors, four wheels (not all visible at all times), a roof, front lights, windshield



If you are thinking in buying a car, you might want to be a bit more specific about your categorization level.

Entry-level categories
(Jolicoeur, Gluck, Kosslyn 1984)

- Typical member of a basic-level category are categorized at the expected level
- Atypical members tend to be classified at a subordinate level.

A bird

An ostrich

We do not need to recognize the exact category

A new class can borrow information from similar categories

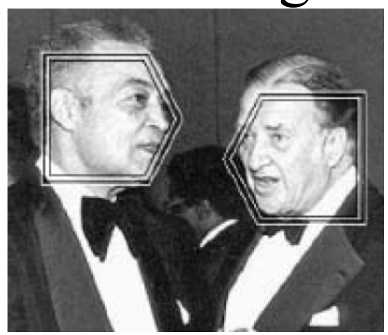
So, where is computer vision?

Well…

Multiclass object detection
the not so early days

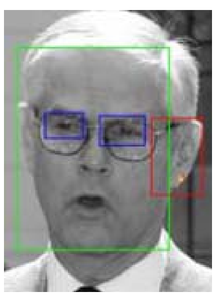
Using a set of independent binary classifiers was a common strategy:

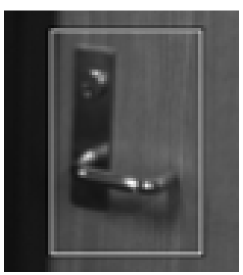
- Viola-Jones extension for dealing with rotations



- two cascades for each view

- Schneiderman-Kanade multiclass object detection



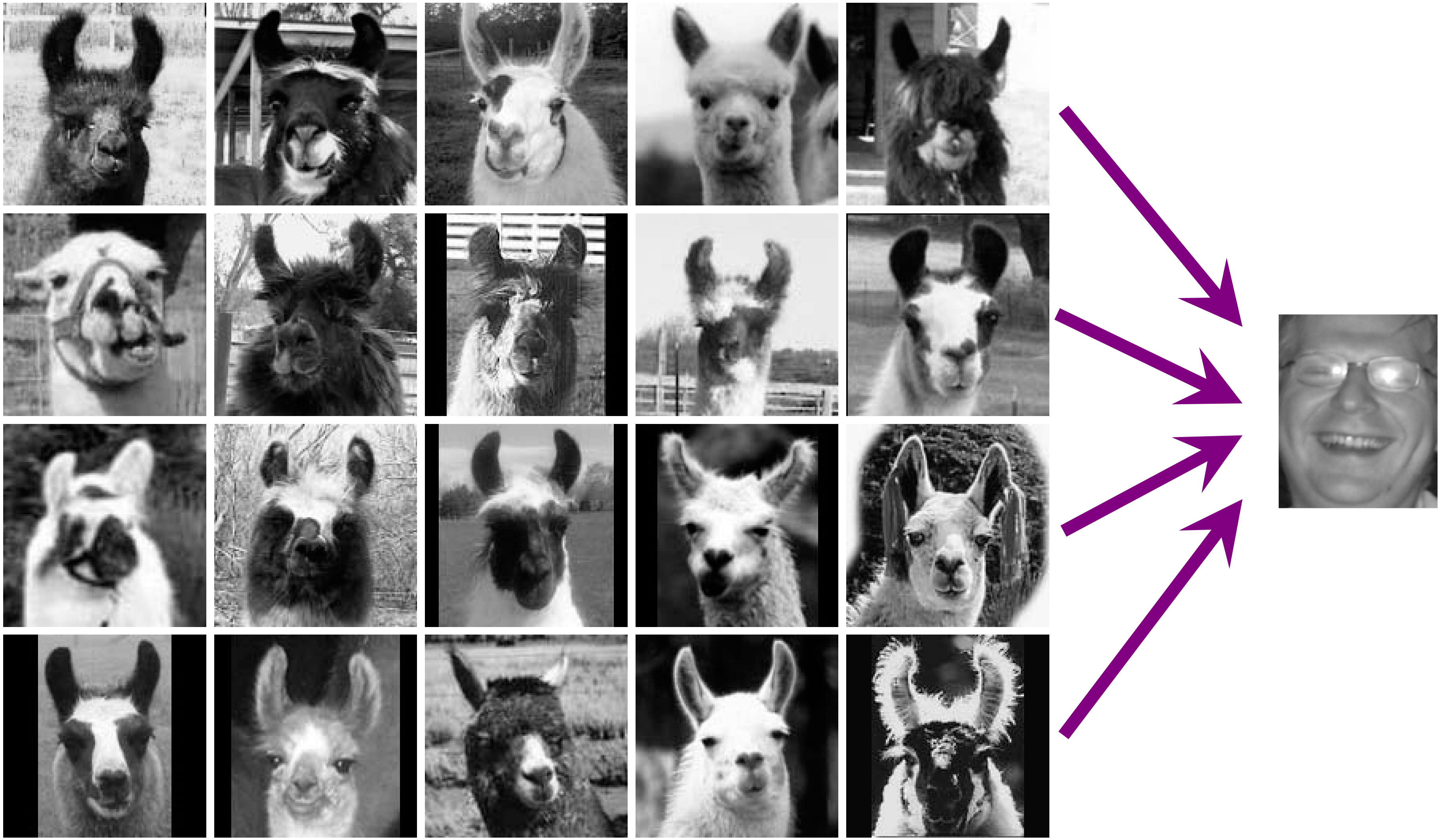


(a) One detector for each class

(b) For cars, classifiers are trained on 8 viewpoints

There is nothing wrong with this approach if you have access to lots of training data and you do not care about efficiency.

Generalizing Across Categories

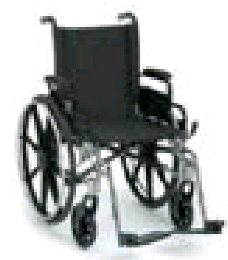


Can we transfer knowledge from one object category to another?

Slide by Erik Sudderth

Shared features

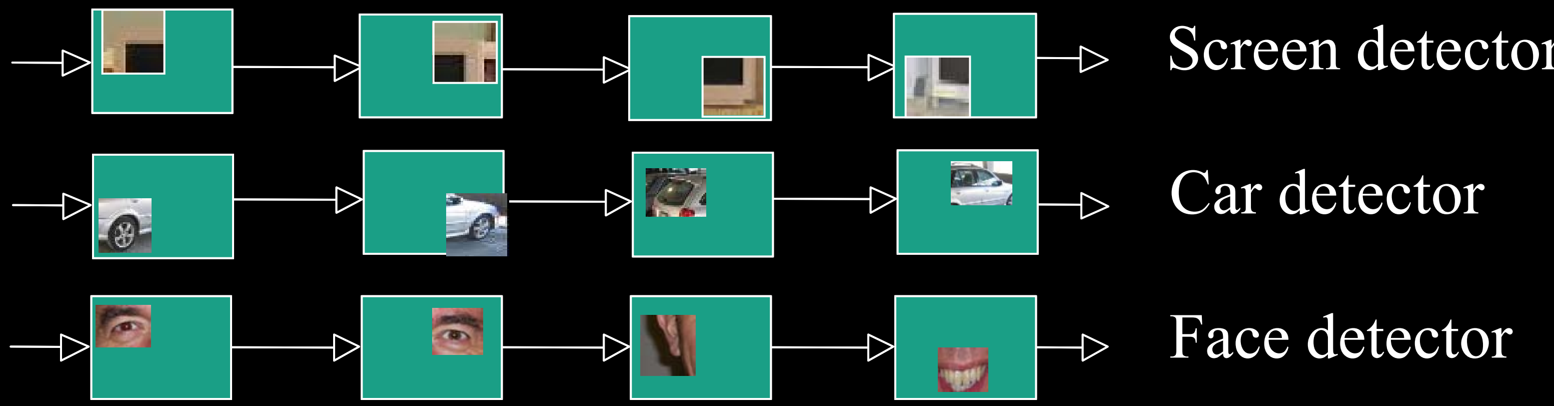
- Is learning the object class 1000 easier than learning the first?

  … 

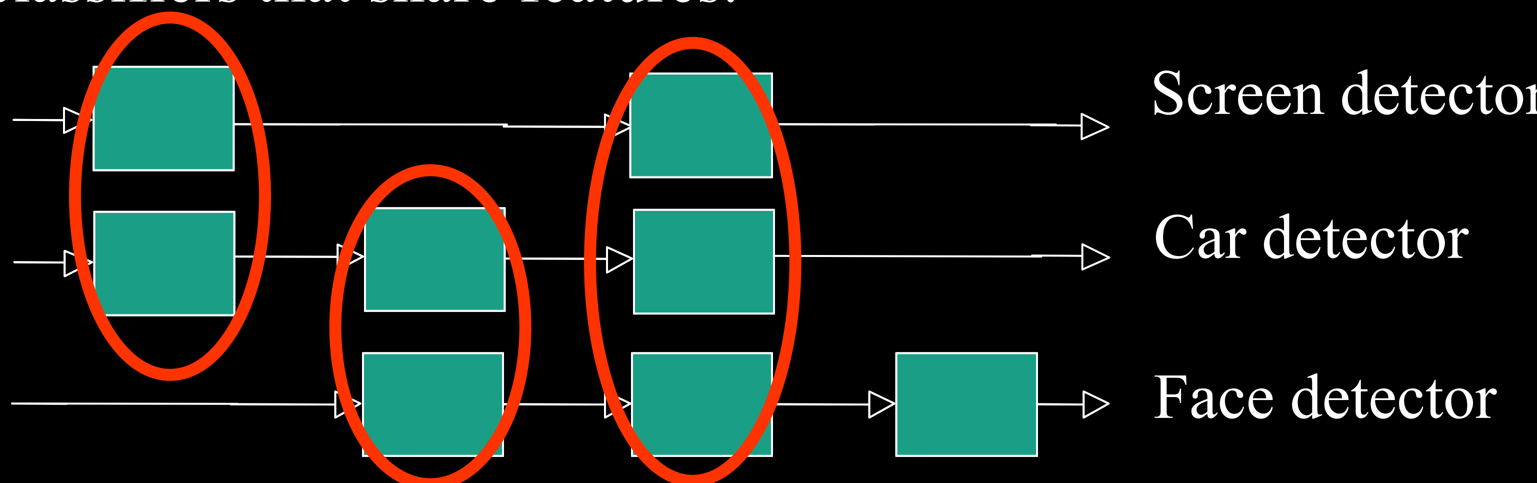
- Can we transfer knowledge from one object to another?
- Are the shared properties interesting by themselves?

Additive models and boosting

- Independent binary classifiers:

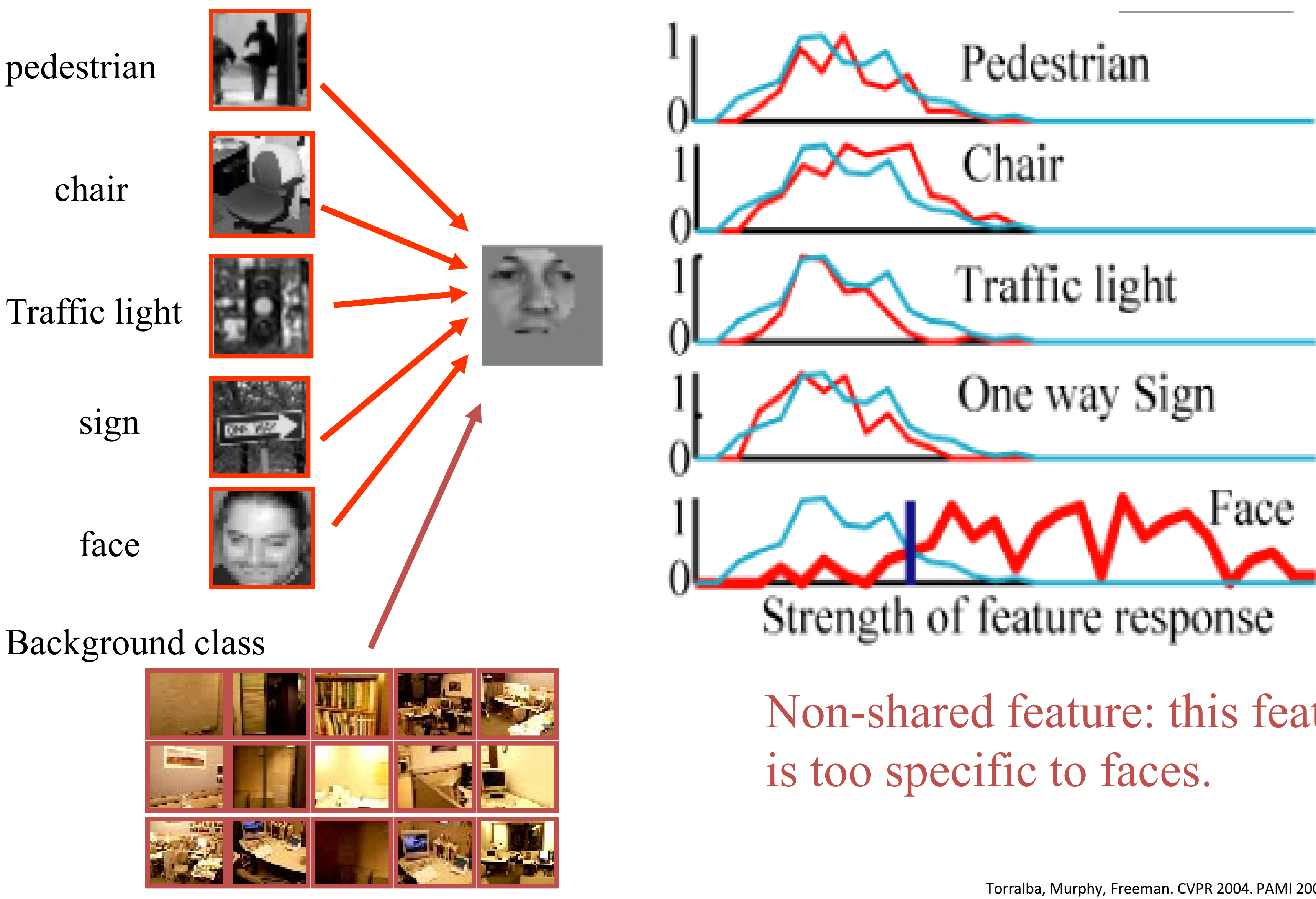


- Binary classifiers that share features:



Torralba, Murphy, Freeman. CVPR 2004. PAMI 2007

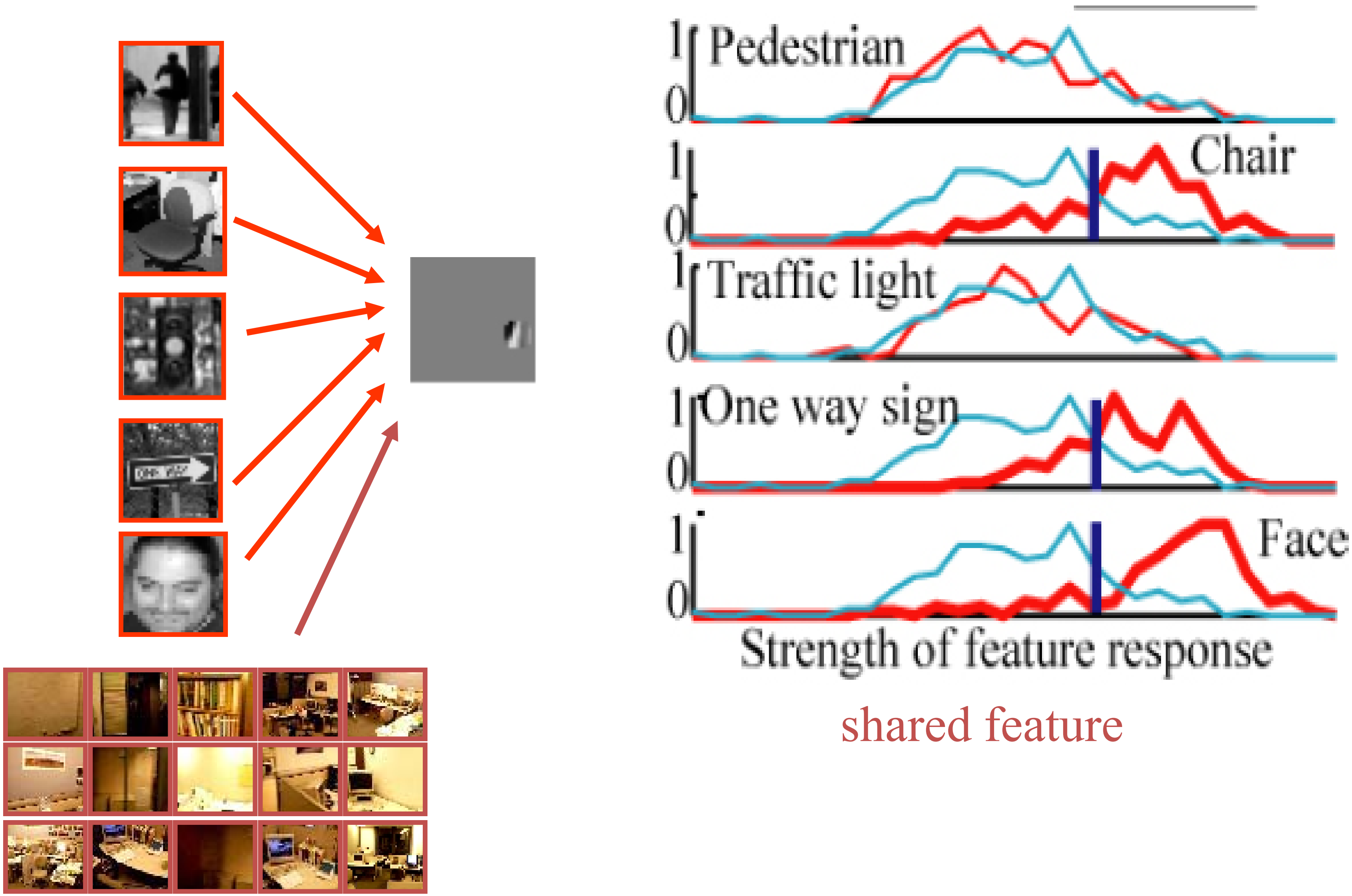
Specific feature



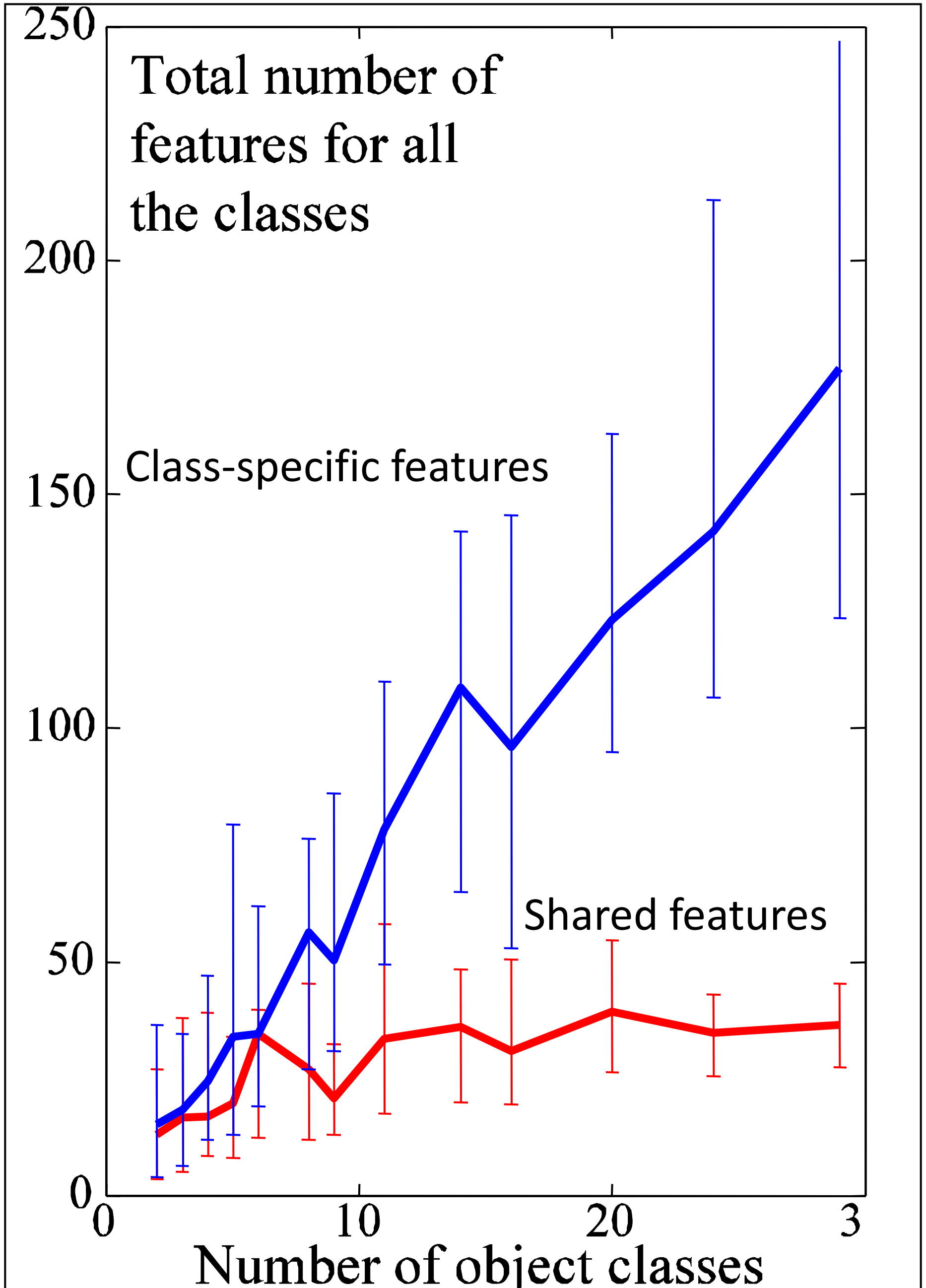
Non-shared feature: this feature is too specific to faces.

