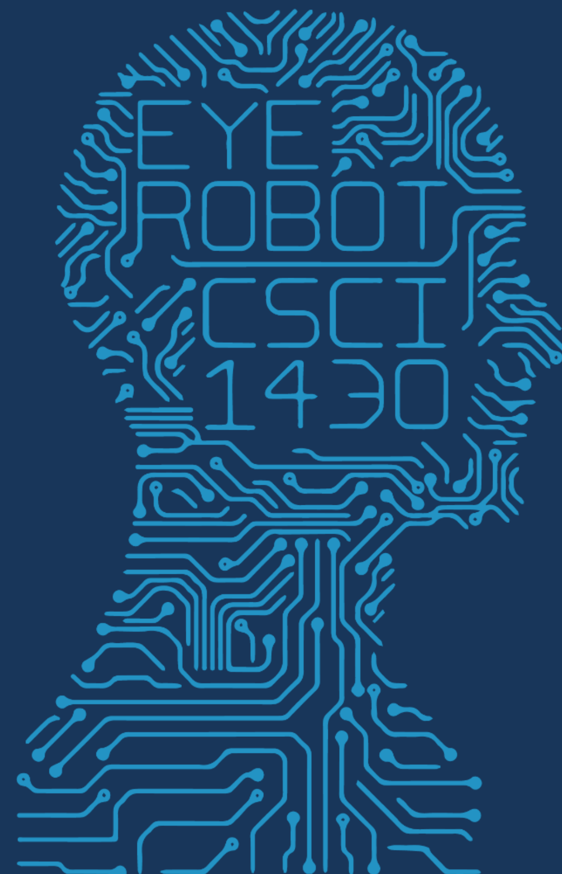
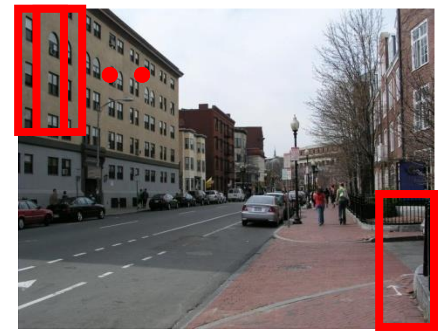
1950
Future Vision

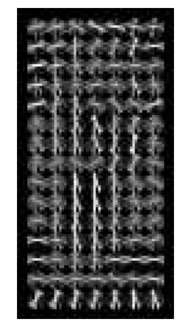


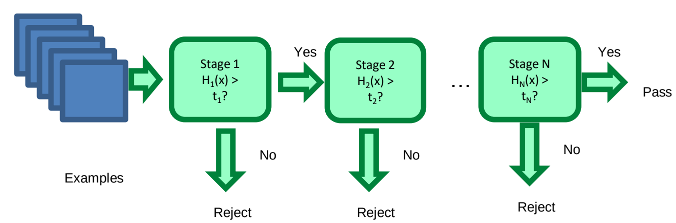
2017 MWF 1pm 368
Computer Vision

Things to remember

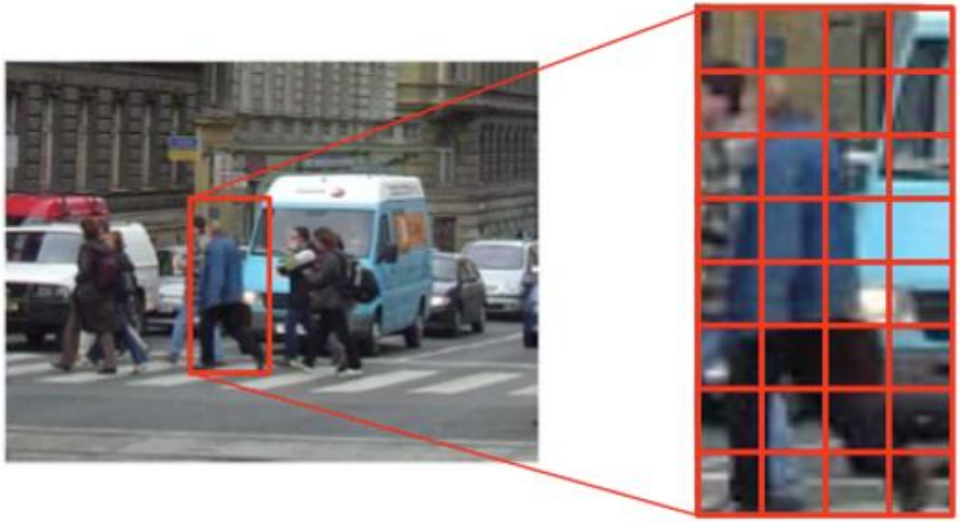
- Sliding window for search
- Features based on differences of intensity (gradient, wavelet, etc.)
  - Excellent results require careful feature design
- Boosting for feature selection
- Integral images, cascade for speed
- Bootstrapping to deal with many, many negative examples







Starting point: sliding window classifiers



Feature vector
$x = [\ldots, \ldots, \ldots, \ldots]$

- Detect objects by testing each subwindow
  - Reduces object detection to binary classification
  - Dalal & Triggs: HOG features + linear SVM classifier
  - Previous state of the art for detecting people

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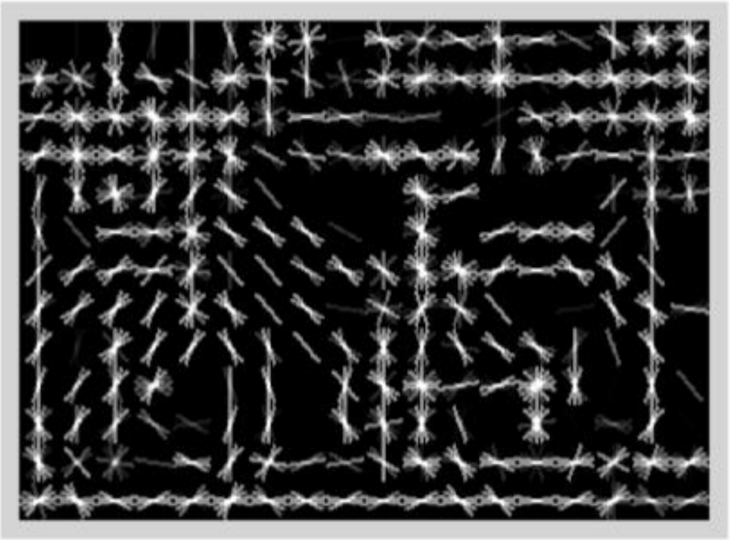
Histogram of Gradient (HOG) features



- Image is partitioned into 8x8 pixel blocks
- In each block we compute a histogram of gradient orientations
  - Invariant to changes in lighting, small deformations, etc.
- Compute features at different resolutions (pyramid)

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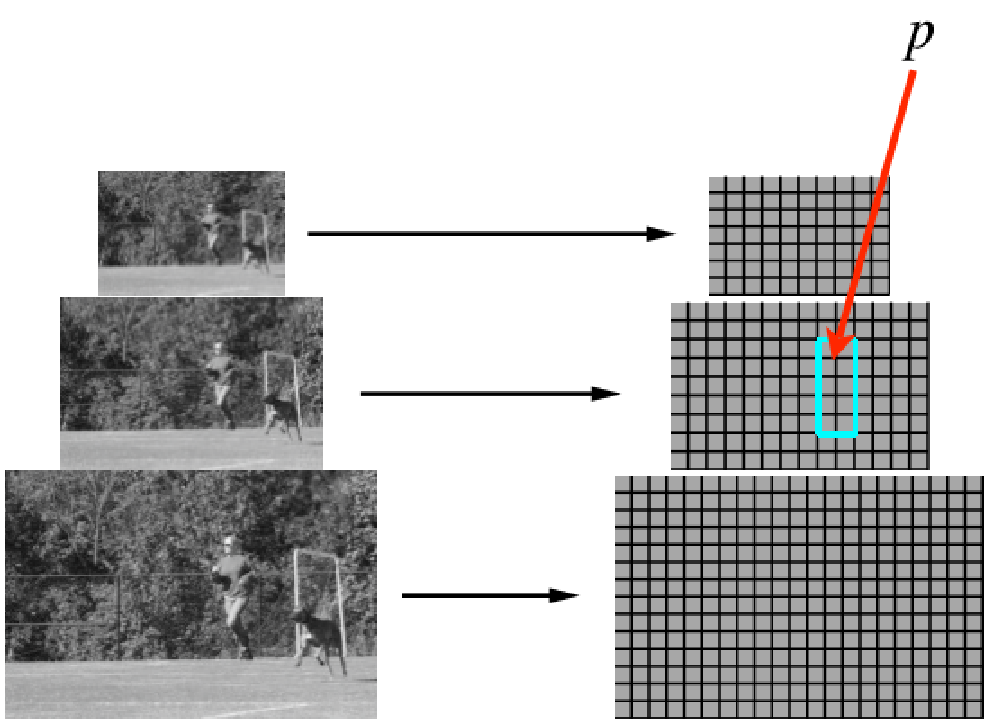
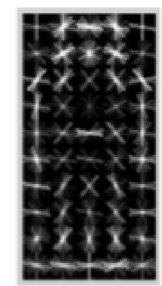
HOG Filters

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



HOG pyramid H

Filter F



Score of F at position p is
$F \cdot \phi(p, H)$

$\phi(p, H)$ = concatenation of
HOG features from
subwindow specified by p

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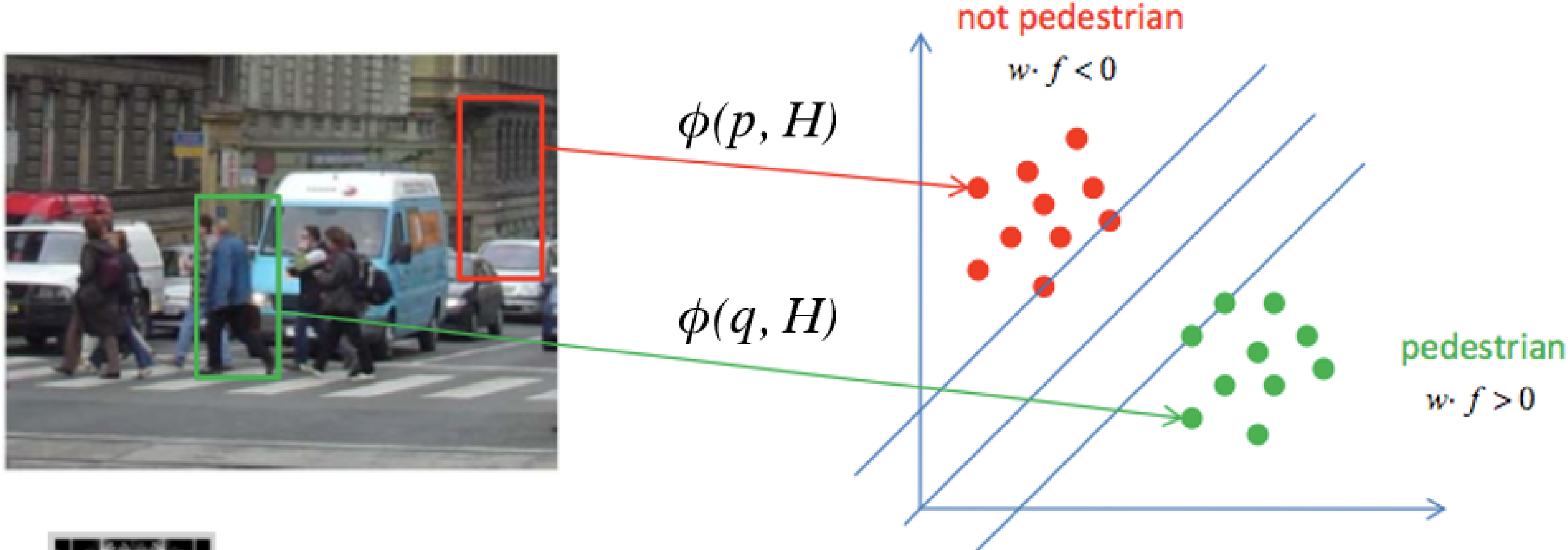
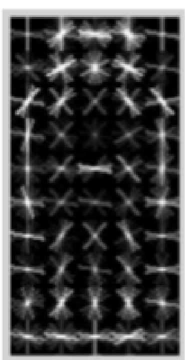
Dalal & Triggs: HOG + linear SVMs





Typical form of a model

There is much more background than objects

Start with random negatives and repeat:

1) Train a model

2) Harvest false positives to define "hard negatives"

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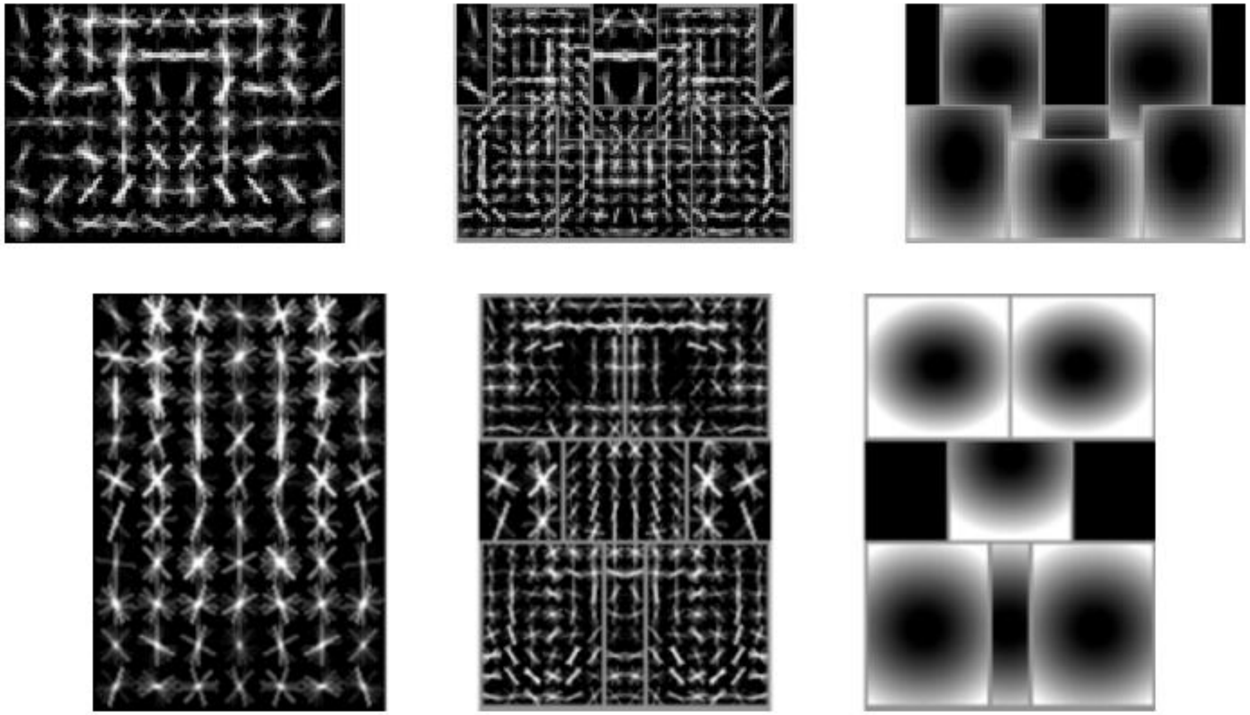
Discriminative part-based models



root filters
coarse resolution

part filters
finer resolution

deformation
models

Each component has a root filter F_0
and n part models (F_i, v_i, d_i)

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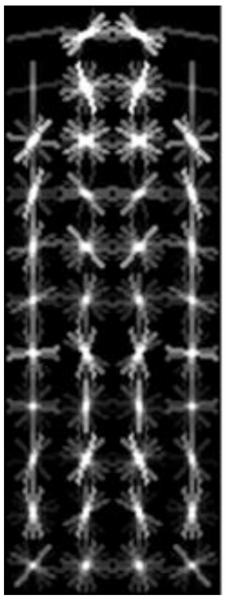
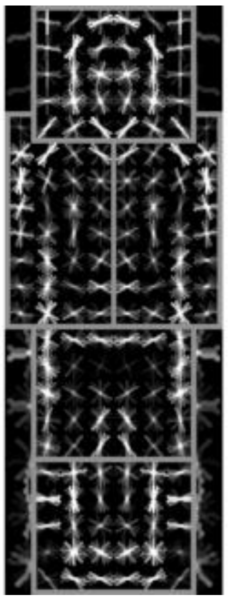
Discriminative part-based models

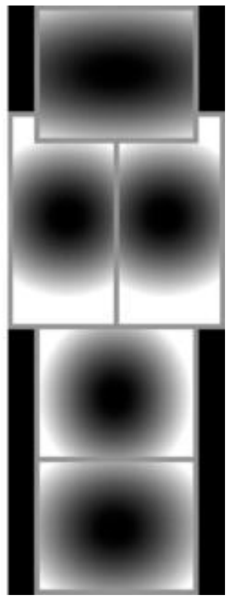
Root filter



Part filters



Deformation weights



P. Felzenszwalb, R. Girshick, D. McAllester, D. Ramanan, [Object Detection with Discriminatively Trained Part Based Models](), PAMI 32(9), 2010

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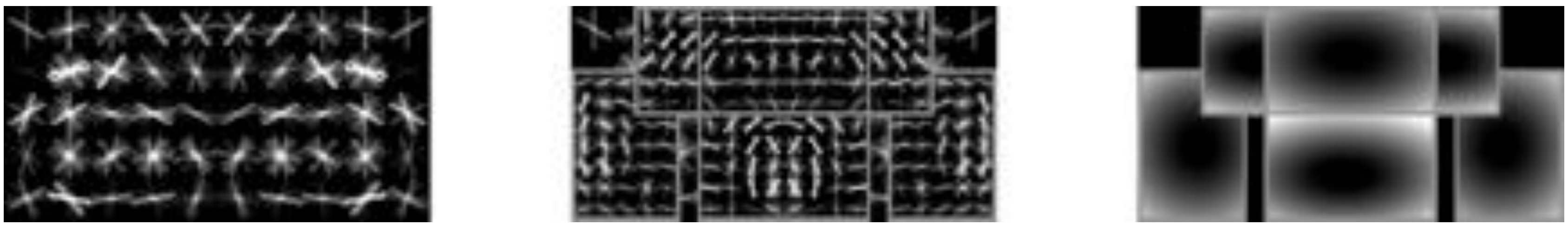
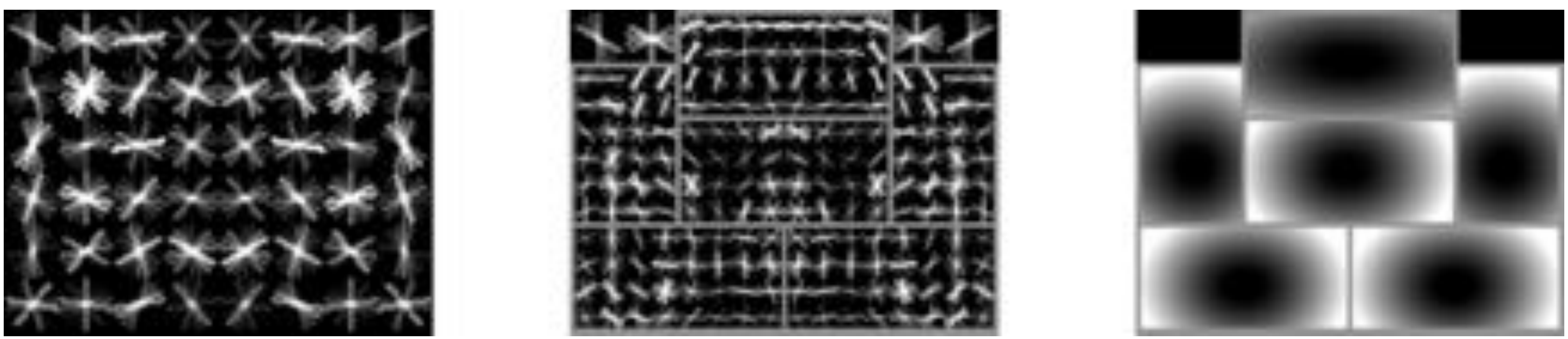
Car model

