

# Computer Vision - Lecture 15

## Part-based Models for Object Categorization

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# Course Outline

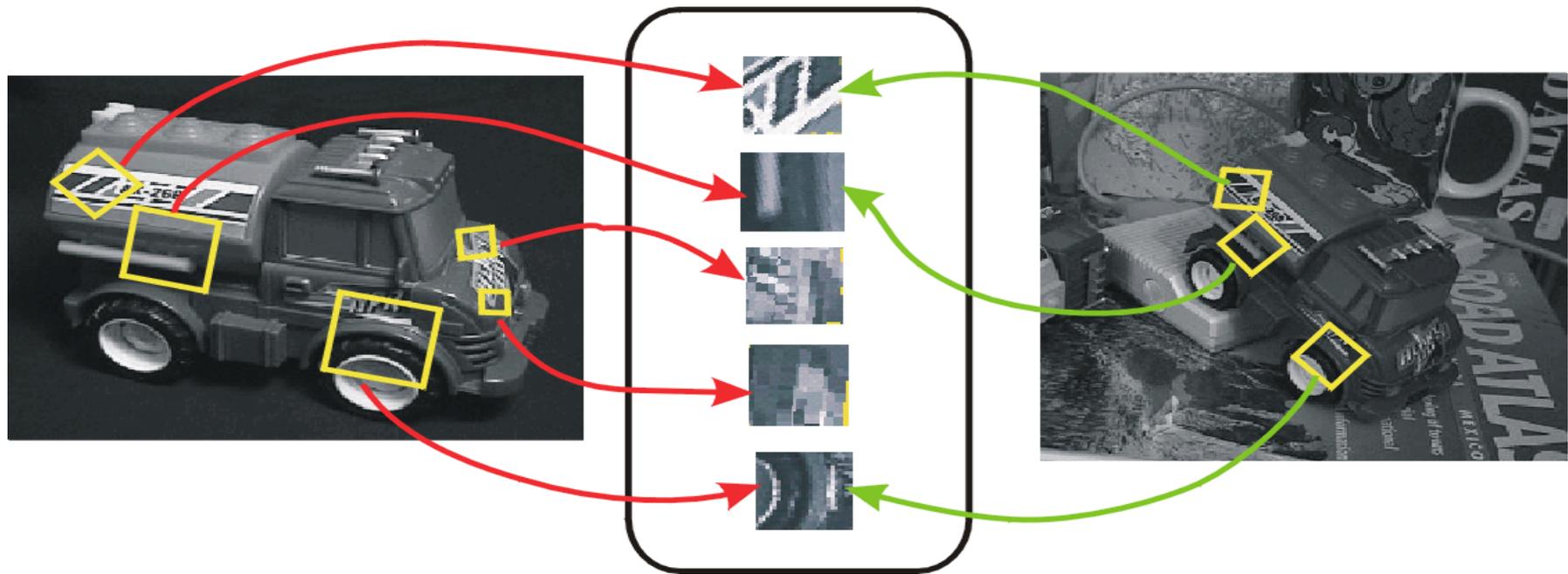
- Image Processing Basics
- Segmentation & Grouping
- Object Recognition
- Object Categorization I
  - Sliding Window based Object Detection
- Local Features & Matching
  - Local Features - Detection and Description
  - Recognition with Local Features
  - Indexing & Visual Vocabularies
- Object Categorization II
  - Bag-of-Words Approaches & Part-based Approaches
  - Deep Learning Methods
- 3D Reconstruction

# Topics of This Lecture

- **Recap: Specific Object Recognition with Local Features**
  - Matching & Indexing
  - Geometric Verification
- **Part-Based Models for Object Categorization**
  - Structure representations
  - Different connectivity structures
- **Bag-of-Words Model**
  - Use for image classification
- **Implicit Shape Model**
  - Generalized Hough Transform for object category detection
- **Deformable Part-based Model**
  - Discriminative part-based detection

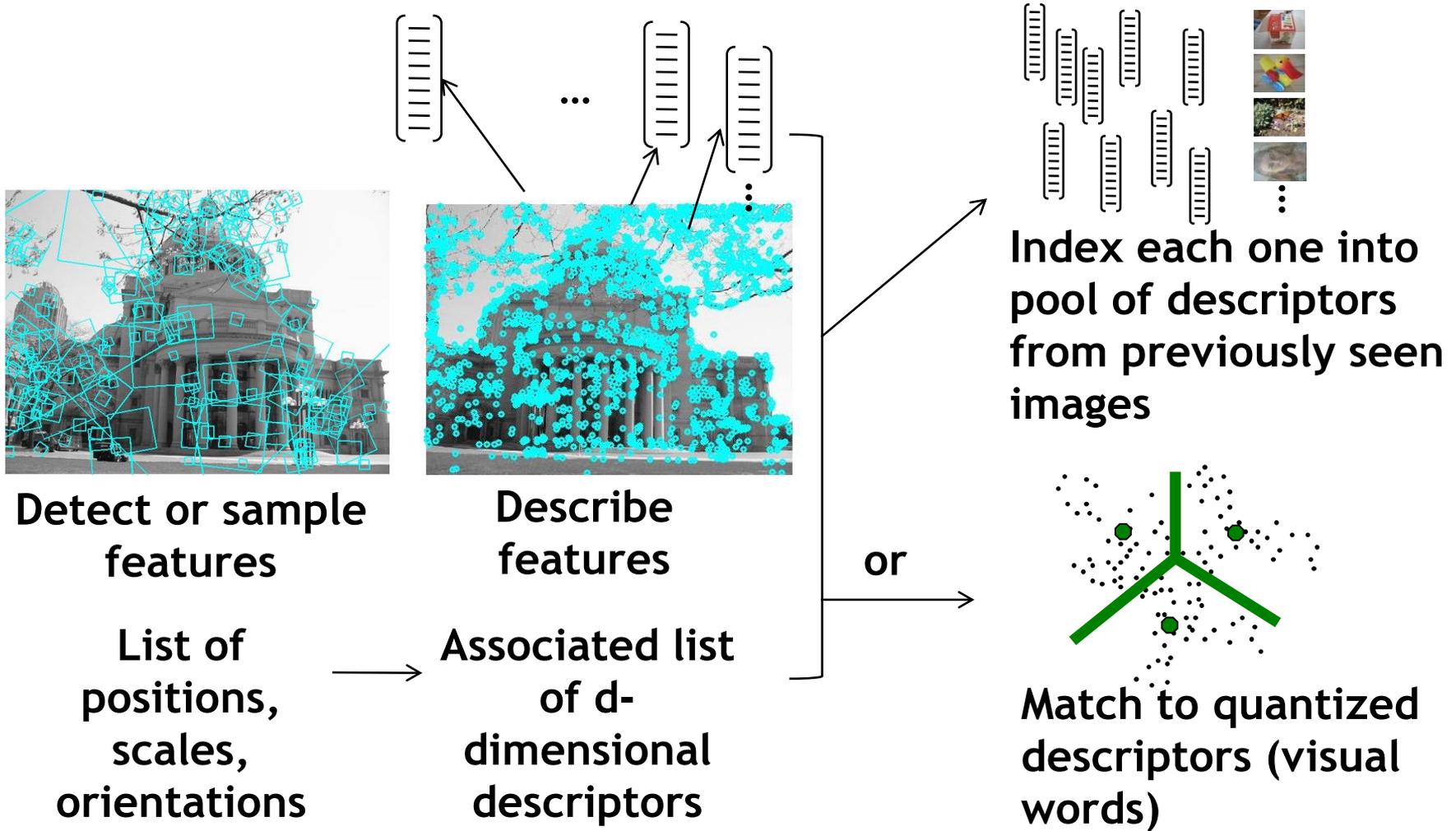
# Recap: Recognition with Local Features

- Image content is transformed into local features that are invariant to translation, rotation, and scale
- Goal: Verify if they belong to a consistent configuration



Local Features,  
e.g. SIFT

# Recap: Indexing features



⇒ *Shortlist of possibly matching images + feature correspondences*

# Extension: *tf-idf* Weighting

- **Term frequency - inverse document frequency**
  - Describe frame by frequency of each word within it, downweight words that appear often in the database
  - (Standard weighting for text retrieval)

Number of occurrences of word  $i$  in document  $d$

Number of words in document  $d$

$$t_i = \frac{n_{id}}{n_d} \log \frac{N}{n_i}$$

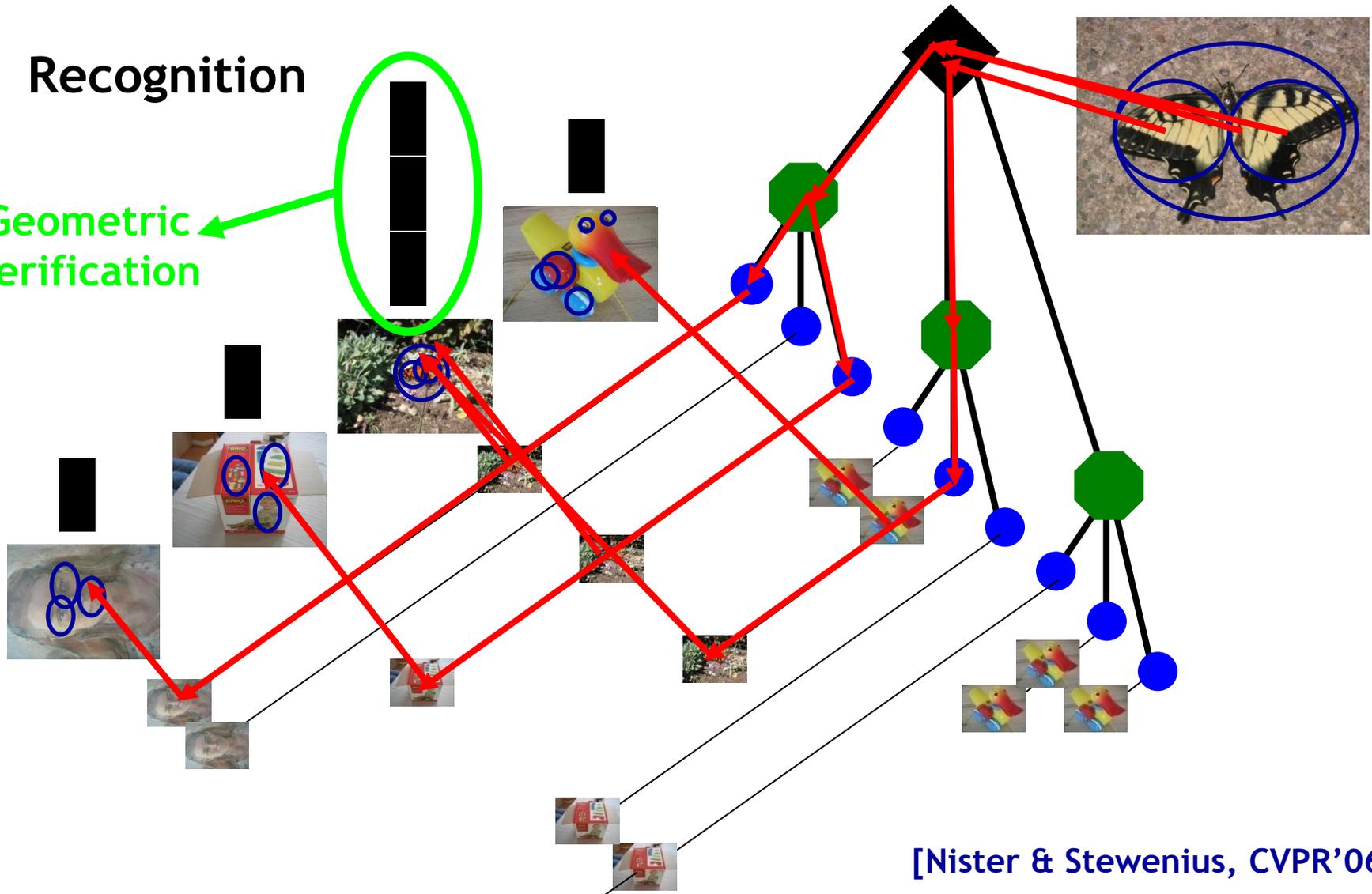
Total number of documents in database

Number of occurrences of word  $i$  in whole database

# Recap: Fast Indexing with Vocabulary Trees

- Recognition

Geometric verification



[Nister & Stewenius, CVPR'06]

# Recap: Geometric Verification by Alignment

- Assumption
  - Known object, rigid transformation compared to model image
  - ⇒ *If we can find evidence for such a transformation, we have recognized the object.*

- You learned methods for

- Fitting an *affine transformation* from  $\geq 3$  correspondences
- Fitting a *homography* from  $\geq 4$  correspondences

Affine: solve a system

$$At = b$$

Homography: solve a system

$$Ah = 0$$

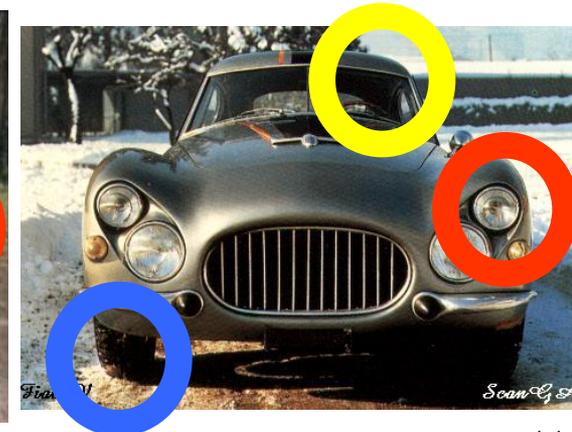
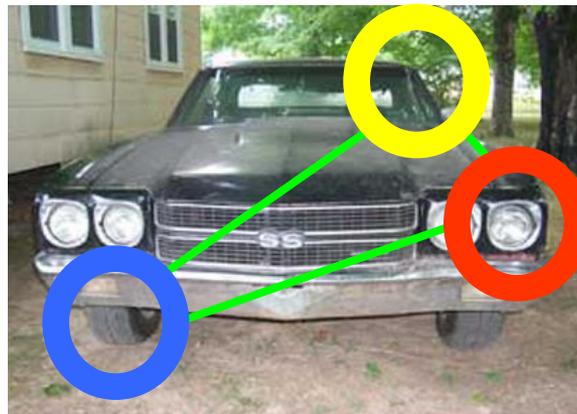
- Correspondences may be noisy and may contain outliers
  - ⇒ Need to use robust methods that can filter out outliers
  - ⇒ Use **RANSAC** or the **Generalized Hough Transform**