Torralba, Murphy, Freeman. CVPR 2004. PAMI 2007

Shared feature



Torralba, Murphy, Freeman. CVPR 2004. PAMI 2007



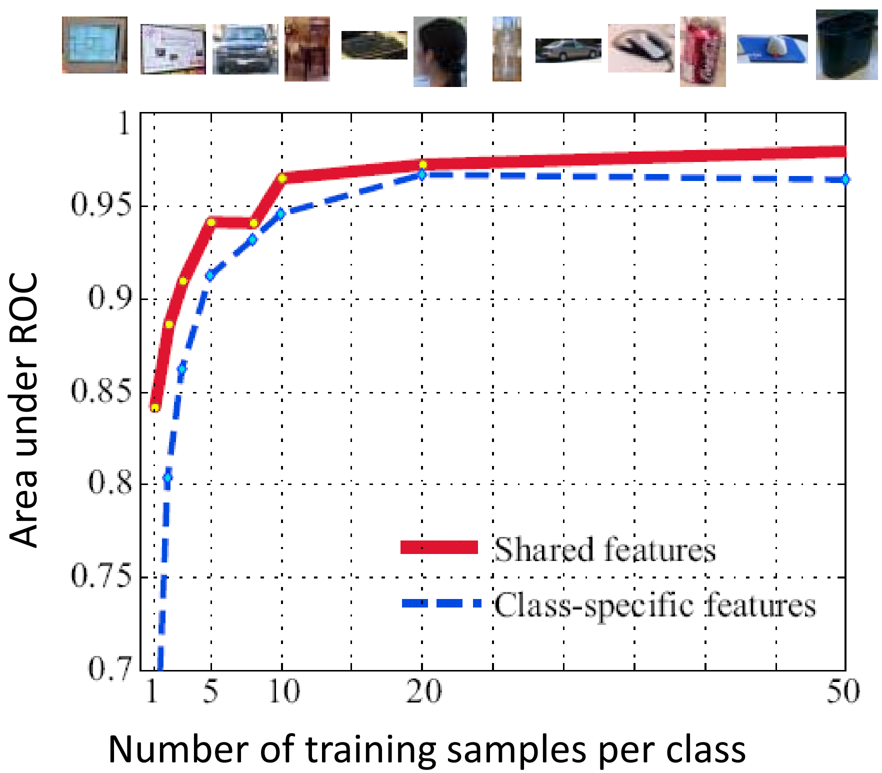
50 training samples/class
29 object classes
2000 entries in the dictionary

Results averaged on 20 runs

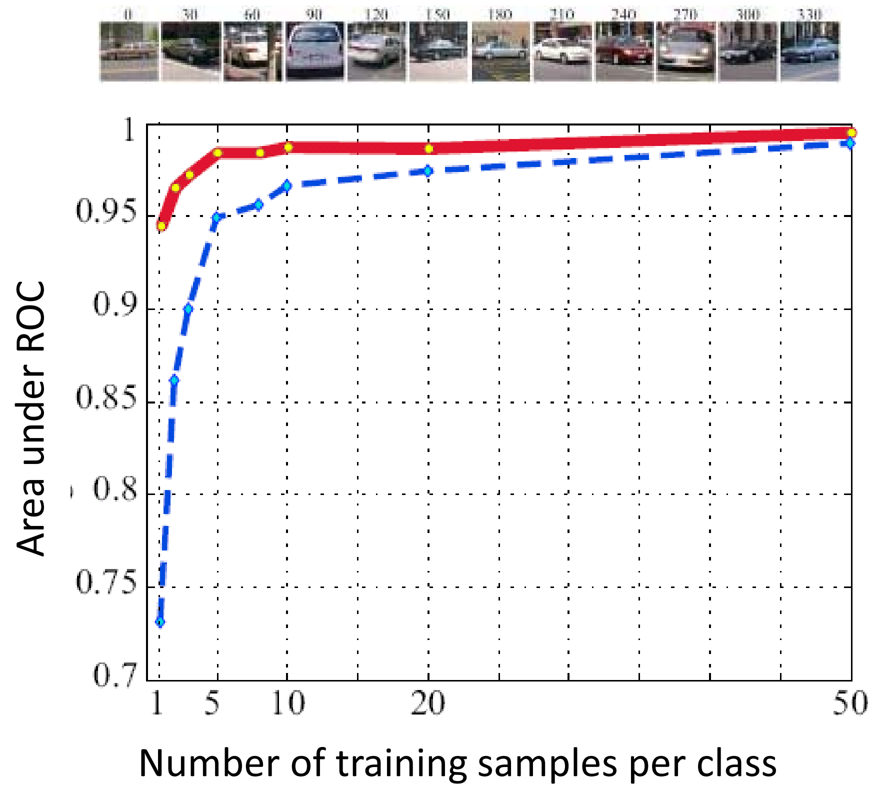
Torralba, Murphy, Freeman. CVPR 2004. PAMI 2007

Generalization as a function of object similarities

12 unrelated object classes

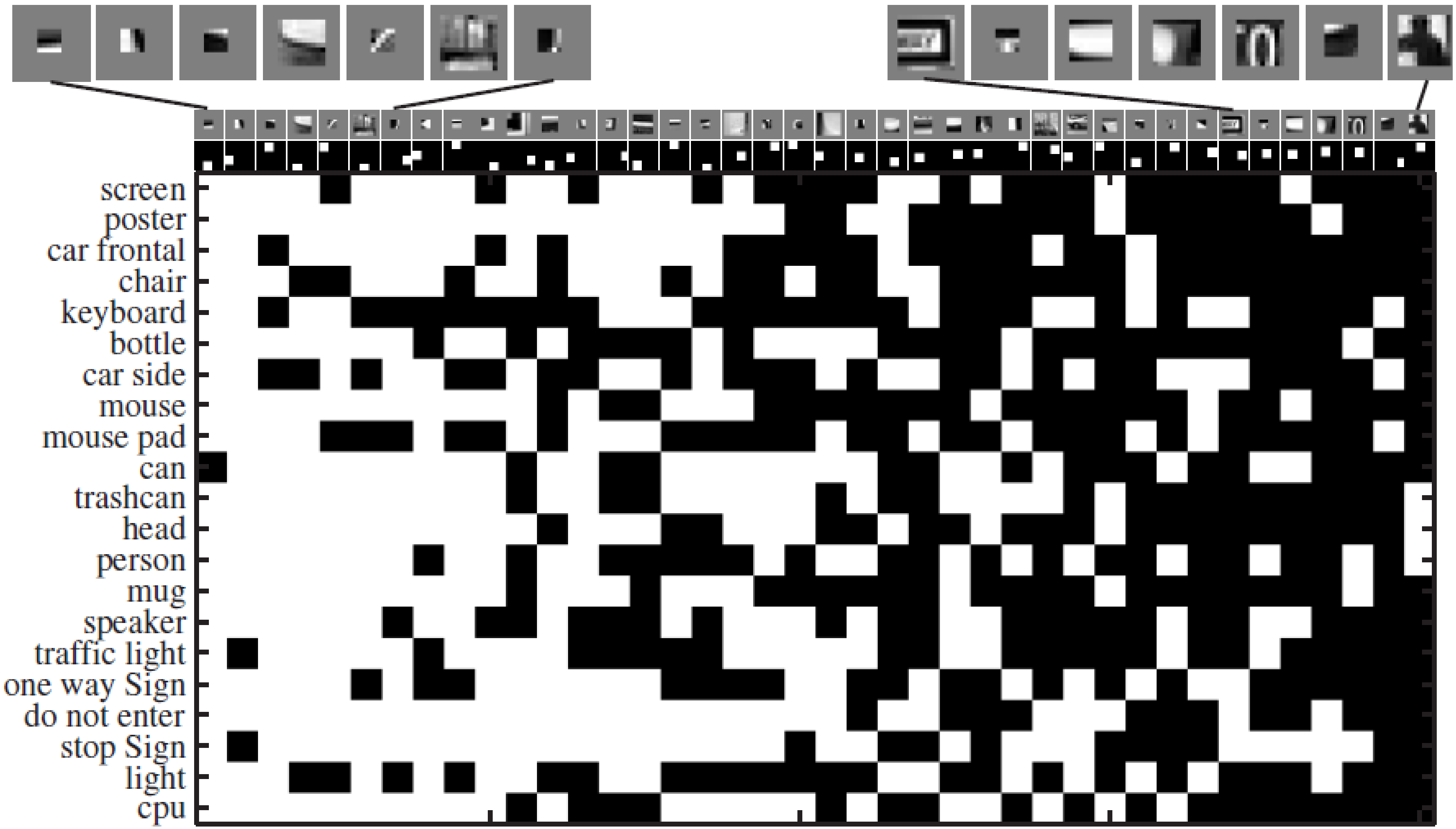


12 viewpoints



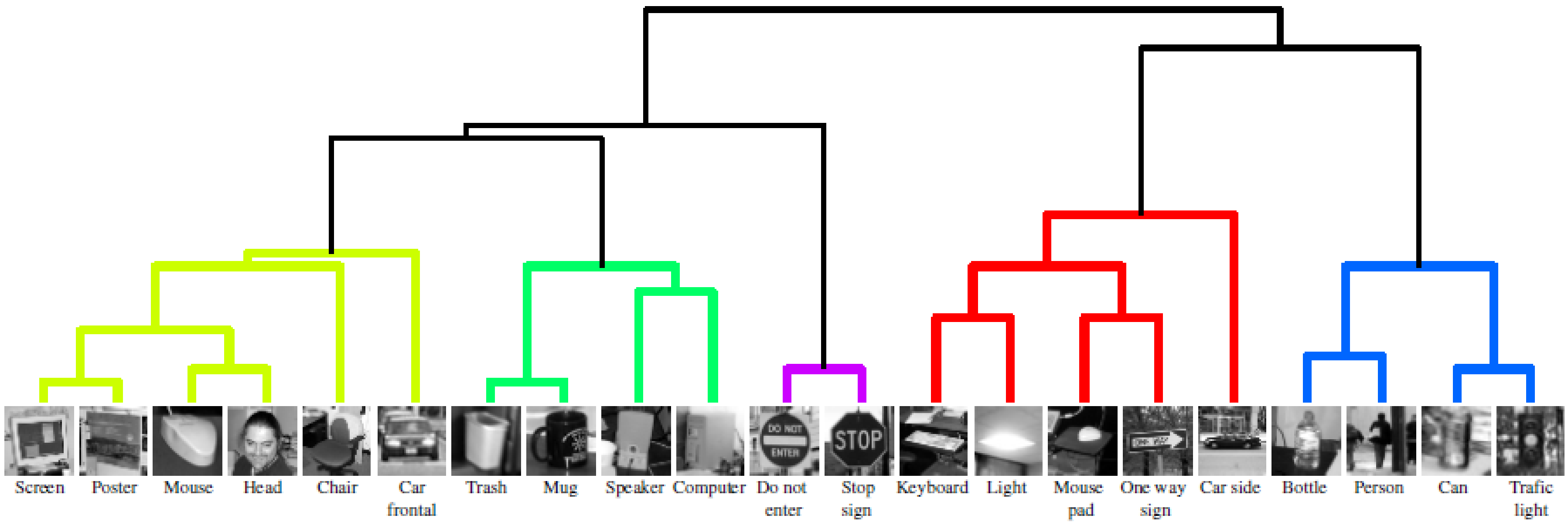
Torralba, Murphy, Freeman. CVPR 2004. PAMI 2007

Generic vs. specific features



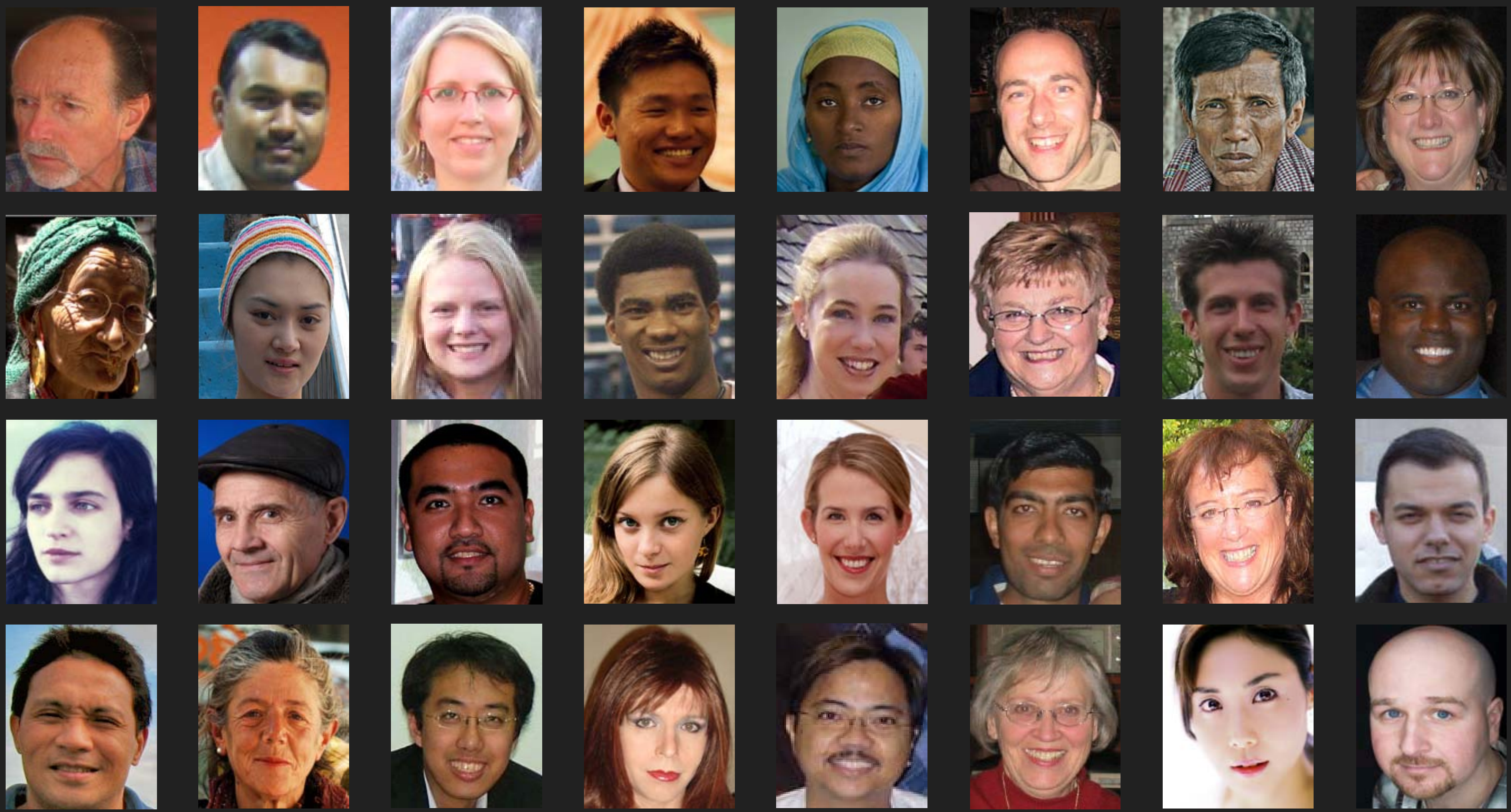
Torralba, Murphy, Freeman. CVPR 2004. PAMI 2007

Object clustering according to shared features



Torralba, Murphy, Freeman. CVPR 2004. PAMI 2007

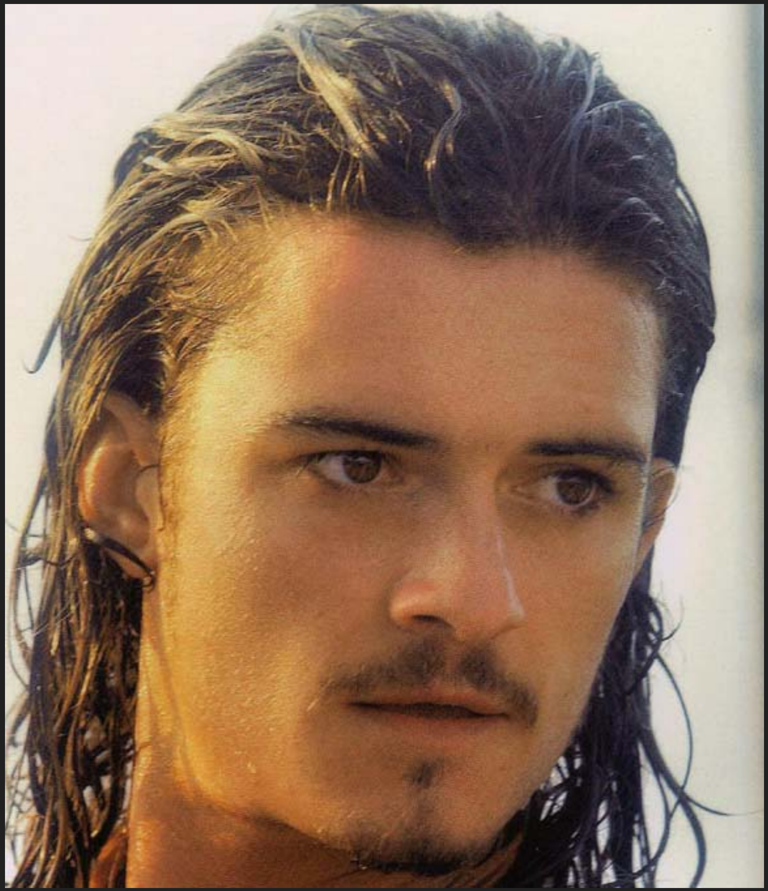
Another multi-class problem: Face recognition



We do not want to learn recognition of each person from scratch!

N. Kumar, A. C. Berg, P. N. Belhumeur, and S. K. Nayar ICCV 2009

Are these images of the same person?



N. Kumar, A. C. Berg, P. N. Belhumeur, and S. K. Nayar ICCV 2009

Prior approaches

Images ⇒ Low-level features ⇒ Verification

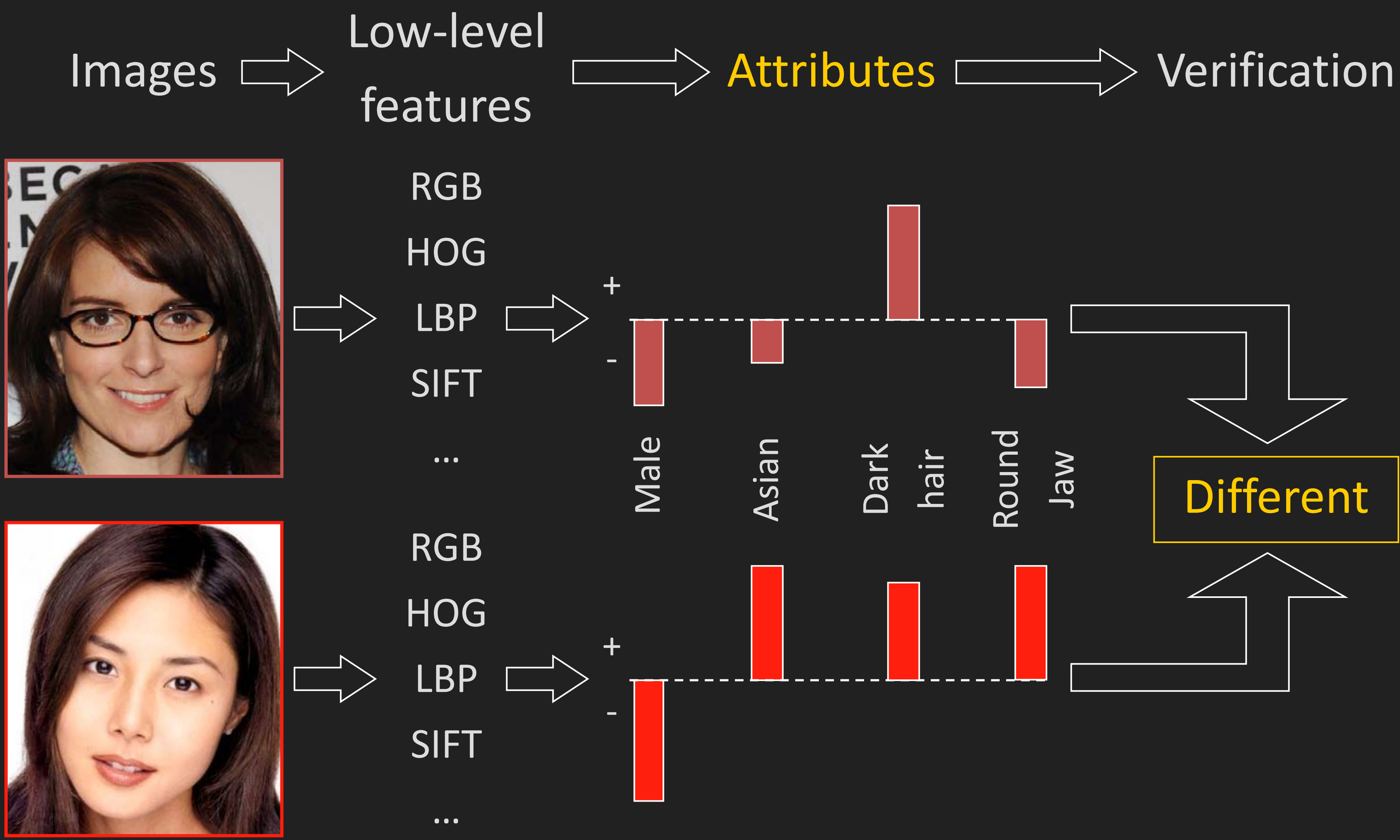
RGB
HOG
LBP
SIFT
...

RGB
HOG
LBP
SIFT
...