Component 1



Component 2



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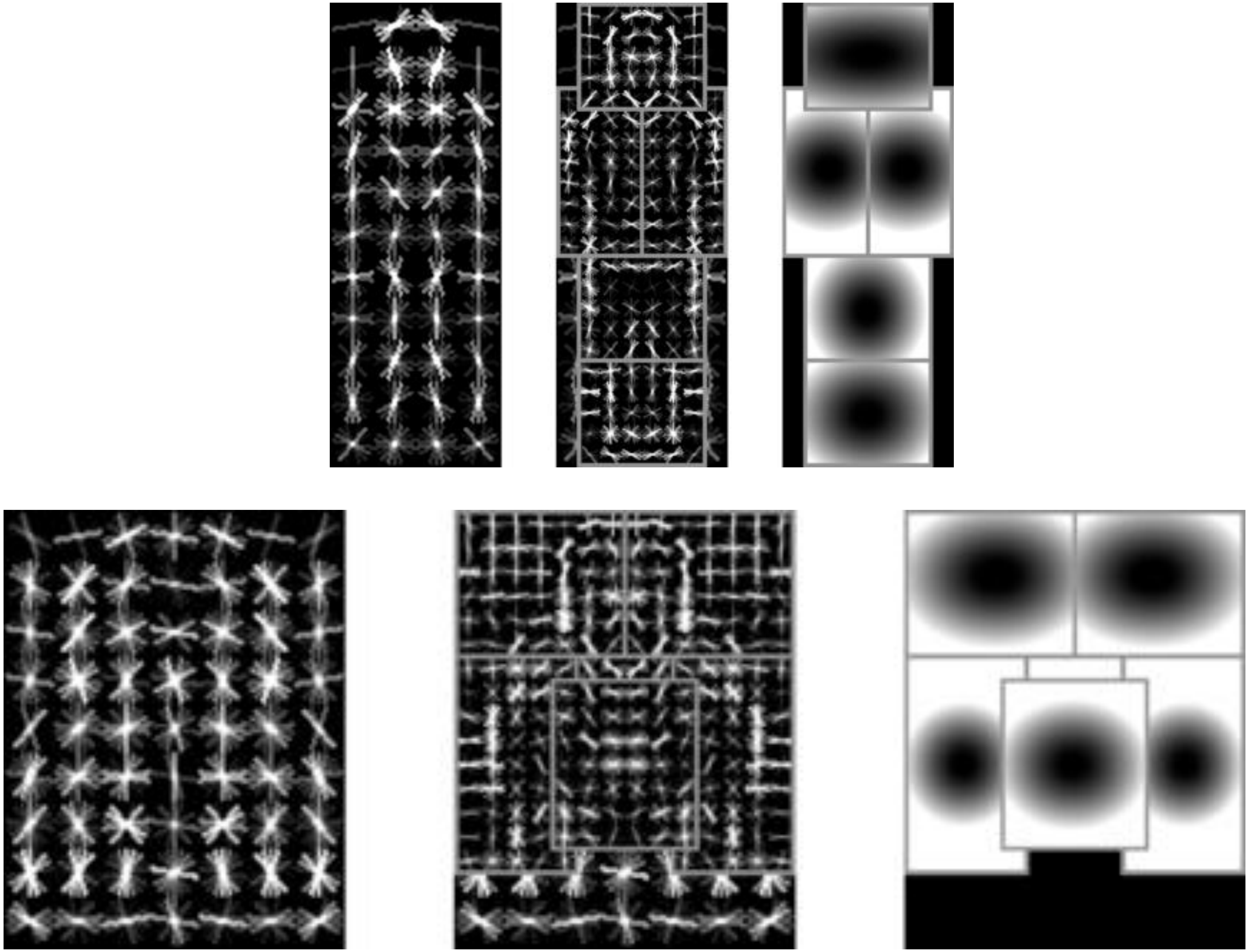
Person model



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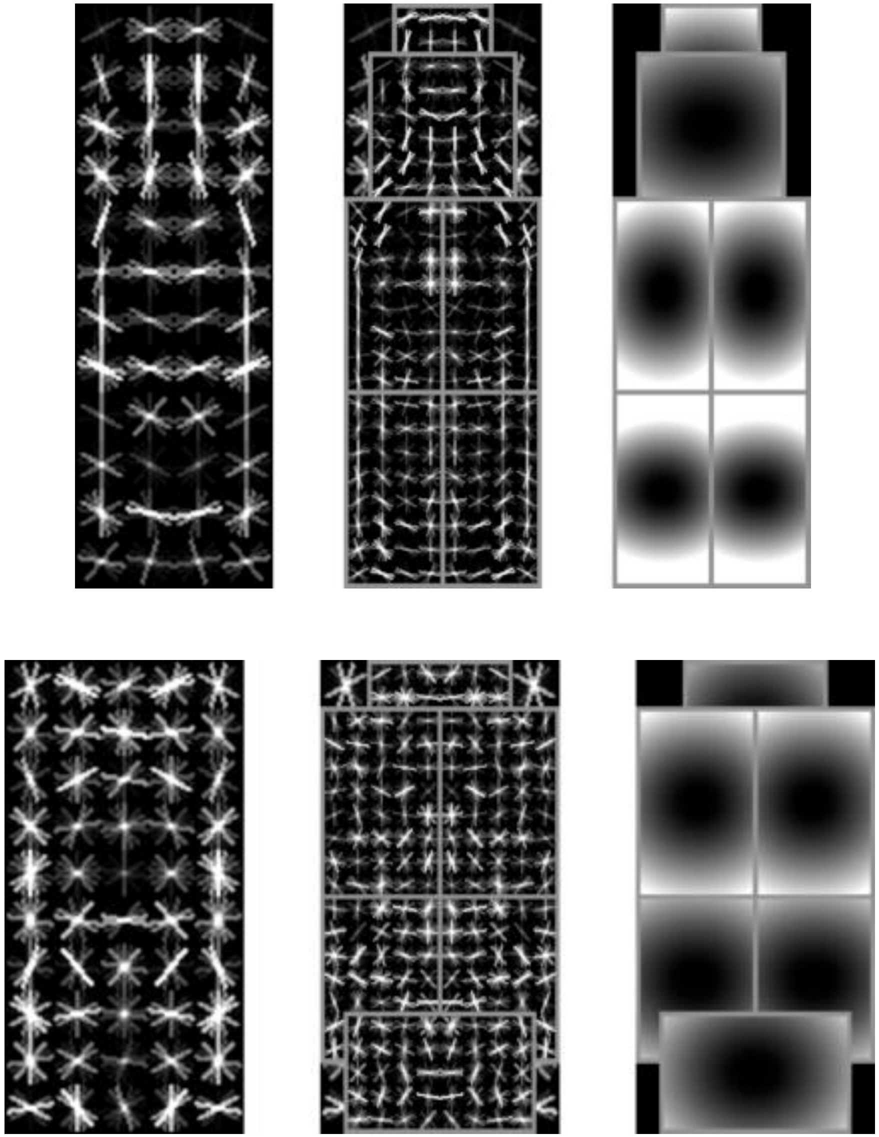
Bottle model



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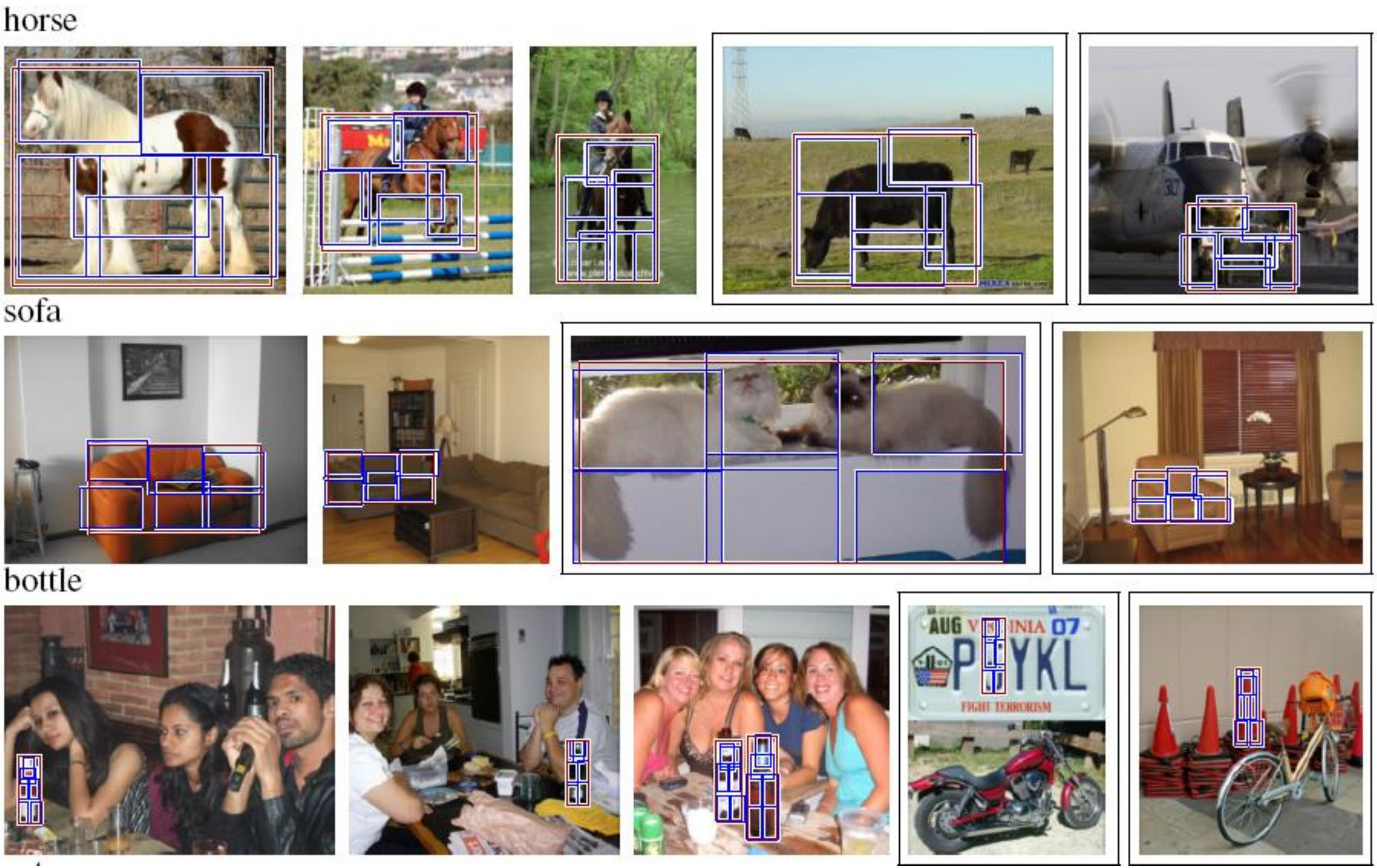
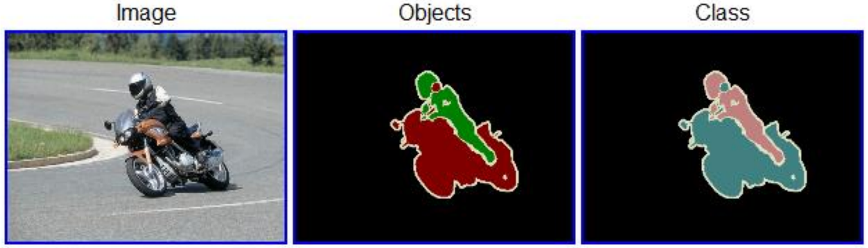
More detections



The PASCAL Visual Object Classes Challenge 2009 (VOC2009)

- Twenty object categories (aeroplane to TV/monitor)

- Three challenges:
  - Classification challenge (is there an X in this image?)
  - Detection challenge (draw a box around every X)
  - Segmentation challenge



Snavely

Dataset: Collection

- Images downloaded from **flickr**
  - 500,000 images downloaded and random subset selected for annotation

Dataset: Annotation

- "Complete" annotation of all objects
- Annotated over web with <u>written guidelines</u>
  - High quality (?)

Dataset: Annotation

- "Complete" annotation of all objects
- Annotated over web with written guidelines
  - High quality (?)

20 classes.
- Train / validation data has 11,530 images containing 27,450 ROI annotated objects and 6,929 segmentations.

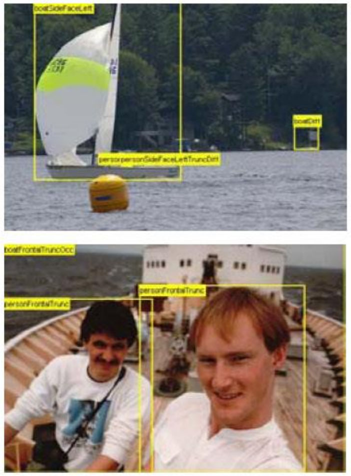
Examples

Aeroplane

Bicycle

Bird

Boat



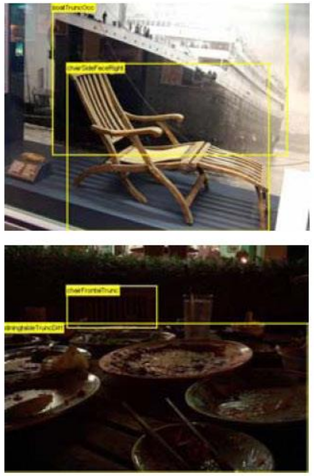
Bottle

Bus

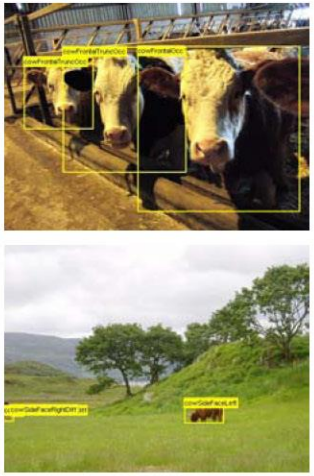
Car

Cat

Chair

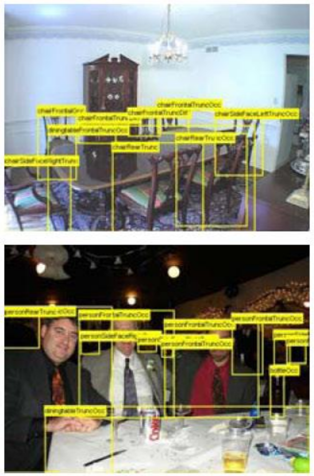


Cow



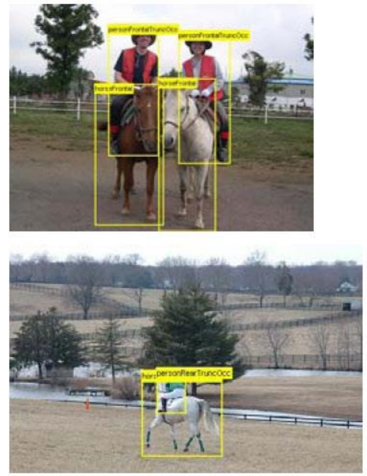
Examples

Dining Table



Dog

Horse

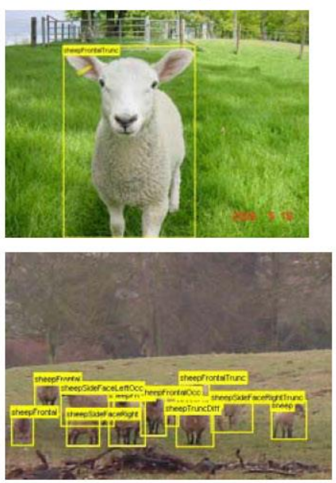


Motorbike

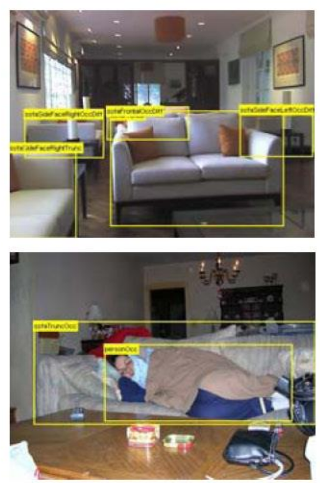
Person

Potted Plant

Sheep



Sofa



Train

TV/Monitor

Classification Challenge

- Predict whether at least one object of a given class is present in an image

is there a cat?