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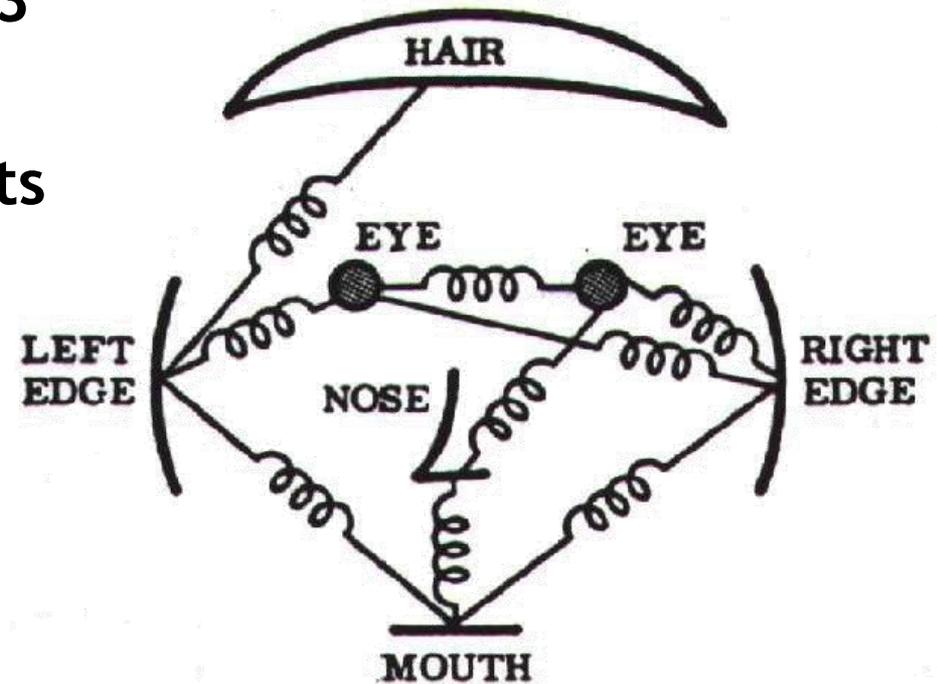
# Recognition of Object Categories

- We no longer have exact correspondences...
- On a local level, we can still detect similar parts.
- Represent objects by their parts  
⇒ Bag-of-features
- How can we improve on this?
  - Encode structure

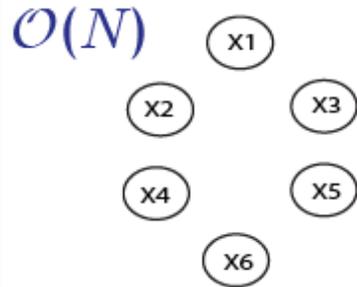


# Part-Based Models

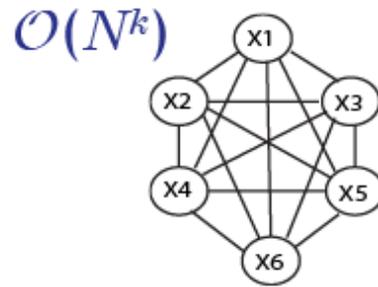
- Fischler & Elschlager 1973
- Model has two components
  - parts  
(2D image fragments)
  - structure  
(configuration of parts)



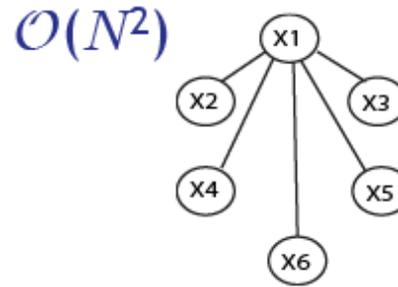
# Different Connectivity Structures



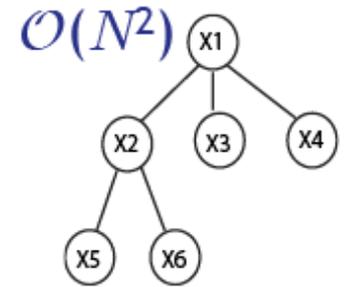
a) Bag of visual words  
Csurka et al. '04  
Vasconcelos et al. '00



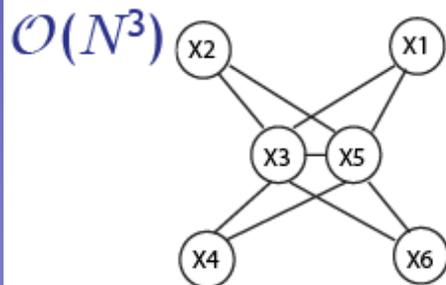
b) Constellation  
Fergus et al. '03  
Fei-Fei et al. '03



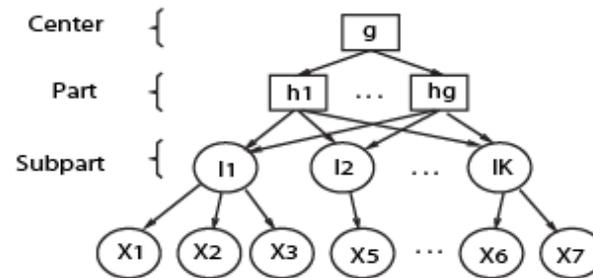
c) Star shape  
Leibe et al. '04, '08  
Crandall et al. '05  
Fergus et al. '05



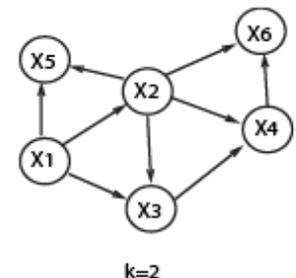
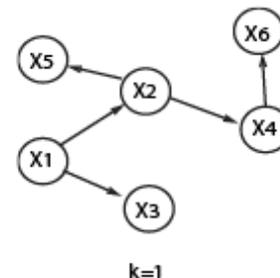
d) Tree  
Felzenszwalb & Huttenlocher '05



e) k-fan ( $k = 2$ )  
Crandall et al. '05



f) Hierarchy  
Bouchard & Triggs '05



g) Sparse flexible model  
Carneiro & Lowe '06

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# Recap: Analogy to Documents

Of all the sensory impressions proceeding to the brain, the visual experiences are the dominant ones. Our perception of the world around us is based essentially on the messages that the brain receives from our eyes. For many years it was thought that the retina was the only point by which the visual information entered the brain; this view was overturned by the discovery of the optic chiasm. In the 1950s, Hubel and Wiesel discovered that the visual system knows the difference between the perception of a vertical line and a horizontal line. In the 1960s, Hubel and Wiesel discovered that the visual system considers the orientation of lines as important events. By following the visual pathway along their path through the layers of the optical cortex, Hubel and Wiesel have been able to demonstrate that the message about the image falling on the retina undergoes a step-wise analysis by a system of nerve cells stored in columns. In this system each cell has its specific function and is responsible for a specific detail in the pattern of the retinal image.

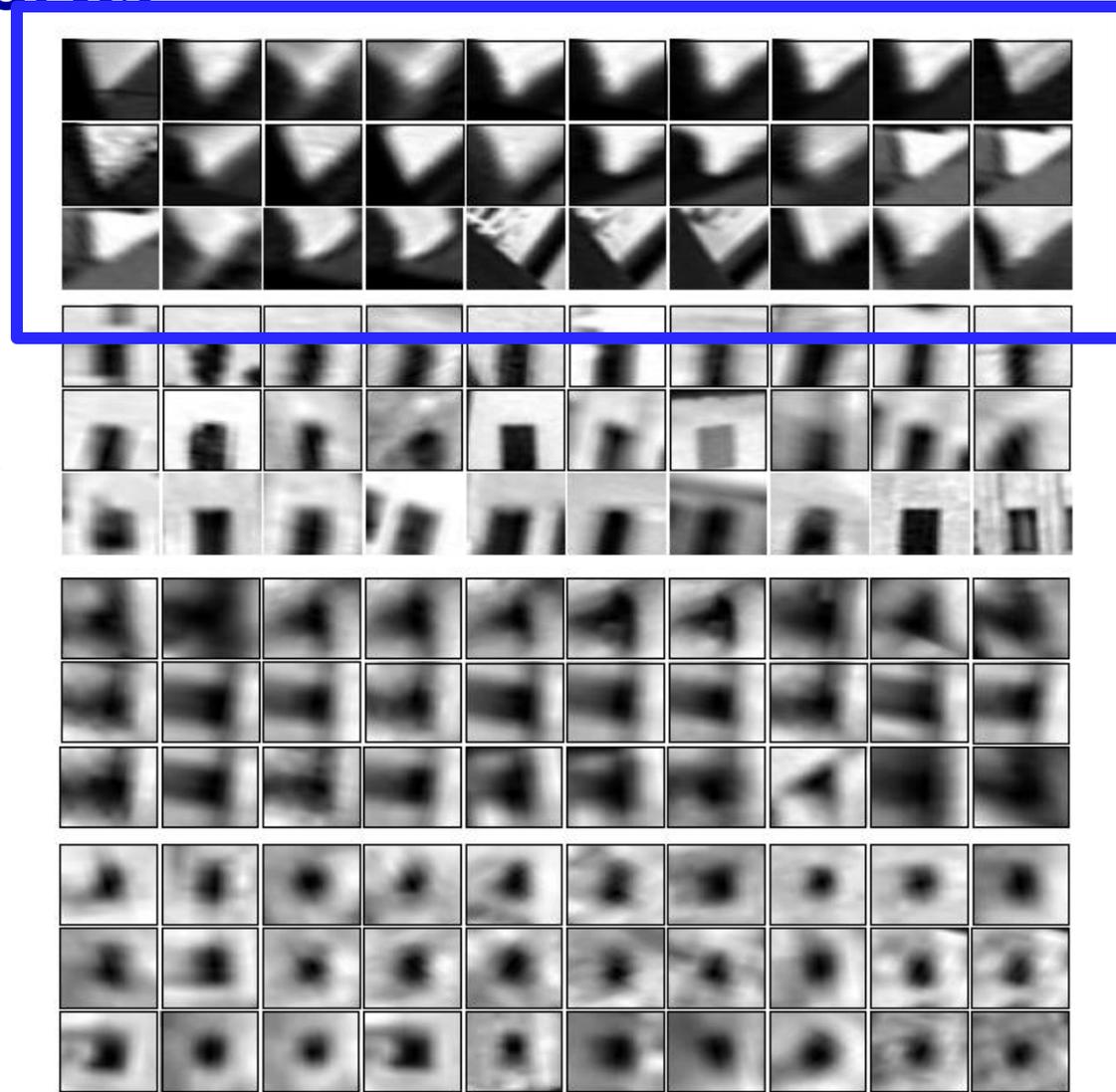
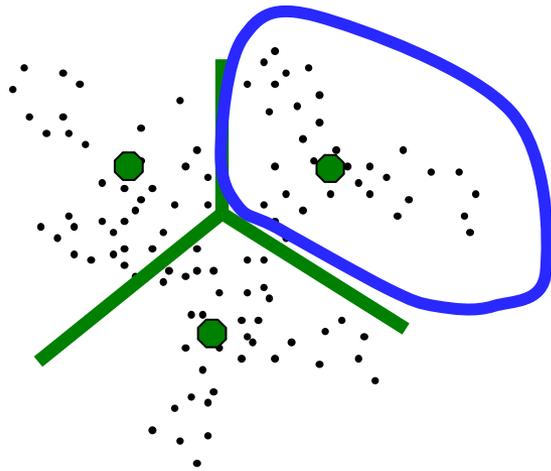
**sensory, brain,  
visual, perception,  
retinal, cerebral cortex,  
eye, cell, optical  
nerve, image  
Hubel, Wiesel**

China is forecasting a trade surplus of \$90bn (£51bn) to \$100bn this year, a threefold increase on 2004's \$32bn. The Commerce Ministry said the surplus would be created by a 30% jump in exports to \$100bn, with a 18% rise in imports. The figures are likely to be revised. China has long complained that the US has long had an unfair trade policy under which it has a trade surplus. Zhou Xiaochuan, head of the People's Bank of China, said only one way to deal with the surplus was to let the yuan rise. Zhou said the yuan needed to rise by 20% to meet the demand so many companies stay in the country. China increased the value of the yuan against the dollar by 2.1% in 2005 and permitted it to trade within a narrow band, but the US wants the yuan to be allowed to trade freely. However, Beijing has made it clear that it will take its time and tread carefully before allowing the yuan to rise further in value.

**China, trade,  
surplus, commerce,  
exports, imports, US,  
yuan, bank, domestic,  
foreign, increase,  
trade, value**

# Recap: Visual Words

- Quantize the feature space into “visual words”
- Perform matching only to those visual words.