Different

N. Kumar, A. C. Berg, P. N. Belhumeur, and S. K. Nayar ICCV 2009

Approach: attributes



N. Kumar, A. C. Berg, P. N. Belhumeur, and S. K. Nayar ICCV 2009

Attributes can define categories

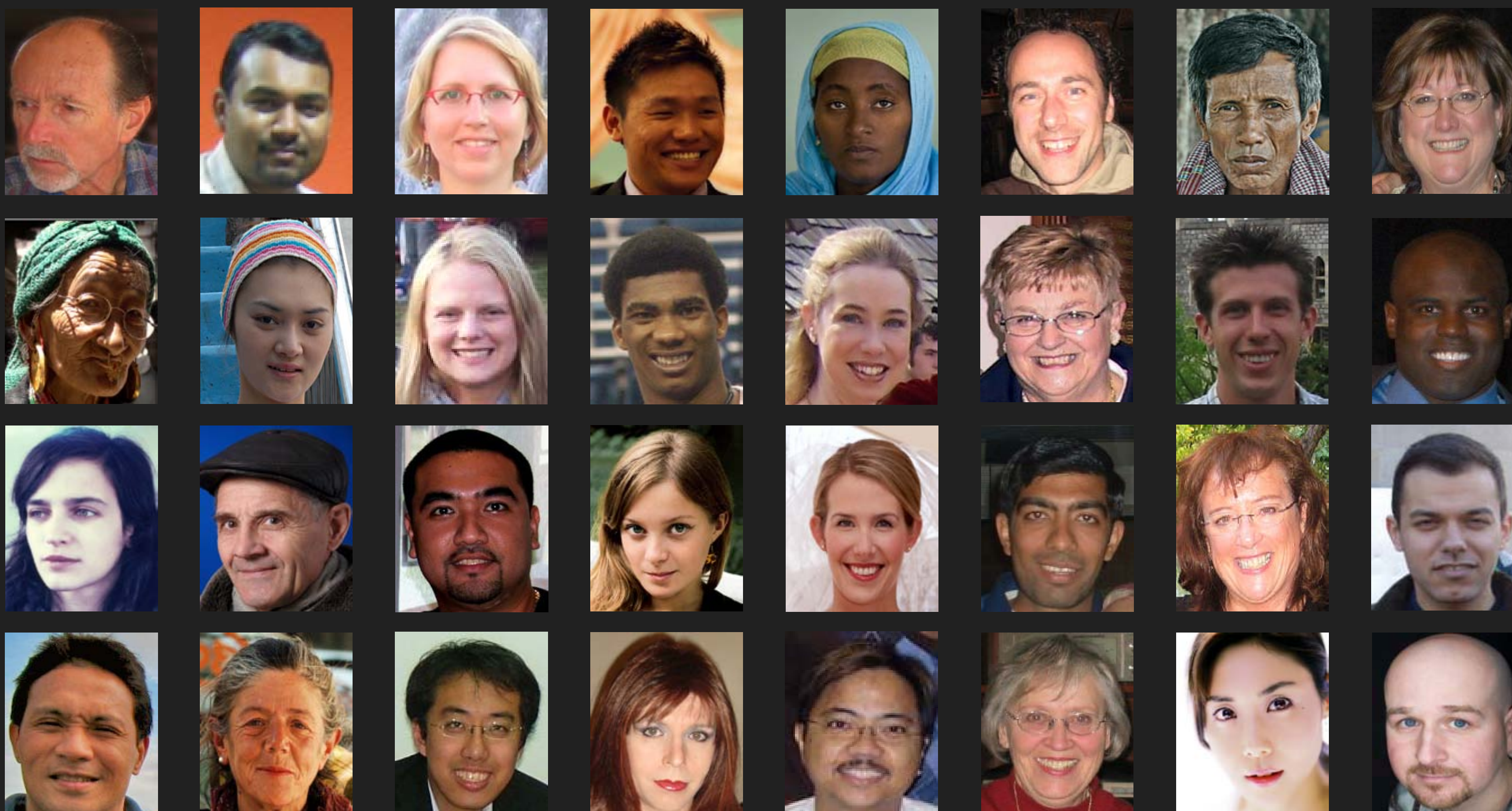
Female

Caucasian

Eyeglasses

Middle-aged

Dark hair



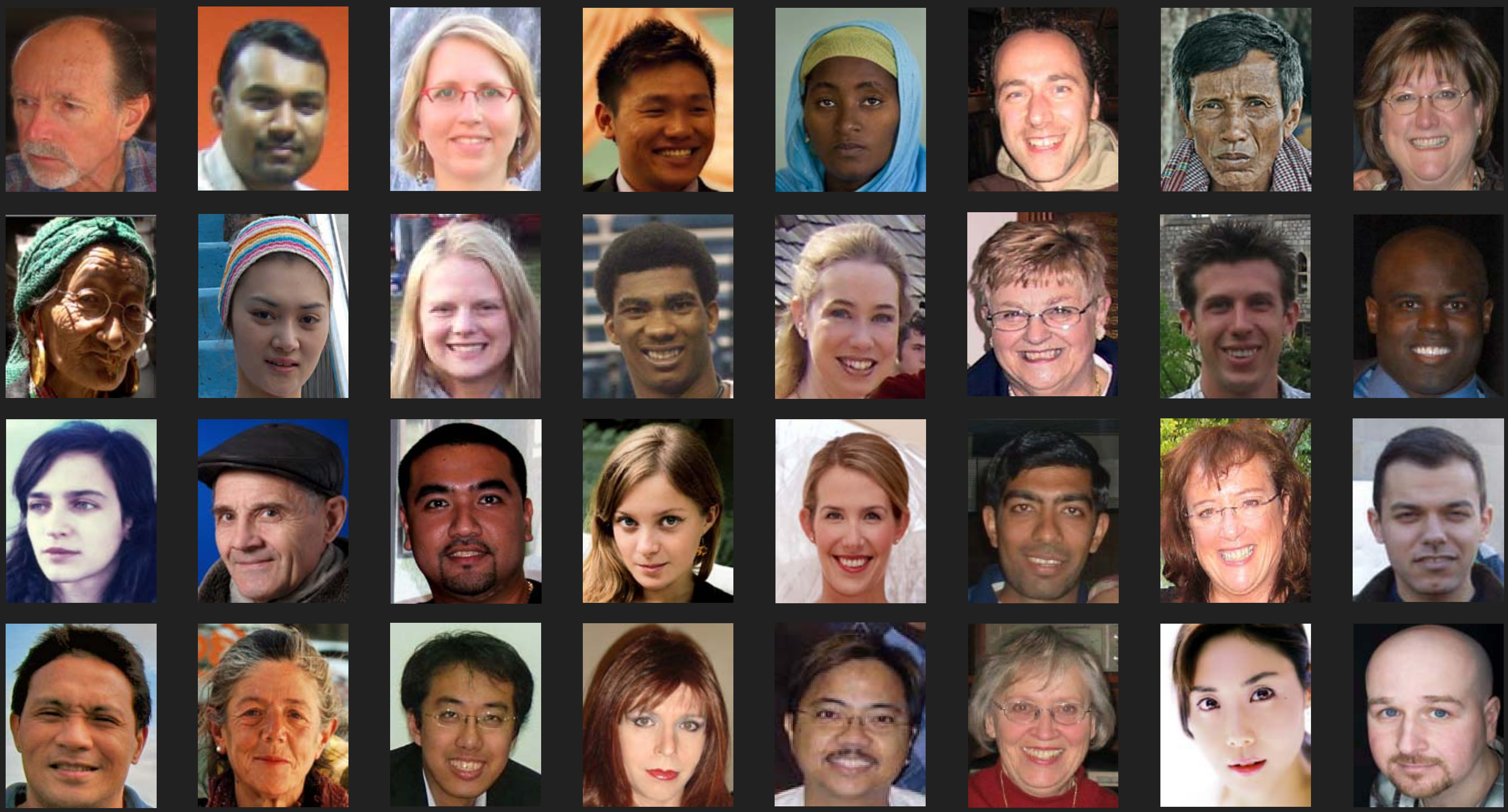
N. Kumar, A. C. Berg, P. N. Belhumeur, and S. K. Nayar ICCV 2009

Some attributes may be irrelevant

Teeth showing

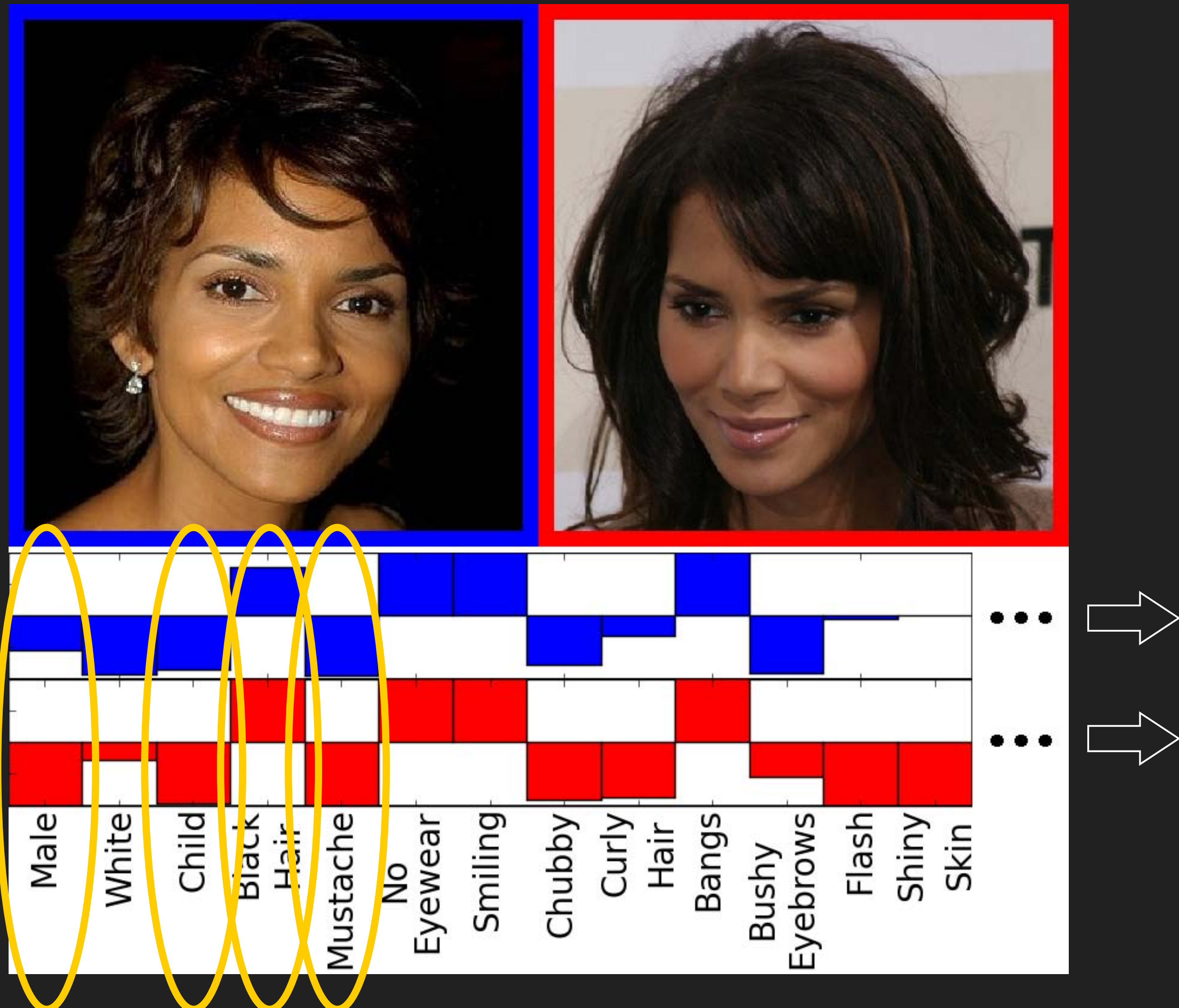
Tilted head

Outside



N. Kumar, A. C. Berg, P. N. Belhumeur, and S. K. Nayar ICCV 2009

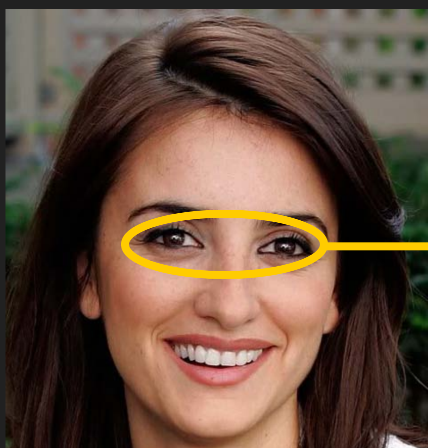
Using attributes to perform verification



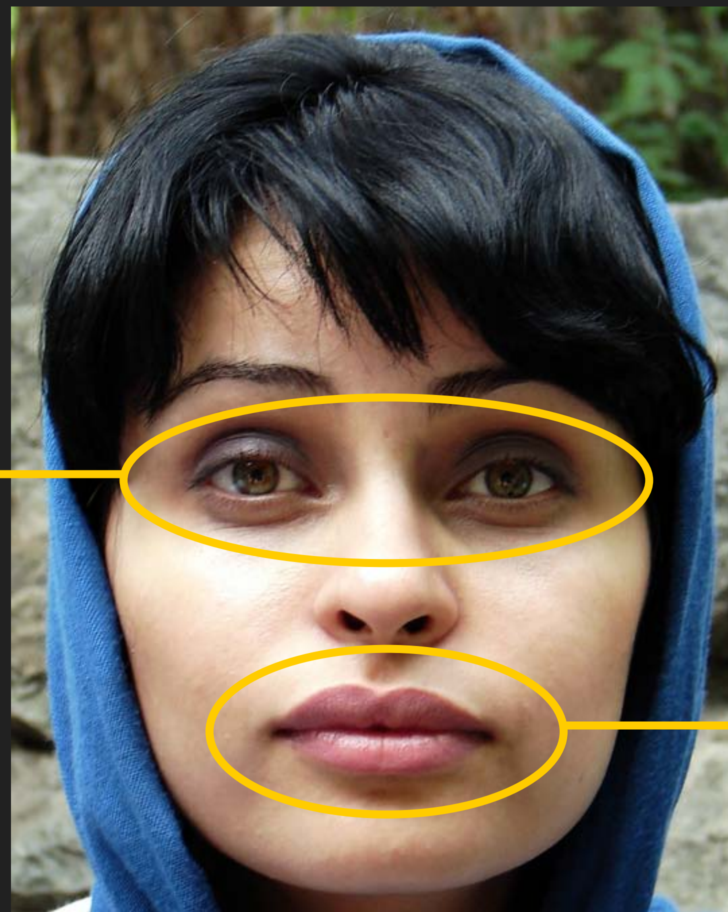
Verification classifier

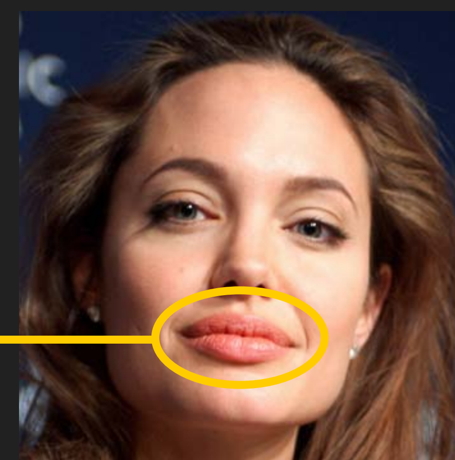
N. Kumar, A. C. Berg, P. N. Belhumeur, and S. K. Nayar ICCV 2009

Describe faces using similes



Penelope Cruz

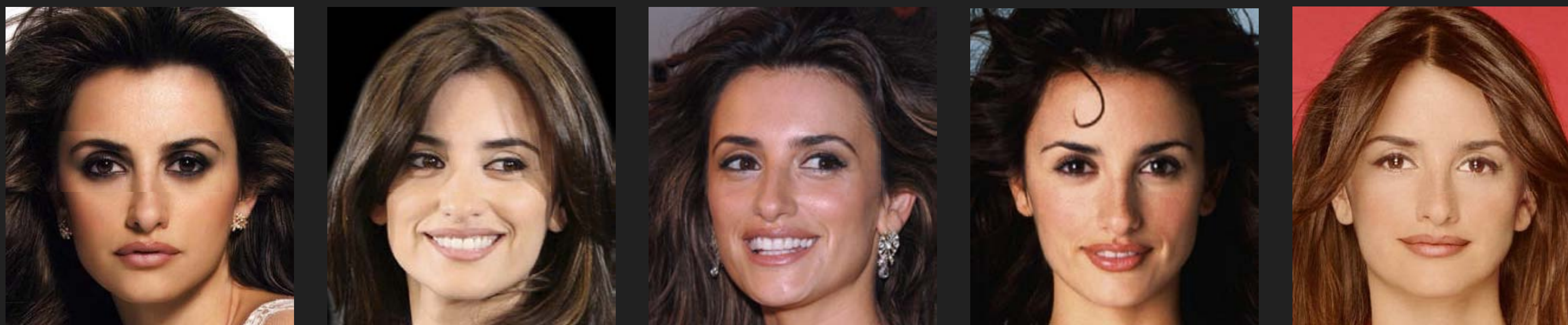




Angelina Jolie

N. Kumar, A. C. Berg, P. N. Belhumeur, and S. K. Nayar ICCV 2009

Training simile classifiers

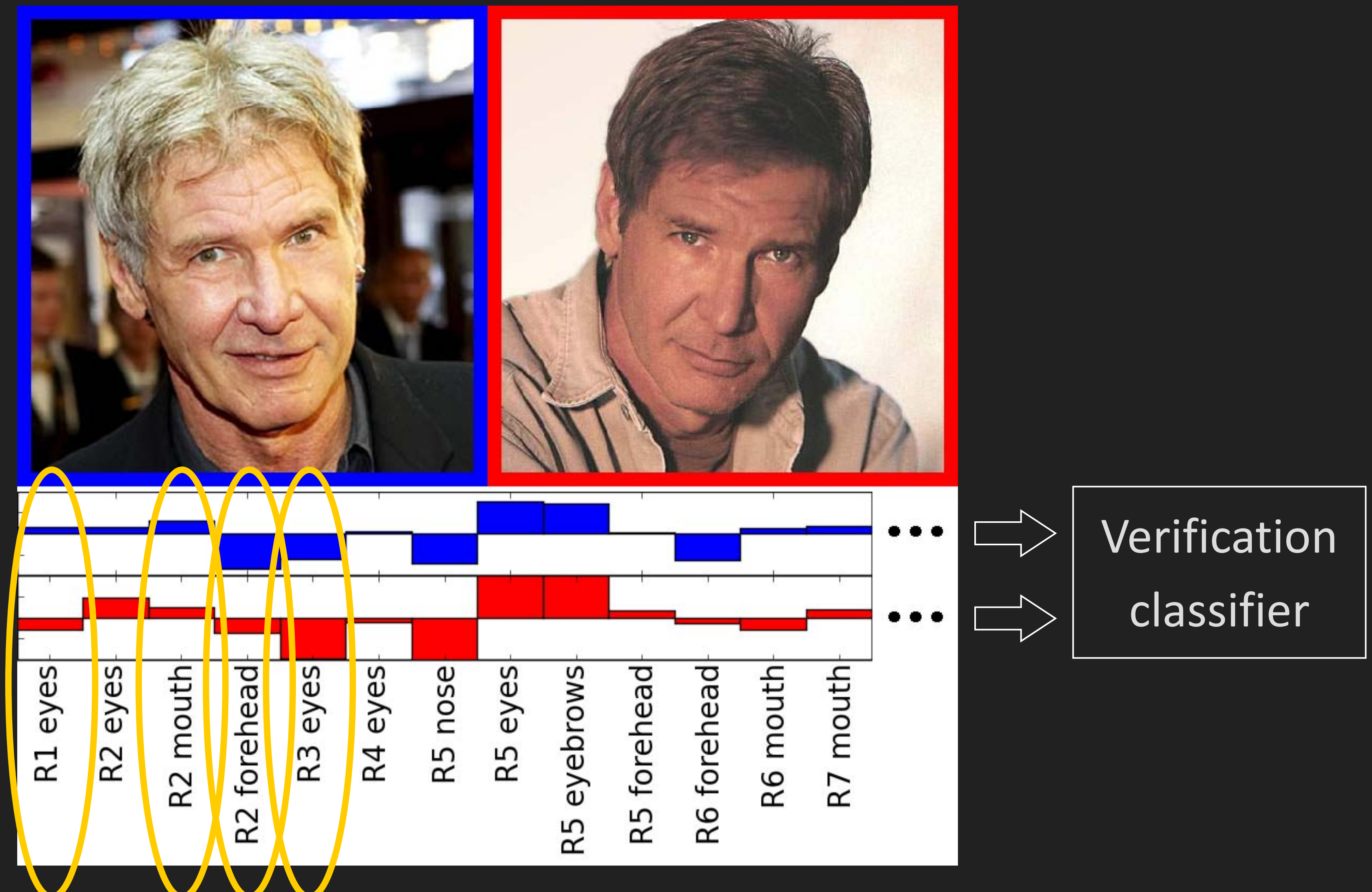


Images of Penelope Cruz ’s eyes

Images of other people ’s eyes

N. Kumar, A. C. Berg, P. N. Belhumeur, and S. K. Nayar ICCV 2009

Using simile classifiers for verification

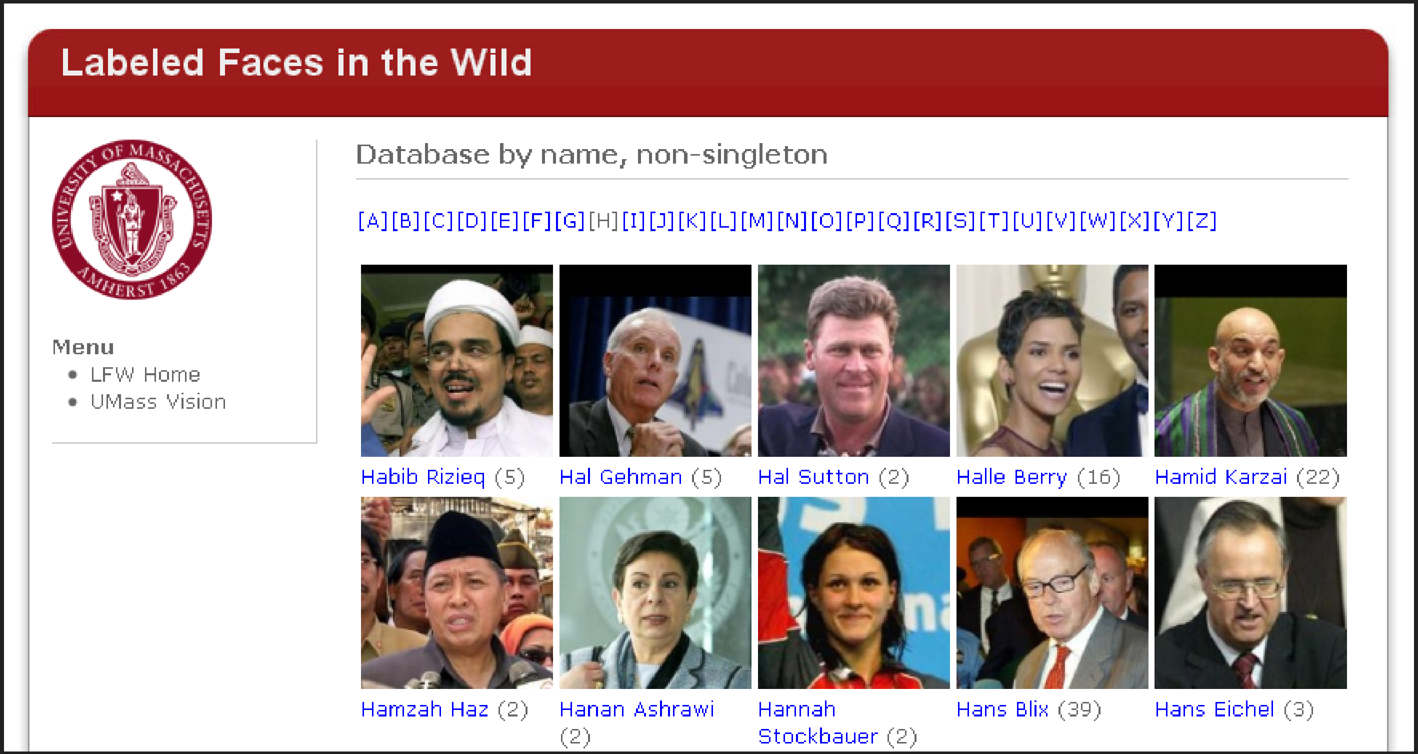


N. Kumar, A. C. Berg, P. N. Belhumeur, and S. K. Nayar ICCV 2009

Experimental evaluation

LFW Image-Restricted Benchmark:

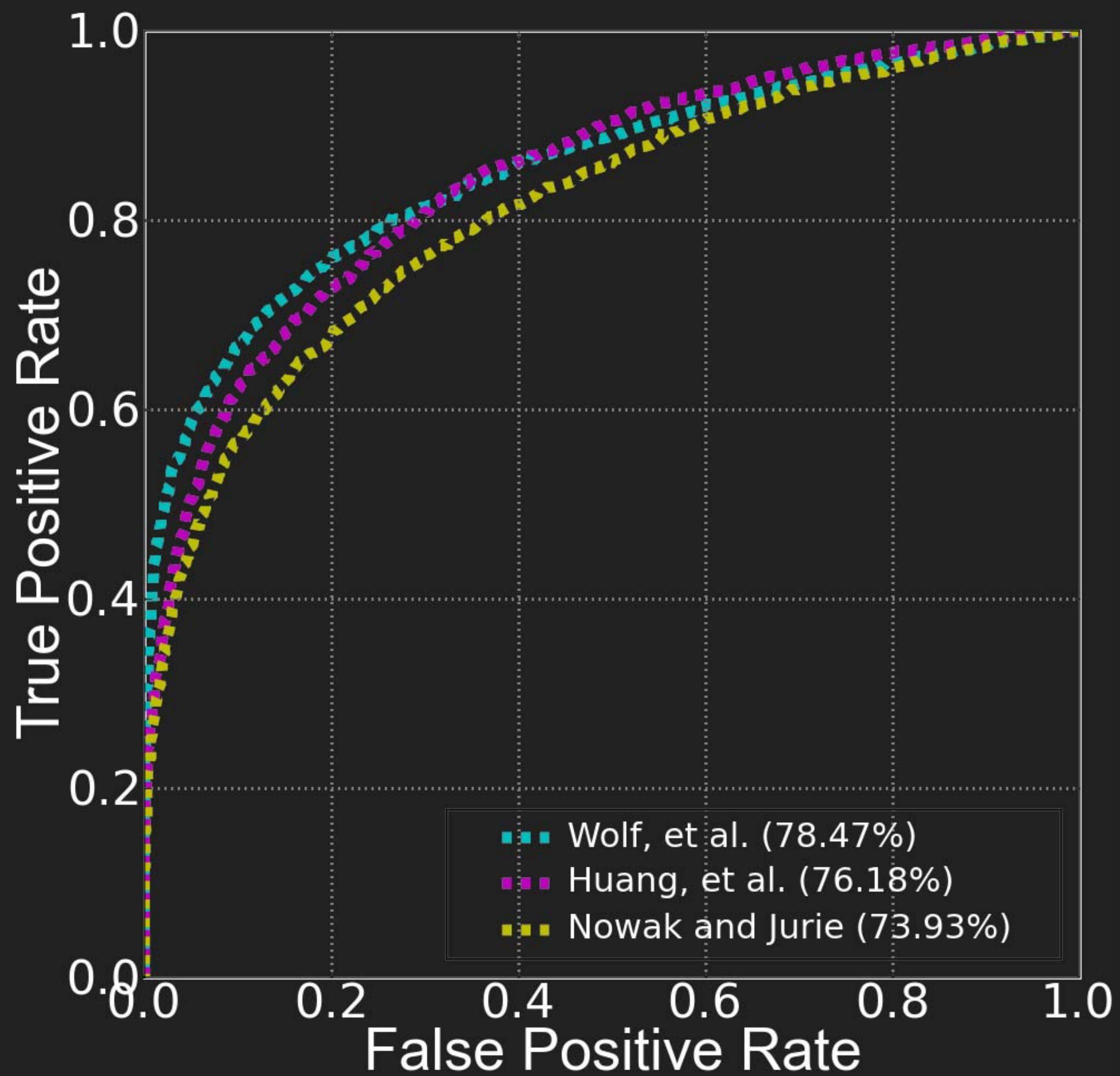
- 6,000 face pairs (3,000 same, 3,000 different)
- 10-fold cross-validation



http://vis-www.cs.umass.edu/lfw

N. Kumar, A. C. Berg, P. N. Belhumeur, and S. K. Nayar ICCV 2009

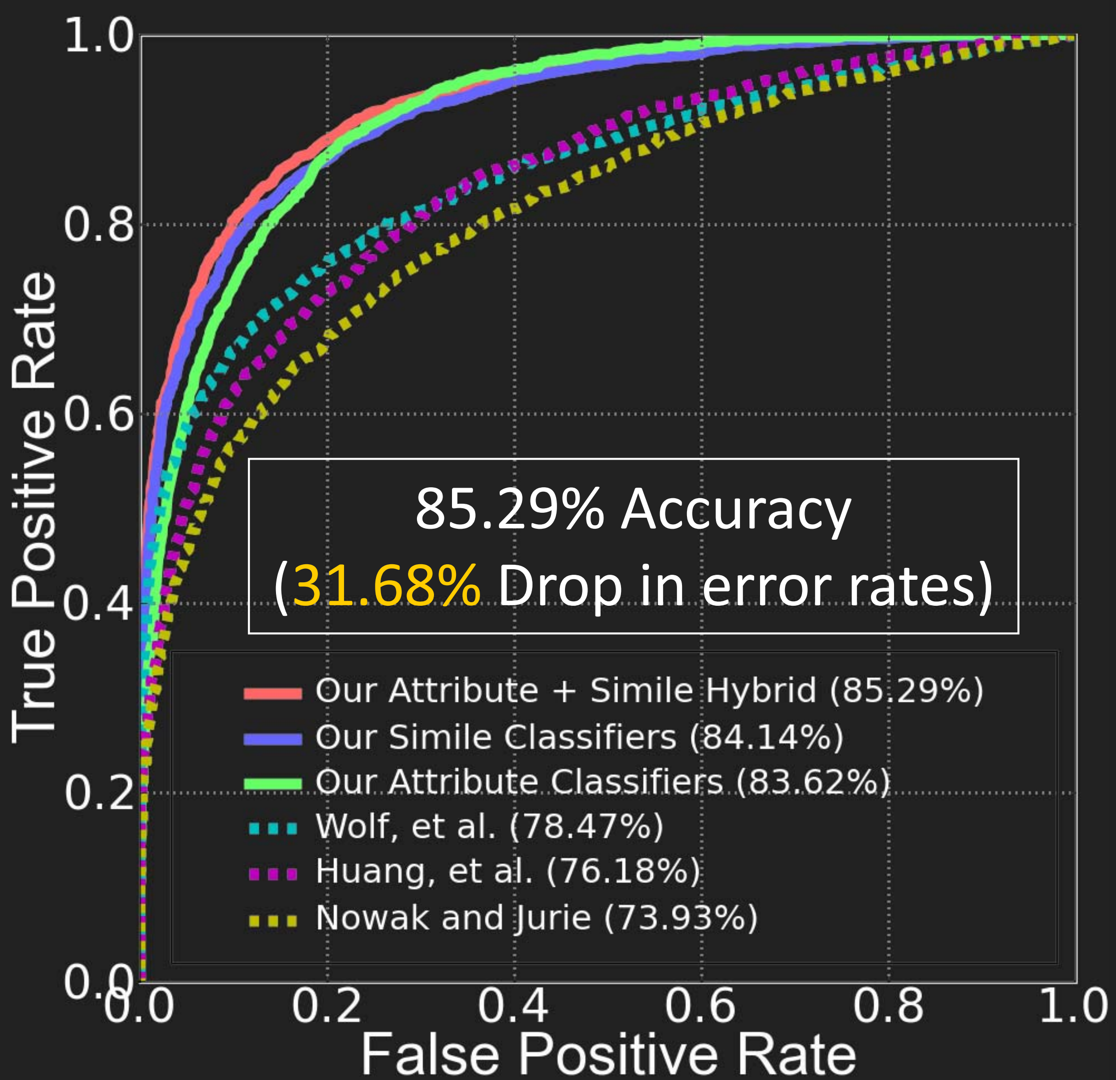
Previous state-of-the-art on LFW



as of May 2009

N. Kumar, A. C. Berg, P. N. Belhumeur, and S. K. Nayar ICCV 2009

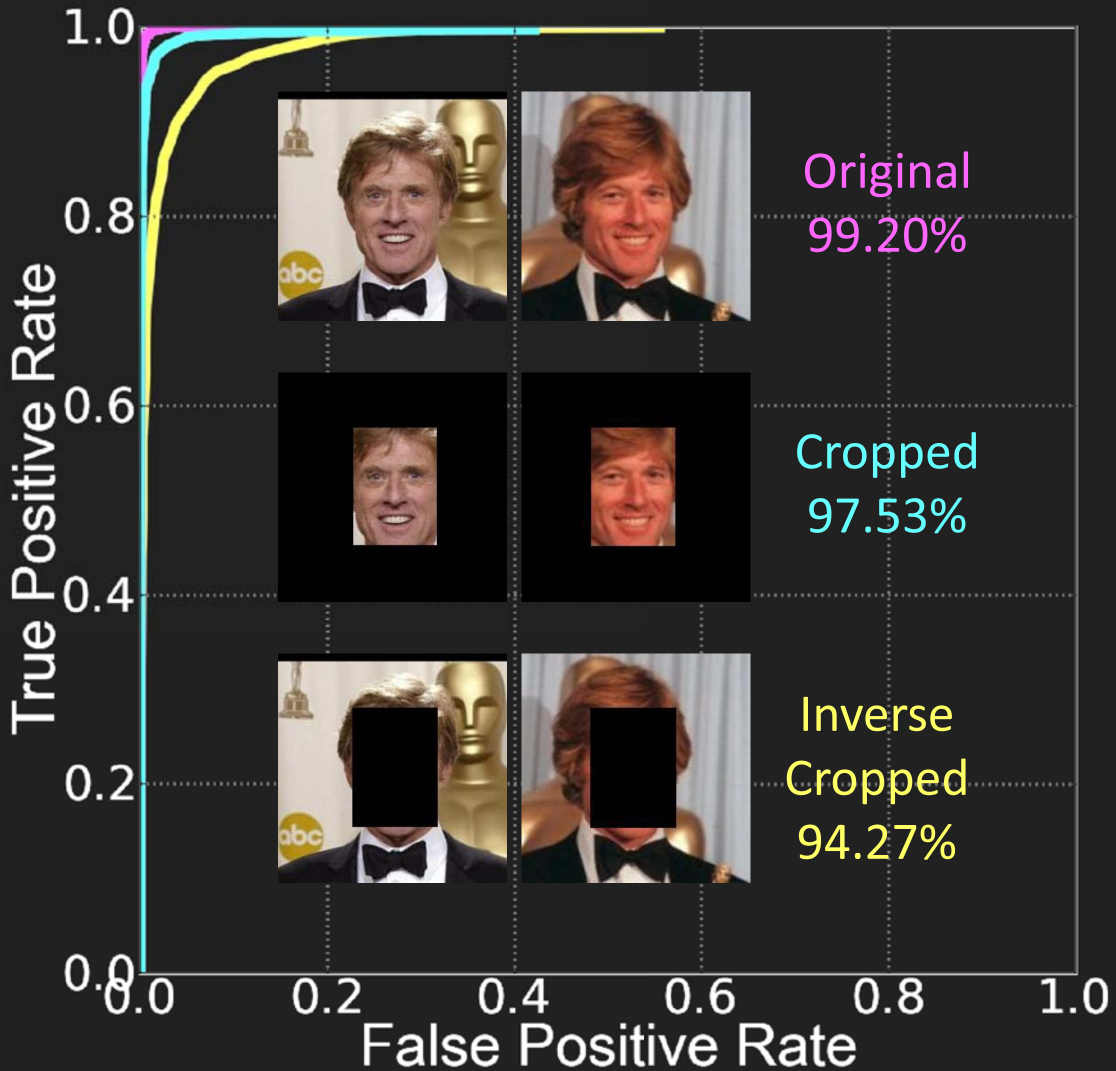
Kumar et al. 2009 on LFW



as of May 2009

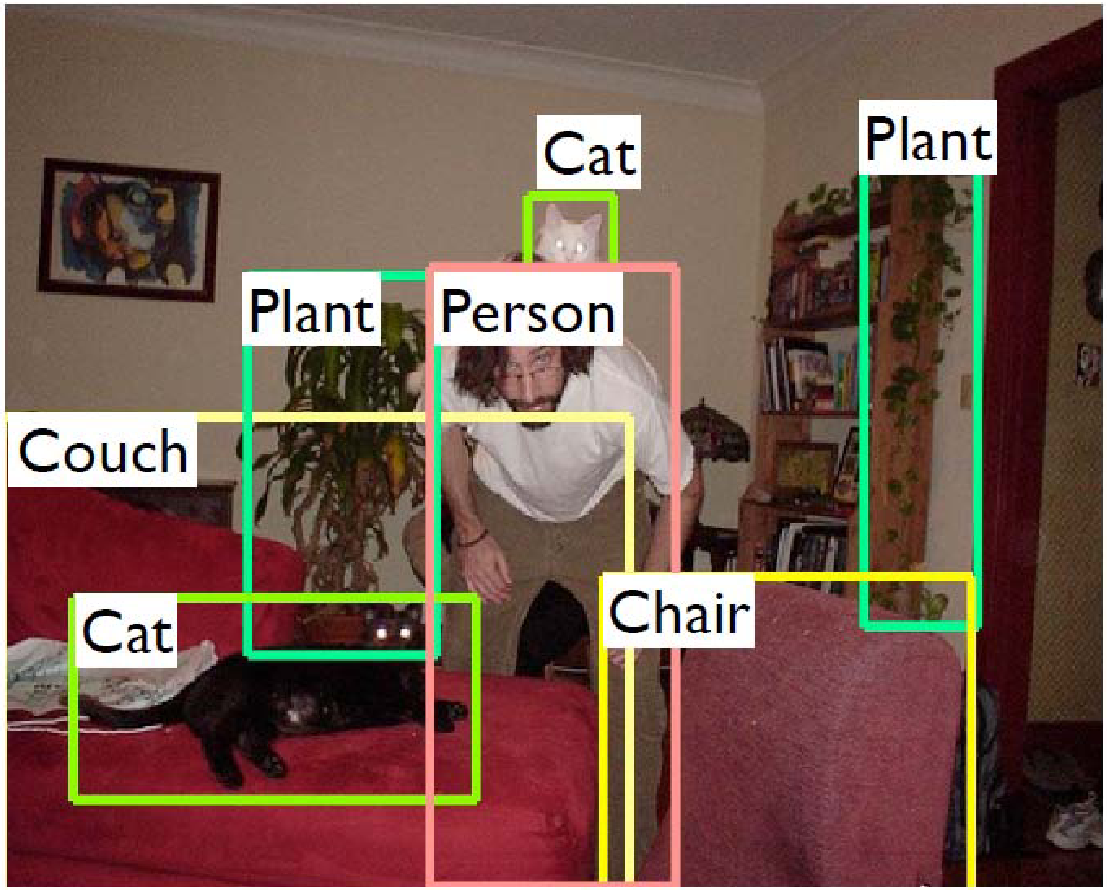
N. Kumar, A. C. Berg, P. N. Belhumeur, and S. K. Nayar ICCV 2009

Human face verification performance



N. Kumar, A. C. Berg, P. N. Belhumeur, and S. K. Nayar ICCV 2009

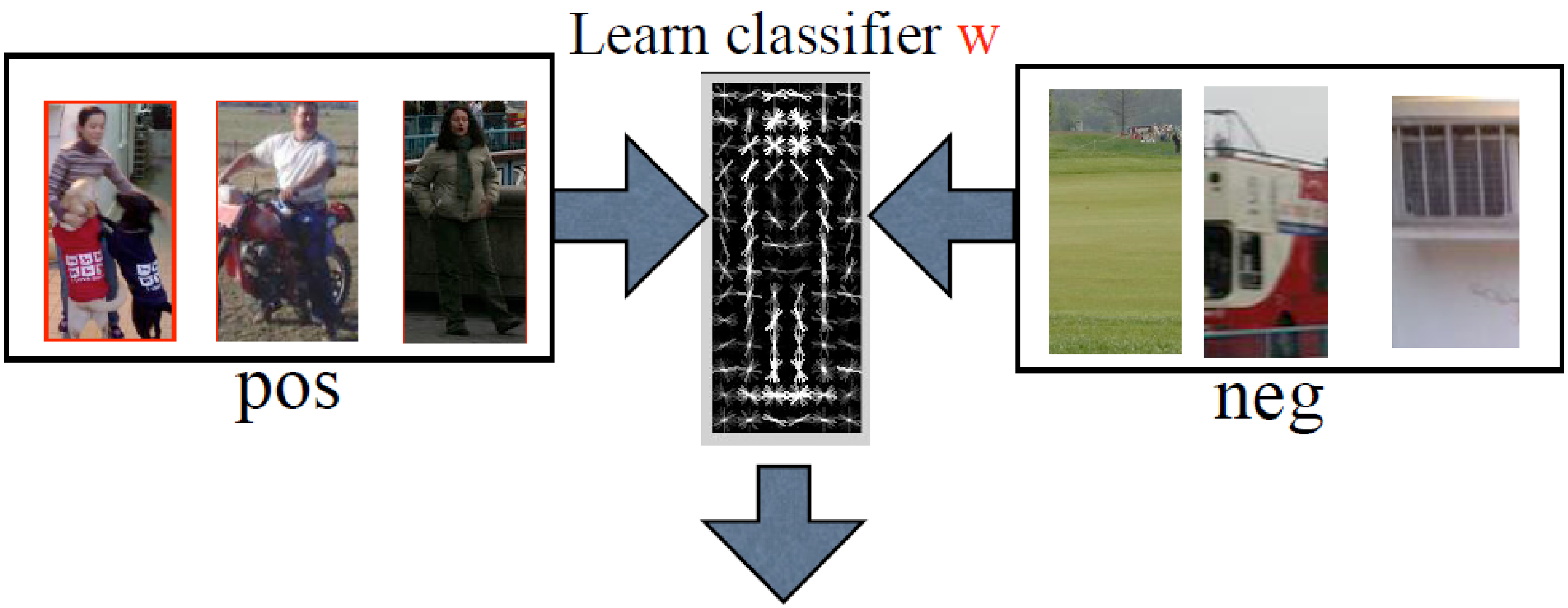
What about multiple objects in the same image?



Multiclass object detection

C. Desai, D. Ramanan, C. Fowlkes ICCV 2009

Scanning-window pattern classification



$w^T x > 0$?