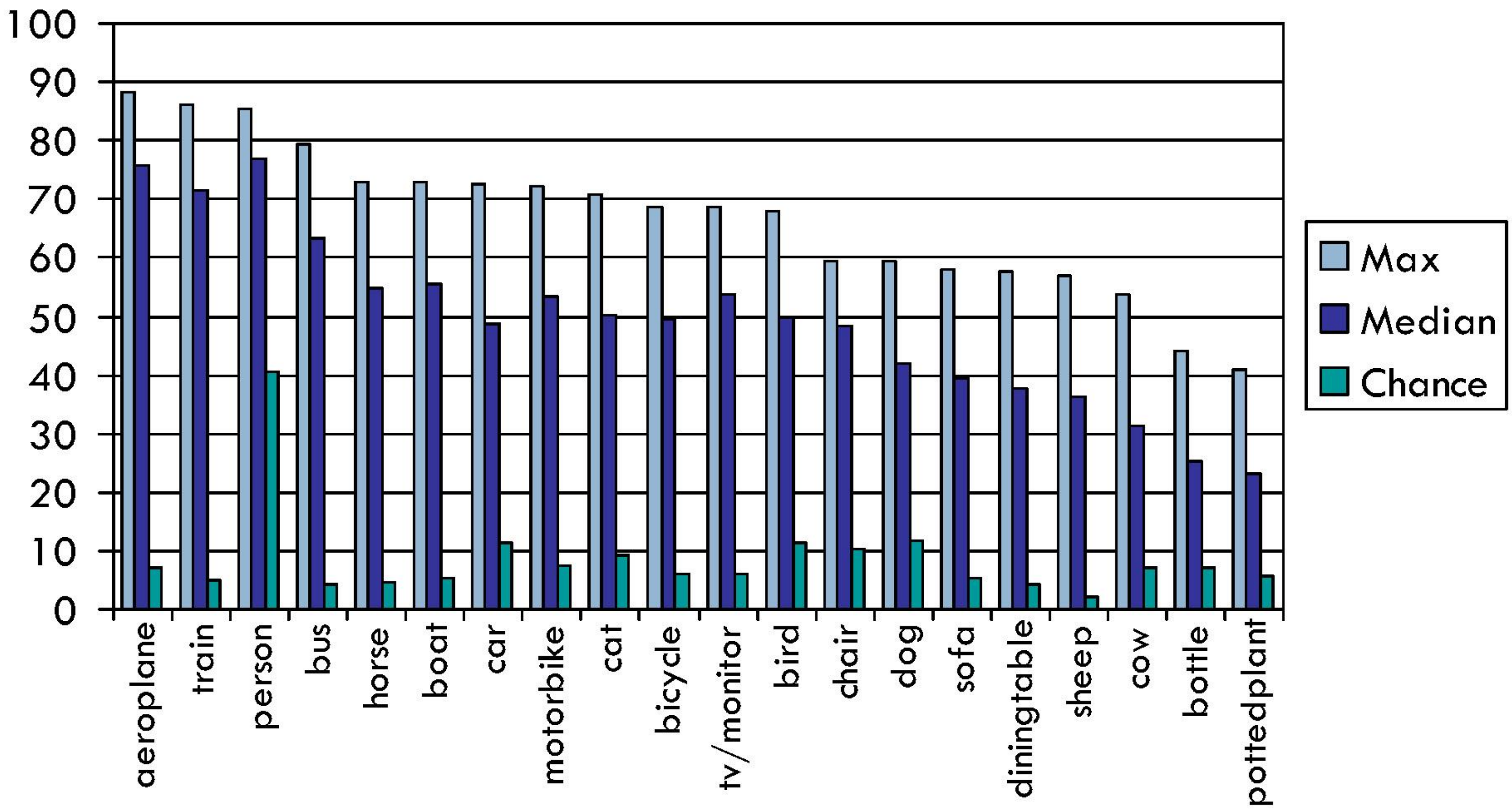
Results: AP by Method and Class

	aero plane	bicycle	bird	boat	bottle	bus	car	cat	chair	cow	dining table	dog	horse	motor bike	person	potted plant	sheep	sofa	train	tv/ monitor
CVC_FLAT	85.3	57.8	66.0	66.1	36.2	70.6	60.6	63.5	55.1	44.6	53.4	49.1	64.4	66.8	84.8	37.4	44.1	47.9	81.9	67.5
CVC_FLAT-HOG-ESS	86.3	60.7	66.4	65.3	41.0	71.7	64.7	63.9	55.5	40.1	51.3	45.9	65.2	68.9	85.0	40.8	49.0	49.1	81.8	68.6
CVC_PLUS	86.6	58.4	66.7	67.3	34.8	70.4	60.0	64.2	52.5	43.0	50.8	46.5	64.1	66.8	84.4	37.5	45.1	45.4	82.1	67.0
FIRSTNIKON_AVGSRKDA	83.3	59.3	62.7	65.3	30.2	71.6	58.2	62.2	54.3	40.7	49.2	50.0	66.6	62.9	83.3	34.2	48.2	46.1	83.4	65.5
FIRSTNIKON_AVGSVM	83.8	58.2	62.6	65.2	32.0	69.8	57.7	61.1	54.5	44.0	50.3	49.6	64.6	61.7	83.2	33.4	46.5	48.0	81.6	65.3
FIRSTNIKON_BOOSTSRKDA	83.0	59.2	61.4	64.6	33.2	71.1	57.5	61.0	54.8	40.7	48.3	50.0	65.5	63.4	82.8	32.8	47.0	47.1	83.3	64.6
FIRSTNIKON_BOOSTSVMS	83.5	56.8	61.8	65.5	33.2	69.7	57.3	60.5	54.6	43.1	48.3	50.3	64.3	62.4	82.3	32.9	46.9	48.4	82.0	64.2
LEAR_CHI-SVM-MULT-LOC	79.5	55.5	54.5	63.9	43.7	70.3	66.4	56.5	54.4	38.8	44.1	46.2	58.5	64.2	82.2	39.1	41.3	39.8	73.6	66.2
NECUIUC_CDCV	88.1	68.0	68.0	72.5	41.0	78.9	70.4	70.4	58.1	53.4	55.7	59.3	73.1	71.3	84.5	32.3	53.3	56.7	86.0	66.8
NECUIUC_CLS-DTCT	88.0	68.6	67.9	72.9	44.2	79.5	72.5	70.8	59.5	53.6	57.5	59.0	72.6	72.3	85.3	36.6	56.9	57.9	85.9	68.0
NECUIUC_LL-CDCV	87.1	67.4	65.8	72.3	40.9	78.3	69.7	69.7	58.5	50.1	55.1	56.3	71.8	70.8	84.1	31.4	51.5	55.1	84.7	65.2
NECUIUC_LN-CDCV	87.7	67.8	68.1	71.1	39.1	78.5	70.6	70.7	57.4	51.7	53.3	59.2	71.6	70.6	84.0	30.9	51.7	55.9	85.9	66.7
UVASURREY_BASELINE	84.1	59.2	62.7	65.4	35.7	70.6	59.8	61.3	56.7	45.3	52.4	50.6	66.1	66.6	83.7	34.8	47.2	47.7	80.8	65.9
UVASURREY_MKFDA+BOW	84.7	63.9	66.1	67.3	37.9	74.1	63.2	64.0	57.1	46.2	54.7	53.5	68.1	70.6	85.2	38.5	47.2	49.3	83.2	68.1
UVASURREY_TUNECOLORKERNELSEL	85.0	62.8	65.1	66.5	37.6	73.5	62.1	62.0	57.4	45.1	54.5	52.5	67.7	69.8	84.8	39.1	46.8	49.9	82.9	68.1
UVASURREY_TUNECOLORSPECKDA	84.6	62.4	65.6	67.2	39.4	74.0	63.4	62.8	56.7	43.8	54.7	52.7	67.3	70.6	85.0	38.8	46.9	50.0	82.2	66.2

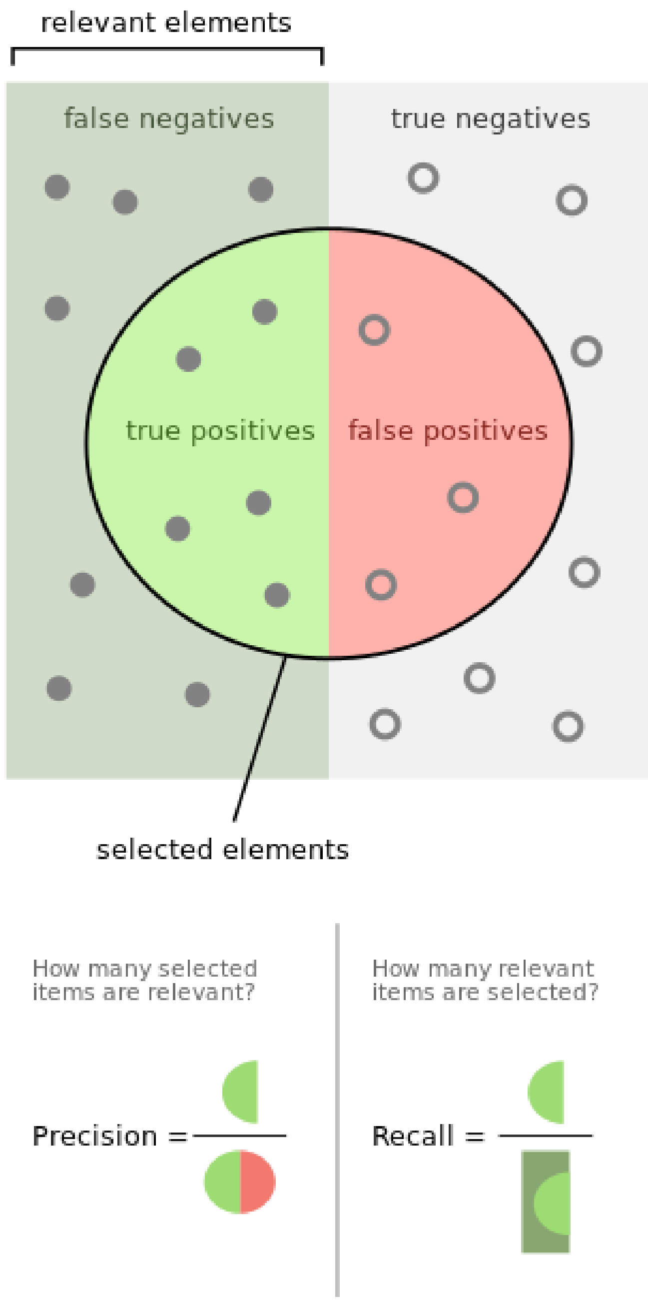
- Only methods in 1st, 2nd or 3rd place by group shown
- Groups: CVC, FIRST/Nikon, NEC/UIUC, UVA/Surrey

AP by Class

AP = average precision

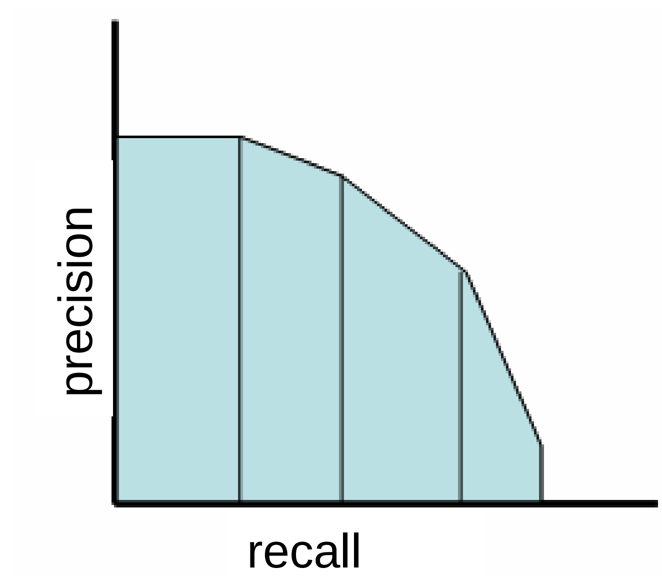


- Max AP: 88.1% (aeroplane) ... 40.8% (potted plant)



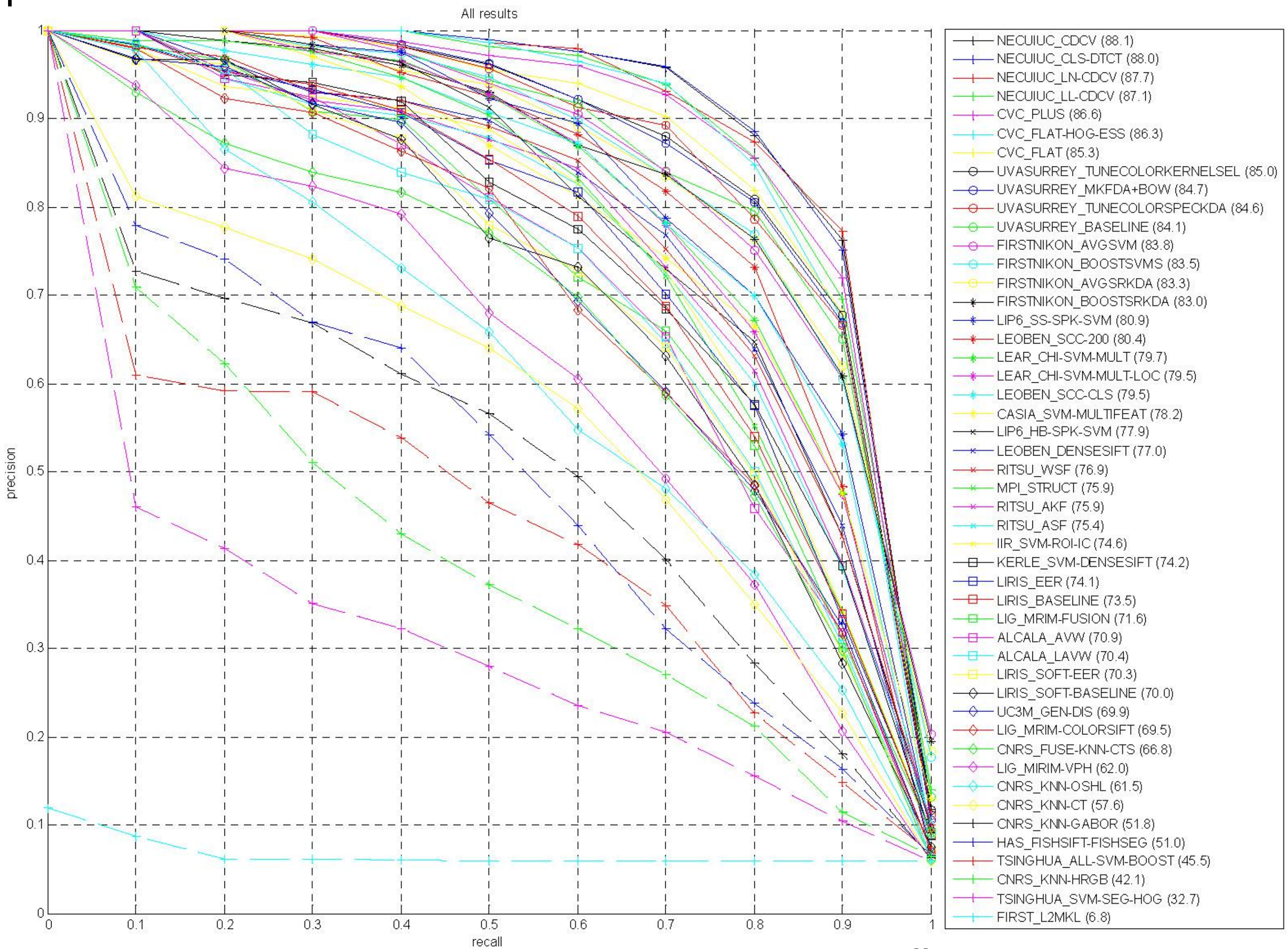
Set threshold on ‘detection’ to create one pair of precision / recall values.

Vary threshold across all values to generate precision / recall curves:



Precision/Recall: Aeroplane (All)

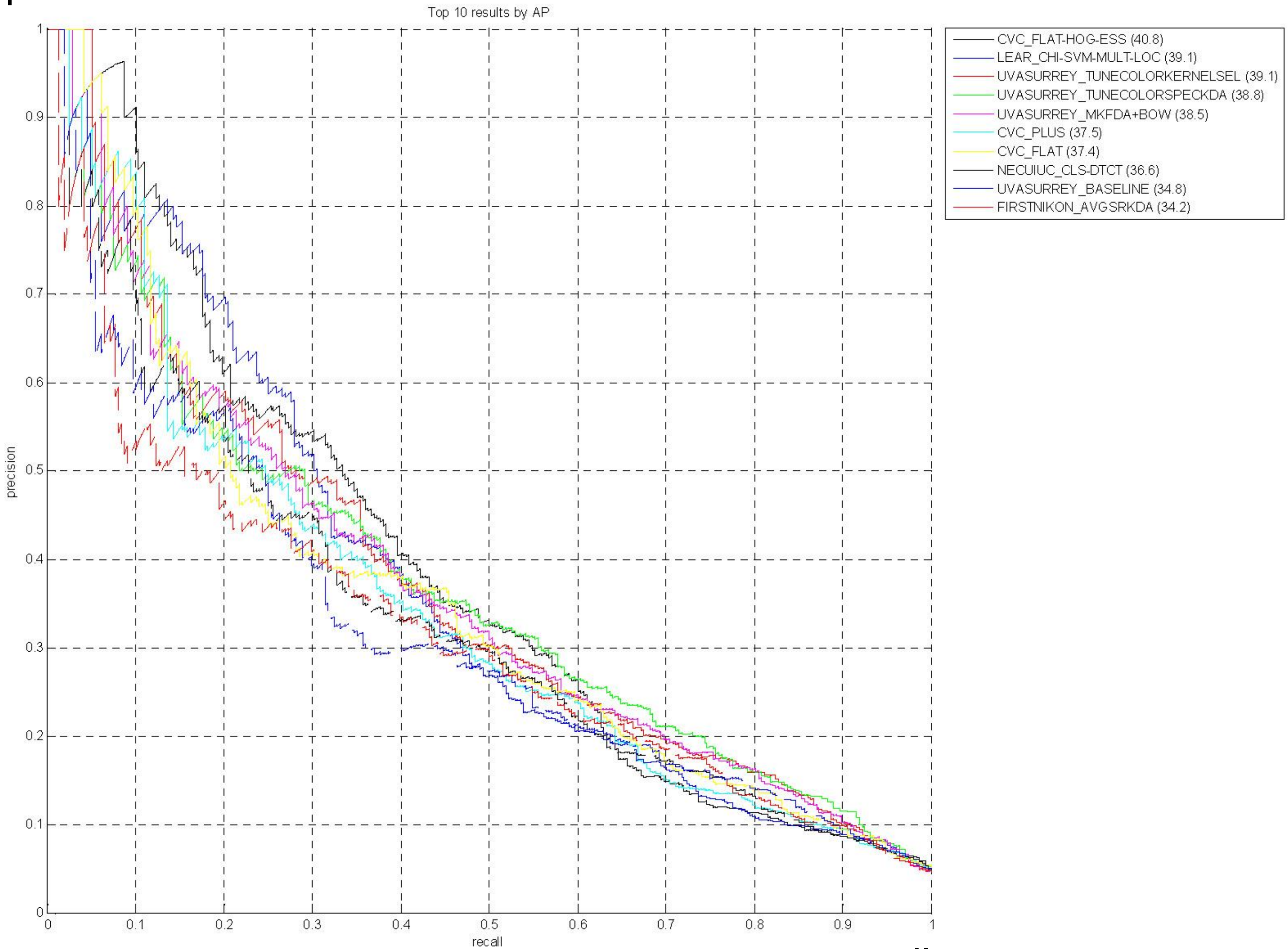
precision



recall

Precision/Recall: Potted plant (Top 10 by AP)