Exact feature matching → Match to same visual word

# Recap: Bag-of-Words Representations (BoW)



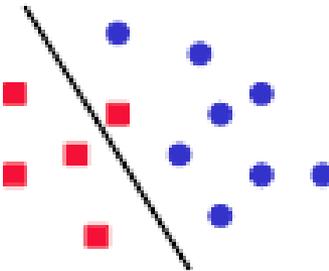
# Recap: Categorization with Bags-of-Words



- Compute the word activation histogram for each image.
- Let each such BoW histogram be a feature vector.
- Use images from each class to train a classifier (e.g., an SVM).

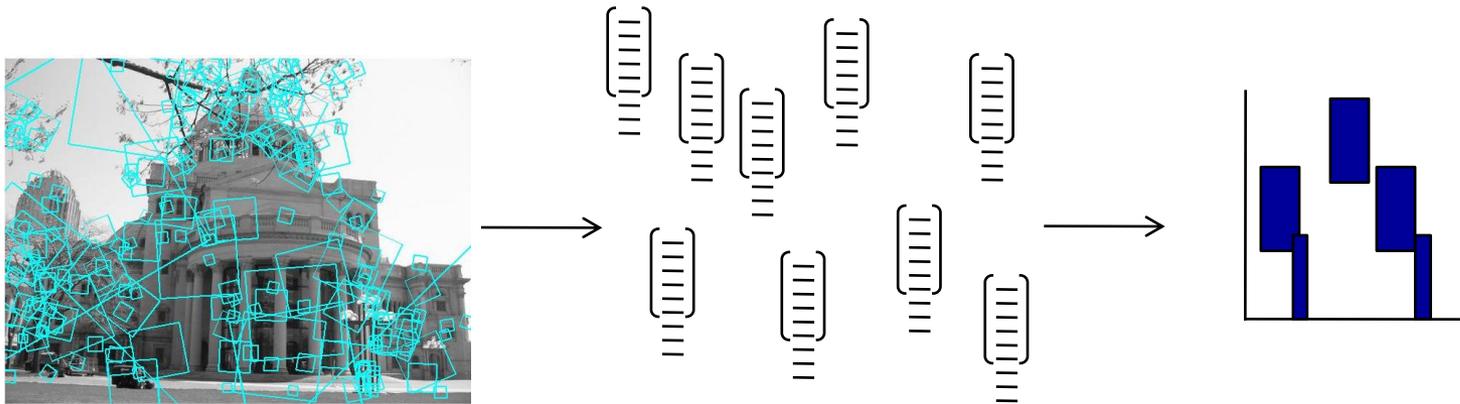


Violins



# Recap: Advantage of BoW Histograms

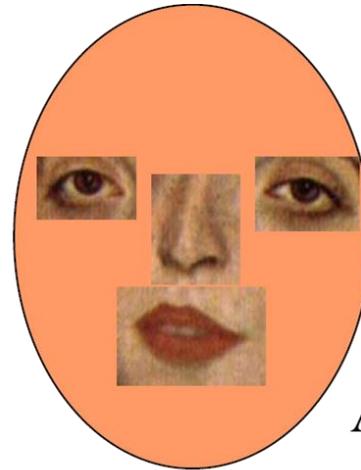
- Bag of words representations make it possible to describe the unordered point set with a single vector (of fixed dimension across image examples).



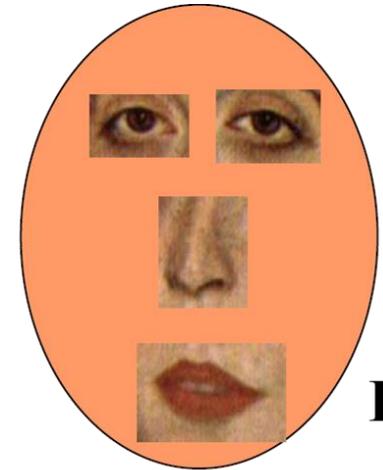
- Provides easy way to use distribution of feature types with various learning algorithms requiring vector input.

# Limitations of BoW Representations

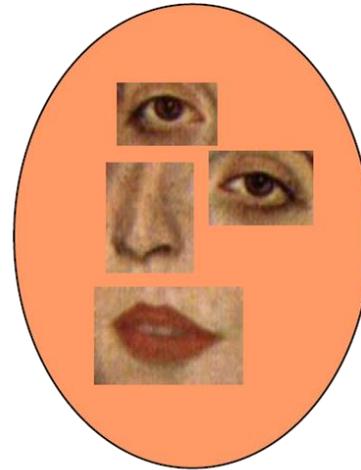
- The bag of words removes spatial layout.
- This is both a strength and a weakness.
- *Why a strength?*
- *Why a weakness?*



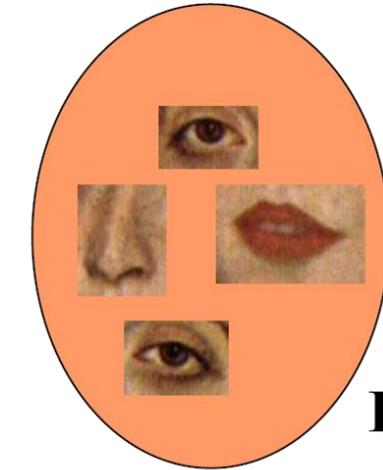
A



B



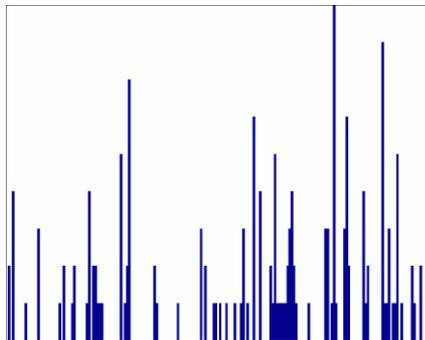
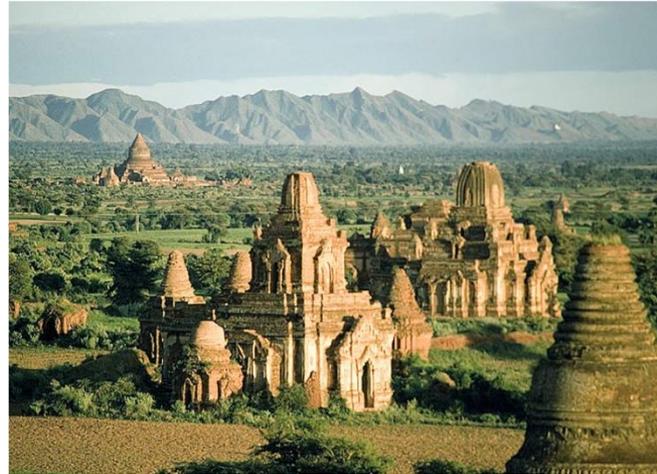
C



D

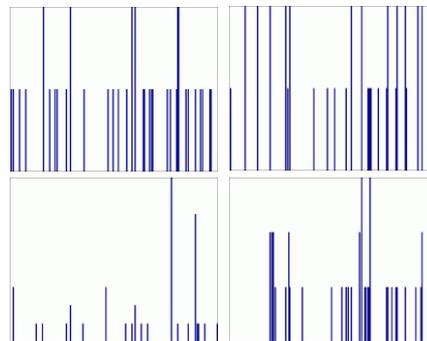
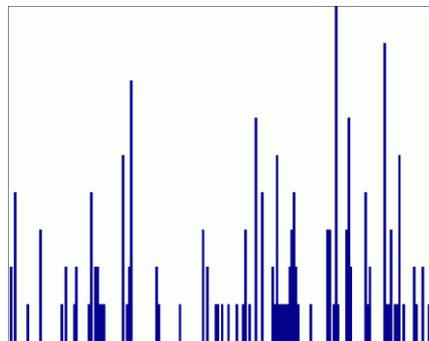
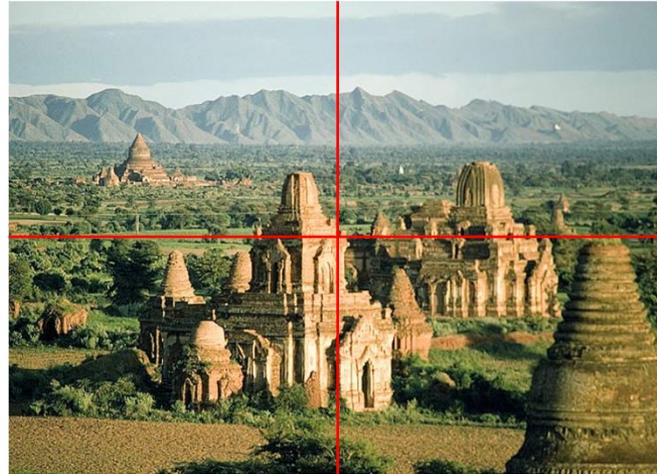
# Spatial Pyramid Representation

- Representation in-between orderless BoW and global appearance



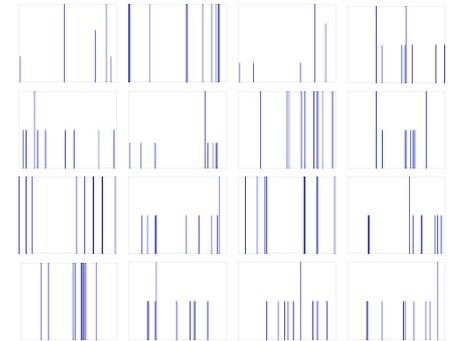
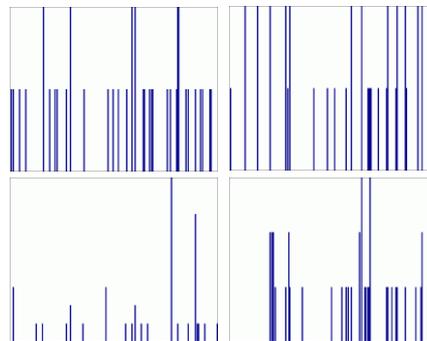
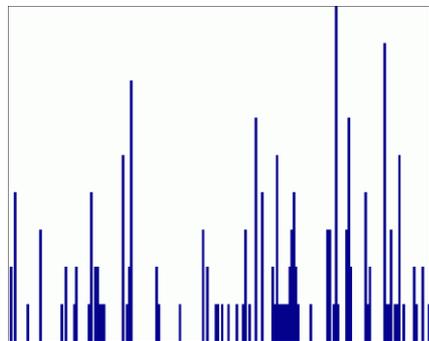
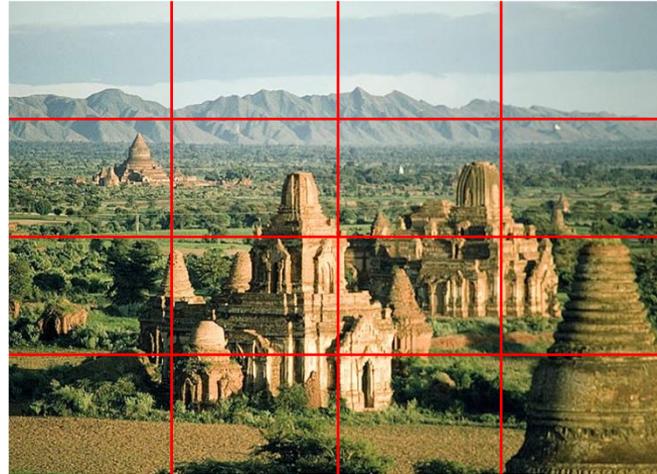
# Spatial Pyramid Representation

- Representation in-between orderless BoW and global appearance



# Spatial Pyramid Representation

- Representation in-between orderless BoW and global appearance



# Summary: Bag-of-Words

- Pros:

- Flexible to geometry / deformations / viewpoint
- Compact summary of image content
- Provides vector representation for sets
- Empirically good recognition results in practice

- Cons:

- Basic model ignores geometry - must verify afterwards, or encode via features.
- Background and foreground mixed when bag covers whole image
- When using interest points or sampling: no guarantee to capture object-level parts  $\Rightarrow$  Dense sampling is often better.

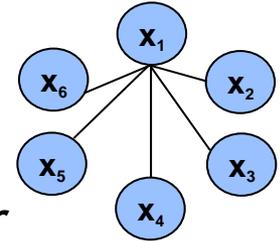
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  - Structure representations
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# Implicit Shape Model (ISM)

- **Basic ideas**

- Learn an appearance codebook
- Learn a star-topology structural model
  - Features are considered independent given obj. center

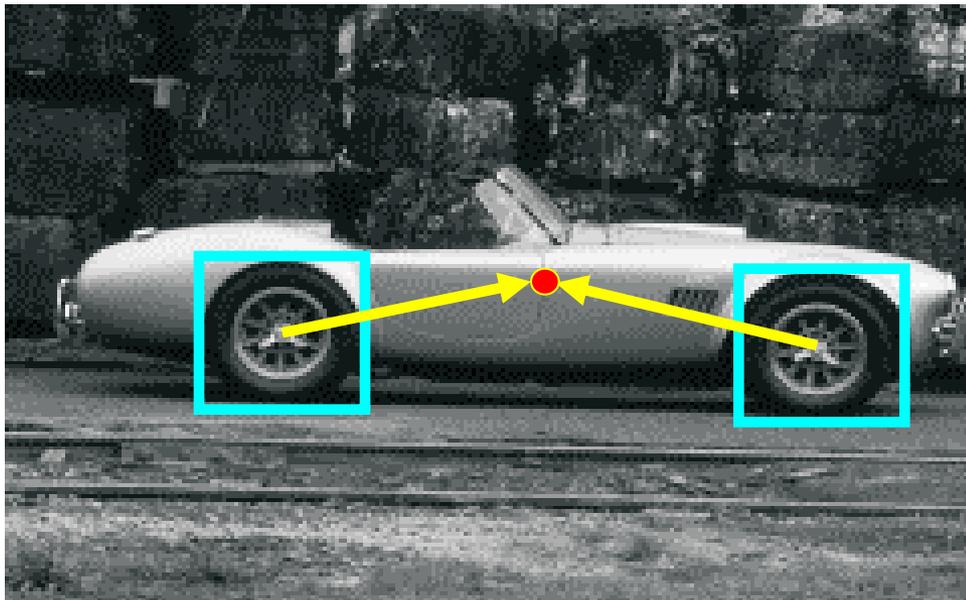


- **Algorithm: probabilistic Gen. Hough Transform**

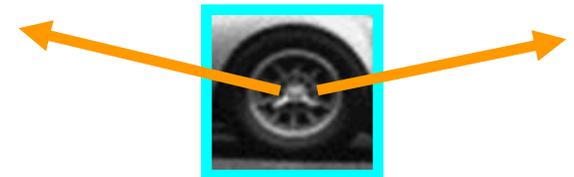
- Exact correspondences → Prob. match to object part
- NN matching → Soft matching
- Feature location on obj. → Part location distribution
- Uniform votes → Probabilistic vote weighting
- Quantized Hough array → Continuous Hough space

# Implicit Shape Model: Basic Idea

- Visual vocabulary is used to index votes for object position [a visual word = “part”].