Face detection

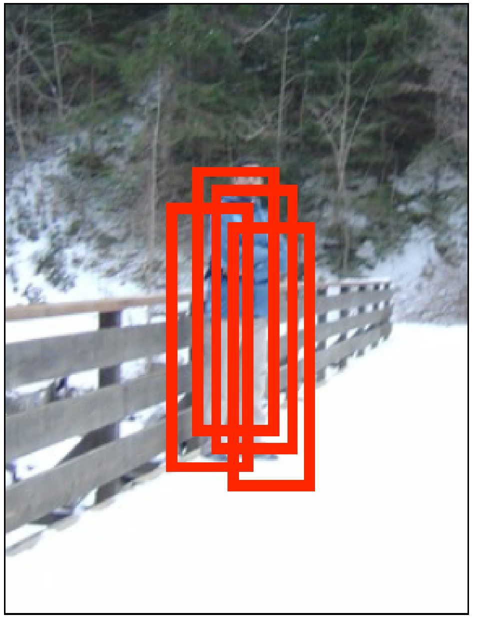
Rowley, Baluja, & Kanade. CVPR 96
Viola & Jones IJCV 01

Pedestrian detection
(and other objects)

Oren et al. CVPR 97
Dalal & Triggs CVPR 05
Felzenswalb et al. PAMI 09

C. Desai, D. Ramanan, C. Fowlkes ICCV 2009

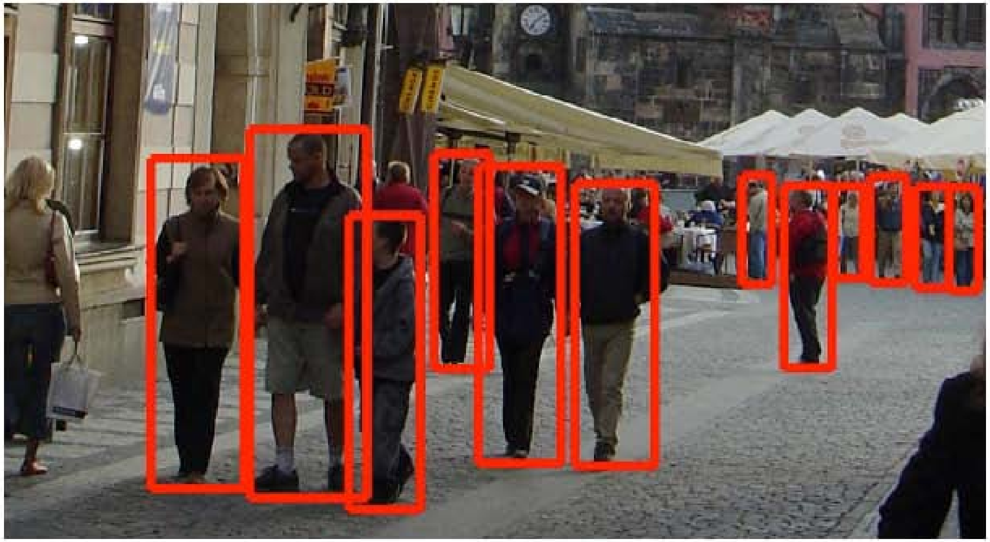
Non-maxima suppression (NMS)



We need to suppress overlapping detections
Many heuristics (mode finding, greedy selection)

C. Desai, D. Ramanan, C. Fowlkes ICCV 2009

NMS in cluttered scenes



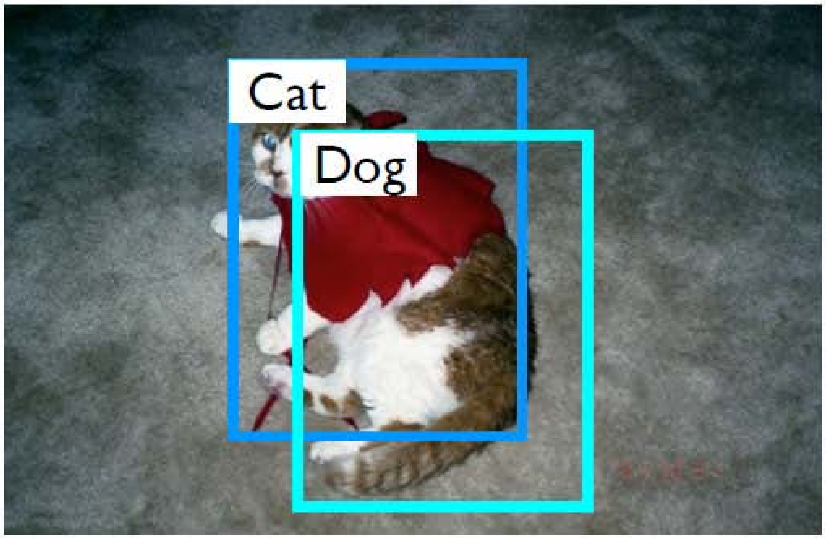
NMS should exploit spatial statistics of objects in real scenes

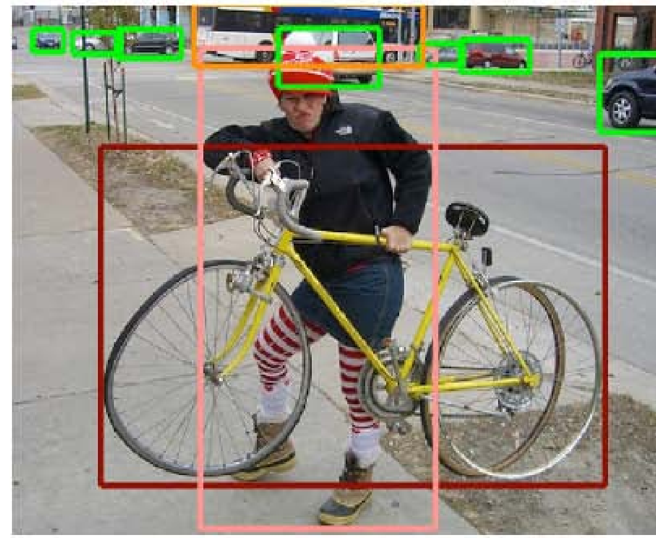
Is there a principled way to learn how to perform NMS?

C. Desai, D. Ramanan, C. Fowlkes ICCV 2009

Inter-class NMS

Mutual exclusion: two objects cannot occupy the same 3D volume





May not be a strict constraint due to porous or transparent objects

C. Desai, D. Ramanan, C. Fowlkes ICCV 2009

Taxonomy of spatial interactions

	within-class	between-class
negative	NMS	mutual exclusion
positive	textures of objects	spatial cueing

Most past work focuses on positive interactions,
heuristically performing NMS & mutual exclusion.

Our contribution: a model for all of the above

Our inspiration: Torralba, Murphy, & Freeman NIPS 04
Kumar & Hebert ICCV 05
He, Zemel, & Carreira-Perpinan CVPR 05
Galleguillos, Rabinovich & Belongie CVPR 08
Hoeim, Efros, & Hebert IJCV 08

Object detection as ....

Classification

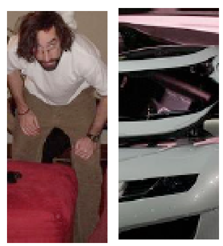
x = image window

$y \in \{0,1\}$

C. Desai, D. Ramanan, C. Fowlkes ICCV 2009

Object detection as a structured labeling task

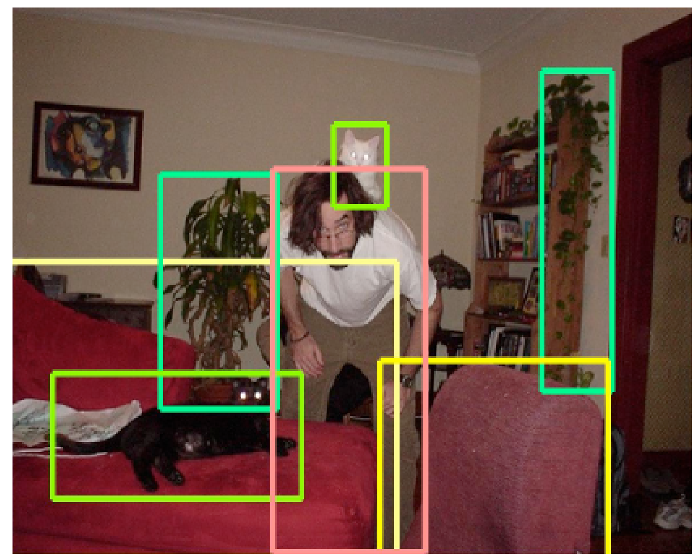
Classification



x = image window

$y \in \{0,1\}$

Structured, sparse label



X = entire image

$Y = [...4...3...2.7..1..]$

C. Desai, D. Ramanan, C. Fowlkes ICCV 2009

Global scoring function

$$S_w(X, Y)$$

$X = \{x_i\}$ $Y = \{y_i\}$

x_i = feature vector extracted from i^{th} window (e.g. HOG)

y_i = class label (0..K) for i^{th} window

C. Desai, D. Ramanan, C. Fowlkes ICCV 2009

Global scoring function

$$S_w(X,Y) = \underbrace{\boxed{\sum_i w_{y_i}^T x_i}}_{\text{sum of per-window classifier scores}}$$

w_{y_i} = template for class y_i

w_{car}

w_{bus}

$\vdots$

$X = \{x_i\}$ $Y = \{y_i\}$

x_i = feature vector extracted from i^{th} window (e.g. HOG)

y_i = class label (0..K)

sum of per-window classifier scores

Global scoring function

$$S_w(X,Y) = \underbrace{\sum_i w_{y_i}^T x_i}_{\text{sum of per-window classifier scores}} + \underbrace{\sum_{i,j} w_{y_i,y_j}^T d_{ij}}_{\text{sum of pairwise window-label interactions}}$$

$X = \{x_i\}$ $Y = \{y_i\}$

x_i = feature vector extracted from i^{th} window (e.g. HOG)

y_i = class label (0..K)

w_{yi} = template for class y_i

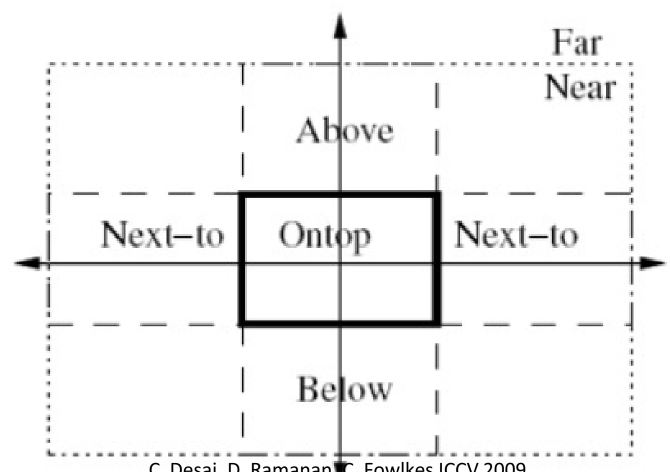
w_{car}

w_{bus}

$\vdots$

d_{ij} = spatial context descriptor for window i and j

w_{yiyj} = spatial interaction model for class y_i & y_j



C. Desai, D. Ramanan, C. Fowlkes ICCV 2009

Inference

$$S_w(X,Y) = \sum_i w_{y_i}^T x_i + \sum_{i,j} w_{y_i,y_j}^T d_{ij}$$

$$L(X) = \underset{Y}{\operatorname{argmax}}\, S_w(X,Y)$$

Looks like an MRF - can we use standard inference techniques?

Our model is not sub-modular

Sub-modular interactions: neighboring labels should be similar

NMS interactions: neighboring labels should be different

Greedy inference

$$L(X) = \underset{Y}{\operatorname{argmax}}\, S(X,Y) \qquad S(X,Y) = \sum_i w_{y_i}^T x_i + \sum_{i,j} w_{y_i,y_j}^T d_{ij}$$

Analogous to common NMS schemes

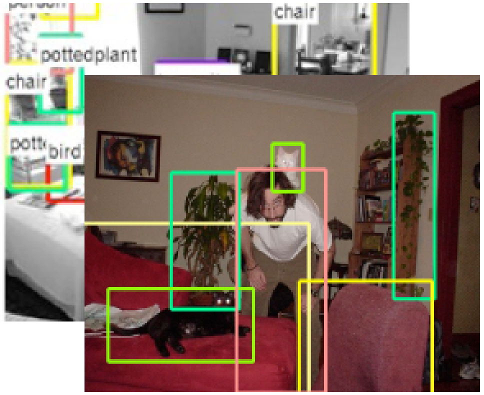
(1) Initialize all labels to bg
Initialize per-window scores with local template
(2) Select highest scoring un-instanced window
(3) Instance it and add pairwise contribution to remaining windows
(4) Stop when remaining windows score < 0

Effectiveness: Greedy solution close to optimal in practice
(See Numhauser et al. 78 for theoretical arguements)

C. Desai, D. Ramanan, C. Fowlkes ICCV 2009

Learning

Training data consists of pairs of $\{X_n, Y_n\}$



$$S_w(X,Y) = \sum_i w_{y_i}^T x_i + \sum_{i,j} w_{y_i,y_j}^T d_{ij}$$

$$S_w(X,Y) = w^T \Psi(X,Y)$$

C. Desai, D. Ramanan, C. Fowlkes ICCV 2009

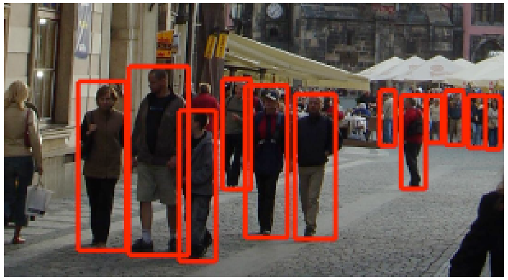
Learning with SVMs

$$\underset{w}{\operatorname{argmin}} \quad \frac{1}{2} w^T w$$

$$\text{s.t.} \quad \forall n, H_n \neq Y_n \qquad w^T \Psi(X_n, Y_n) - w^T \Psi(X_n, H_n) \geq 1$$

"Find a small w such that for each image, score of true label Y_n dominates all other hypothesized labels H_n by at least 1 unit"

Y_n



H_n

Only a tiny fraction of exponential number of constraints are necessary (i.e., support vectors)

Structured Prediction
Tsochantaridis et al. ICML 04

C. Desai, D. Ramanan, C. Fowlkes ICCV 2009

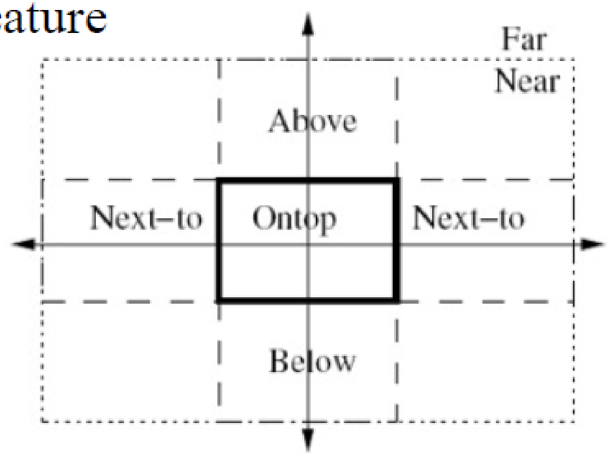
Experiments

1) We use PASCAL 2007 training and test data
   20 classes, 5000 training images, 5000 test images

2) Baseline: Felzenswalb et al. PAMI 09 (with default NMS)

3) Local feature = [score of baseline detector 1]
   (We learn bias and offset for each local detector)

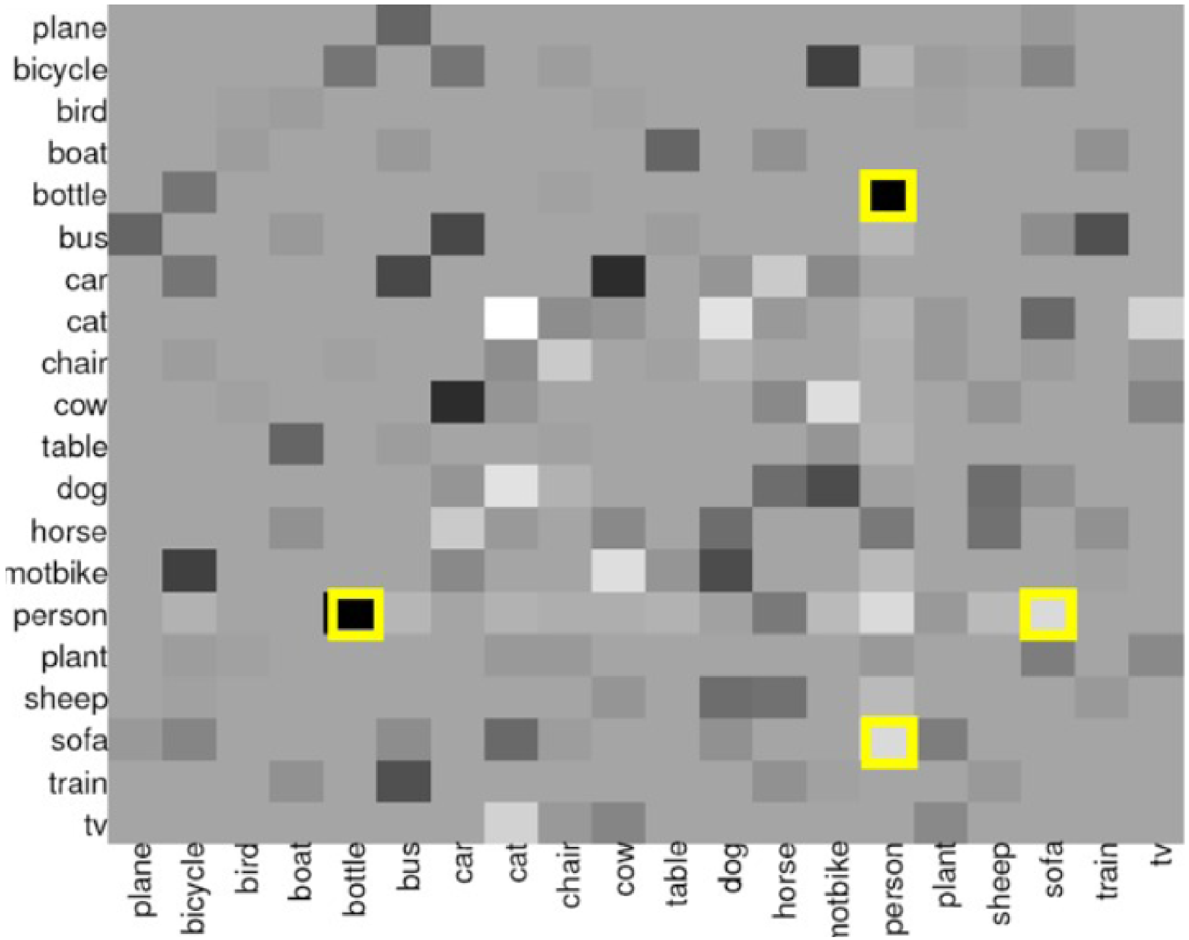
4) Pairwise feature



+ 50% overlap feature

C. Desai, D. Ramanan, C. Fowlkes ICCV 2009

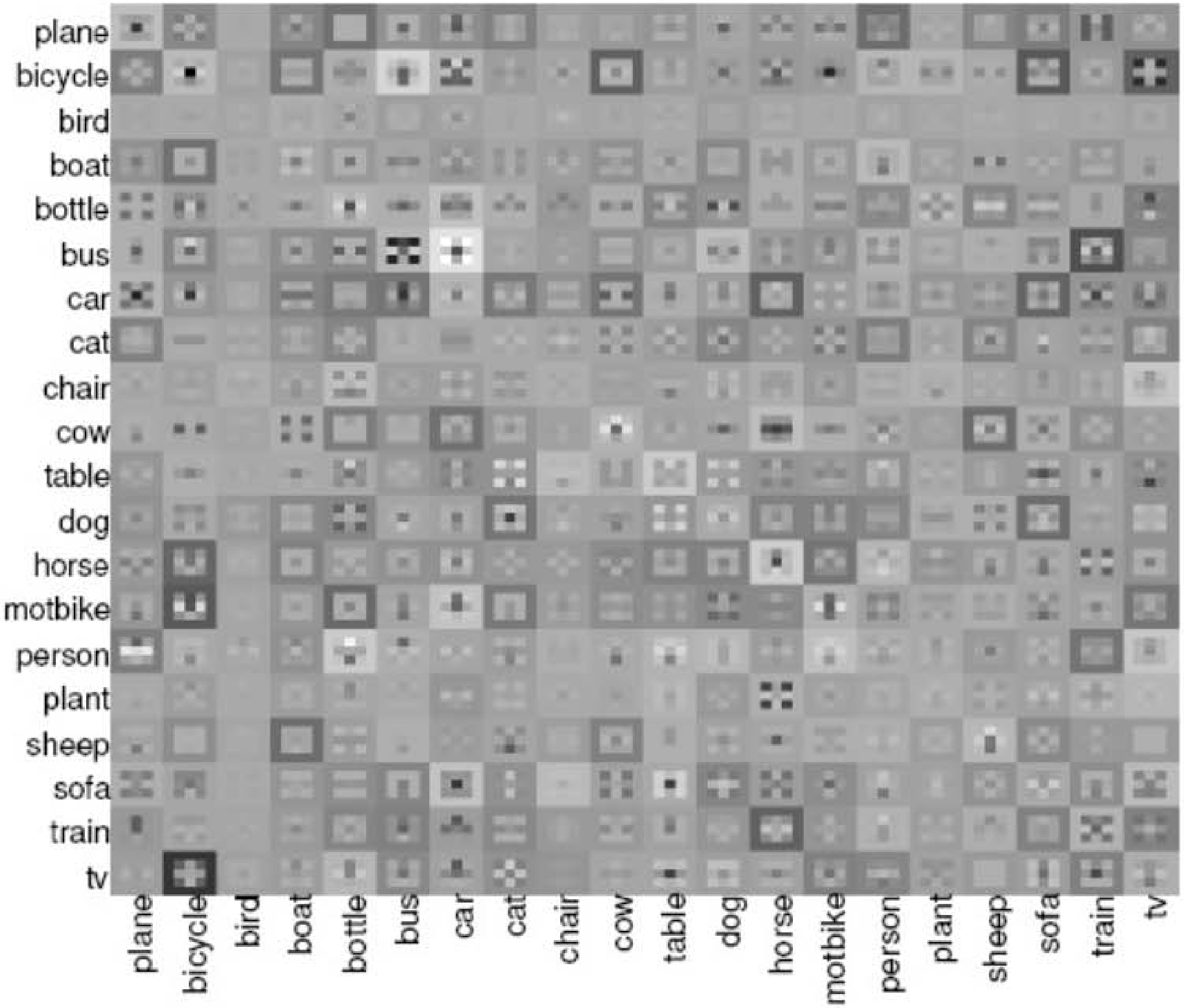
Overlap feature in pairwise potential



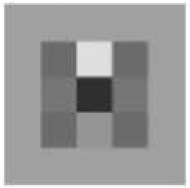
Mutual exclusion can be subtle
Parameters are trained with knowledge of local detectors