precision



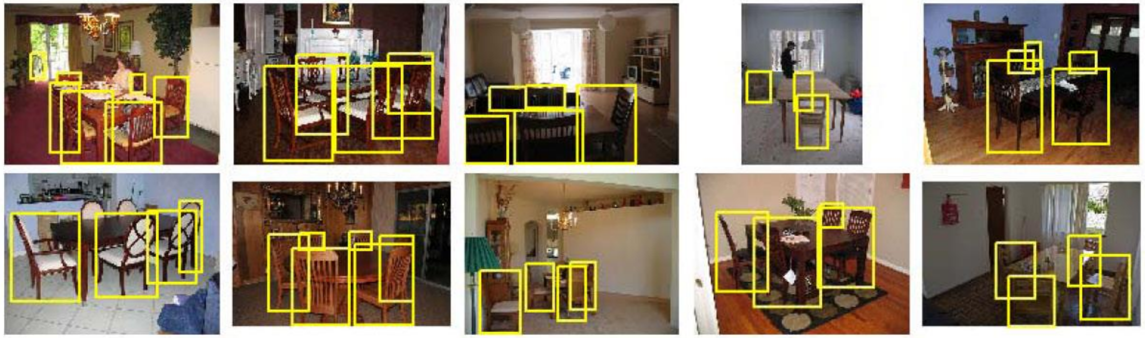
recall

Ranked Images: Aeroplane

- Class images: Highest ranked

Ranked Images: Chair

- Class images: Highest ranked

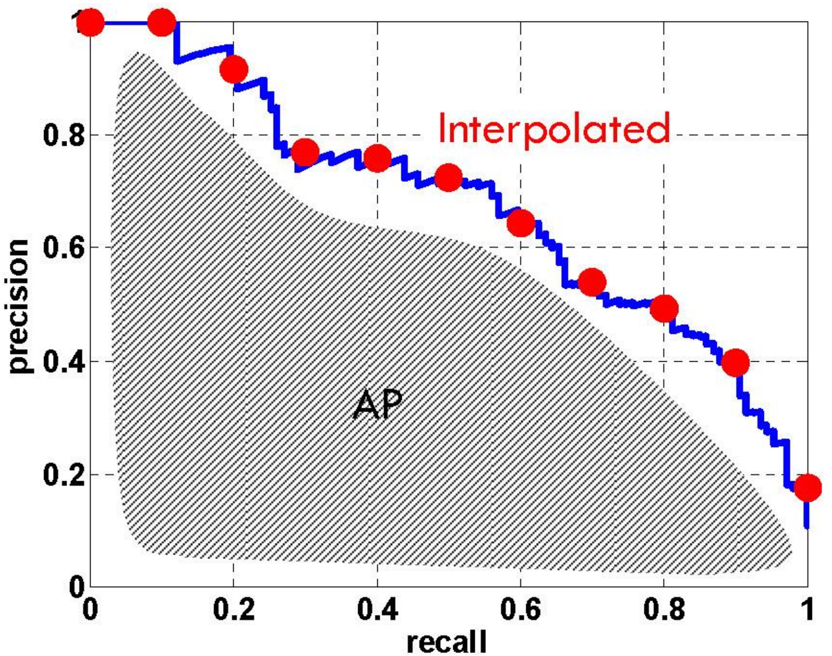


Detection Challenge

- Predict the bounding boxes of all objects of a given class in an image (if any)

Evaluation

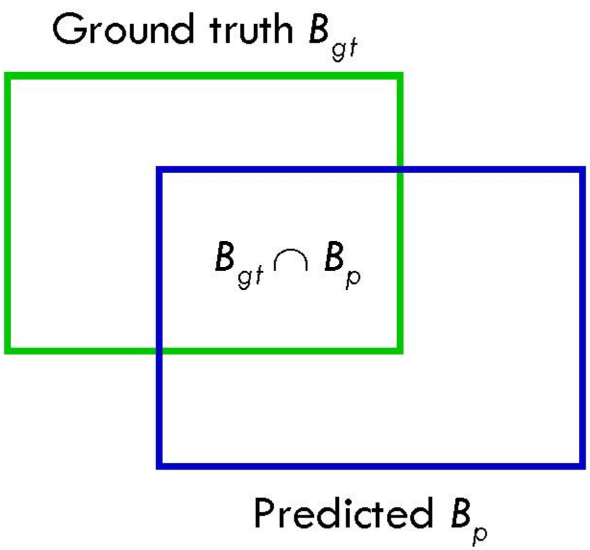
- Average Precision [TREC] averages precision over the entire range of recall
  - Curve interpolated to reduce influence of "outliers"



- A good score requires both high recall and high precision
- Application-independent
- Penalizes methods giving high precision but low recall

Evaluating Bounding Boxes

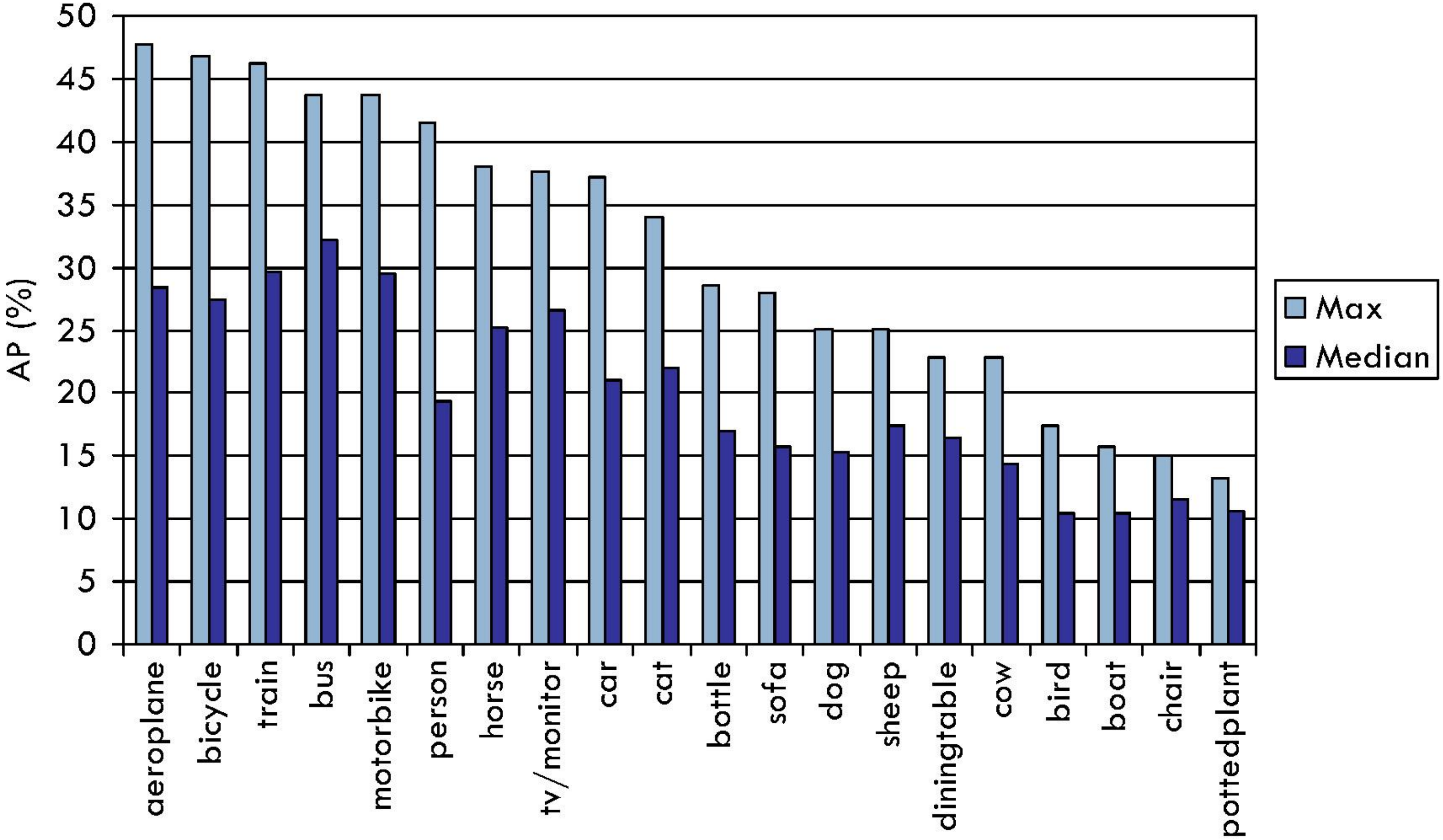
- Area of Overlap (AO) Measure



$$AO(B_{gt}, B_p) = \frac{|B_{gt} \bigcap B_p|}{|B_{gt} \bigcup B_p|}$$

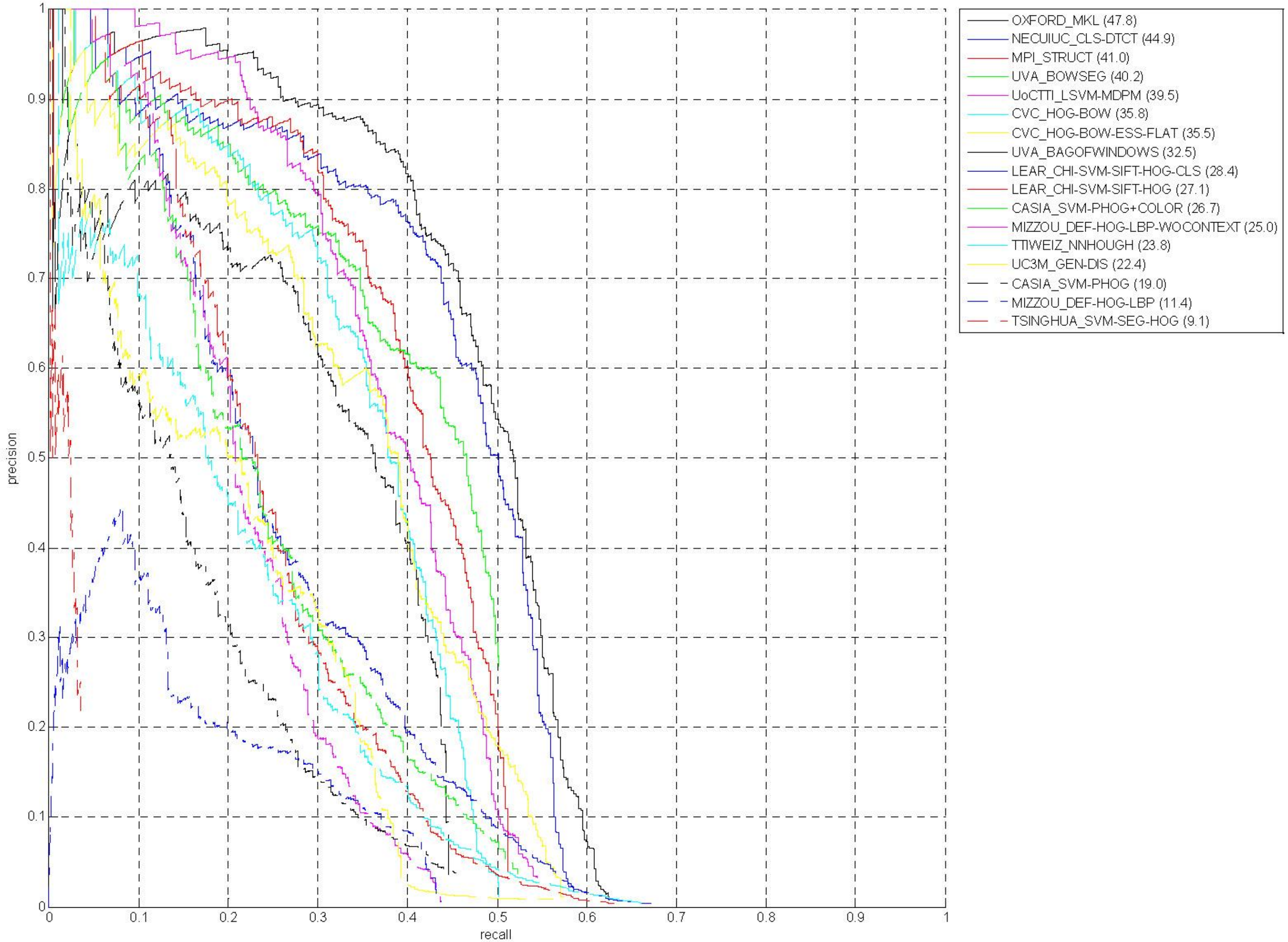
- Need to define a threshold *t* such that $AO(B_{gt}, B_p)$ implies a correct detection: 50%