Training image



Visual codeword with displacement vectors

B. Leibe, A. Leonardis, and B. Schiele, [Robust Object Detection with Interleaved Categorization and Segmentation](#), International Journal of Computer Vision, Vol. 77(1-3), 2008.

# Implicit Shape Model: Basic Idea

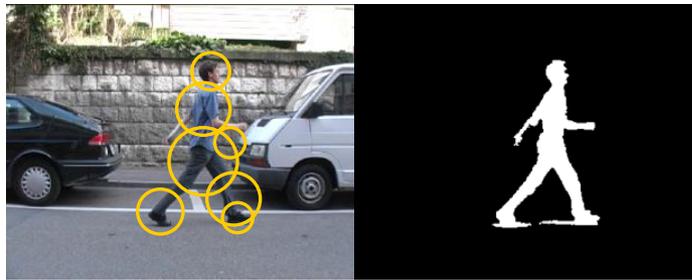
- Objects are detected as consistent configurations of the observed parts (visual words).



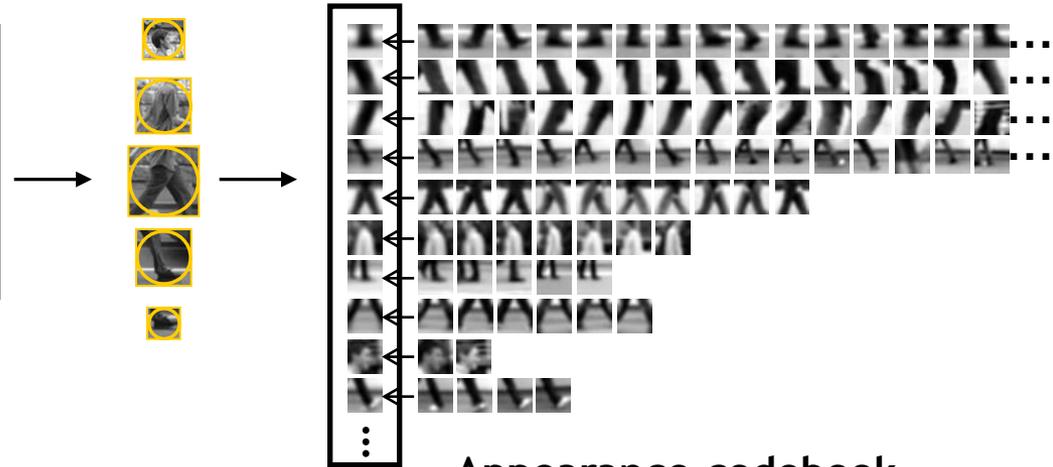
Test image

B. Leibe, A. Leonardis, and B. Schiele, [Robust Object Detection with Interleaved Categorization and Segmentation](#), International Journal of Computer Vision, Vol. 77(1-3), 2008.

# Implicit Shape Model - Representation

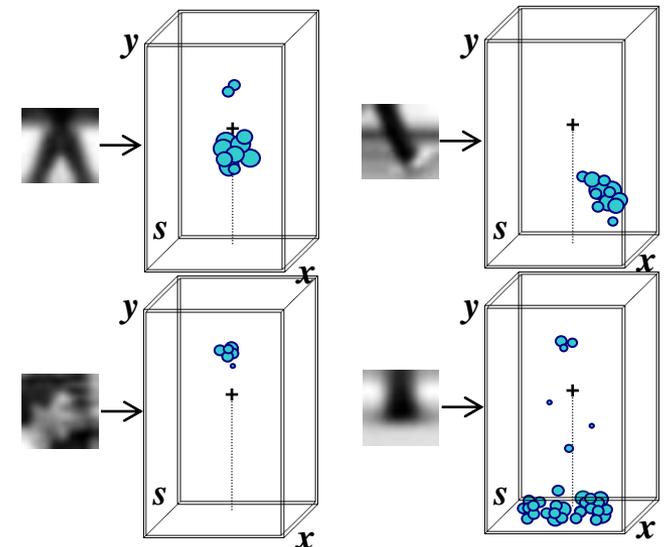


Training images  
(+reference segmentation)



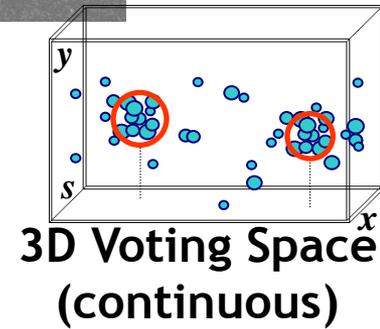
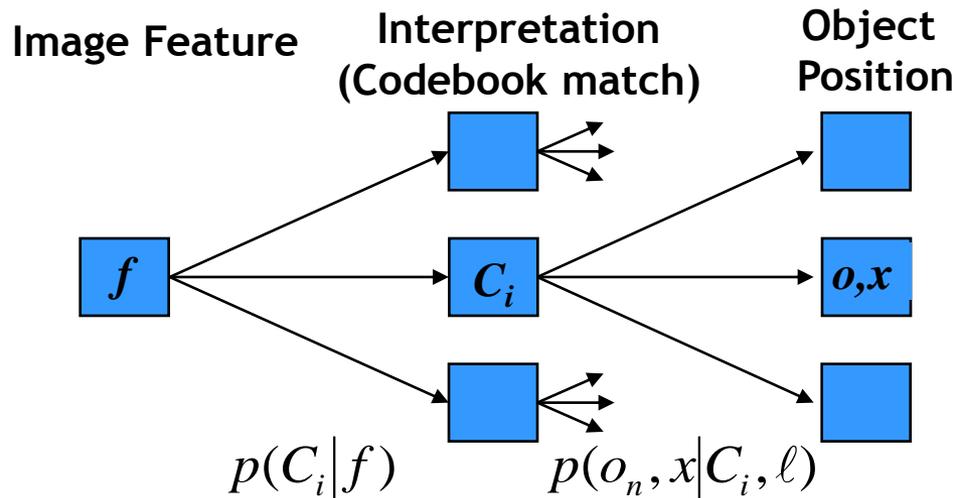
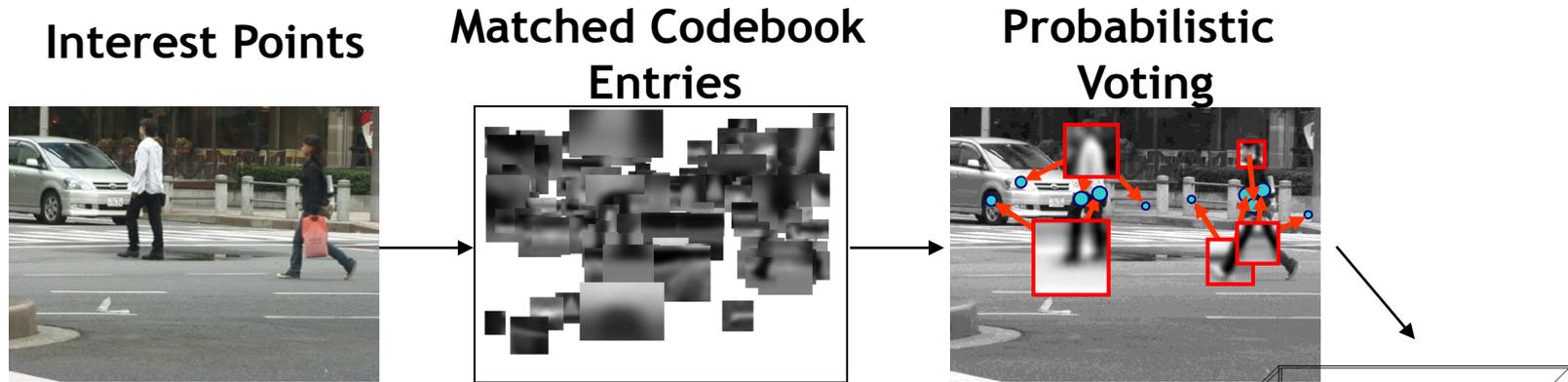
Appearance codebook

- Learn appearance codebook
  - Extract local features at interest points
  - Agglomerative clustering  $\Rightarrow$  codebook
- Learn spatial distributions
  - Match codebook to training images
  - Record matching positions on object