C. Desai, D. Ramanan, C. Fowlkes ICCV 2009

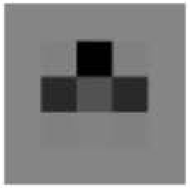
Remaining pairwise potentials



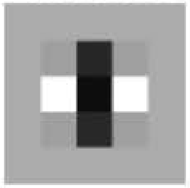
bottles wrt tables



cars wrt trains



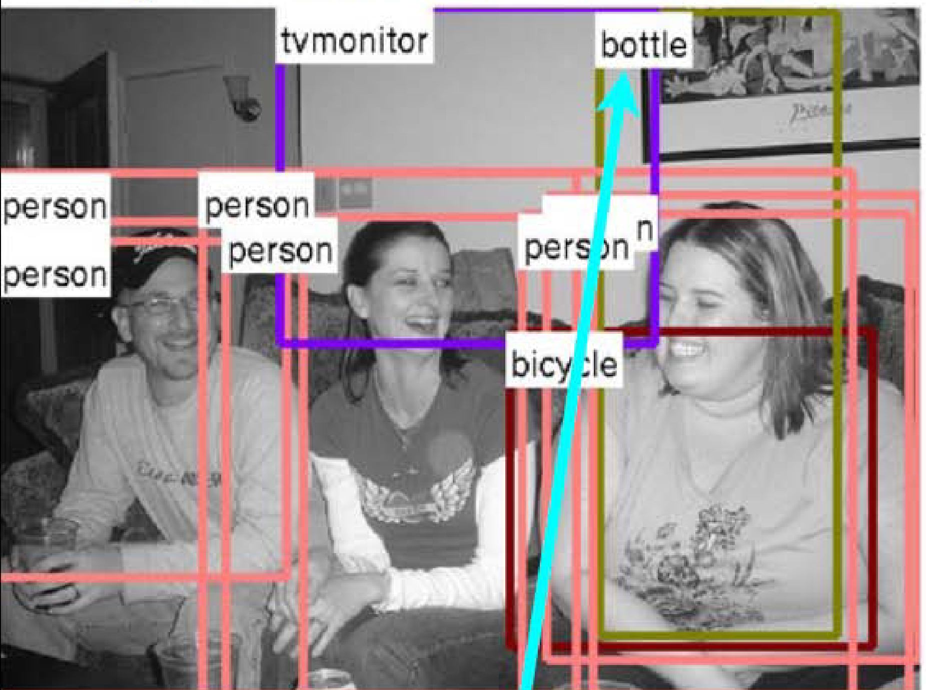
m.bikes wrt m.bikes



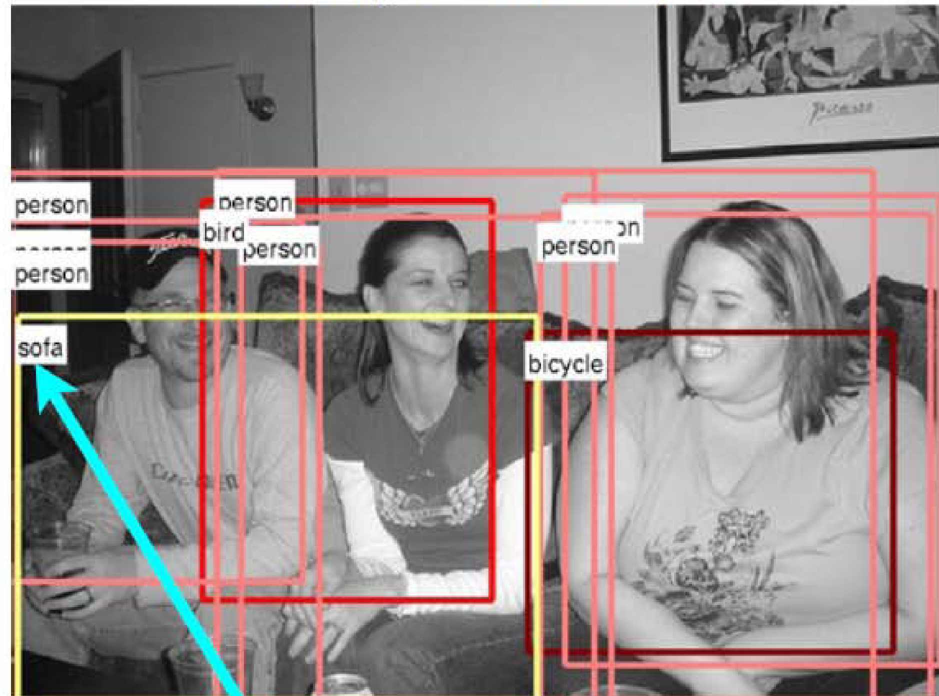
C. Desai, D. Ramanan, C. Fowlkes ICCV 2009

Results

Top 10 detections for baseline



Our top 10 detections



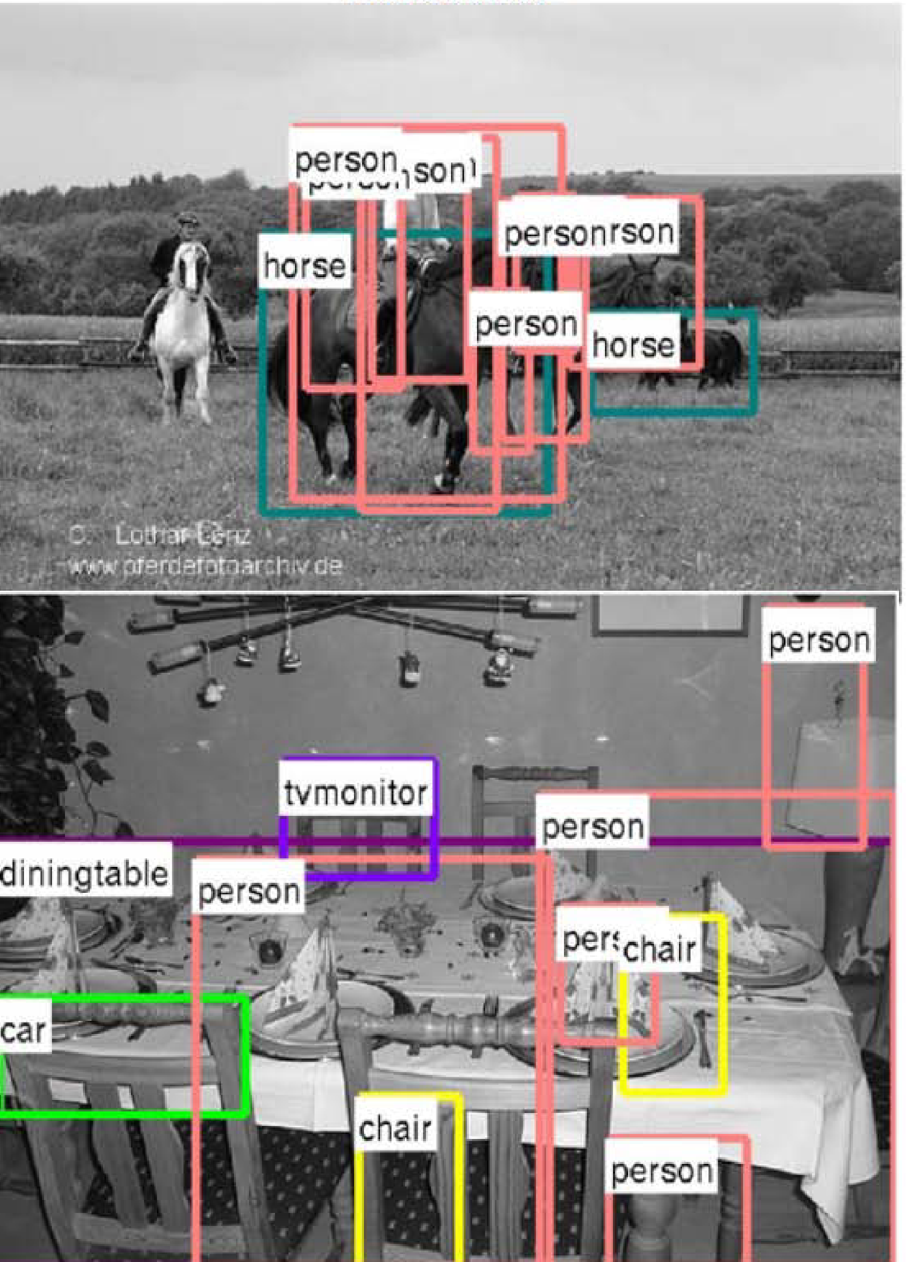
Inhibit
overlapping people & bottles
because local detectors confuse them

Favor
overlapping people & sofas
because people sit on sofas

C. Desai, D. Ramanan, C. Fowlkes ICCV 2009

Results

Baseline



Our model

C. Desai, D. Ramanan, C. Fowlkes ICCV 2009

Default NMS heuristics

Default heuristics don't work for Mutual Exclusion

	Winning PASCAL07 score	Felzenszwalb et al. PAMI 09 code	Mutual Exclusion	Our model
plane	.262	0.278	0.270	**0.288**
bike	.409	0.559	0.444	**0.562**
bird	**.098**	0.014	0.015	0.032
boat	.094	**0.146**	0.125	0.142
bottle	.214	0.257	0.185	**0.294**
bus	**.393**	0.381	0.299	0.387
car	.432	0.470	0.466	**0.487**
cat	**.240**	0.151	0.133	0.124
chair	.128	**0.163**	0.145	0.160
cow	.140	0.167	0.109	**0.177**
table	.098	0.228	0.191	**0.240**
dog	**.162**	0.111	0.091	0.117
horse	.335	0.438	0.371	**0.450**
motbike	.375	0.373	0.325	**0.394**
person	.221	0.352	0.342	**0.355**
plant	.120	0.140	0.091	**0.152**
sheep	**.175**	0.169	0.091	0.161
sofa	.147	0.193	0.188	**0.201**
train	.334	0.319	0.318	**0.342**
TV	.289	**0.373**	0.359	0.354

Our model outperforms Felzenszwalb et al.'s baseline for most classes

C. Desai, D. Ramanan, C. Fowlkes ICCV 2009

Yet, another multi-object detection problem

Inria
INVENTEURS DU MONDE NUMÉRIQUE

ENS
LETTRES SCIENCES
ECOLE NORMALE SUPERIEURE

Density-aware person detection and tracking in crowds

M. Rodriguez, I. Laptev, J. Sivic, J.-Y. Audibert

Motivation

- Recognize crowd events
- Predict future [potentially dangerous] events
  - Detect and track individual people

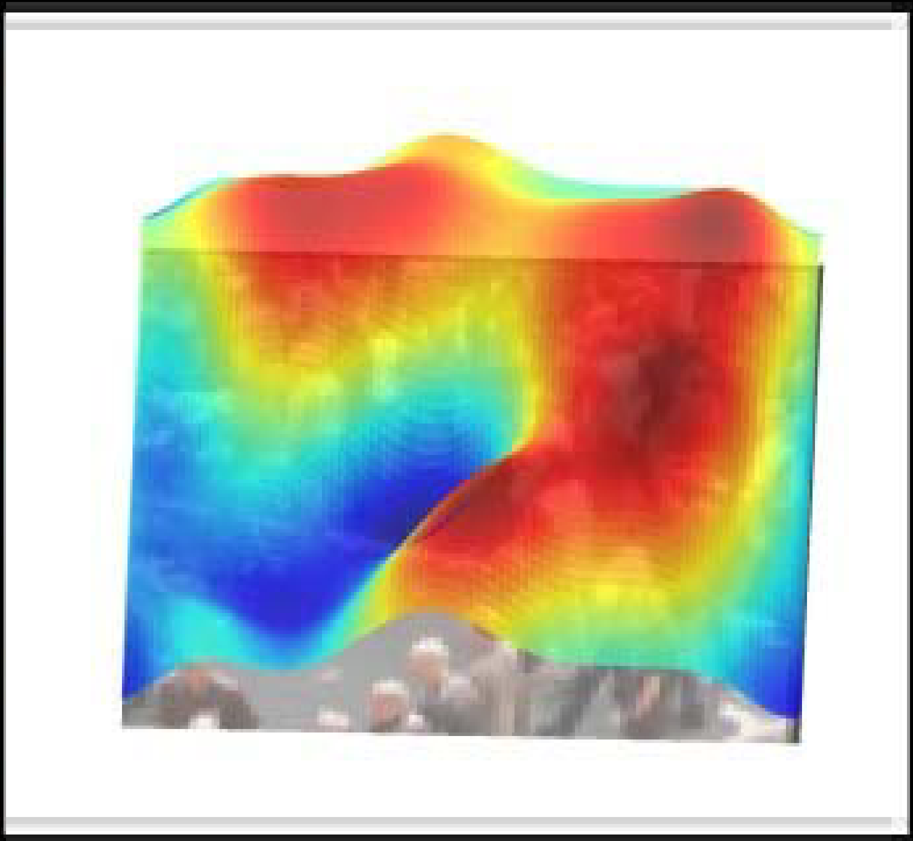
Problem

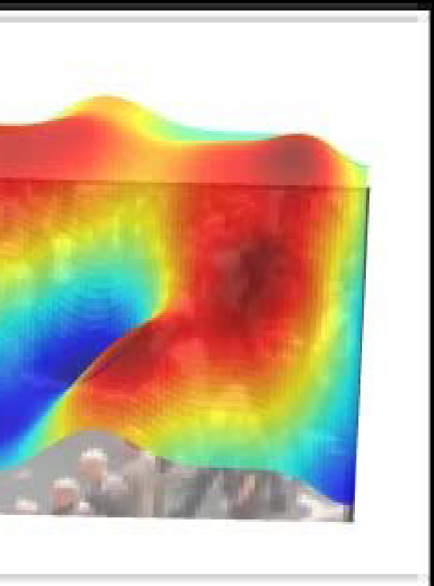
- As the density of people in a scene increases:
  - The accuracy of current detection and tracking methods degrades

Detection and Tracking

Typical state-of-the-art detection and tracking

Density Estimation





Density estimate

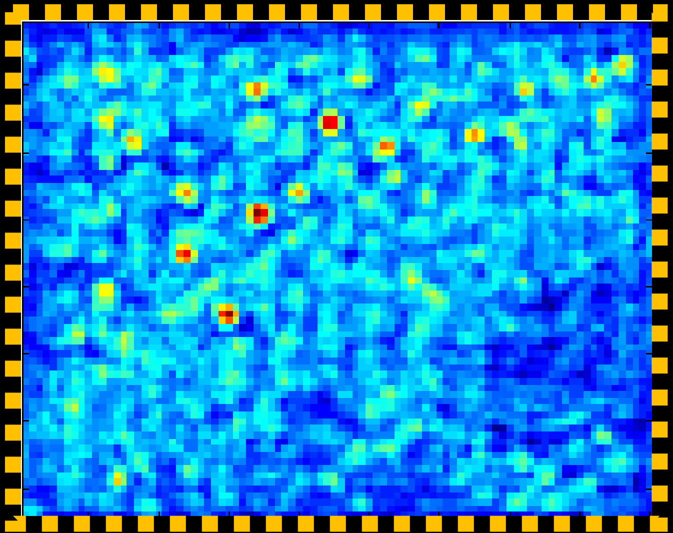
Improved Detection and Tracking

Crowd Model

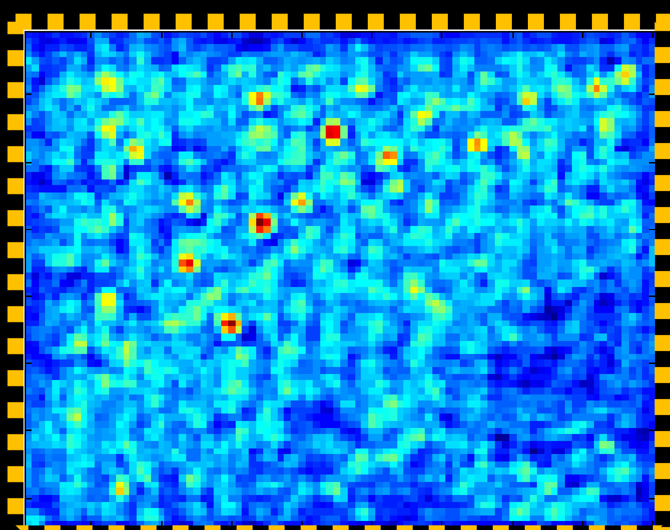
Energy Formulation

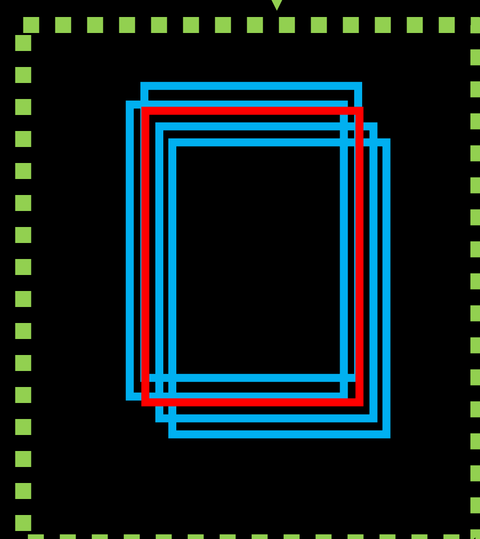
$$\min_{\mathbf{x}\in\{0,1\}^N} \underbrace{-s(\mathbf{p})^\top\mathbf{x}}_{E_S} + \underbrace{\mathbf{x}^\top W\mathbf{x}}_{E_P} + \underbrace{\alpha\|D(\mathbf{p}) - A\mathbf{x}\|_2^2}_{E_D}$$

$$\min_{\mathbf{x}\in\{0,1\}^N} \underbrace{-\boxed{s(\mathbf{p})}^\top \mathbf{x}}_{E_S} + \underbrace{\mathbf{x}^\top W \mathbf{x}}_{E_P} + \underbrace{\alpha \|D(\mathbf{p}) - A\mathbf{x}\|_2^2}_{E_D}$$

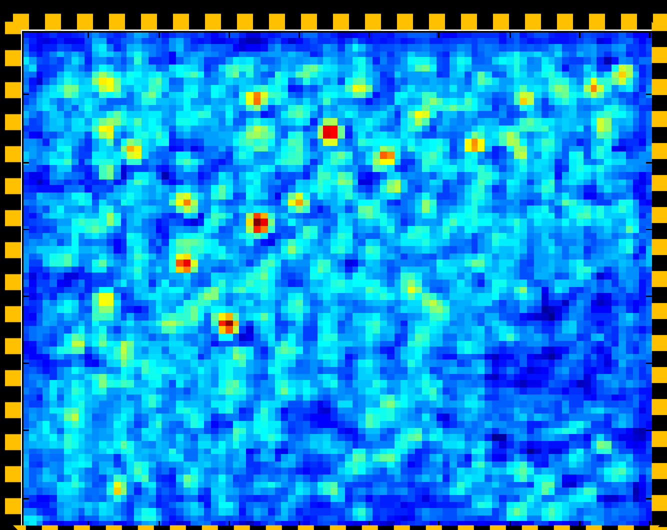


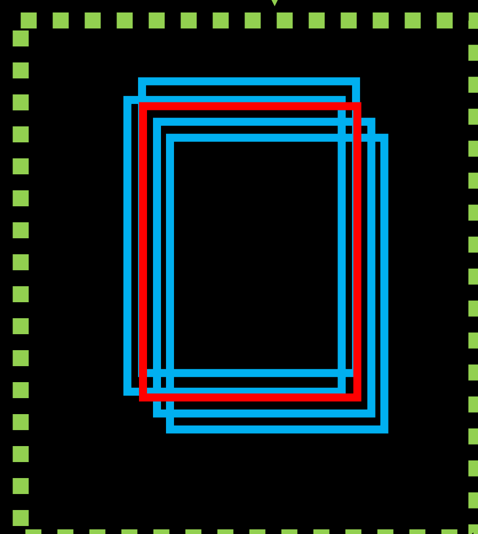
$$\min_{\mathbf{x}\in\{0,1\}^N} \; - \underbrace{\boxed{s(\mathbf{p})}^\top \mathbf{x}}_{E_S} + \underbrace{\mathbf{x}^\top W \mathbf{x}}_{\boxed{E_P}} + \underbrace{\alpha\|D(\mathbf{p}) - A\mathbf{x}\|_2^2}_{E_D}$$

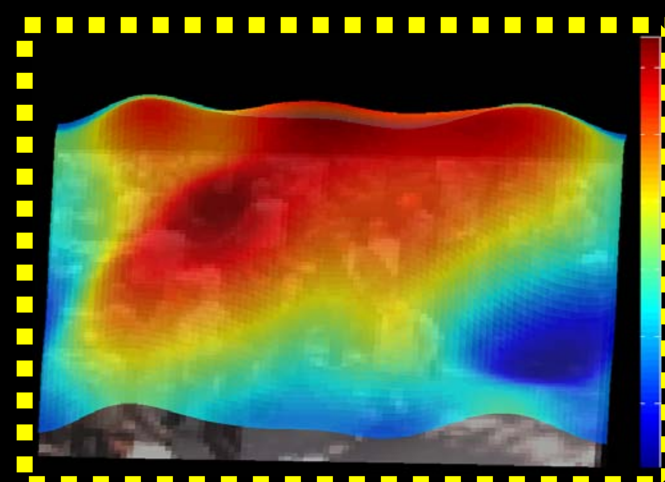




$$\min_{\mathbf{x}\in\{0,1\}^N} \; - \underbrace{\boxed{s(\mathbf{p})}^\top\mathbf{x}}_{E_S} + \underbrace{\mathbf{x}^\top W\mathbf{x}}_{\boxed{E_P}} + \underbrace{\alpha\|\boxed{D(\mathbf{p})} - A\mathbf{x}\|_2^2}_{E_D}$$