AP by Class

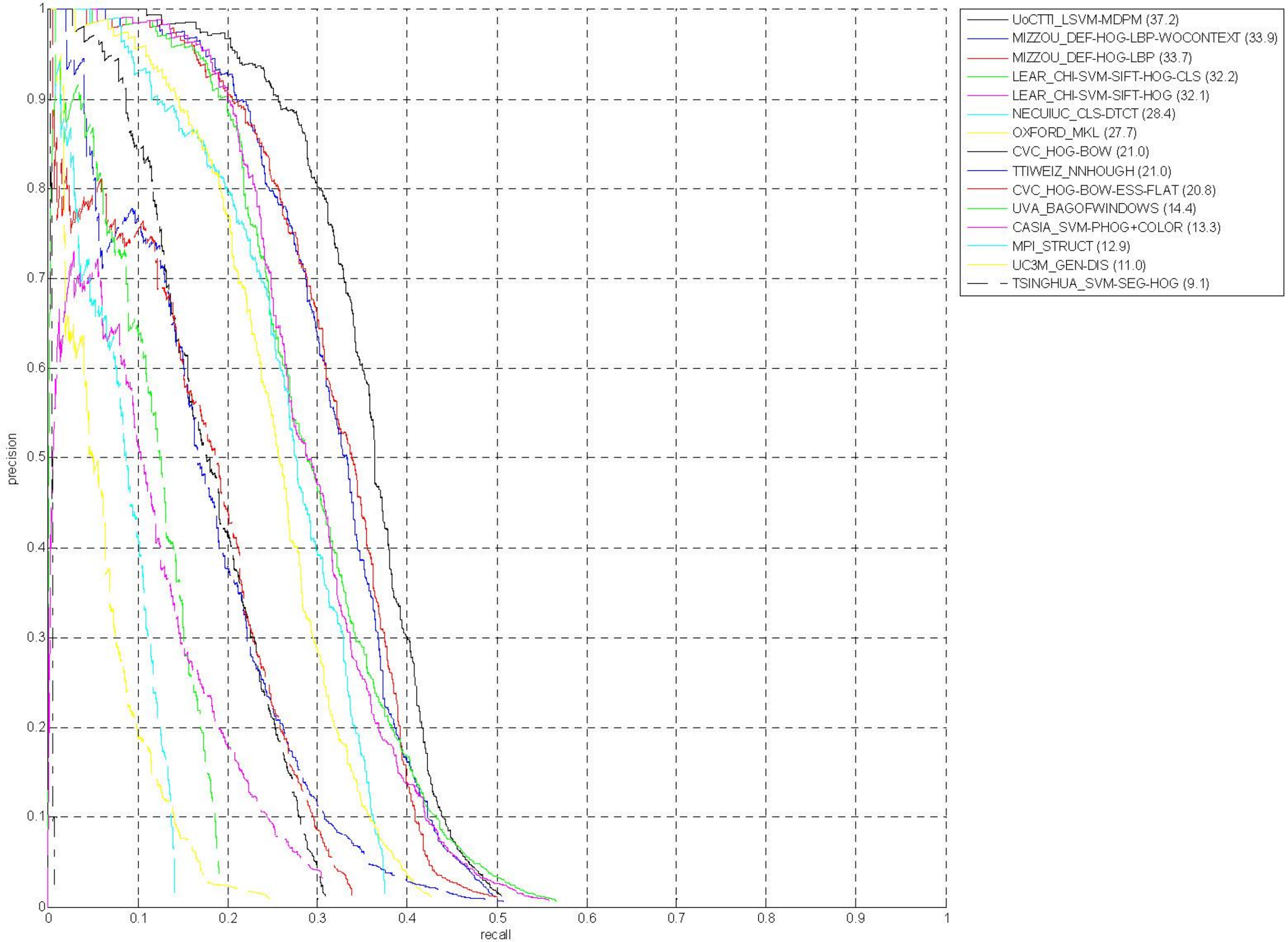


Chance essentially 0

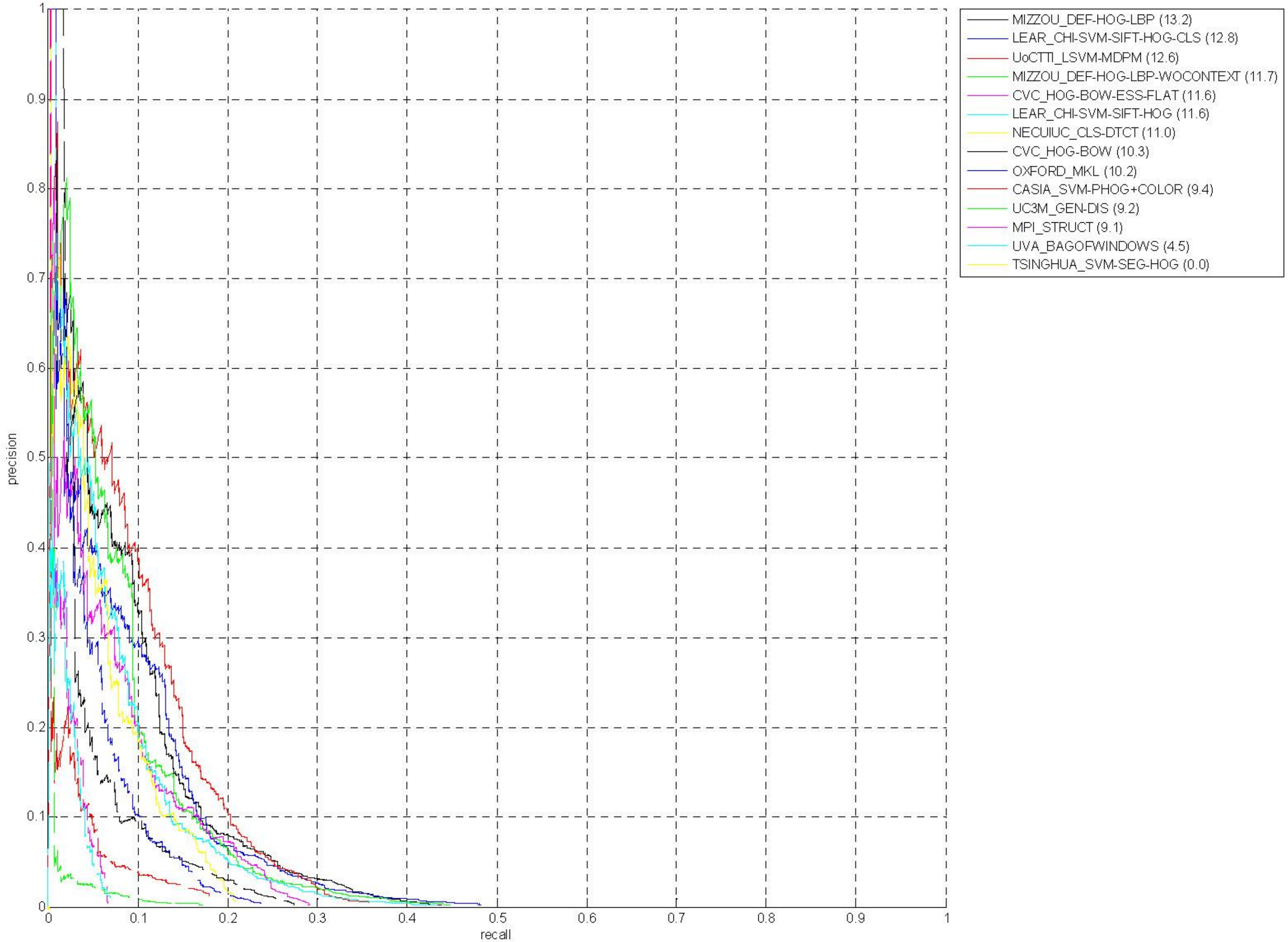
Precision/Recall - Aeroplane



Precision/Recall - Car



Precision/Recall – Potted plant



True Positives - Person

UoCTTI_LSVM-MDPM

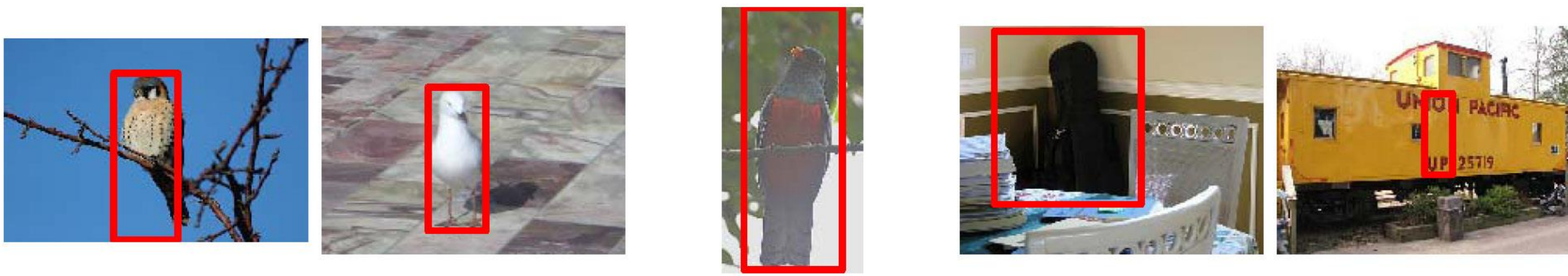
MIZZOU_DEF-HOG-LBP

NECUIUC_CLS-DTCT

False Positives - Person

UoCTTI_LSVM-MDPM

MIZZOU_DEF-HOG-LBP



NECUIUC_CLS-DTCT

“Near Misses” - Person

UoCTTI_LSVM-MDPM

MIZZOU_DEF-HOG-LBP

NECUIUC_CLS-DTCT

True Positives - Bicycle

UoCTTI_LSVM-MDPM

OXFORD_MKL

NECUIUC_CLS-DTCT

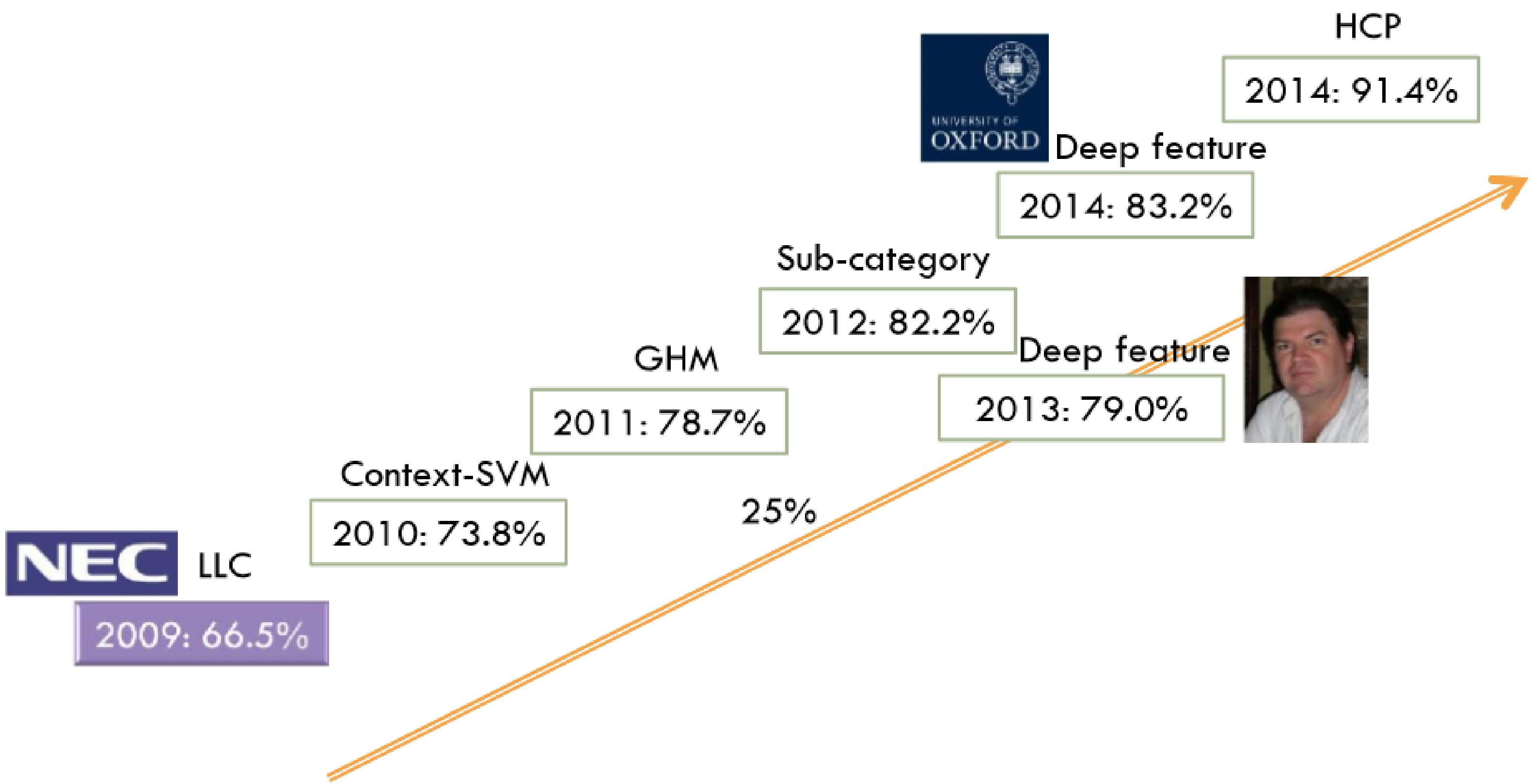
False Positives - Bicycle

UoCTTI_LSVM-MDPM

OXFORD_MKL

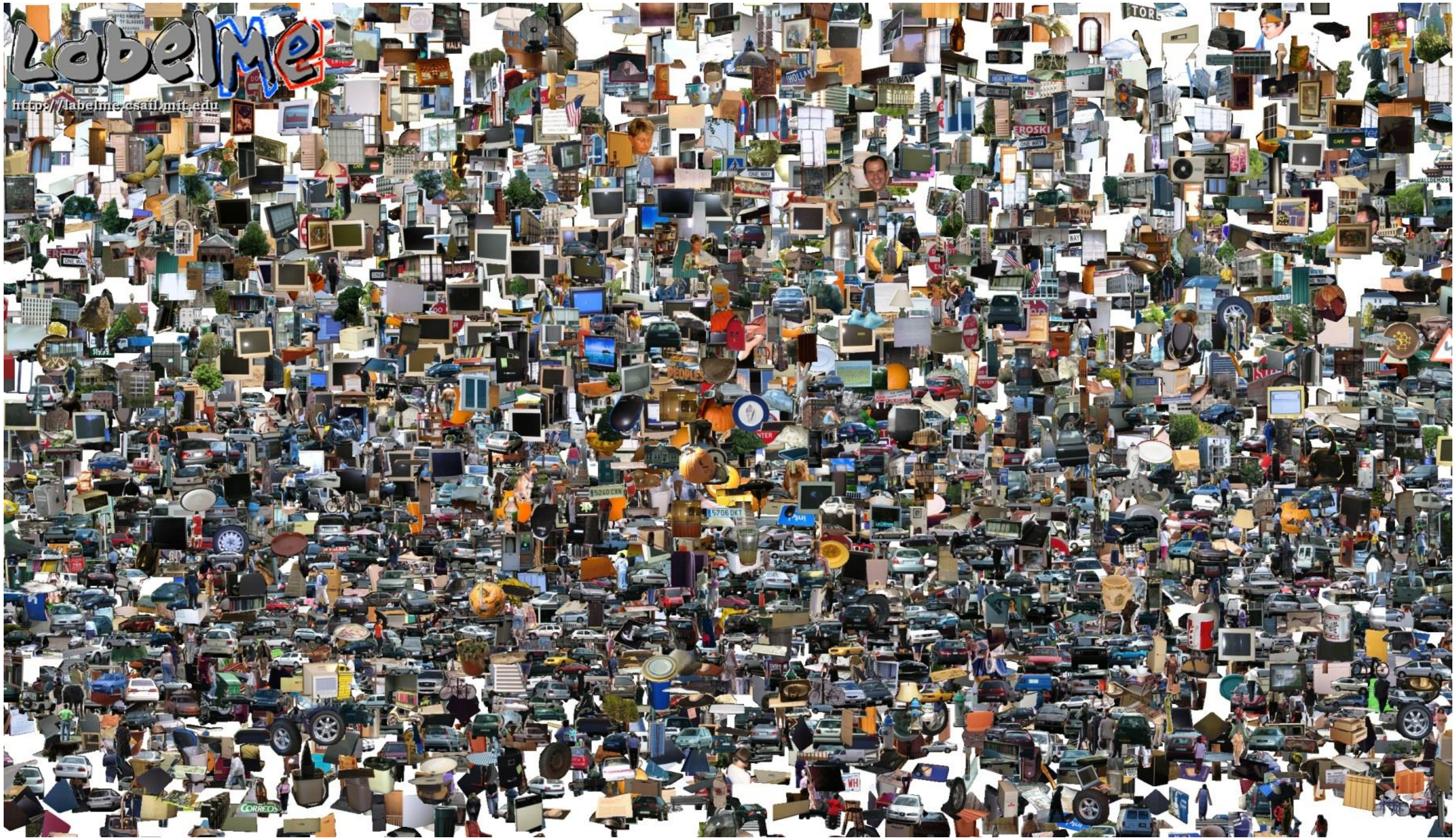
NECUIUC_CLS-DTCT

PASCAL VOC: 2010-2014



Shuicheng Yan

Opportunities of Scale



Computer Vision

James Hays

Many slides from James Hays, Alyosha Efros, and Derek Hoiem

Graphic from Antonio Torralba

Computer Vision so far

- The geometry of image formation
  - Ancient / Renaissance
- Signal processing / Convolution
  - 1800, but really the 50’s and 60’s
- Hand-designed Features for recognition, either instance-level or categorical
  - 1999 (SIFT), 2003 (Video Google), 2005 (Dalal-Triggs), 2006 (spatial pyramid)
- Learning from Data
  - 1991 (EigenFaces) but late 90’s to now especially

What has changed in the last decade?

- The Internet
- Crowdsourcing
- Learning representations from the data these sources provide (deep learning)

Google and massive data-driven algorithms

A.I. for the postmodern world:

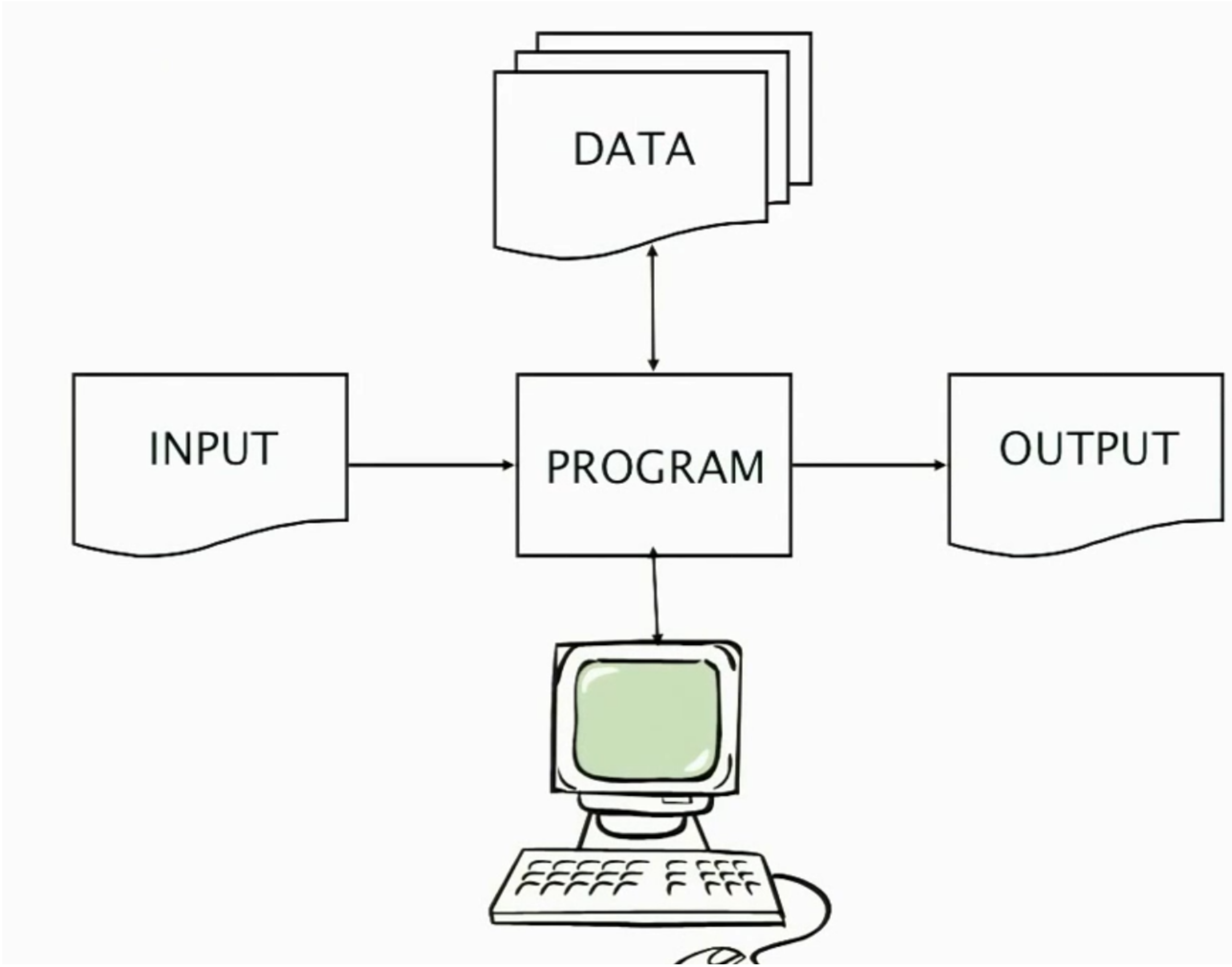
- all questions have already been answered…many times, in many ways
- Google is dumb, the “intelligence” is <u>in the data</u>

The Unreasonable Effectiveness of Data

Peter Norvig
Google

Peter Norvig

The Unreasonable
Effectiveness of Data


DATA
INPUT
PROGRAM
OUTPUT

Chinese Room, John Searle (1980)

If a machine can convincingly simulate an intelligent conversation, does it necessarily understand? In the experiment, Searle imagines himself in a room, acting as a computer by manually executing a program that convincingly simulates the behavior of a native Chinese speaker.

Most of the discussion consists of attempts to refute it. "The overwhelming majority," notes *BBS* editor Stevan Harnad,“ still think that the Chinese Room Argument is dead wrong." The sheer volume of the literature that has grown up around it inspired Pat Hayes to quip that the field of cognitive science ought to be redefined as "the ongoing research program of showing Searle's Chinese Room Argument to be false.

Yann LeCun

October 23 at 9:58pm ·

Questions from the piece:

Q1. Does the Chinese Room argument prove the impossibility of machine consciousness?
A1: Hell no. ... See More

Can Machines Become Moral?

The question is heard more and more often, both from those who think that machines cannot become moral, and who think that to believe otherwise is a dangerous illusion, and from those who think that machines must become moral,...