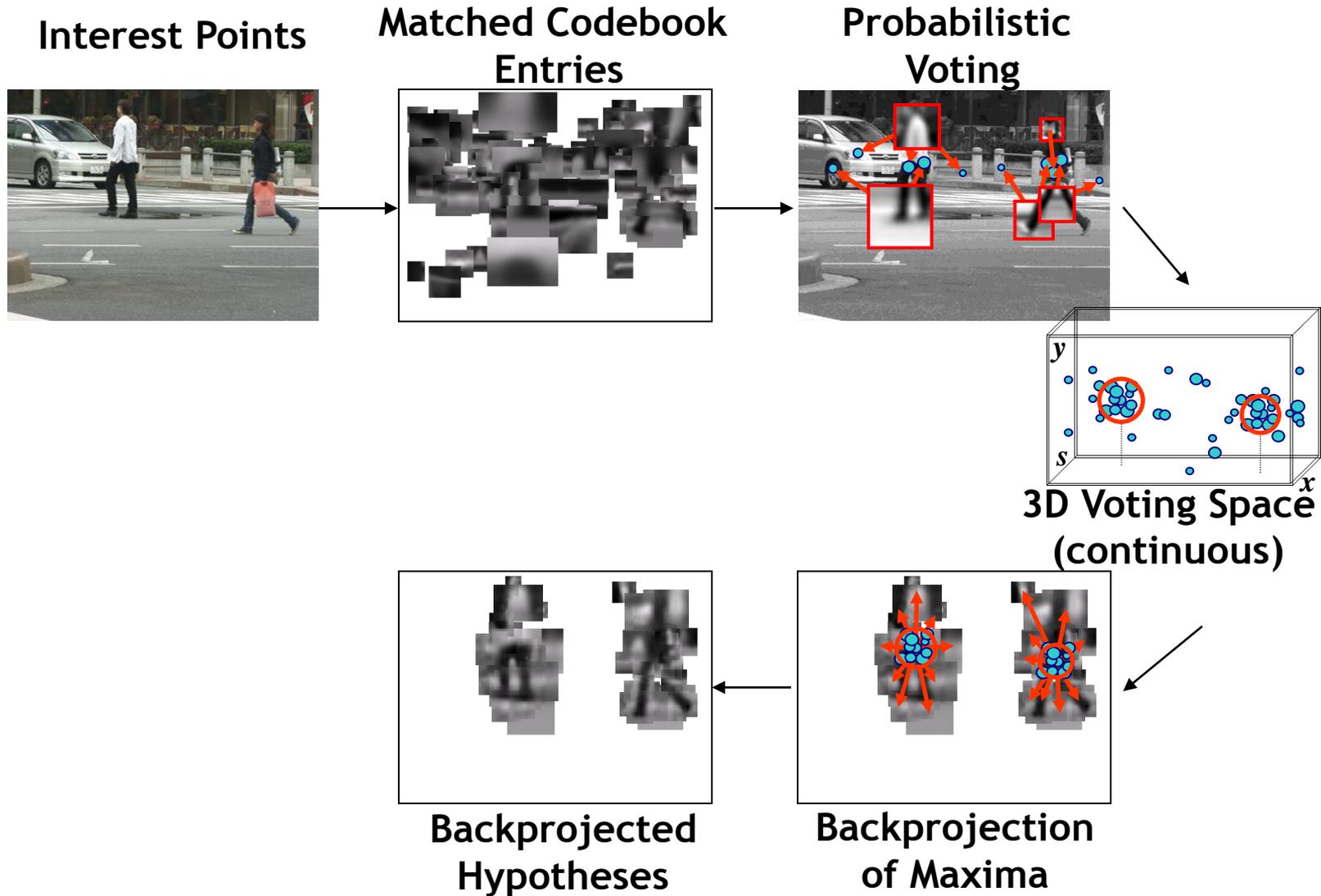
Spatial occurrence distributions

# Implicit Shape Model - Recognition



Probabilistic vote weighting

# Implicit Shape Model - Recognition



# Example: Results on Cows



Original image

# Example: Results on Cows



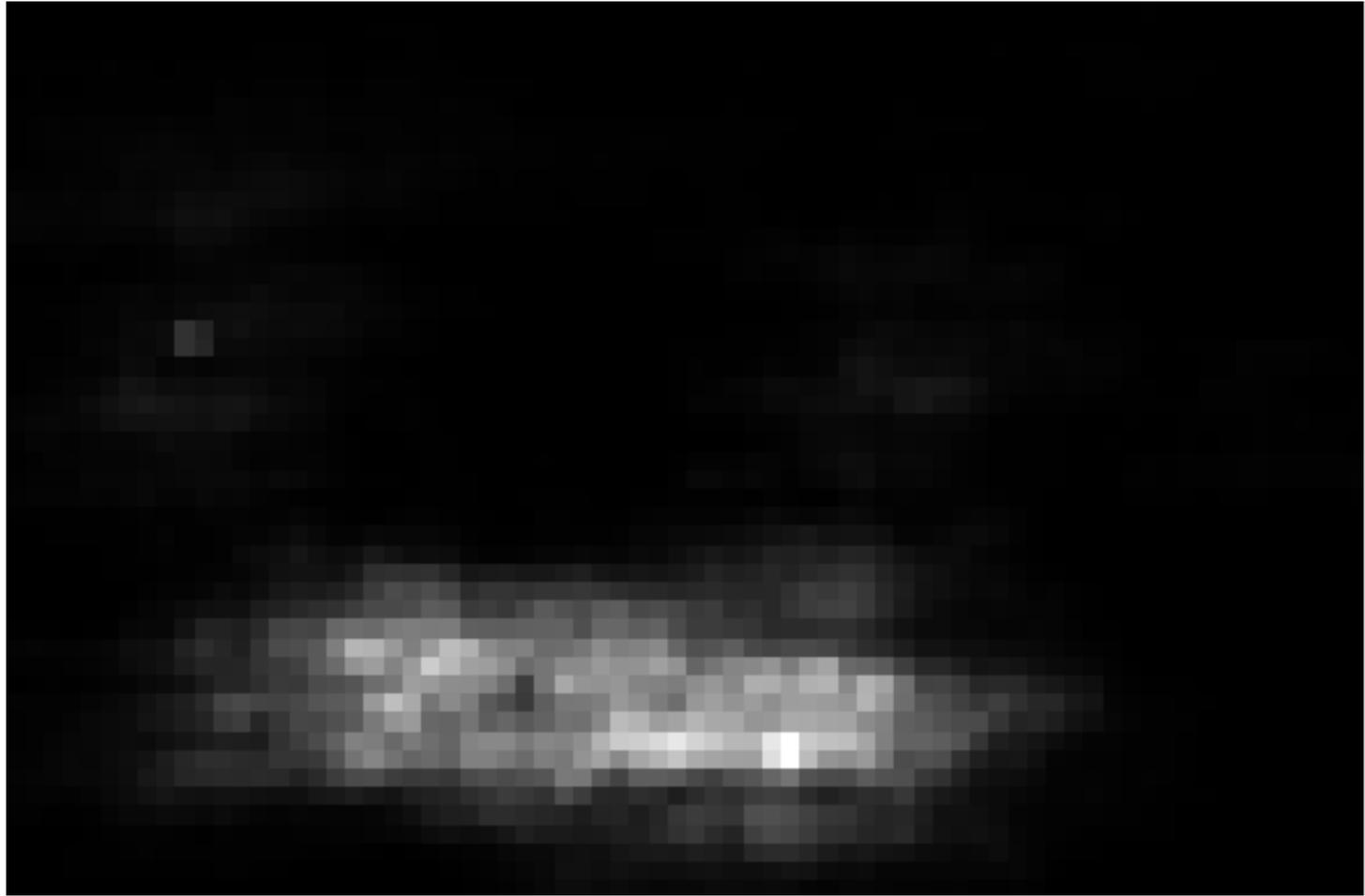
Interest points

# Example: Results on Cows



Matched patches

# Example: Results on Cows



Prob. Votes

# Example: Results on Cows



**1<sup>st</sup> hypothesis**

K. Grauman, B. Leibe

# Example: Results on Cows



**2<sup>nd</sup> hypothesis**

B. Leibe

# Example: Results on Cows



3<sup>rd</sup> hypothesis

# Scale Invariant Voting

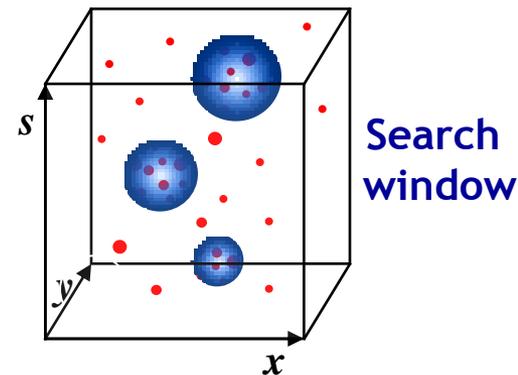
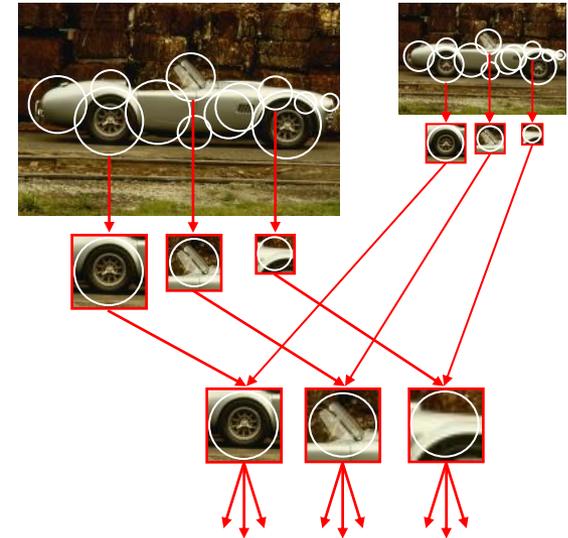
- Scale-invariant feature selection
  - Scale-invariant interest regions
  - Extract scale-invariant descriptors
  - Match to appearance codebook
- Generate scale votes
  - Scale as 3<sup>rd</sup> dimension in voting space

$$x_{vote} = x_{img} - x_{occ}(s_{img}/s_{occ})$$

$$y_{vote} = y_{img} - y_{occ}(s_{img}/s_{occ})$$

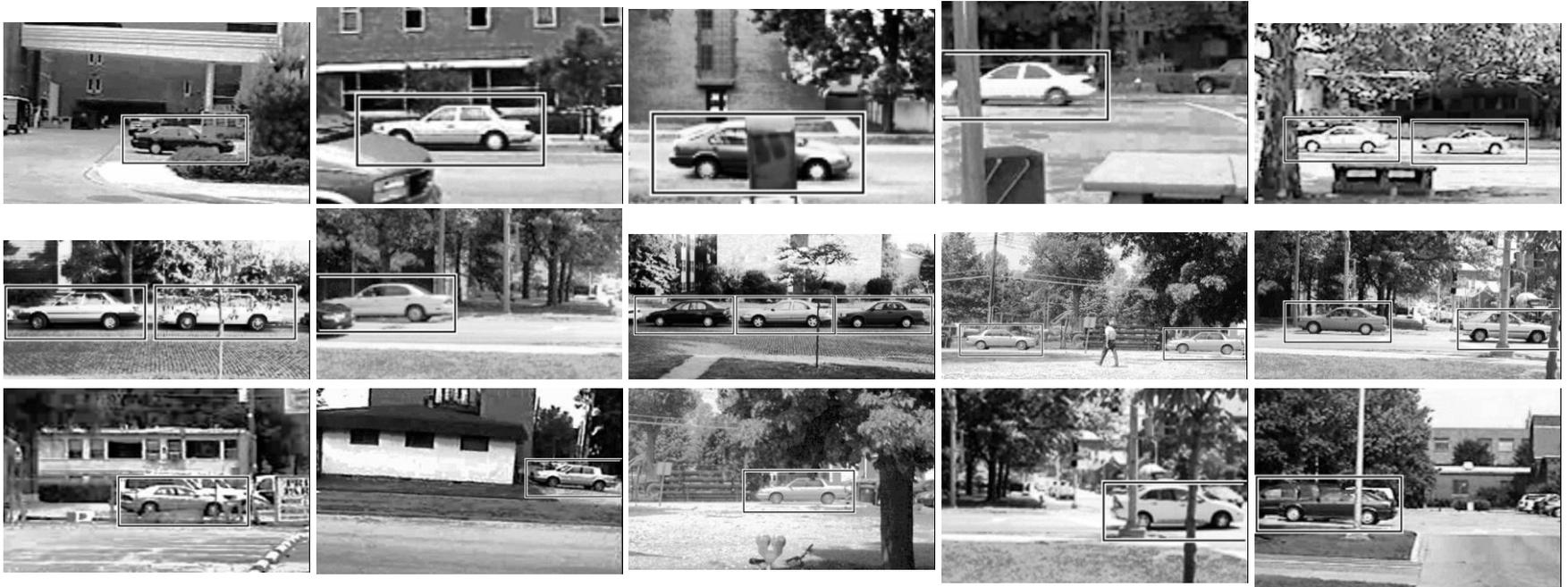
$$s_{vote} = (s_{img}/s_{occ}).$$

- Search for maxima in 3D voting space

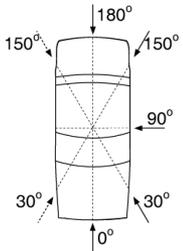


# Detection Results

- Qualitative Performance
  - Recognizes different kinds of objects
  - Robust to clutter, occlusion, noise, low contrast



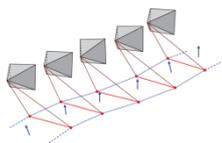
# Detections Using Ground Plane Constraints



Battery of 5  
ISM detectors  
for different  
car views

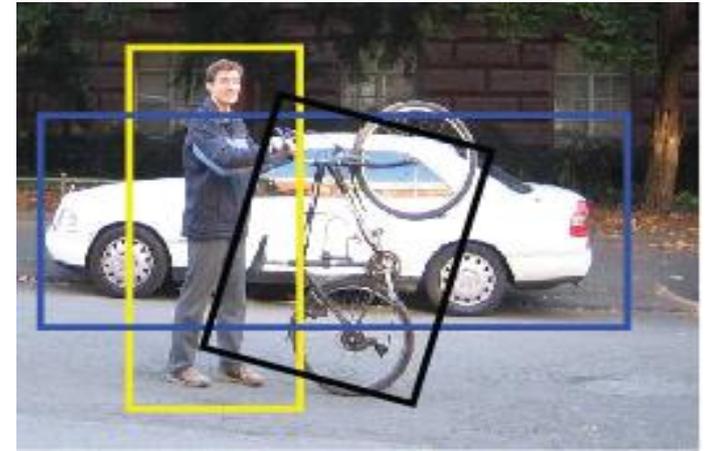
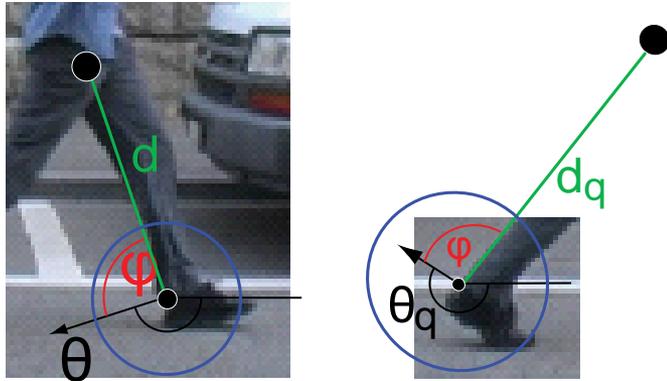


left camera  
1175 frames



# Extension: Rotation-Invariant Detection

- Polar instead of Cartesian voting scheme



- **Benefits:**

- Recognize objects under image-plane rotations
- Possibility to share parts between articulations.