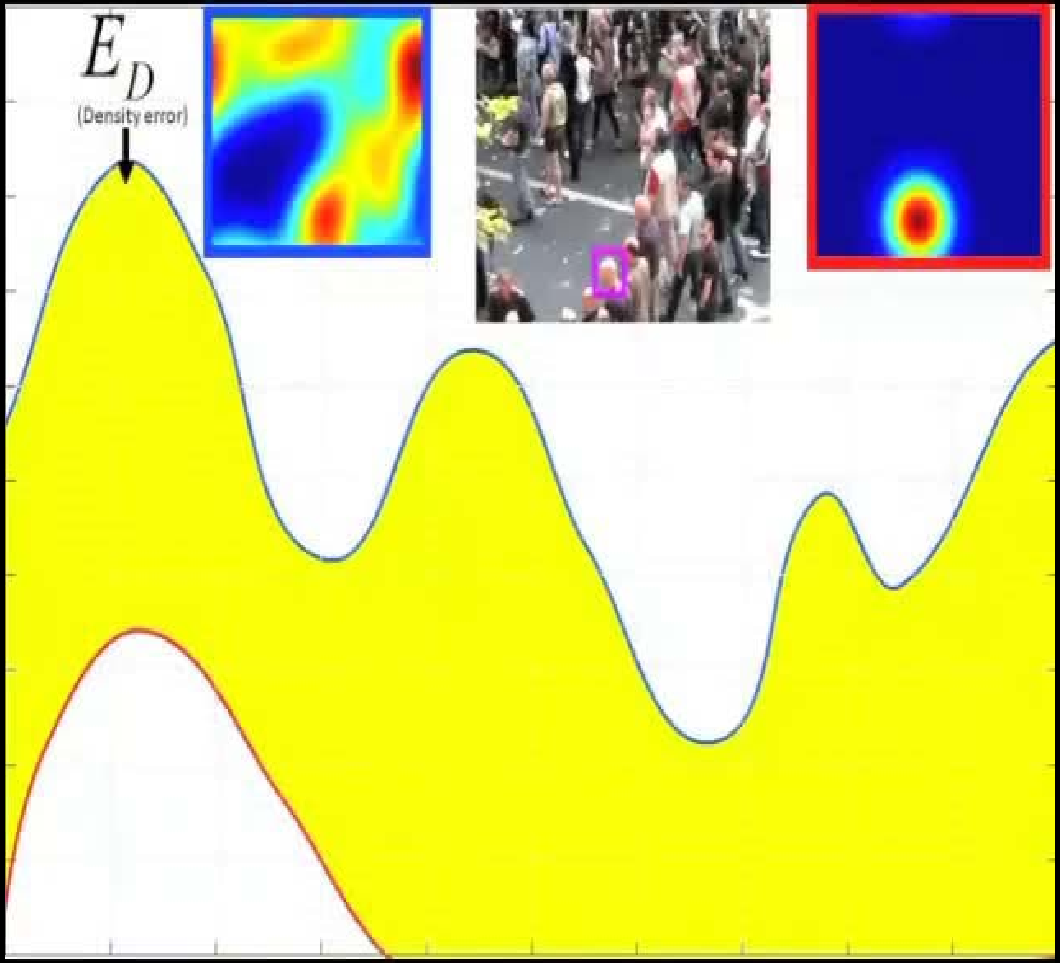




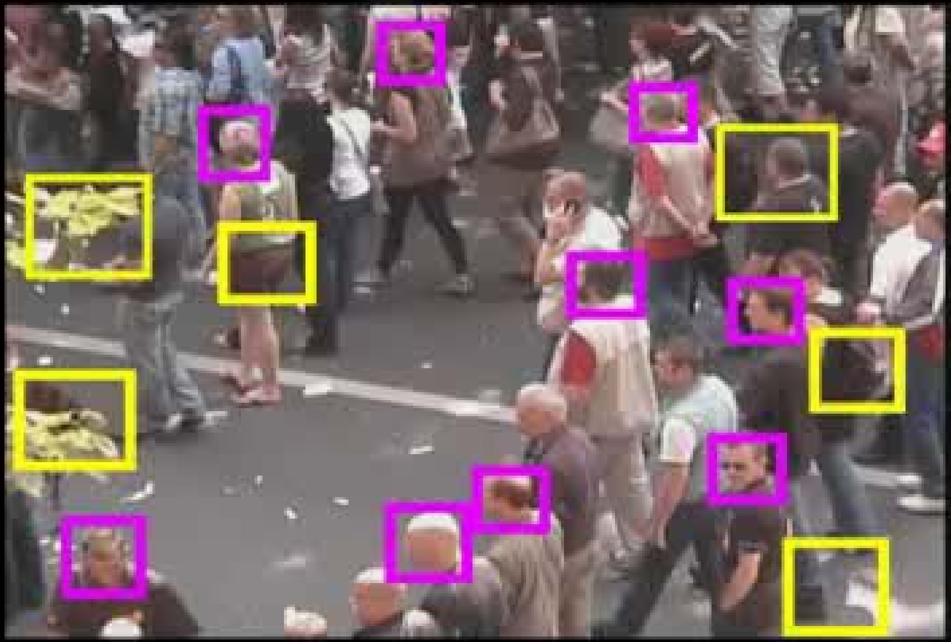
Optimization

- NP-hard problem
- We adopt a greedy search procedure

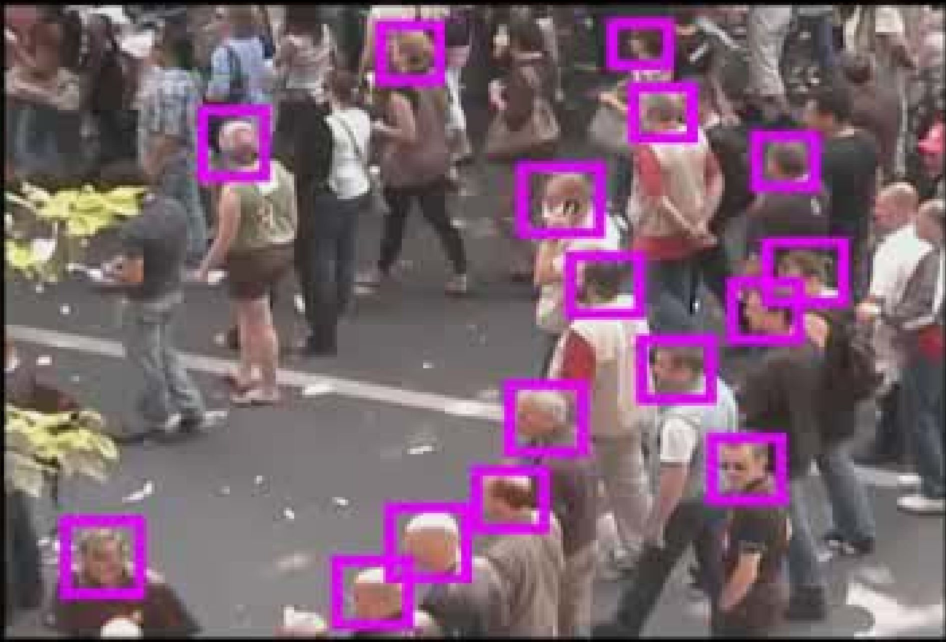
1D illustrative animation



Results and Evaluation



Baseline



Density-aware

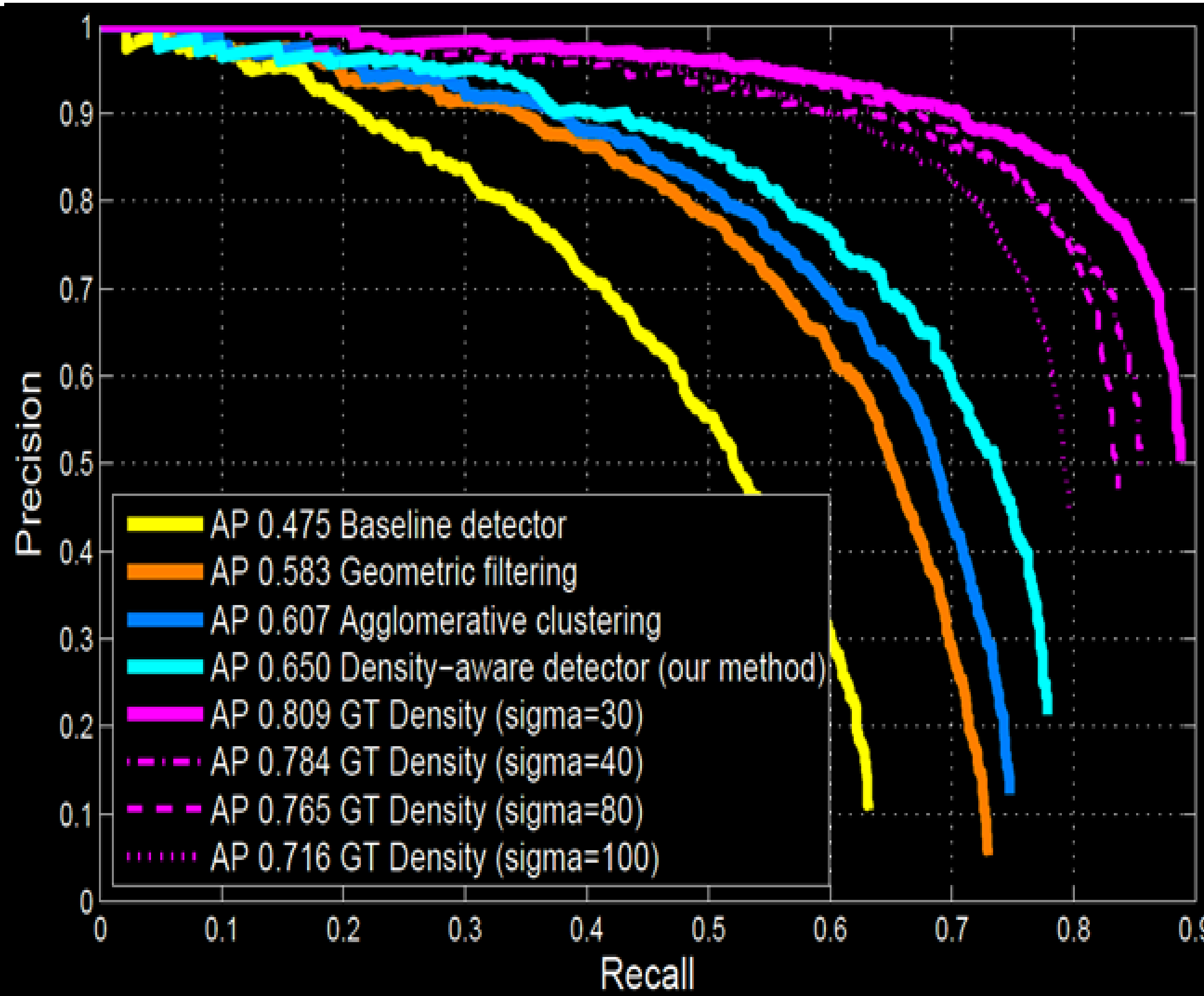
Incorrect track

Baseline

Density-aware

Incorrect track

Detection Evaluation

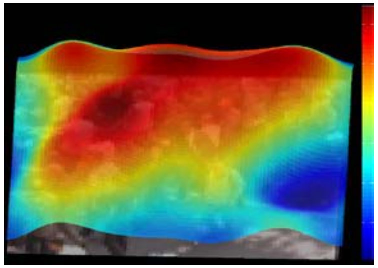


Inrernship Topic 1

Person Detection and Tracking in Crowds

Willow team, advisors: Ivan Laptev and Josef Sivic

http://www.di.ens.fr/willow/teaching/recvis11/internships



Goals:

- Improve person detection and tracking with *better person density estimation.*
- Leverage space-time constraints with *density-aware track detection.*
- Address new research problems such as person *detection and tracking in low resolution video*

Potential outcomes:

- Impact on the very active and challenging research domain
- Conference/journal publication and the start of a PhD thesis

What to do about The Object That Cannot Be Named?

Slides by Derek Hoiem
Computer Science Department
University of Illinois at Urbana- Champaign

A. Farhadi, I. Endres, and D. Hoiem 2010

A failure/success story

A. Farhadi, I. Endres, and D. Hoiem 2010

Photo by Ivan Makarov

Dealing with inevitable failure

Failure in categorization should not mean failure in recognition

A. Farhadi, I. Endres, and D. Hoiem 2010

What to do about the

Object That Cannot Be Named?

A. Farhadi, I. Endres, and D. Hoiem 2010

Example

Assisted Driving

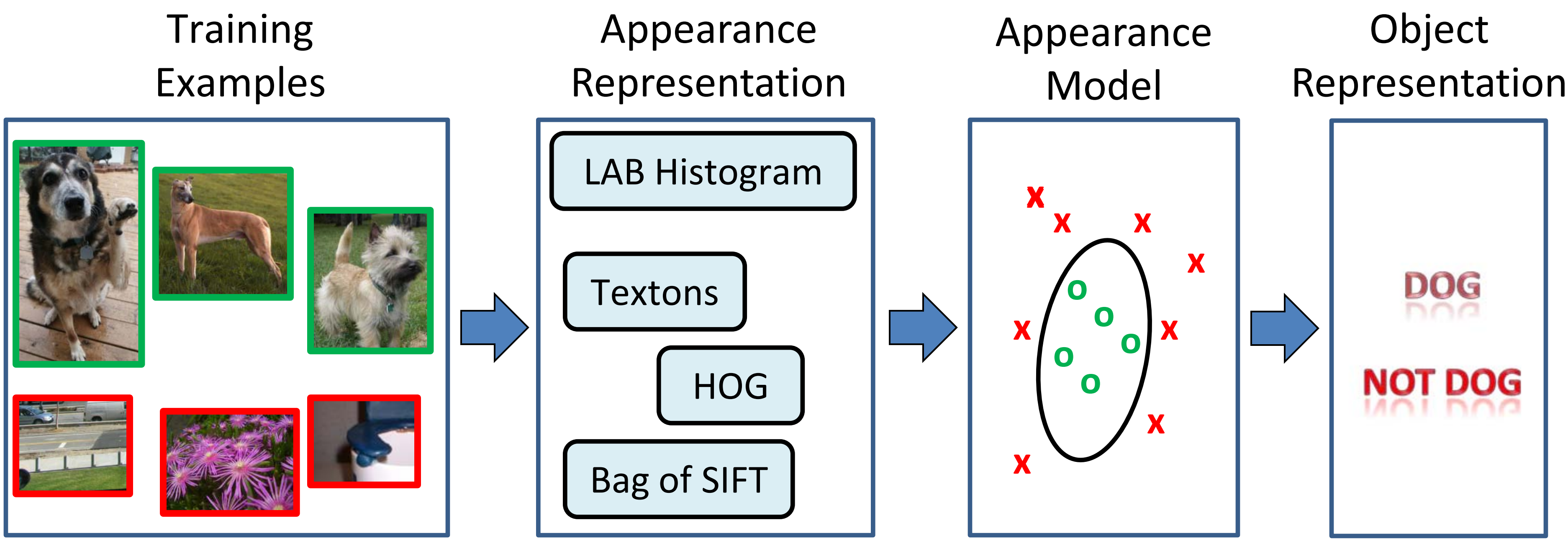
A. Farhadi, I. Endres, and D. Hoiem 2010

Example

Security

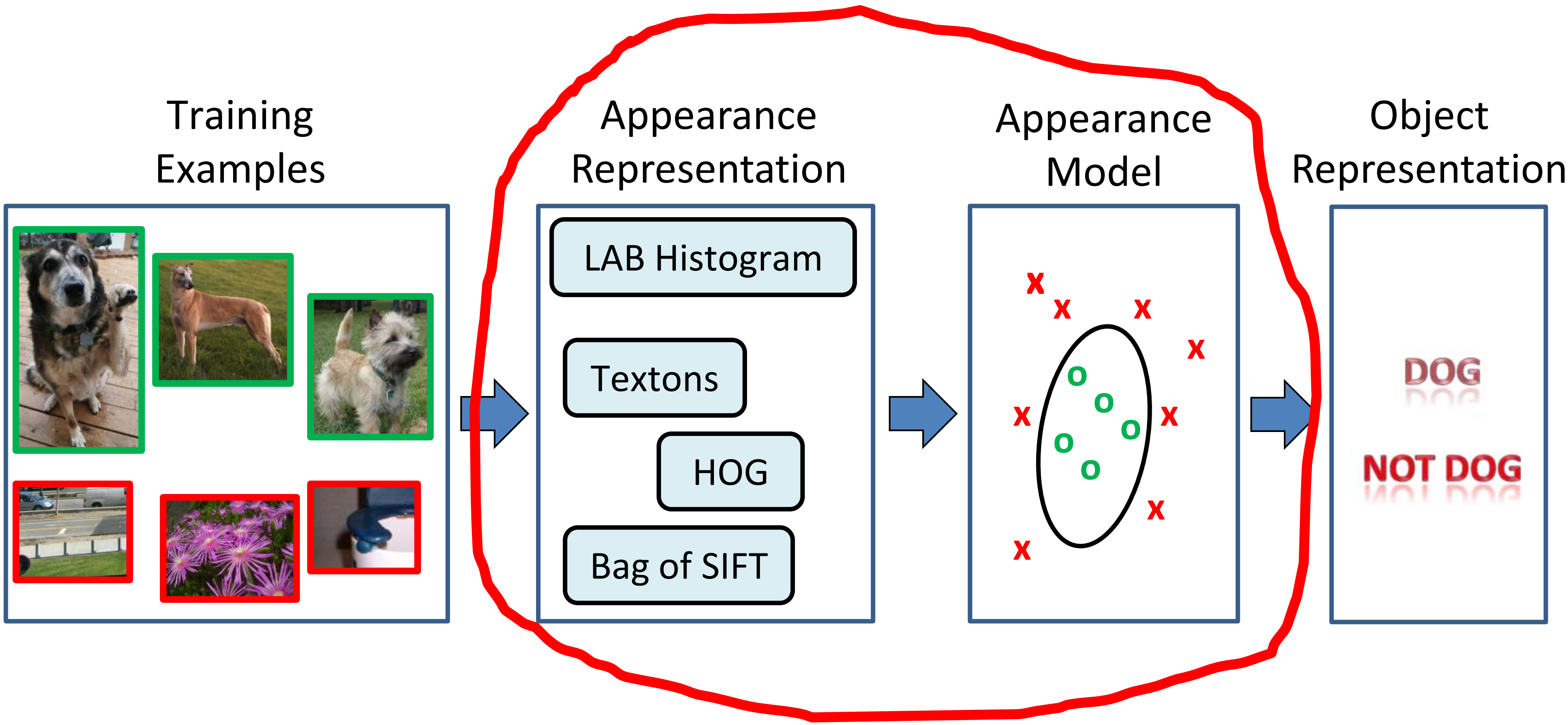
A. Farhadi, I. Endres, and D. Hoiem 2010

Current View of Recognition



A. Farhadi, I. Endres, and D. Hoiem 2010

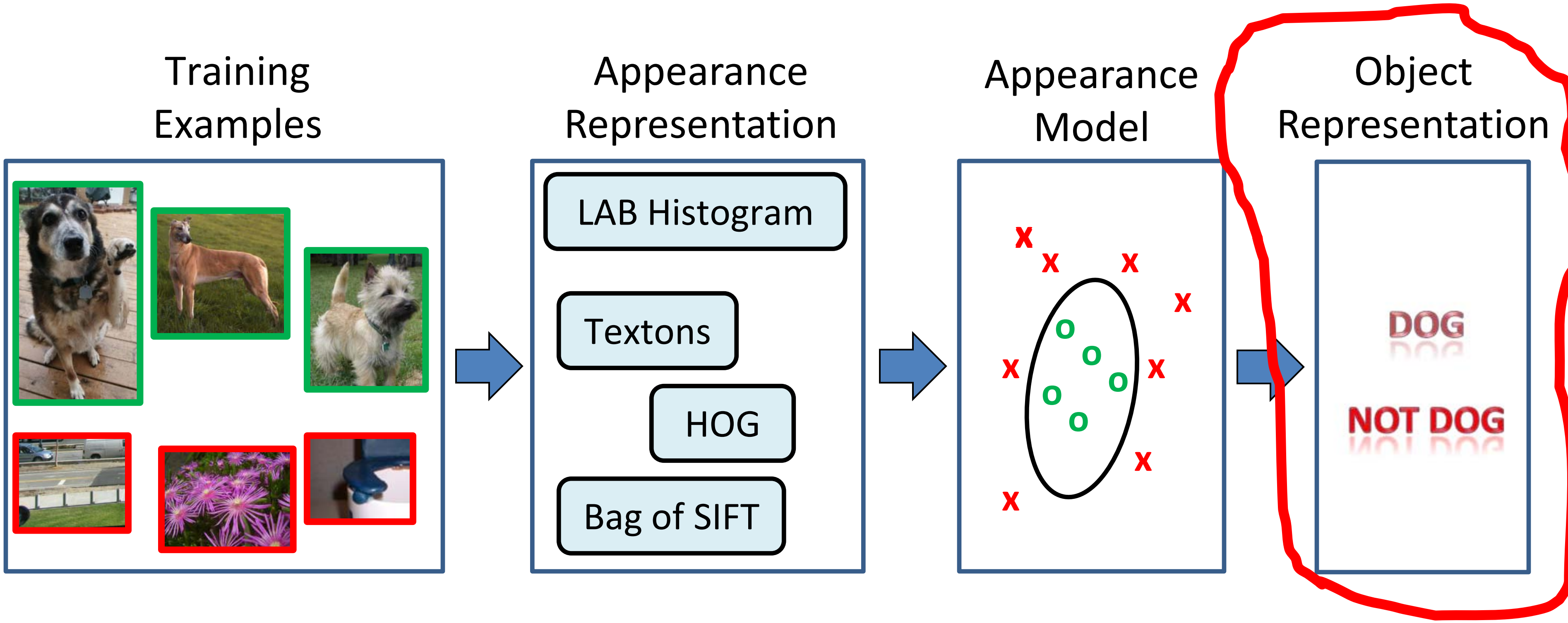
Current View of Recognition



Lots of effort – fancy stuff

A. Farhadi, I. Endres, and D. Hoiem 2010

Current View of Recognition



Not much changed

A. Farhadi, I. Endres, and D. Hoiem 2010

Category-based representation

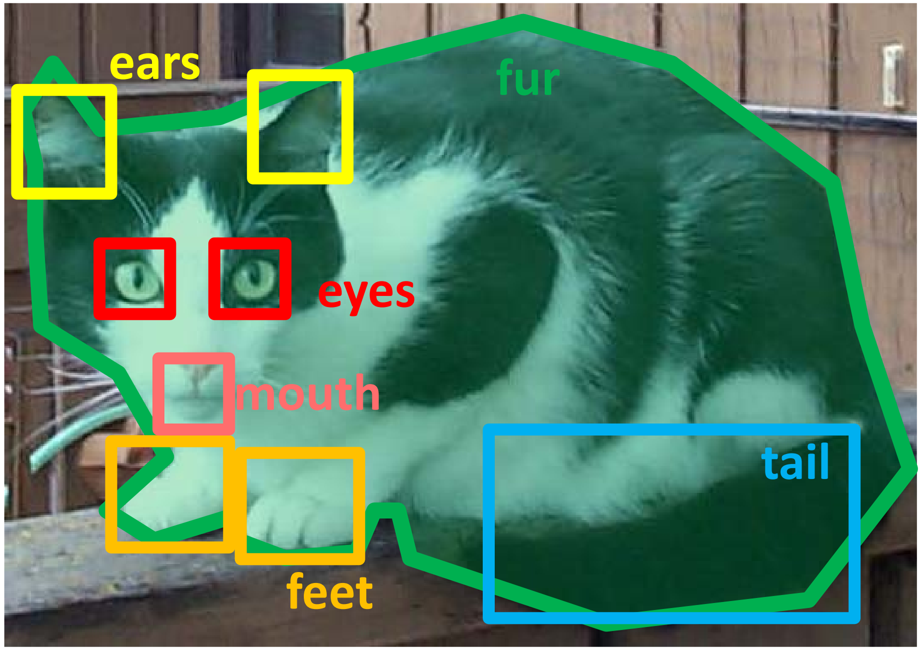
- Limited description and prediction
- No generalization to objects outside of learned categories
- Provides little guidance for learning

So what would make a better representation?