BIGQUESTIONSONLINE.COM | BY DON HOWARD

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Big Idea

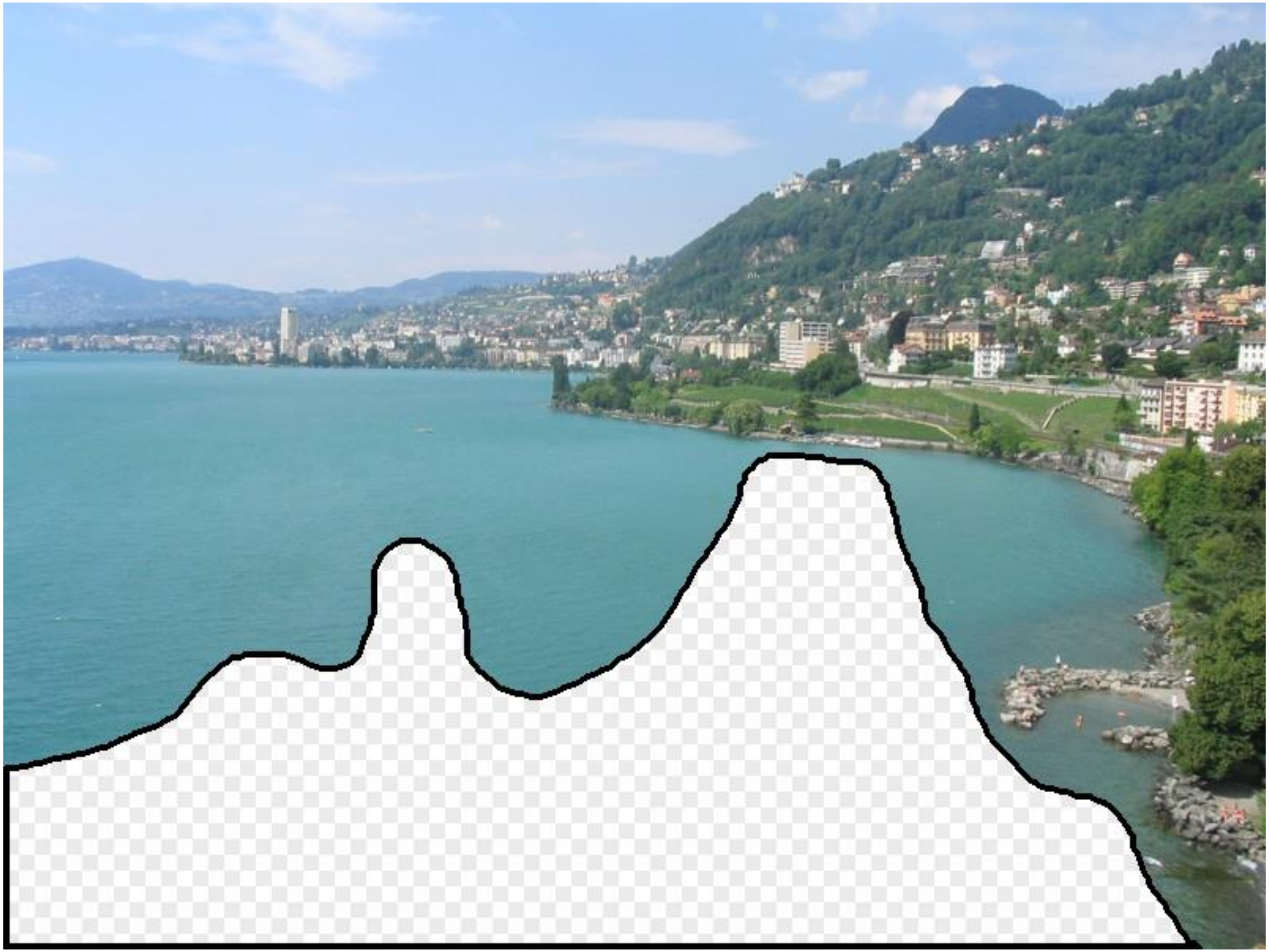
- Do we need computer vision systems to have strong AI-like reasoning about our world?
- What if invariance / generalization isn't actually the core difficulty of computer vision?
- What if we can perform high level reasoning with brute-force, data-driven algorithms?

Image Completion Example

[Hays and Efros. Scene Completion Using Millions of Photographs. SIGGRAPH 2007 and CACM October 2008.]

http://graphics.cs.cmu.edu/projects/scene-completion/

What should the missing region contain?



Which is the original?

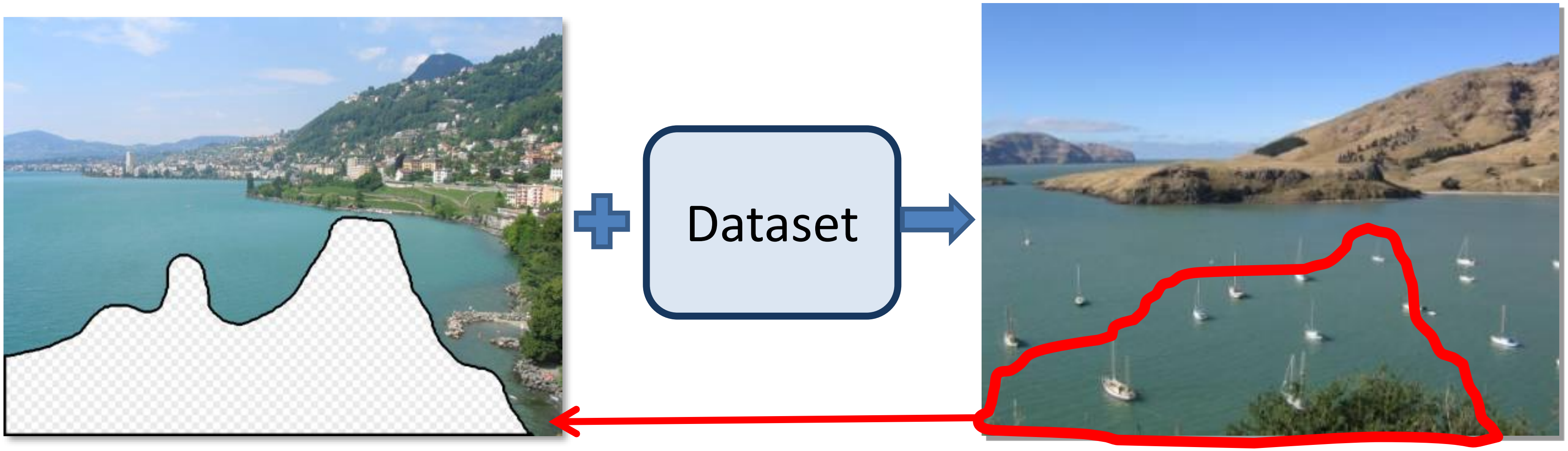
(a)

(b)

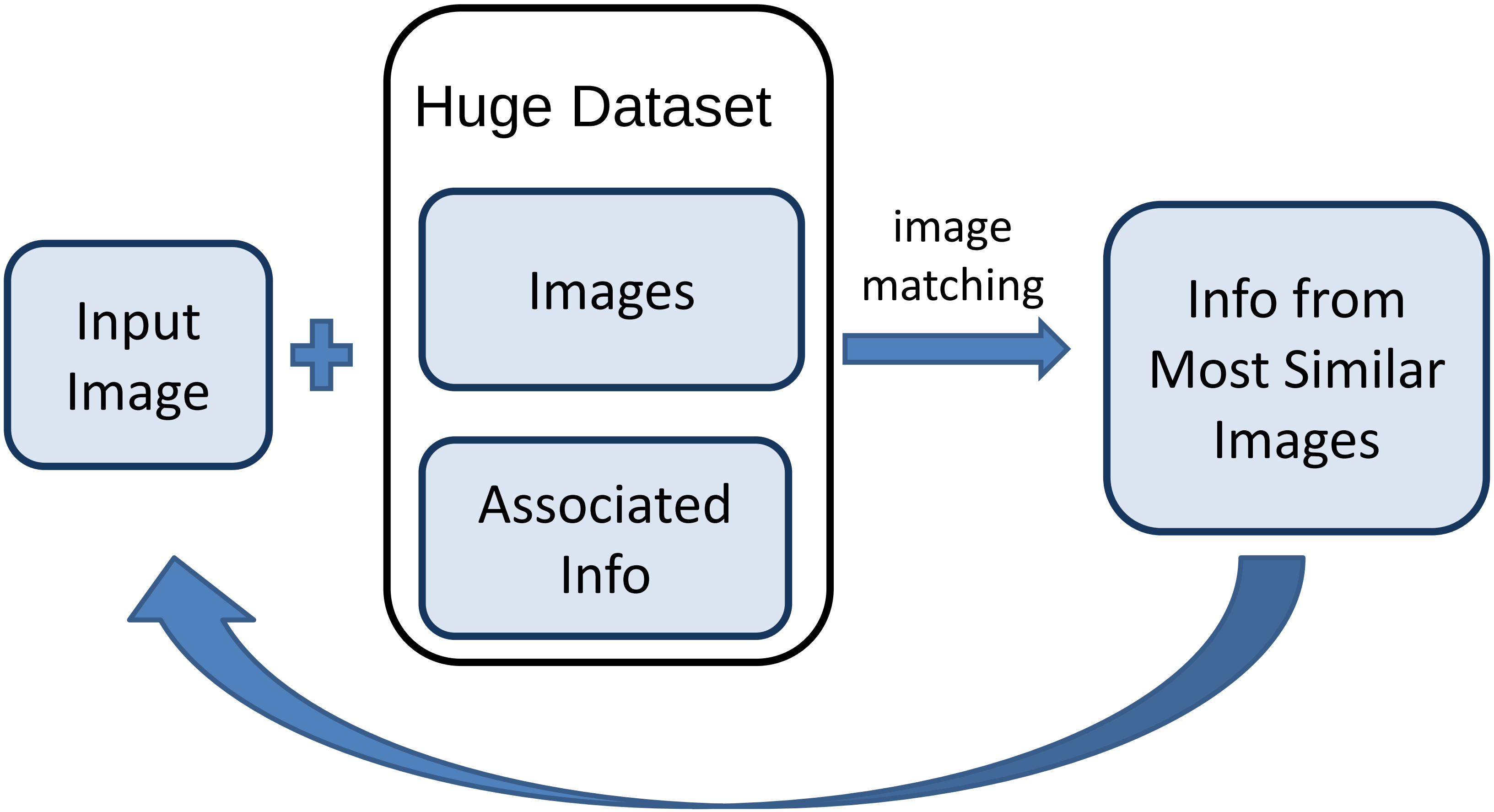
(c)

How it works

- Find a similar image from a large dataset
- Blend a region from that image into the hole

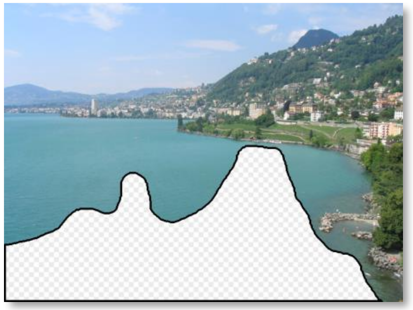


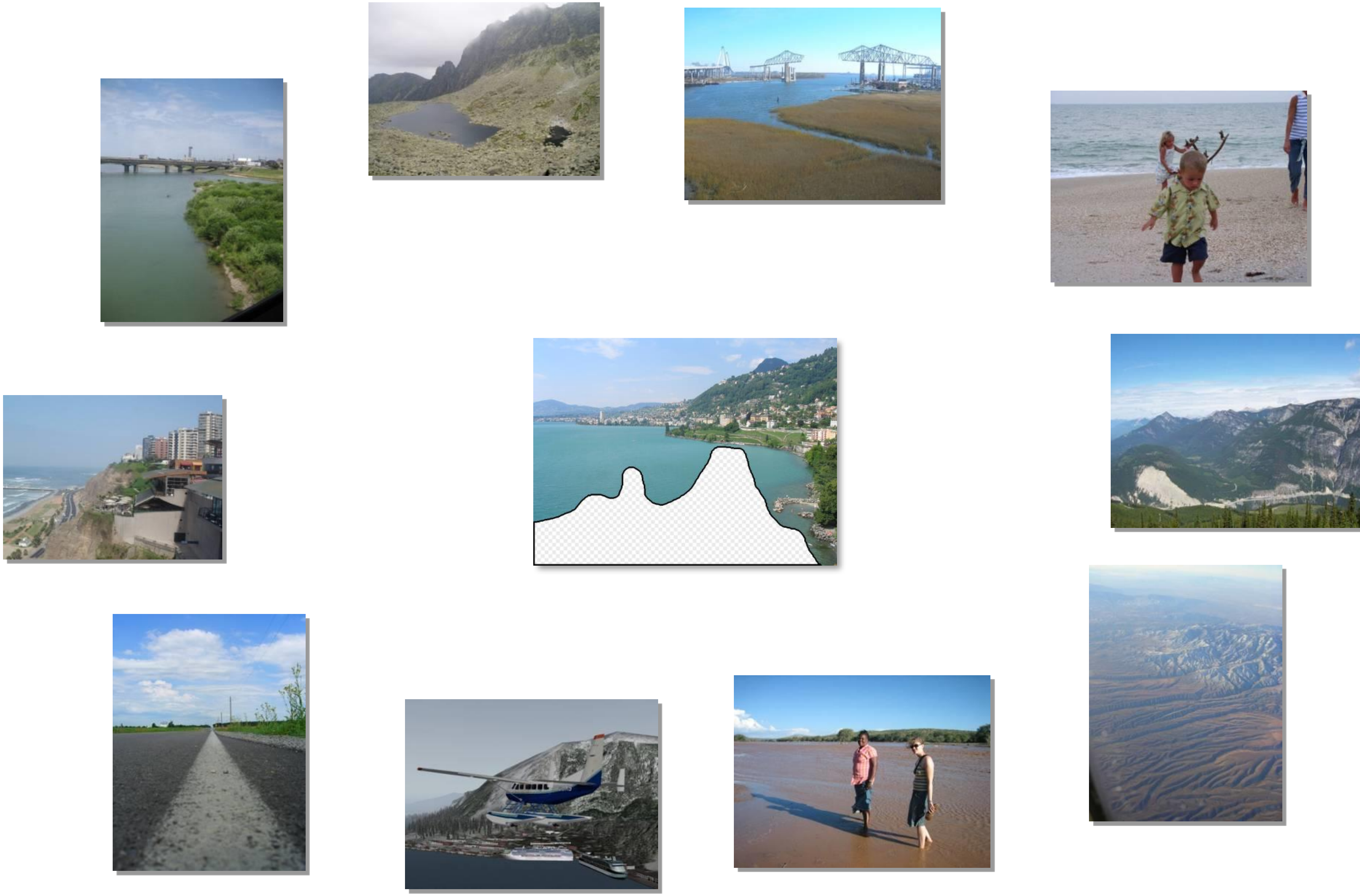
General Principal



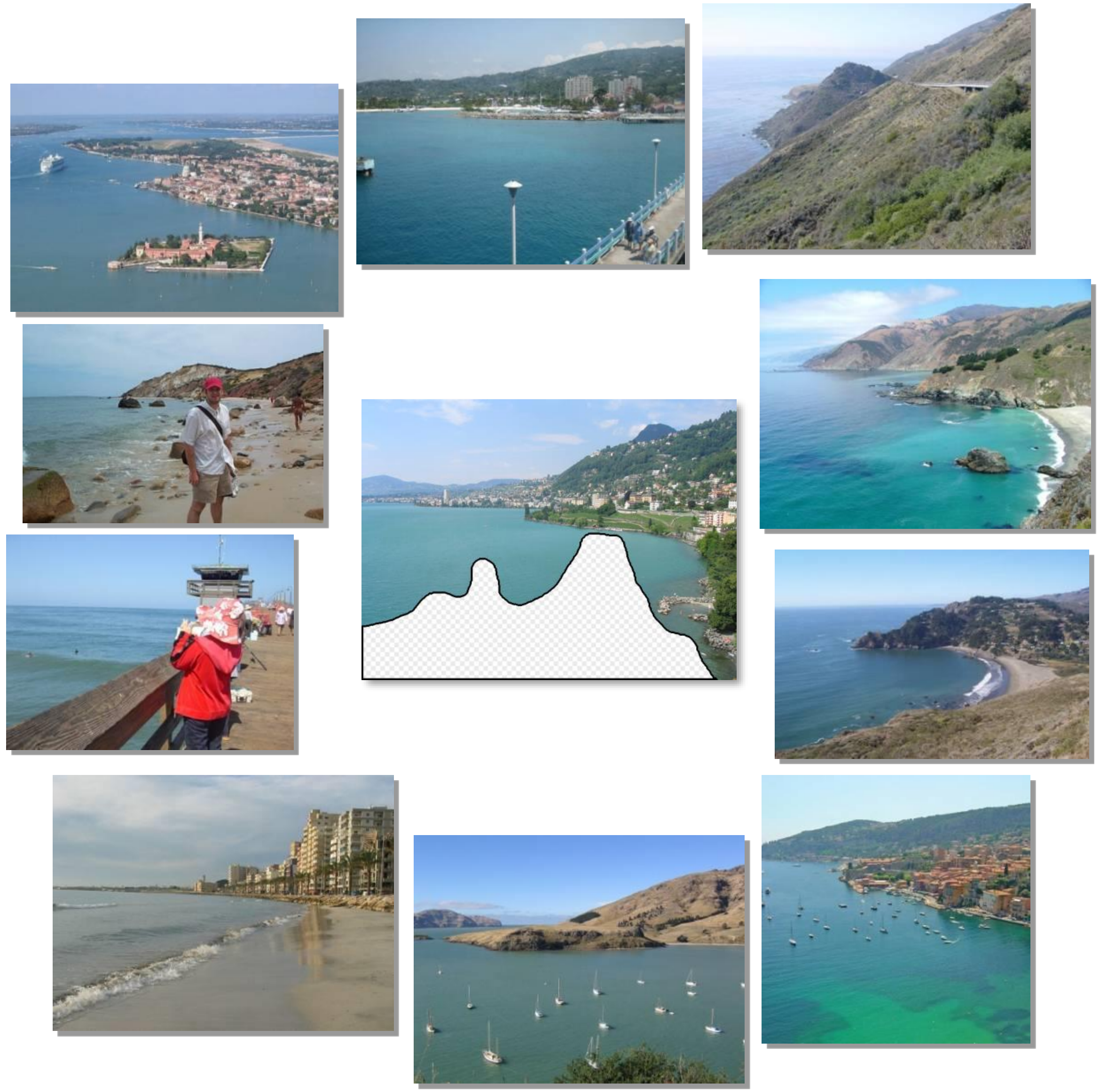
Hopefully, If you have enough images, the dataset will contain very similar images that you can find with simple matching methods.

How many images is enough?