- **Caveats:**

- Rotation invariance should only be used when it's really needed. (Also increases false positive detections)

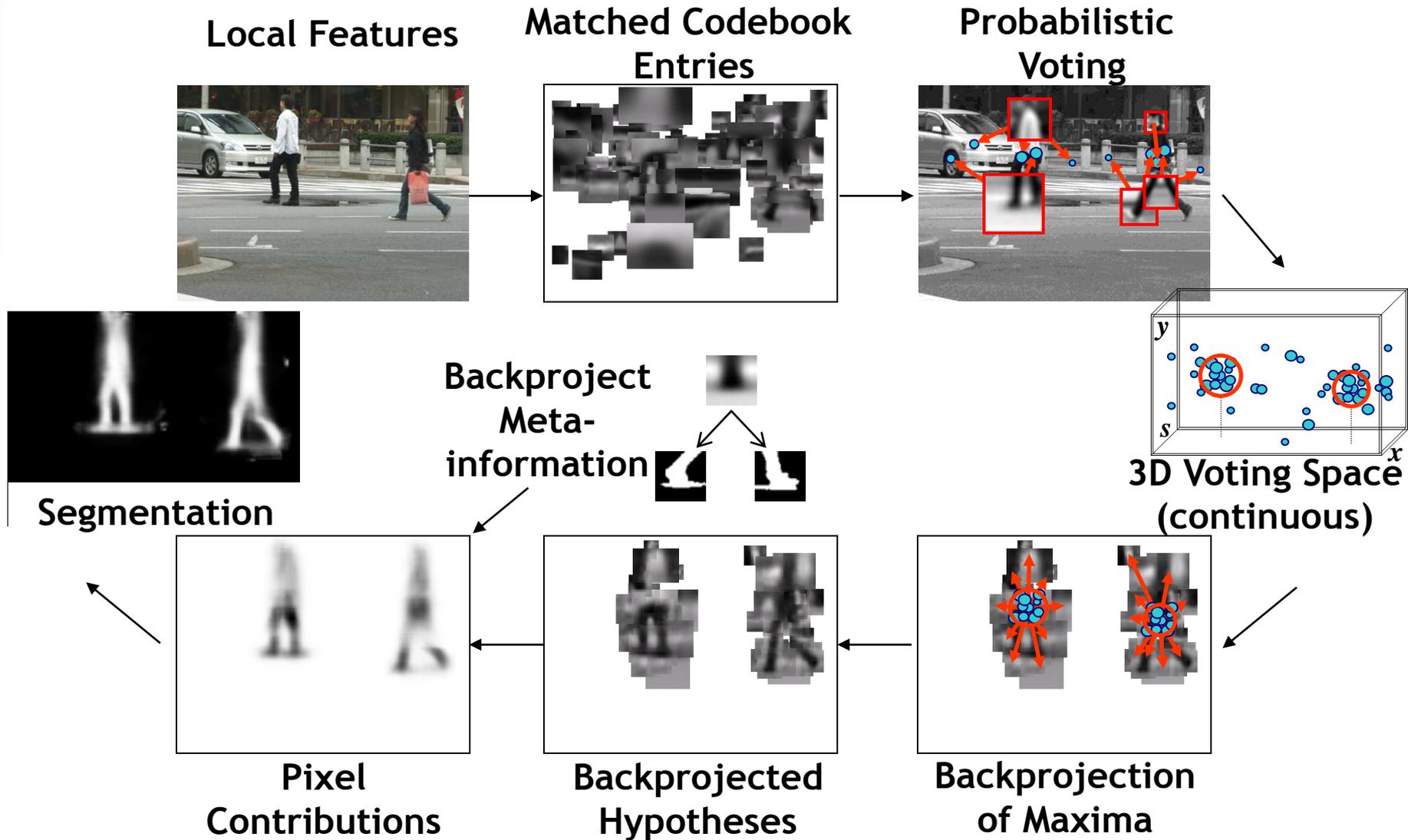
# Sometimes, Rotation Invariance Is Needed...



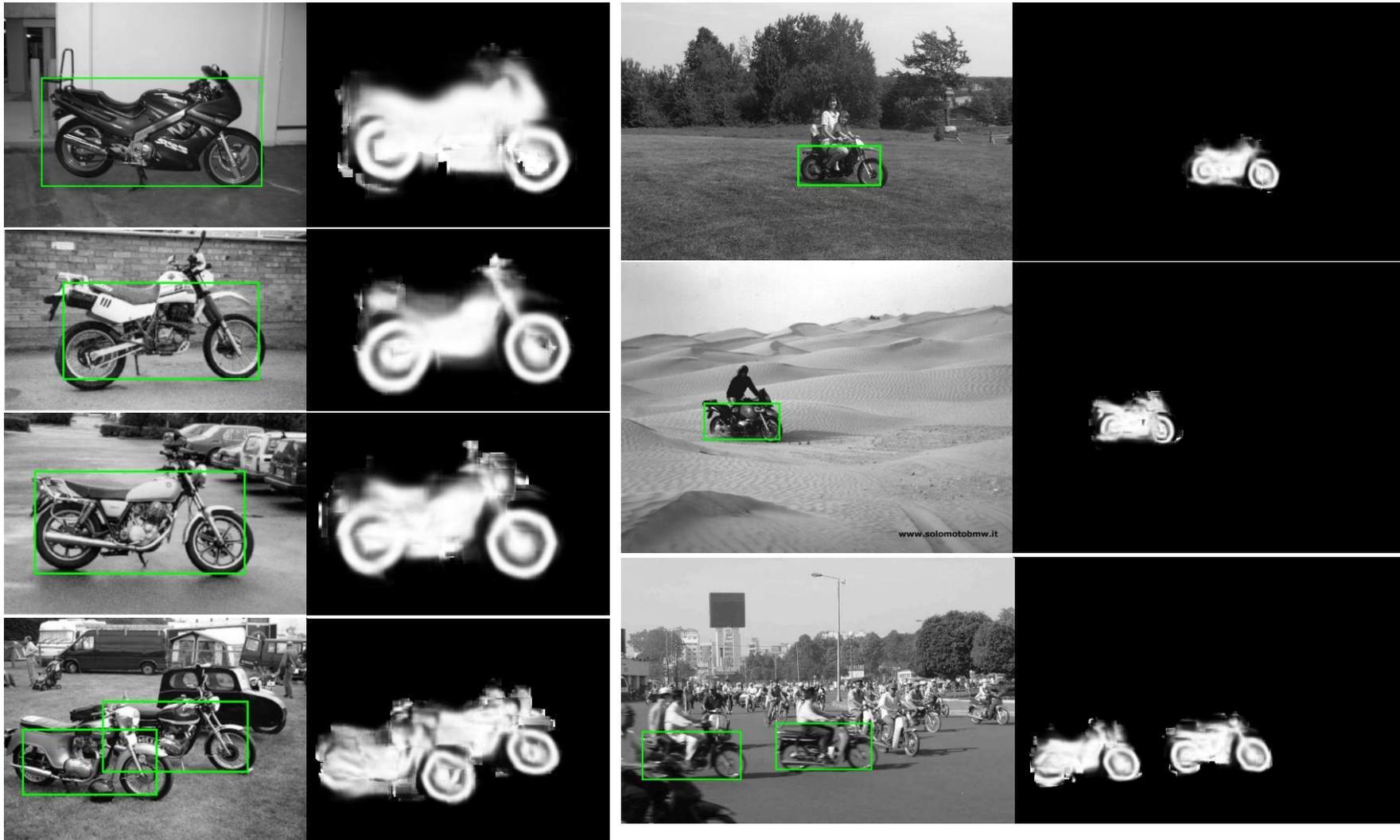
Figure from [Mikolajczyk et al., CVPR'06]

B. Leibe

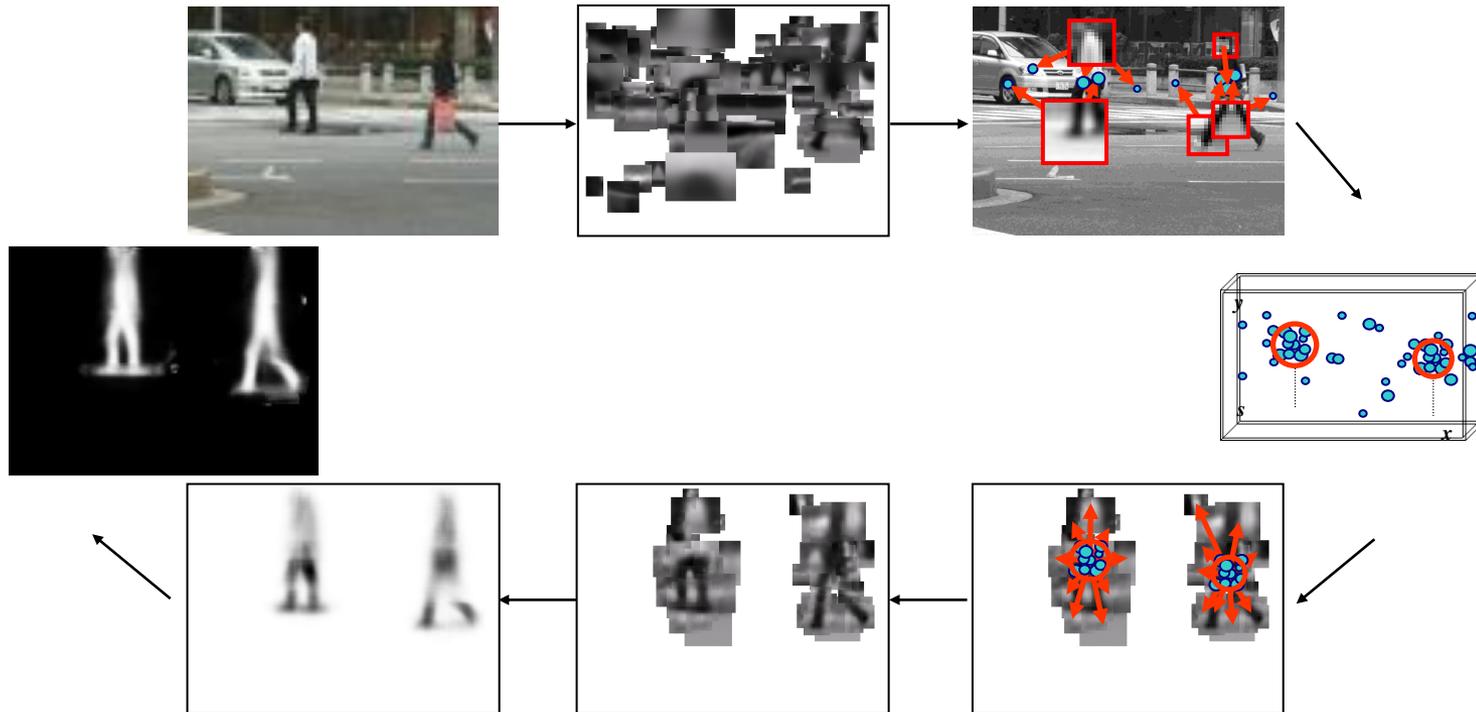
# Implicit Shape Model - Segmentation



# Example Results: Motorbikes



# You Can Try It At Home...

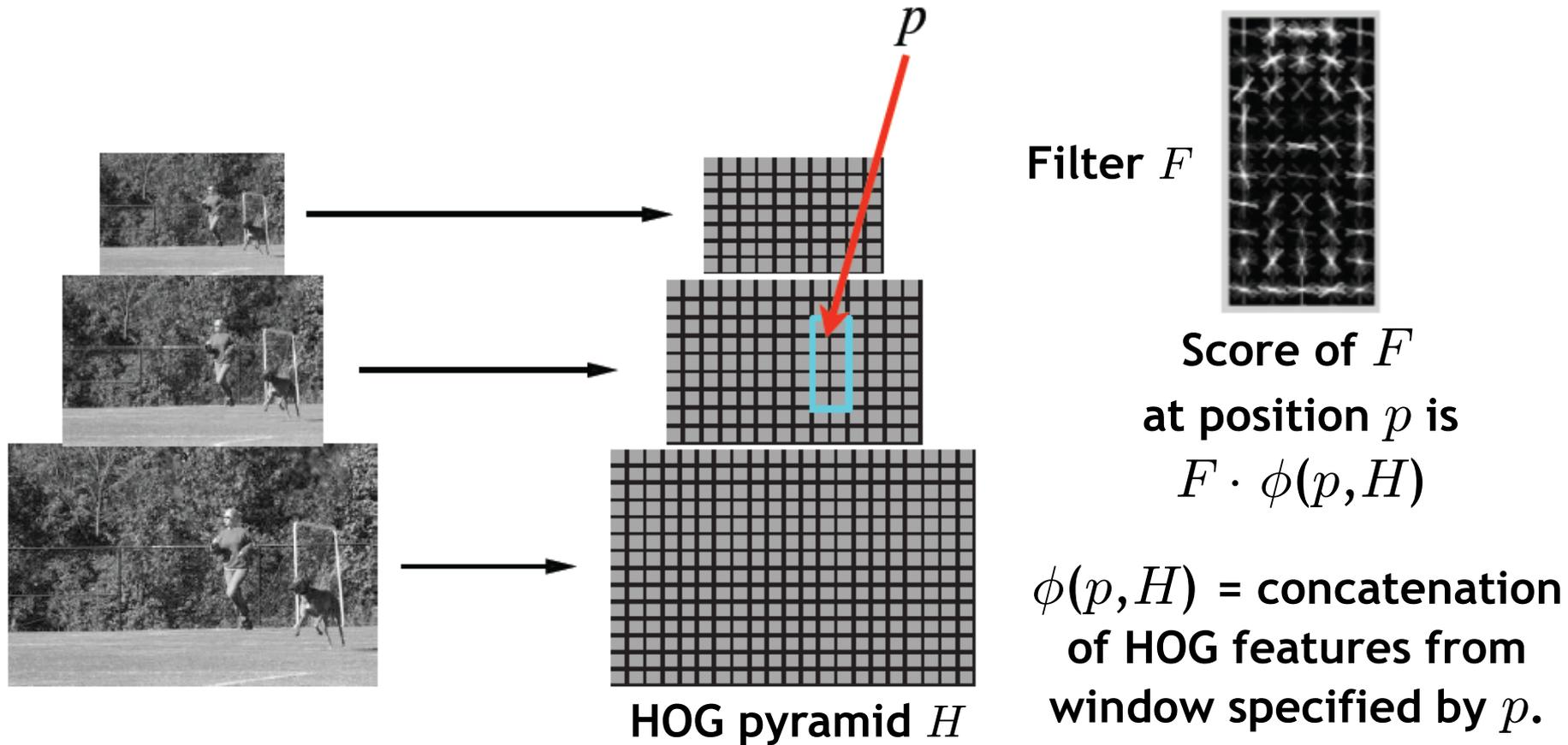


- **Linux source code & binaries available**
  - Including datasets & several pre-trained detectors
  - <http://www.vision.rwth-aachen.de/software>