A. Farhadi, I. Endres, and D. Hoiem 2010

Attribute-based Representation

- Properties that we want to describe or predict
- Shared across basic categories
- Made explicit through supervision



Multiple Categories
animal, land animal, ..., cat

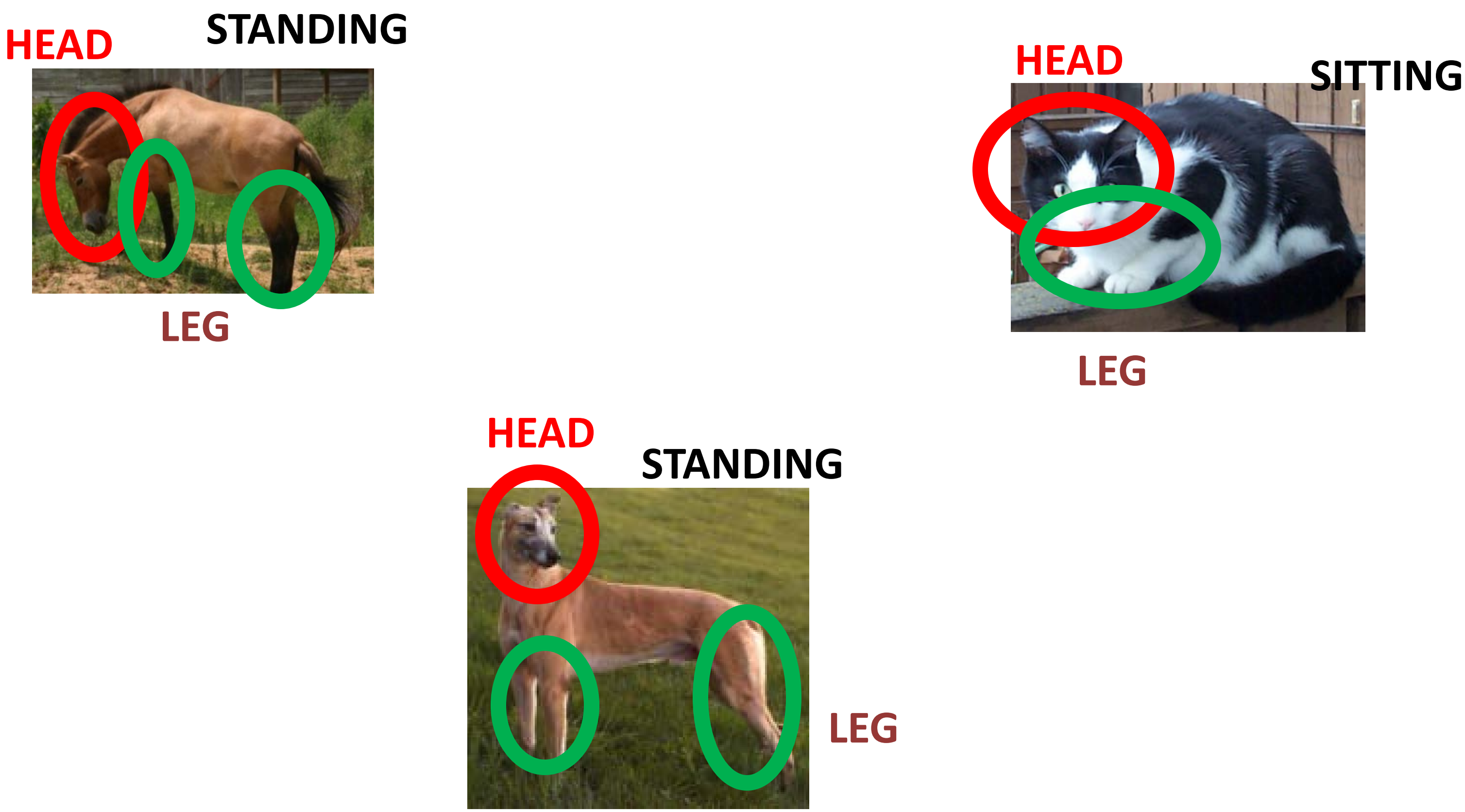
Viewpoint/pose
lying down, left side, facing camera

Function
fast runner, climb trees, eat small animals, jump high, household pet, scratch

A. Farhadi, I. Endres, and D. Hoiem 2010

Advantages of supervised attributes

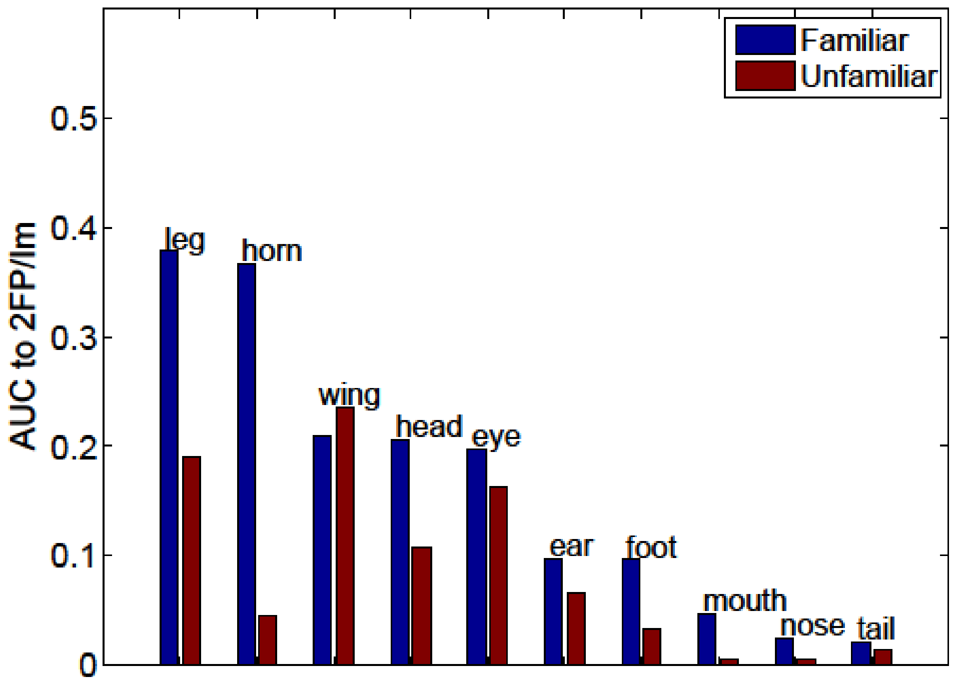
- Provides correspondence for objects from different categories



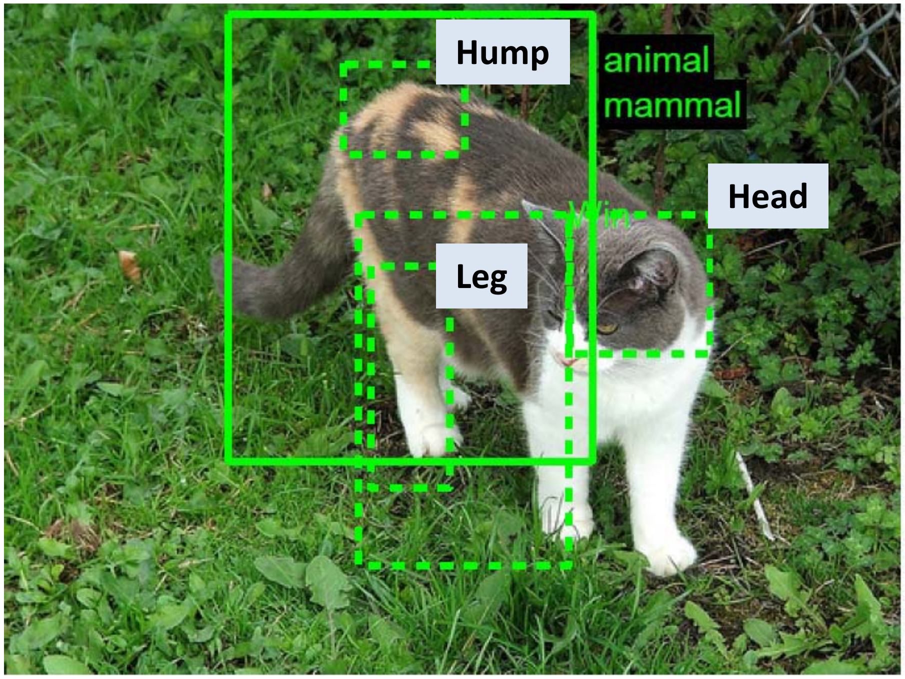
A. Farhadi, I. Endres, and D. Hoiem 2010

Result: Part detectors can generalize across categories

Animal Parts

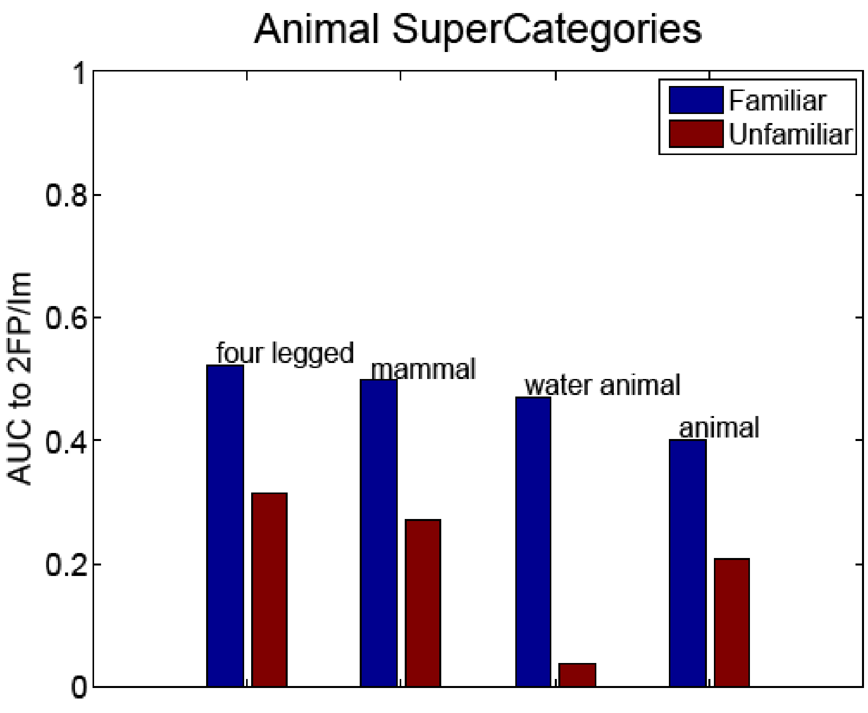


Part Detections for Novel Object

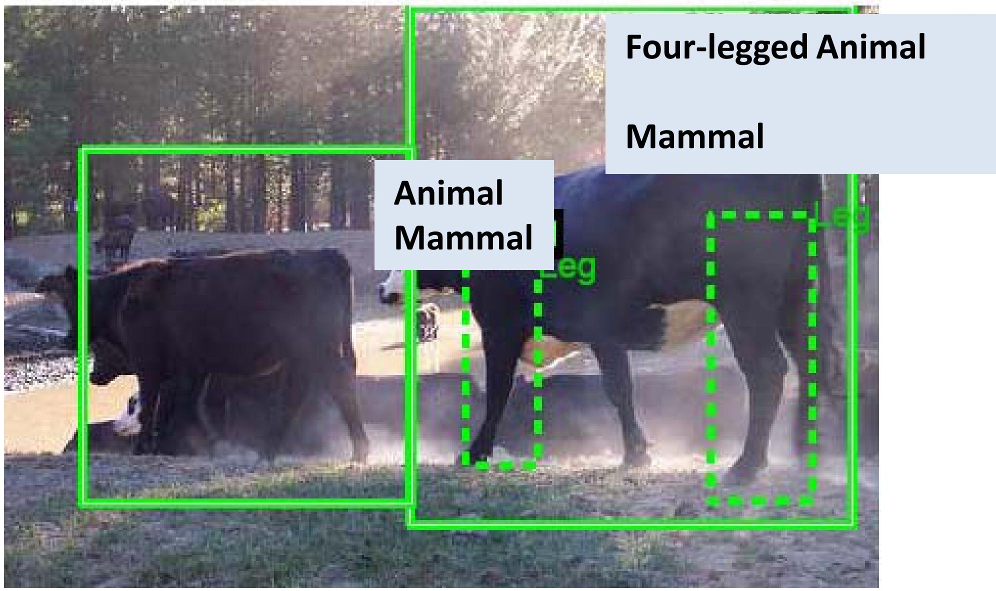


Detectors trained using (Felzenszwalb Girshik McAllester Ramanan 2009) method

Result: Broad category detectors can generalize across basic categories

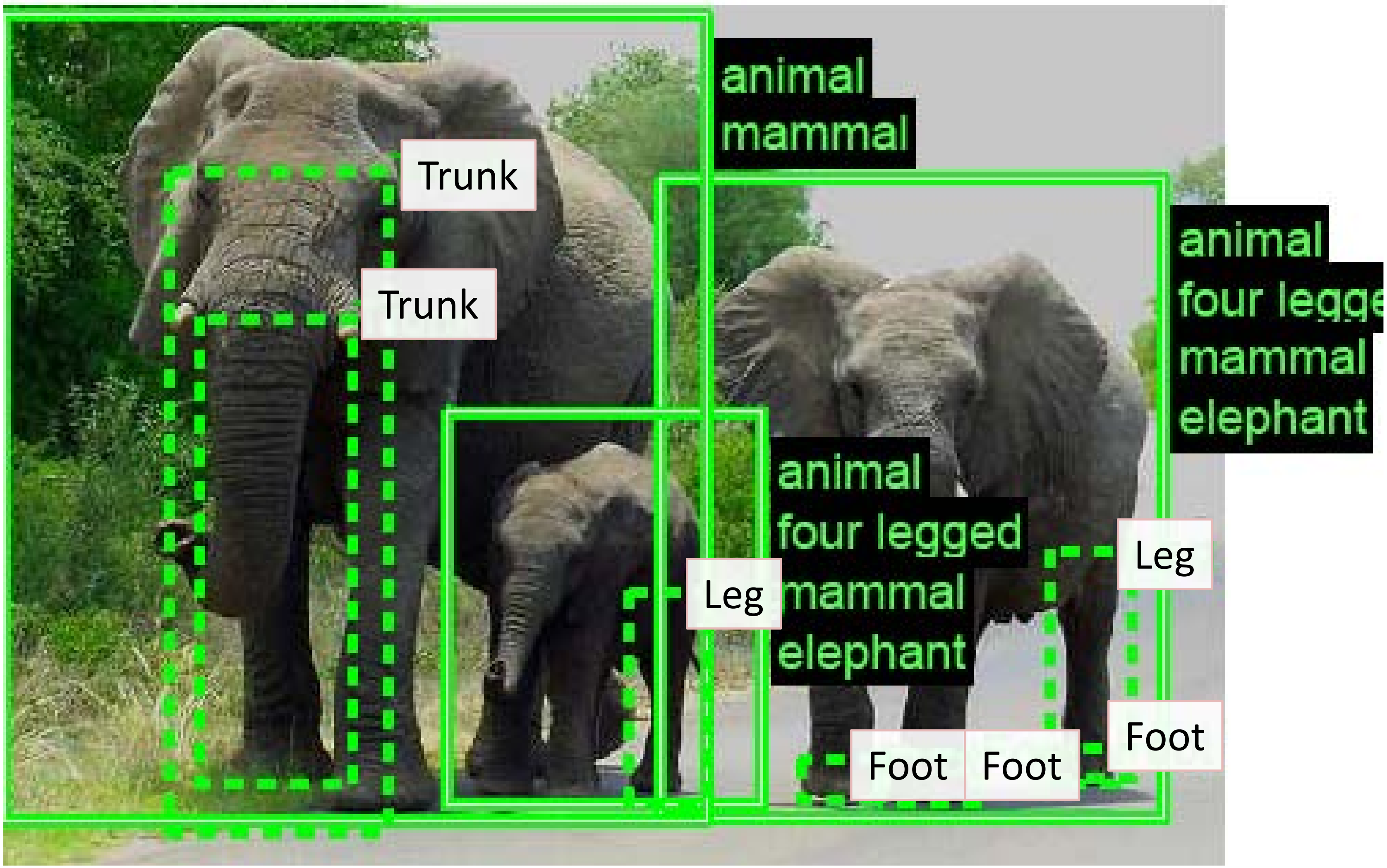


Category Detections for Novel Object



Detectors trained using (Felzenszwalb Girshik McAllester Ramanan 2009) method

Result: We can better find and describe objects from familiar categories

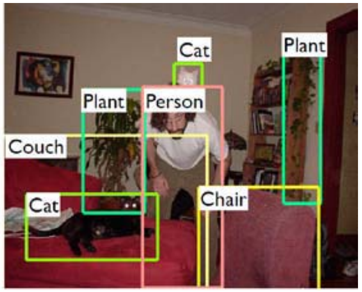


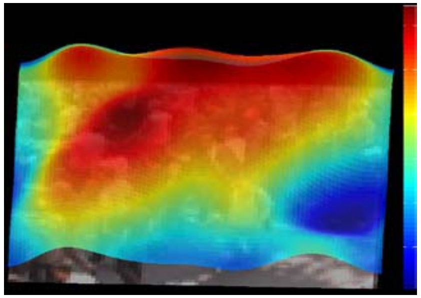
A. Farhadi, I. Endres, and D. Hoiem 2010

What we have seen so far?

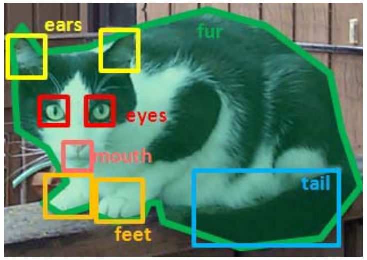
- Objects in the context of scenes.

- Objects in relation with each other





- Objects defined by parts and attributes

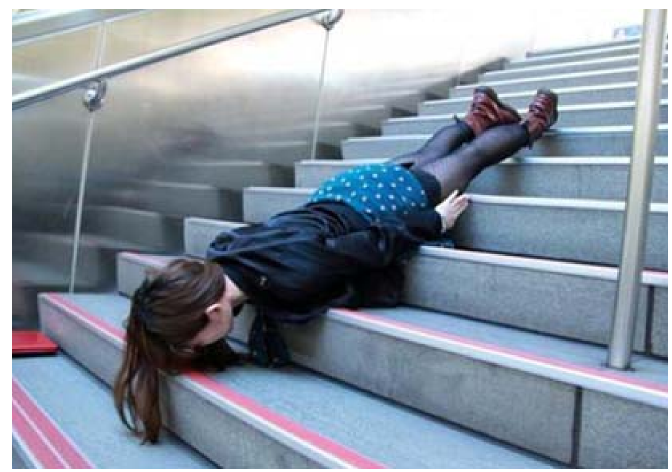


Is this the end of the story?


cat
woman
trash bin

It seems important to recognize object use



How to reason about typical / non-typical object use?

The perception of function

- Direct perception (affordances): Gibson (70s-80s)

Flat surface
Horizontal
Knee-high
… → Sittable upon

- Mediated perception (Categorization)

Flat surface
Horizontal
Knee-high
… → Chair → Sittable upon