Nearest neighbors from a
collection of 20 thousand images



Nearest neighbors from a collection of 2 million images

Image Data on the Internet

- Flickr (as of Sept. 19th, 2010)
  - 5 billion photographs
  - 100+ million geotagged images
- Facebook (as of 2009)
  - 15 billion

http://royal.pingdom.com/2010/01/22/internet-2009-in-numbers/

Image Data on the Internet

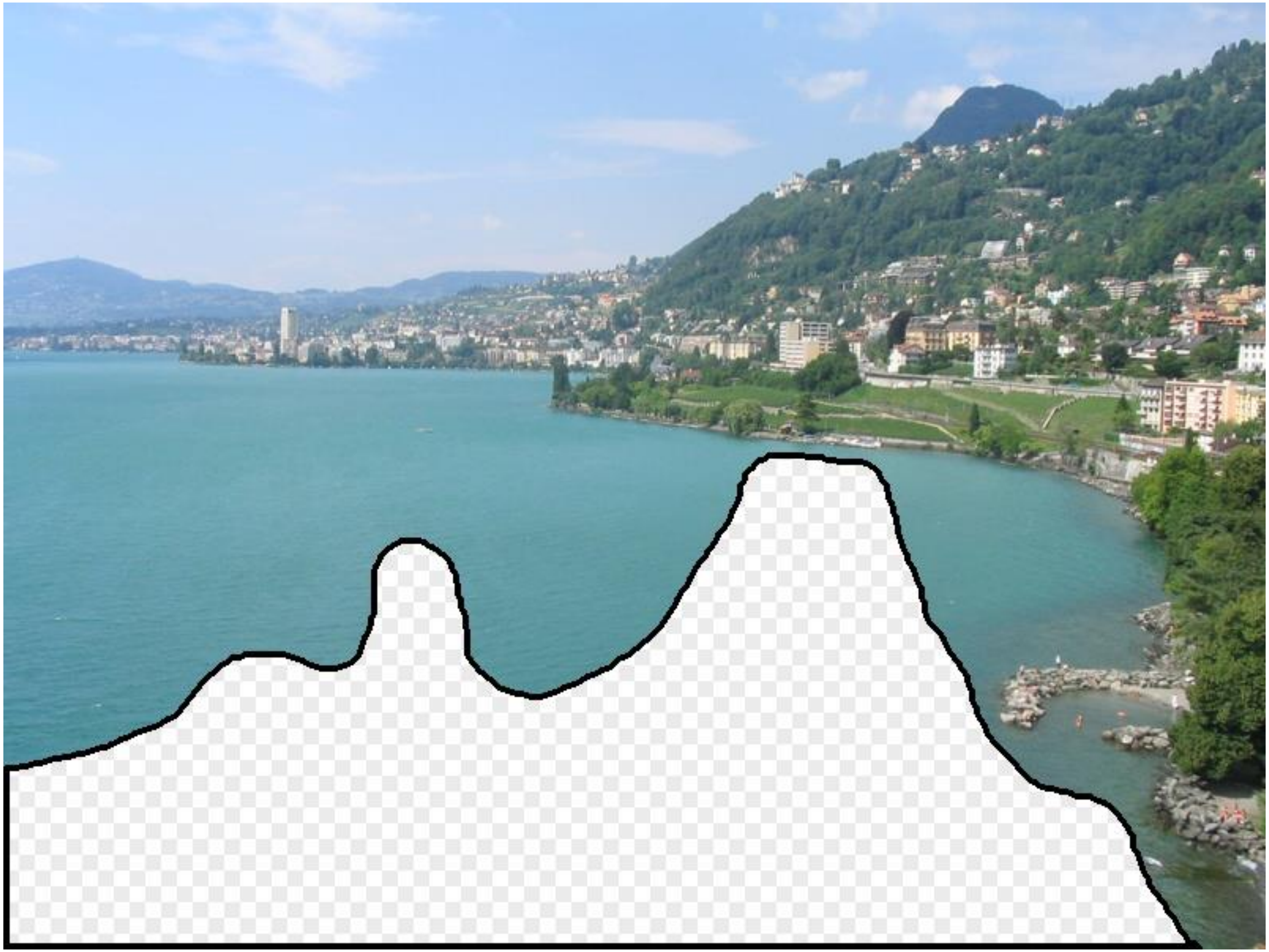
- Flickr (as of Nov 2013)
  - 10 billion photographs
  - 100+ million geotagged images
  - 3.5 million a day
- Facebook (as of Sept 2013)
  - 250 billion+
  - 300 million a day
- Instagram
  - 55 million a day

Image completion: how it works

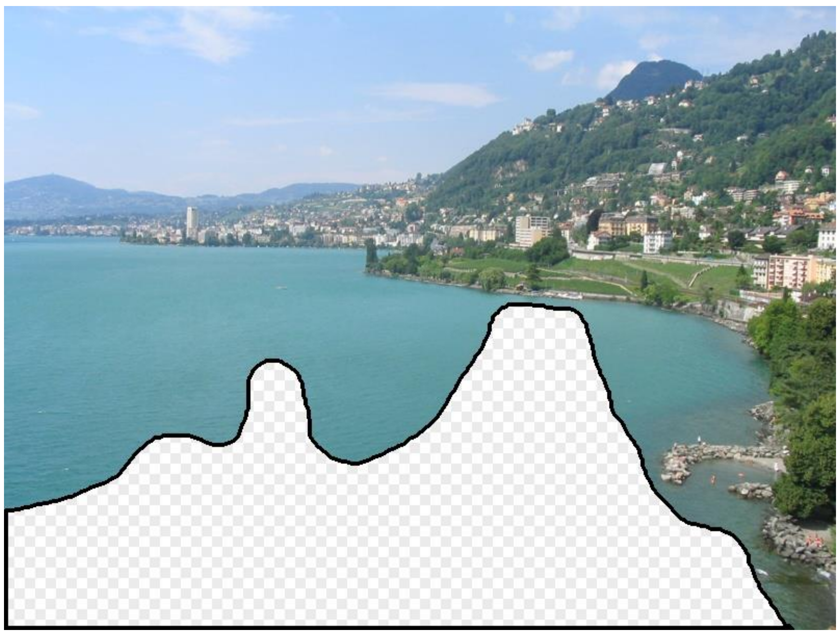
[Hays and Efros. Scene Completion Using Millions of Photographs. SIGGRAPH 2007 and CACM October 2008.]

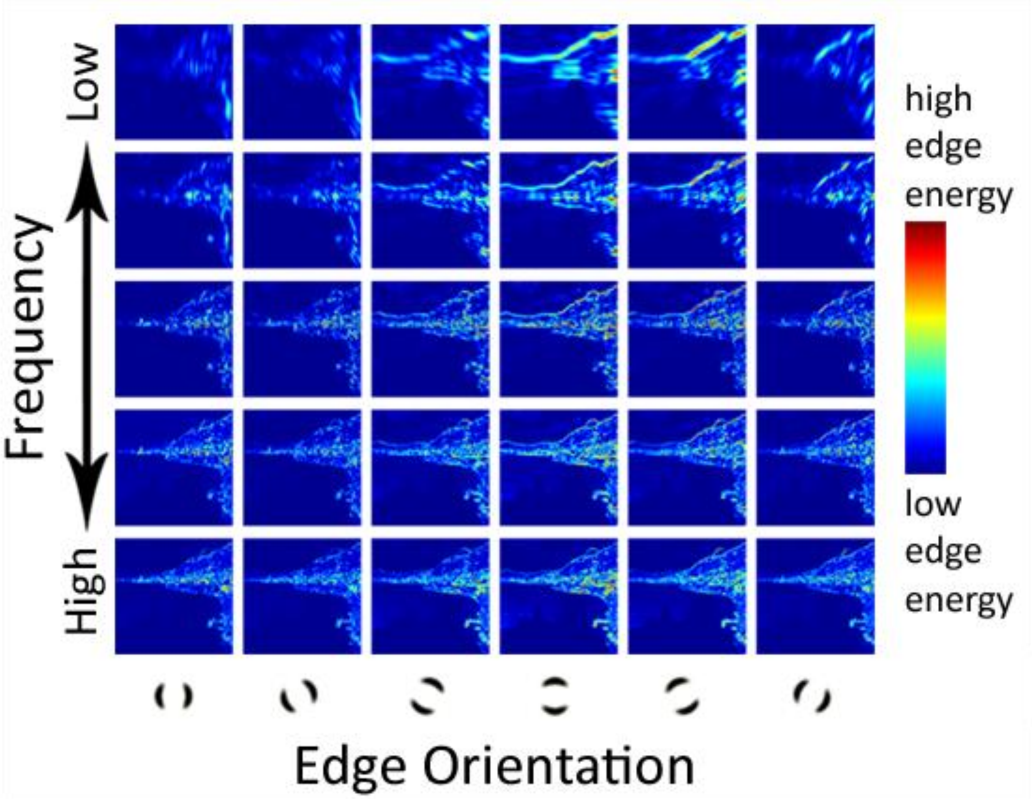
The Algorithm

Scene Matching

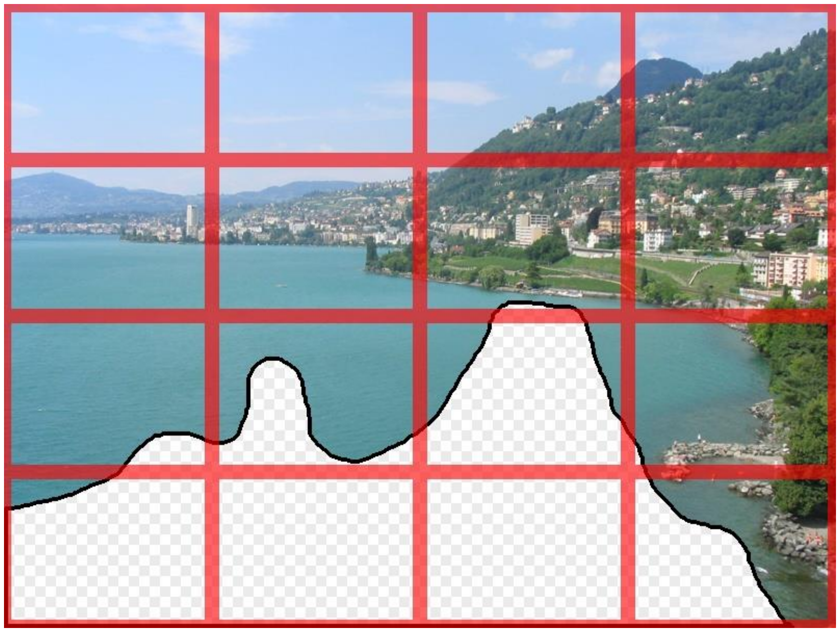


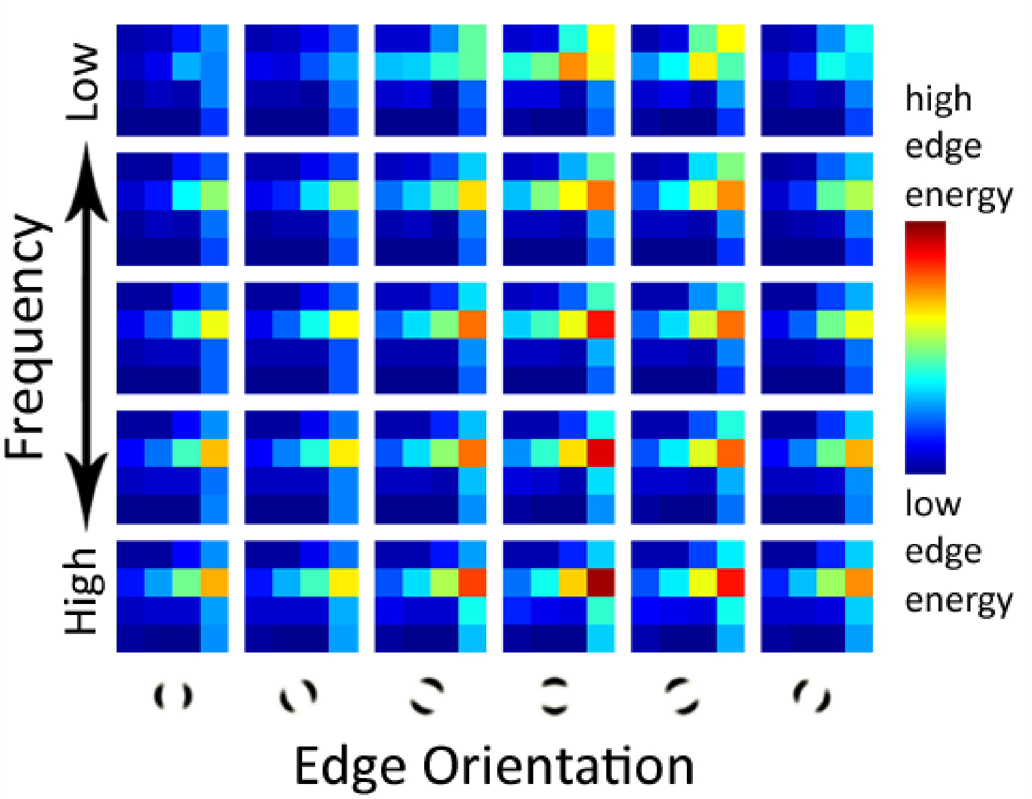
Scene Descriptor





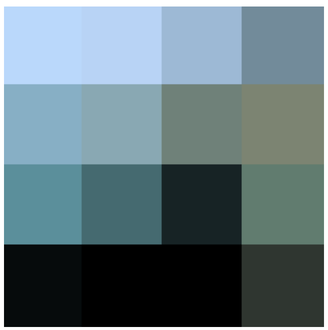
Scene Descriptor



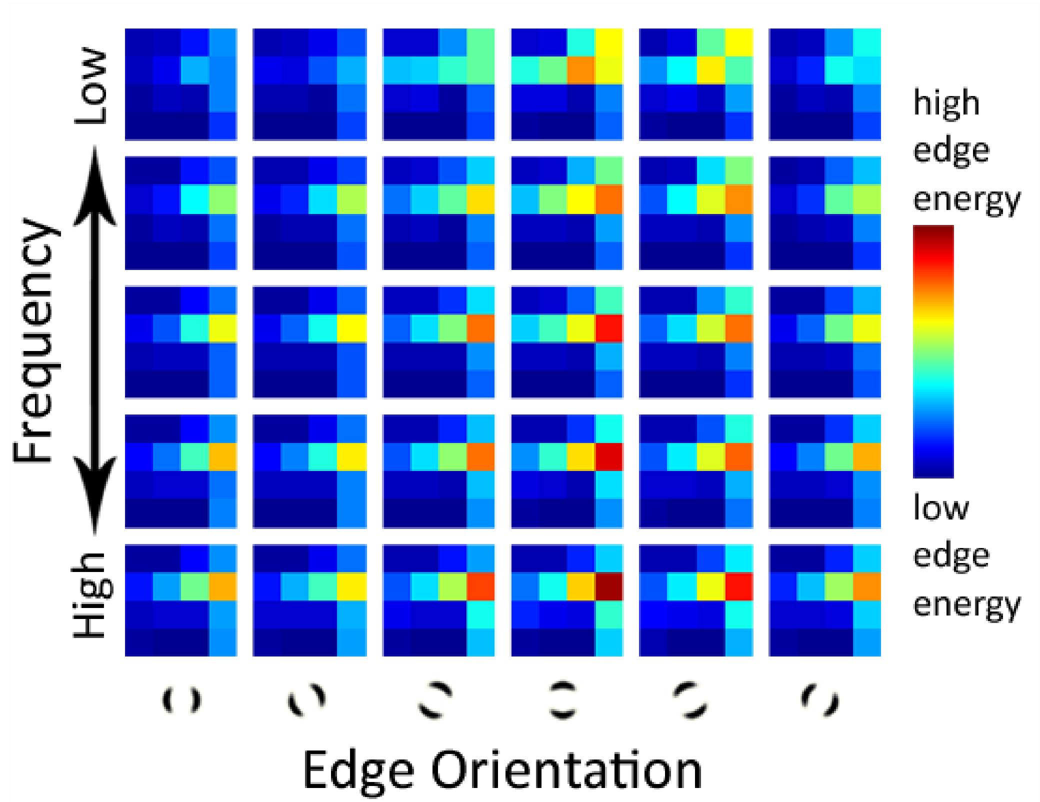


Scene Gist Descriptor
(Oliva and Torralba 2001)

Scene Descriptor

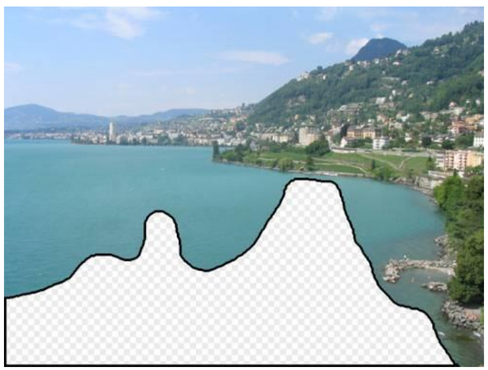


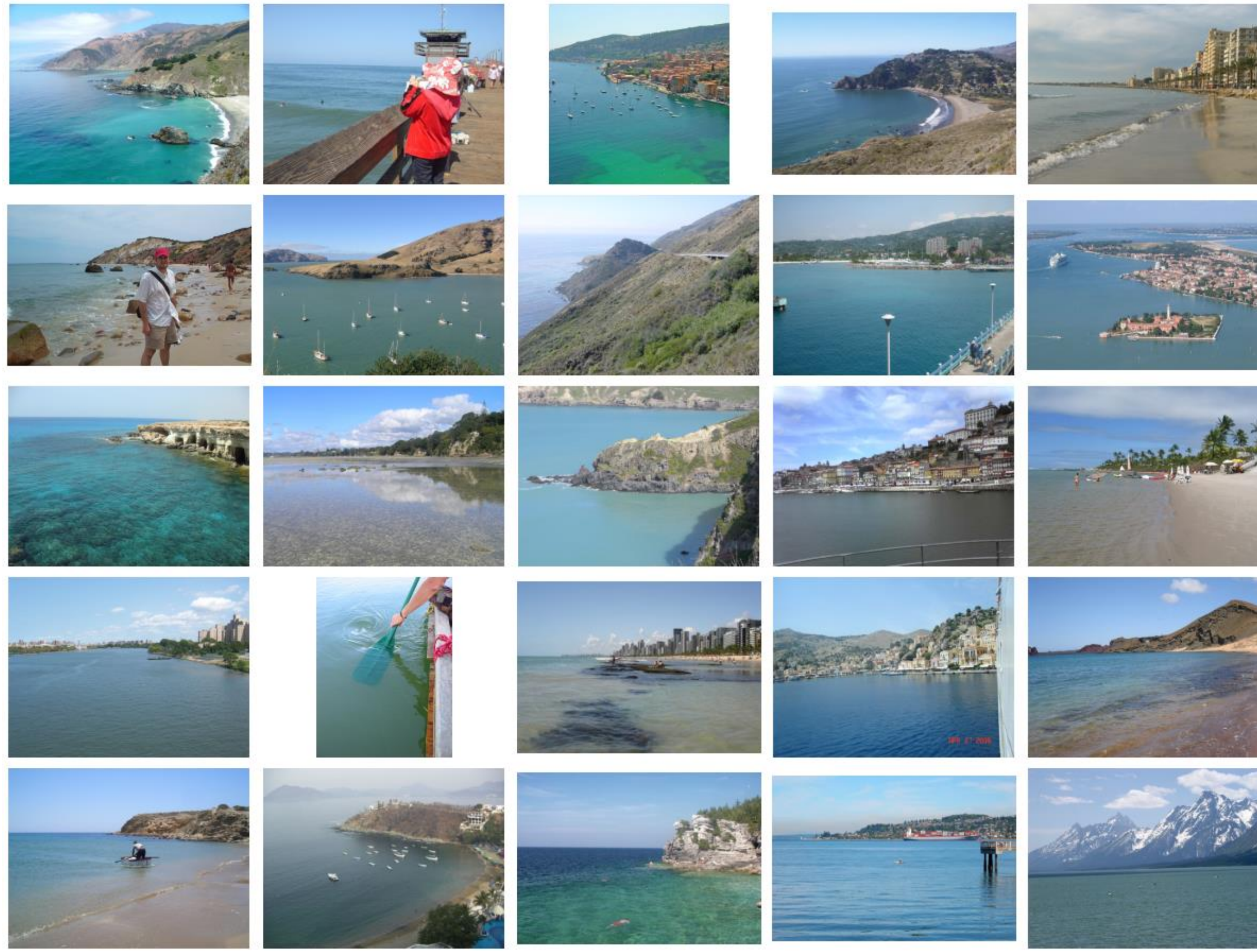
+



Scene Gist Descriptor
(Oliva and Torralba 2001)