# Topics of This Lecture

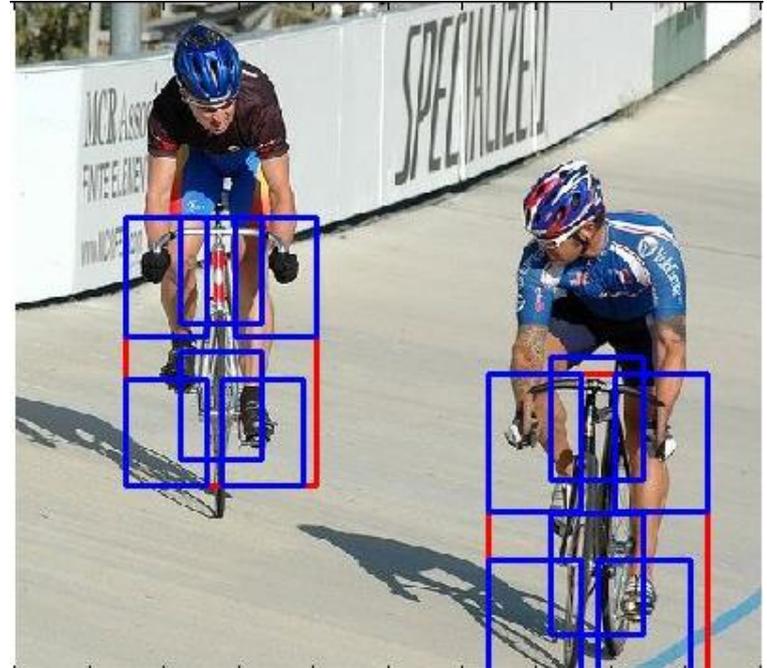
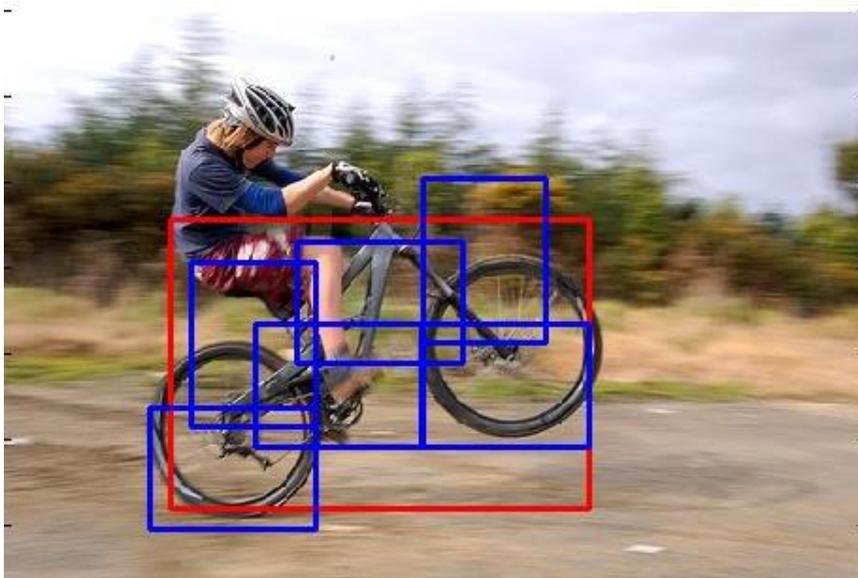
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  - **Discriminative part-based detection**

# Starting Point: HOG Sliding-Window Detector



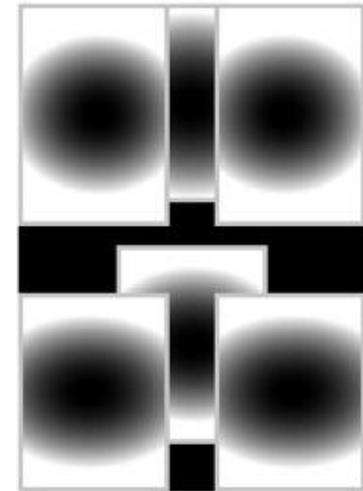
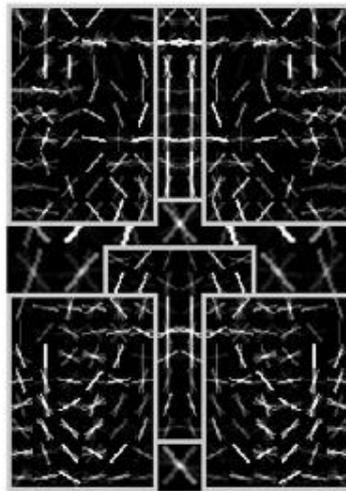
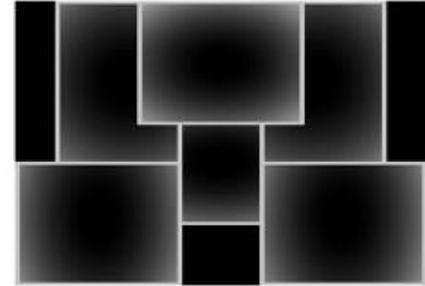
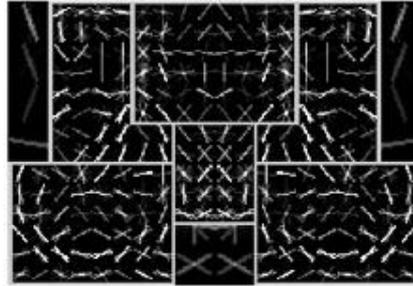
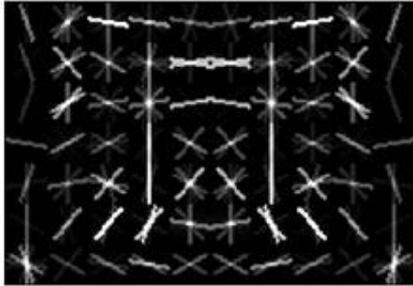
- Array of weights for features in window of HOG pyramid
- Score is dot product of filter and vector

# Deformable Part-based Models



- Mixture of deformable part models (pictorial structures)
- Each component has global template + deformable parts
- Fully trained from bounding boxes alone

# 2-Component Bicycle Model

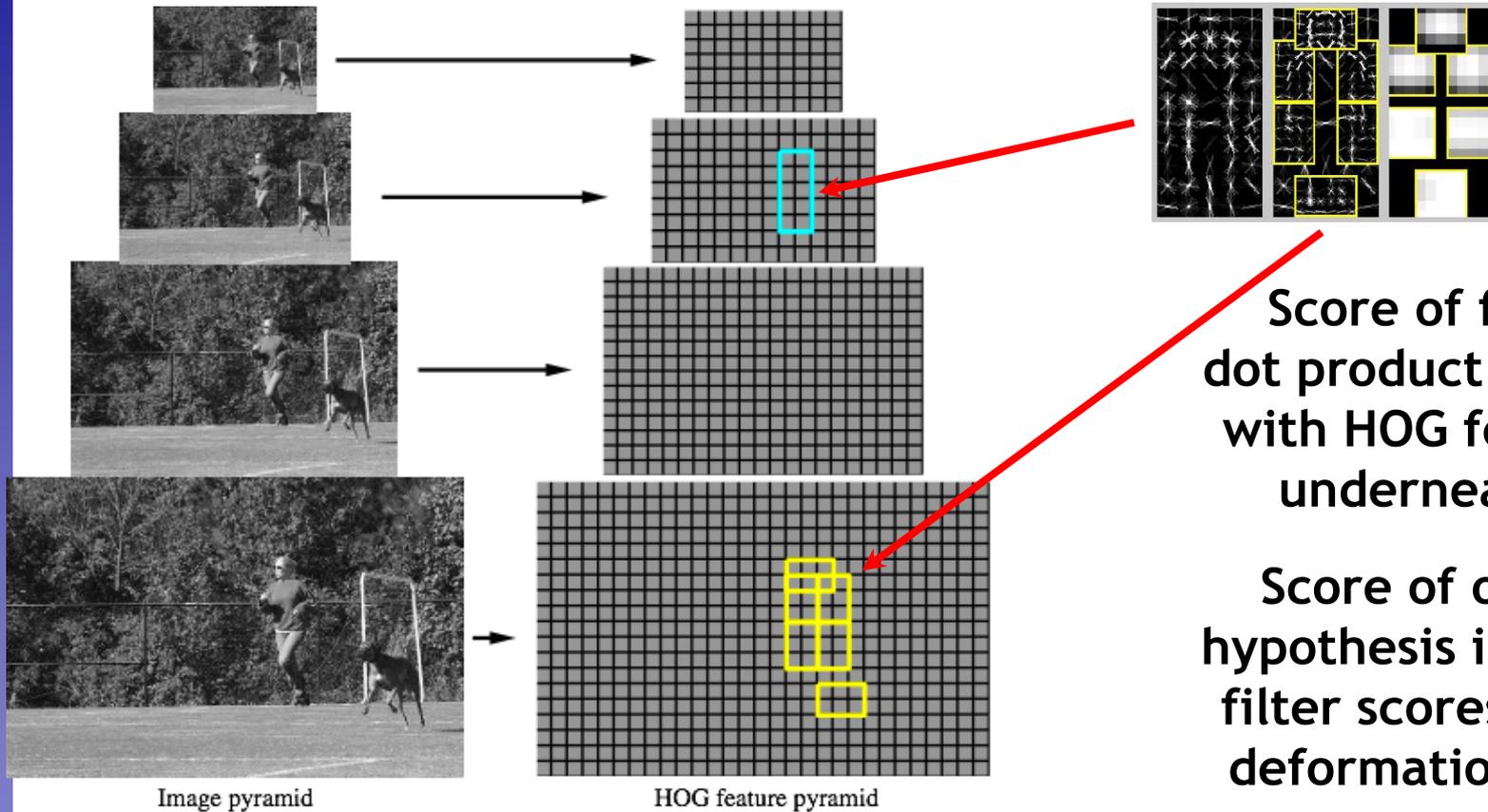


**Root filters**  
coarse resolution

**Part filters**  
finer resolution

**Deformation**  
models

# Object Hypothesis



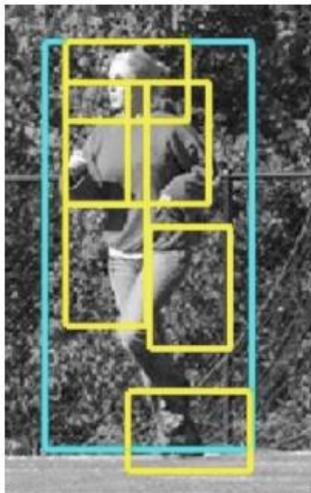
- **Multiscale model captures features at two resolutions**

# Score of a Hypothesis

$$\text{score}(p_0, \dots, p_n) = \sum_{i=0}^n F_i \cdot \phi(H, p_i) - \sum_{i=1}^n d_i \cdot (dx_i^2, dy_i^2)$$

“data term”  
 $\sum_{i=0}^n F_i \cdot \phi(H, p_i)$   
↑  
filters

 “spatial prior”  
 $\sum_{i=1}^n d_i \cdot (dx_i^2, dy_i^2)$   
↑  
 displacements  
 deformation parameters



$$\text{score}(z) = \beta \cdot \Psi(H, z)$$

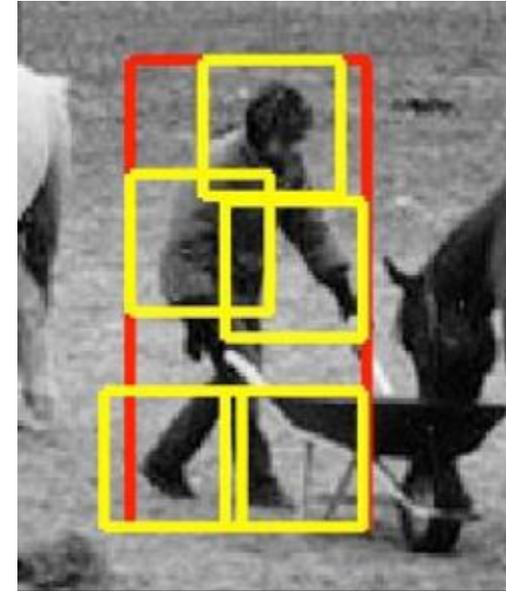
concatenation filters and  
deformation parameters

concatenation of HOG  
features and part  
displacement features

# Recognition Model



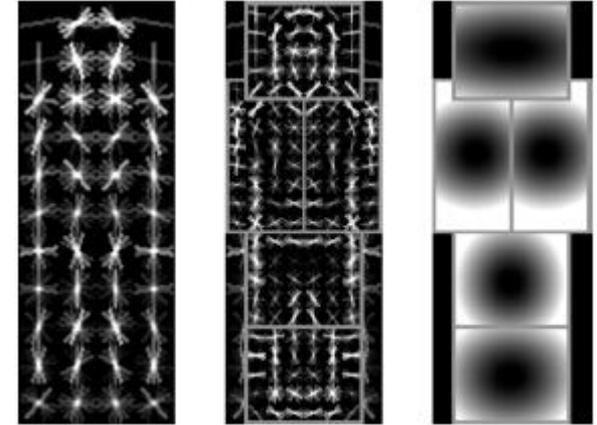
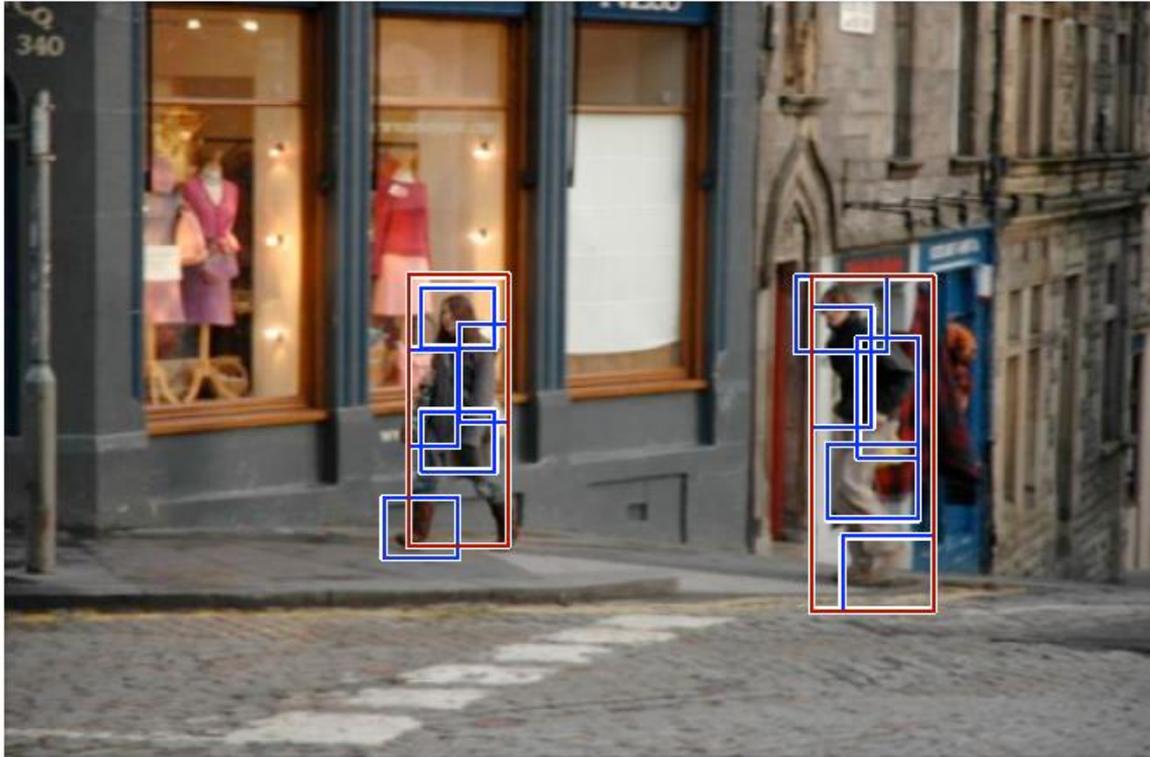
$$f_w(x) = w \cdot \Phi(x)$$