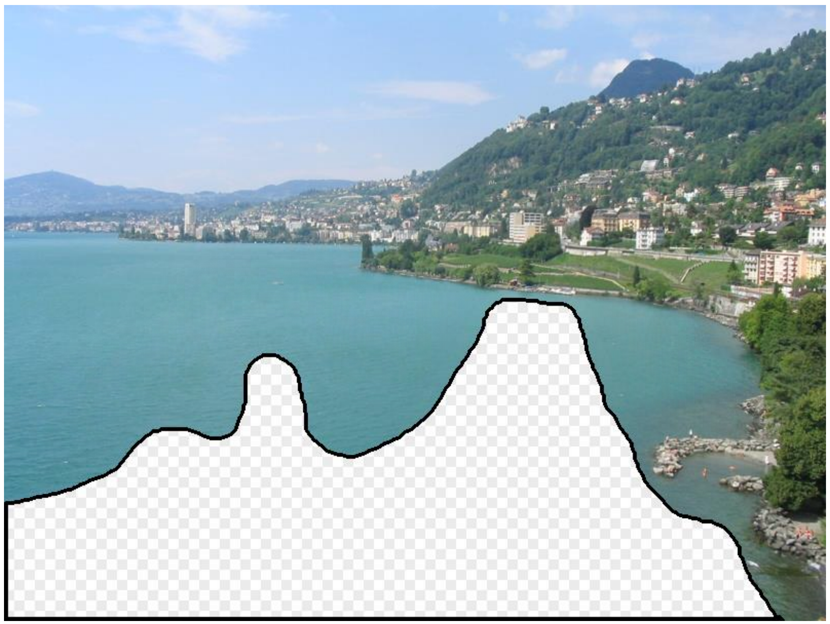
2 Million Flickr Images





… 200 total

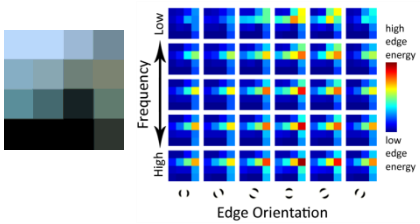
Context Matching



Graph cut + Poisson blending

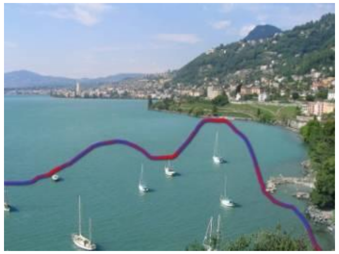
Result Ranking

We assign each of the 200 results a score which is the sum of:

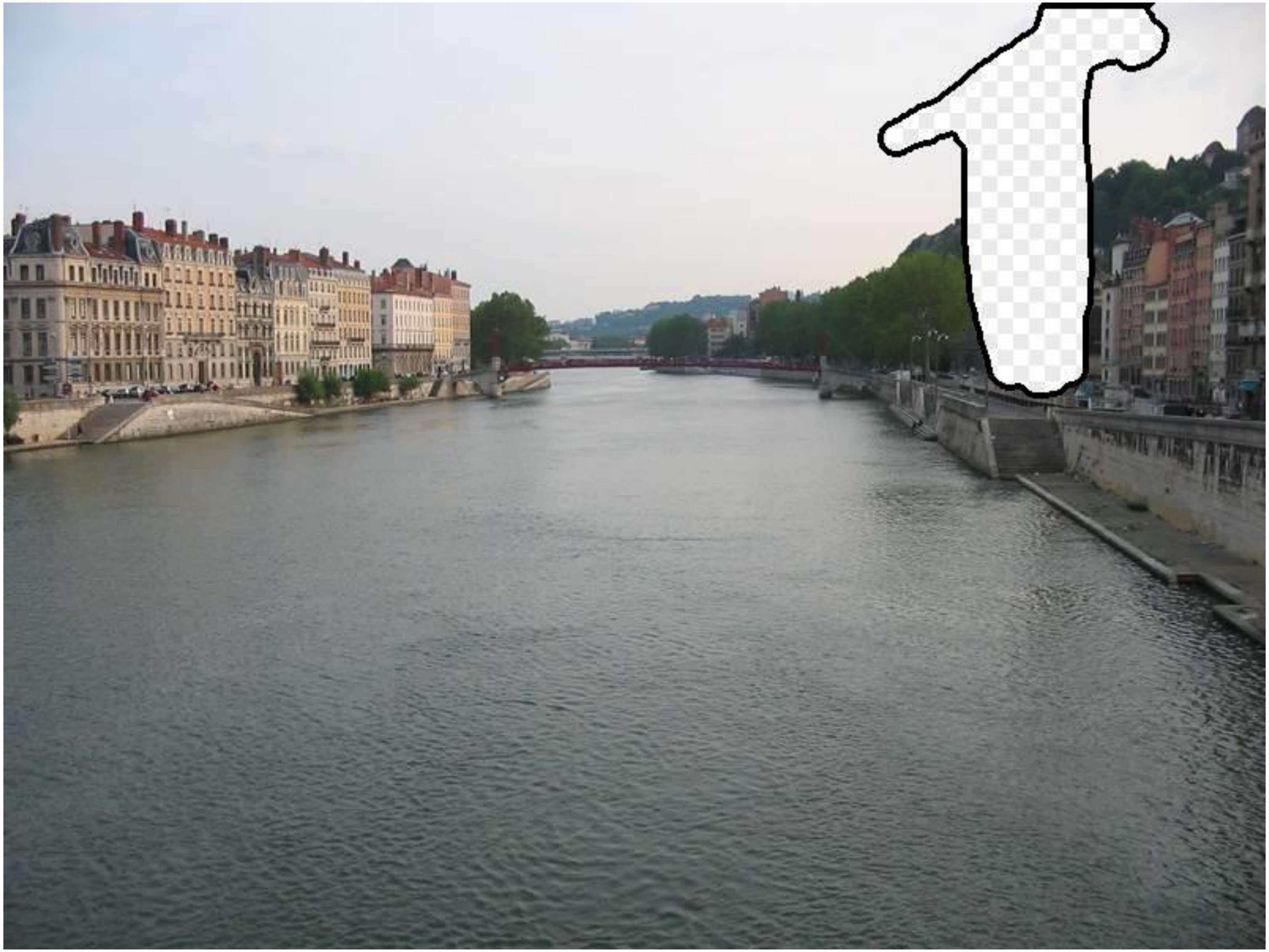


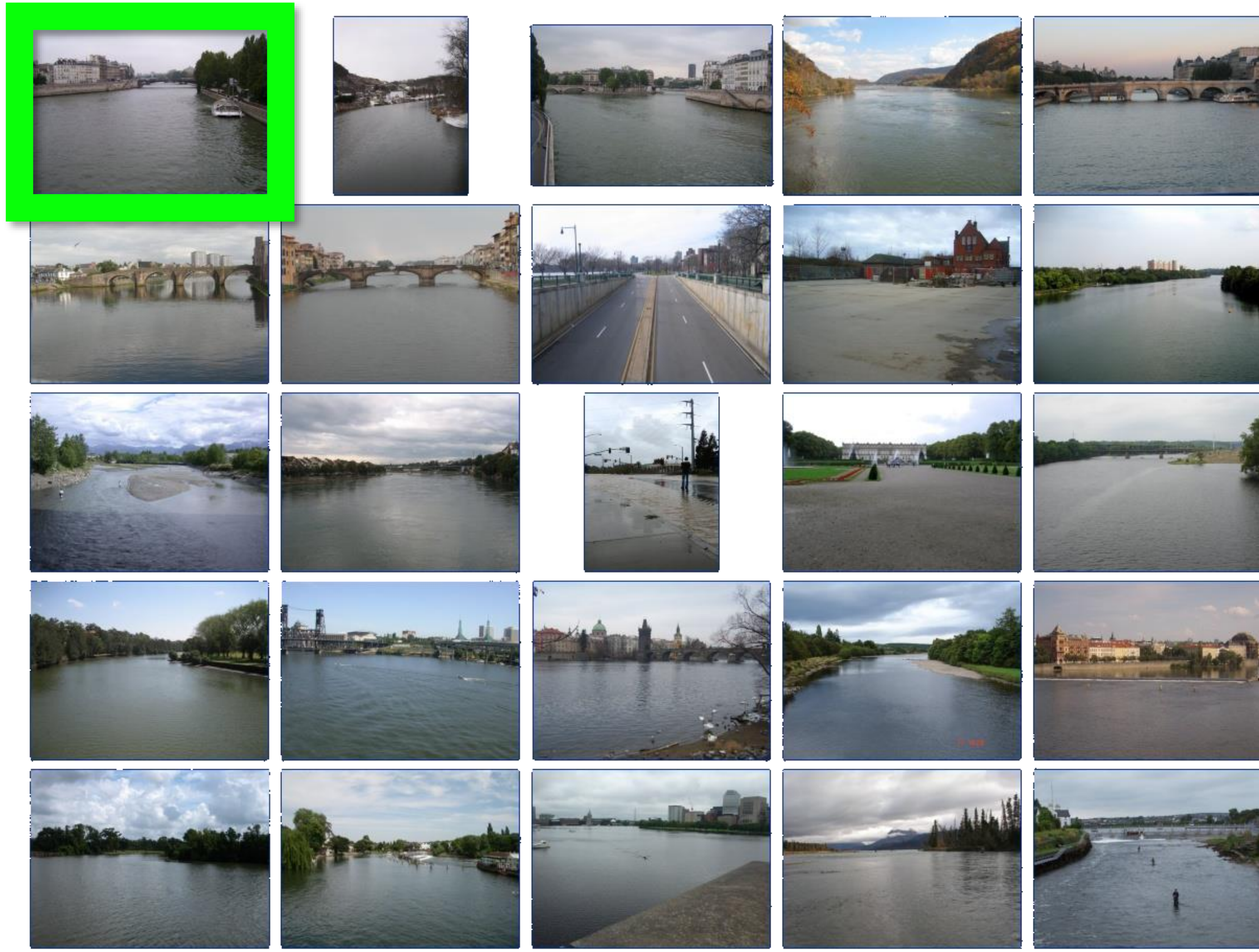
The scene matching distance

The context matching distance (color + texture)

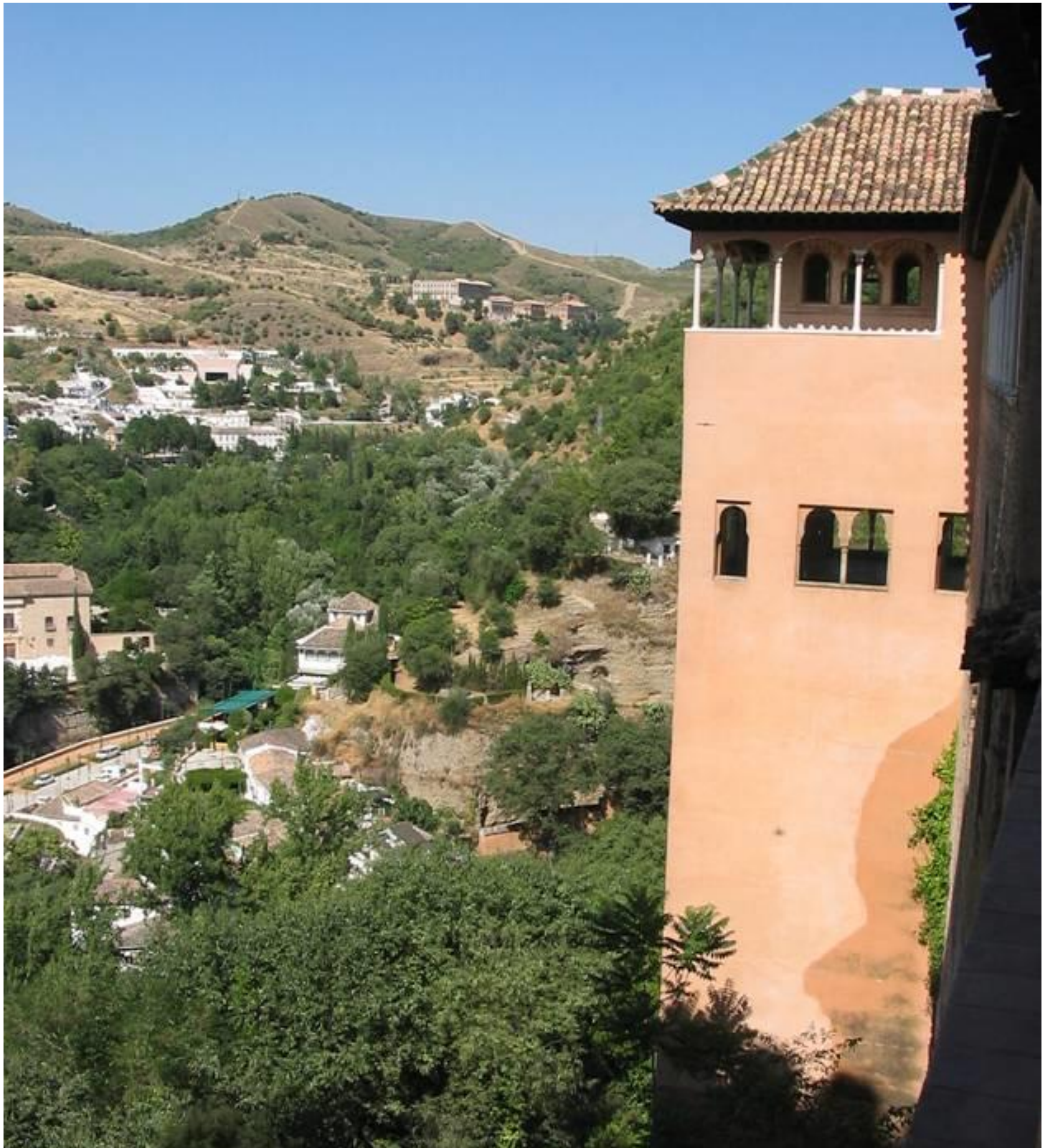


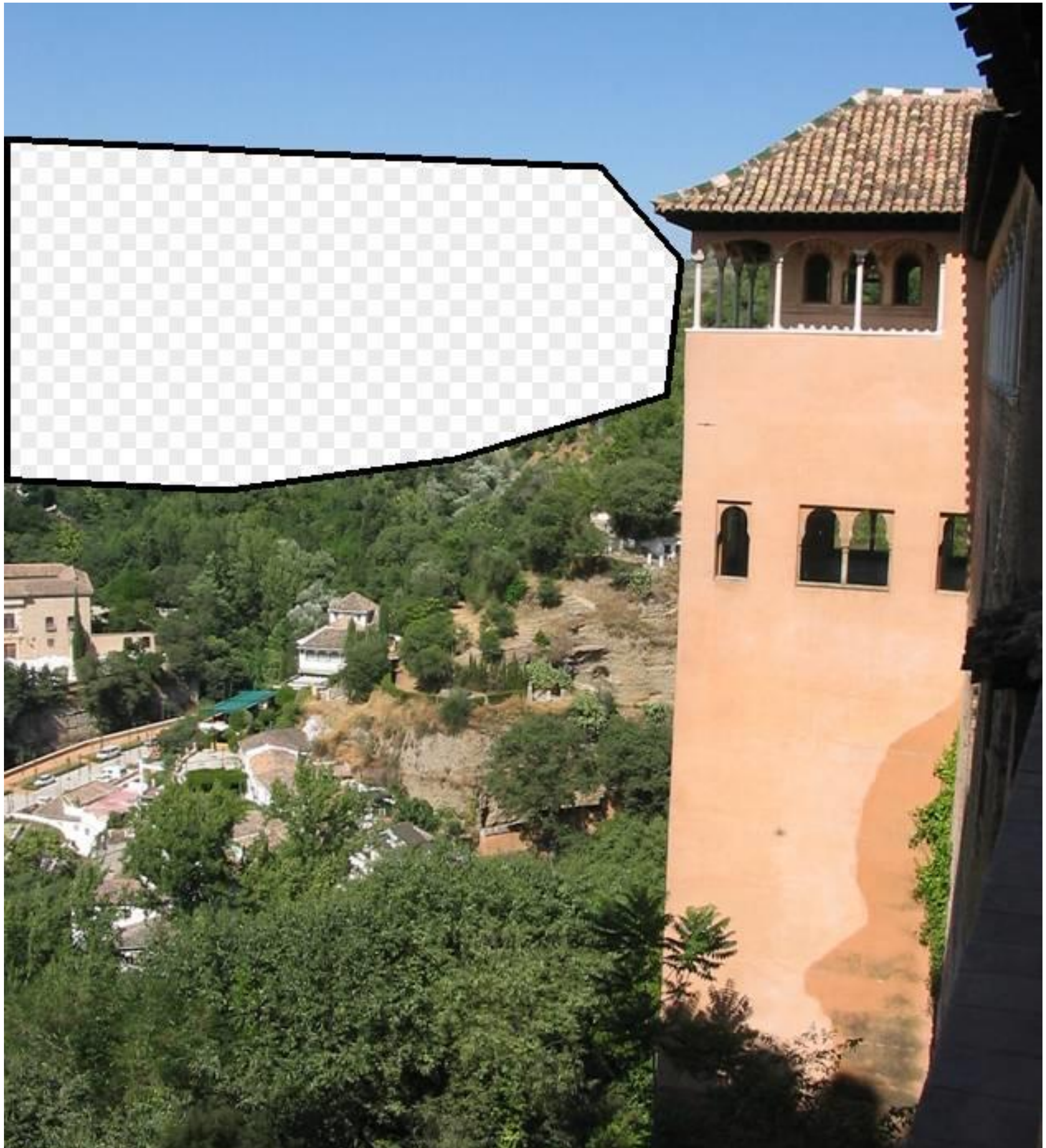
The graph cut cost





… 200 scene matches





Which is the original?