$$f_w(x) = \max_z w \cdot \Phi(x, z)$$

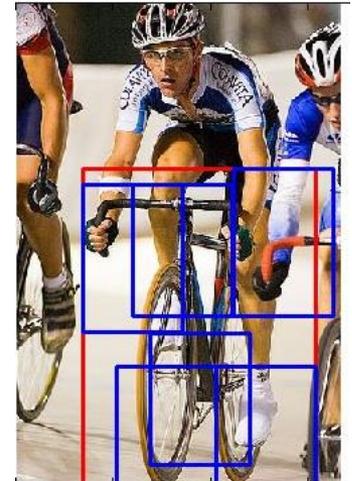
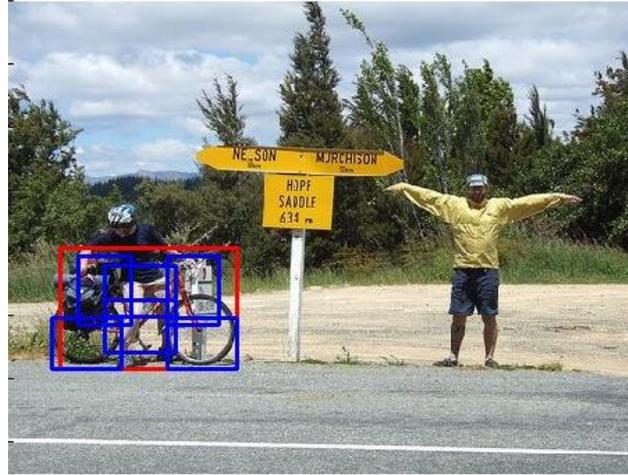
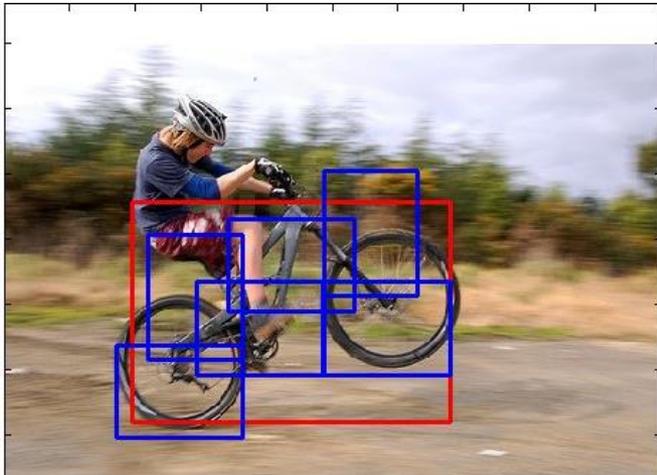
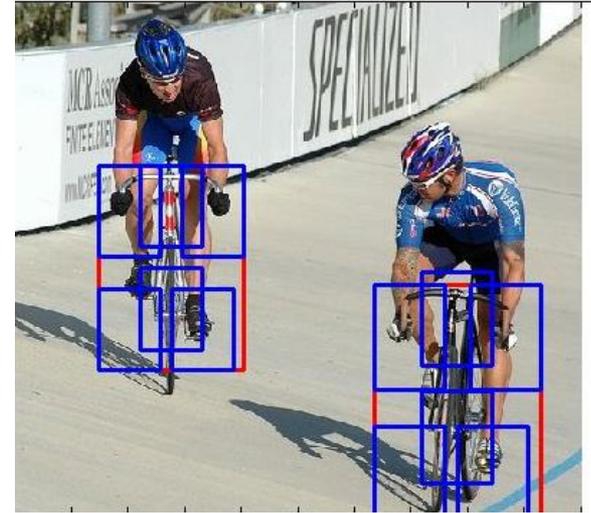
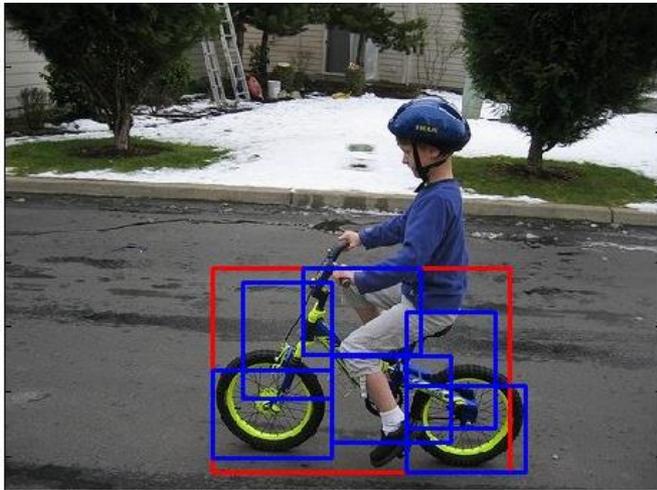
- $z$  : vector of part offsets
- $\Phi(x, z)$  : vector of HOG features (from root filter & appropriate part sub-windows) and part offsets

# Results: Persons



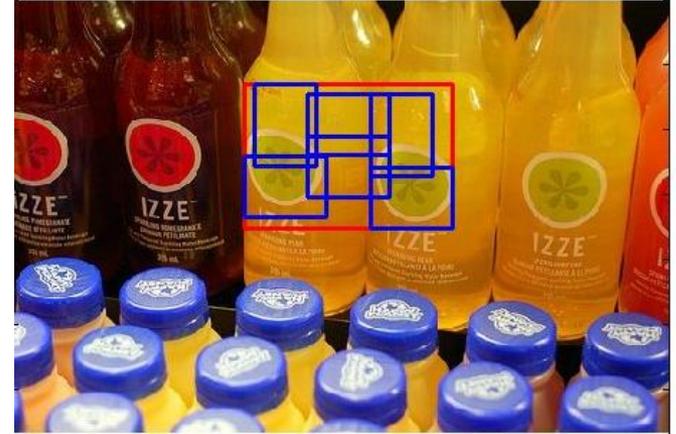
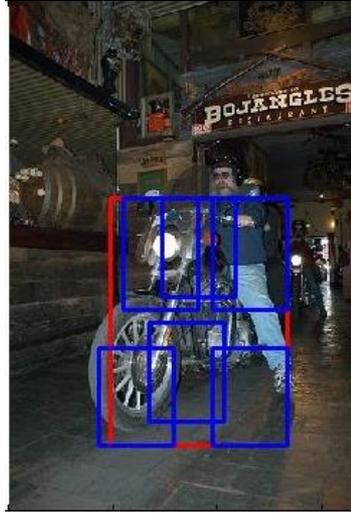
- **Results (after non-maximum suppression)**
  - ~1s to search all scales

# Results: Bicycles

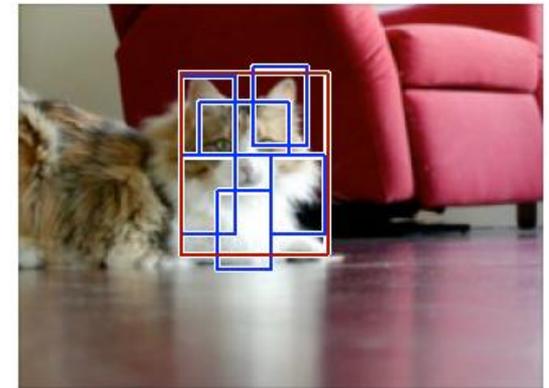
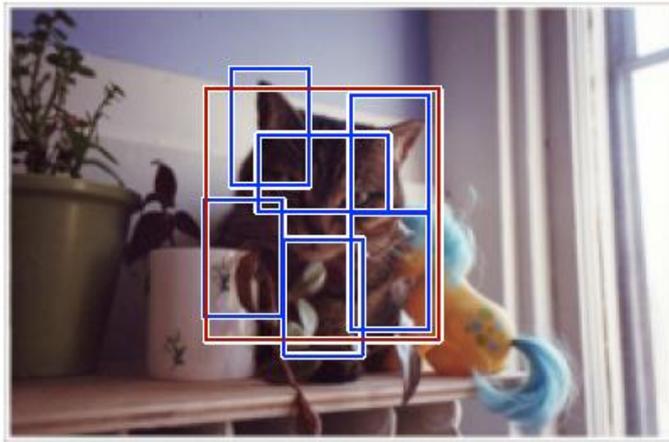
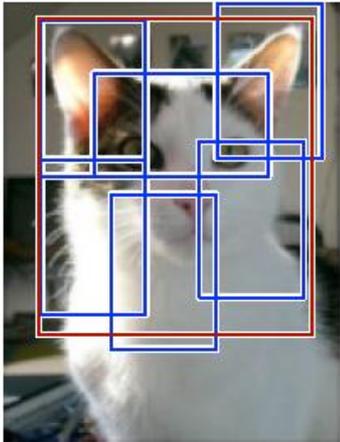
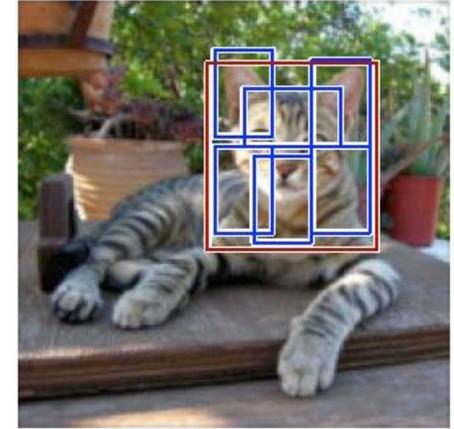
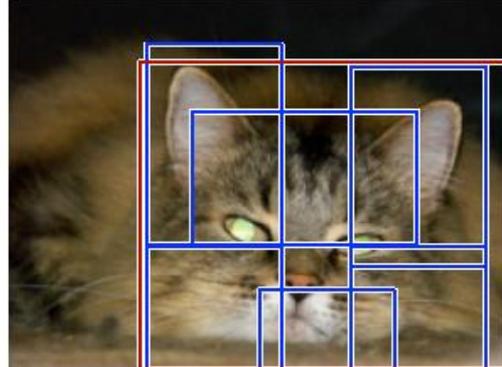
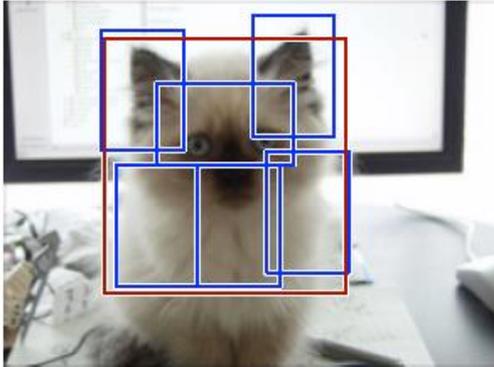


# False Positives

- Bicycles



# Results: Cats



**High-scoring true positives**

**High-scoring false positives  
(not enough overlap)**

# You Can Try It At Home...

- Deformable part-based models have been very successful at several recent evaluations.  
⇒ Currently, state-of-the-art approach in object detection
- Source code and models trained on PASCAL 2006, 2007, and 2008 data are available here:

<http://www.cs.uchicago.edu/~pff/latent>

# References and Further Reading

- Details about the ISM approach can be found in
  - *B. Leibe, A. Leonardis, and B. Schiele,*  
[Robust Object Detection with Interleaved Categorization and Segmentation](#), International Journal of Computer Vision, Vol. 77(1-3), 2008.
- Details about the DPMs can be found in
  - *P. Felzenszwalb, R. Girshick, D. McAllester, D. Ramanan,*  
[Object Detection with Discriminatively Trained Part Based Models](#), IEEE Trans. PAMI, Vol. 32(9), 2010.
- Try the ISM Linux binaries
  - <http://www.vision.ee.ethz.ch/bleibe/code>
- Try the Deformable Part-based Models
  - <http://www.cs.uchicago.edu/~pff/latent>