

Uncertainty Modeling Framework for Constraint-based Elementary Scenario Detection in Vision System

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	Uncertainty Modeling Framework for
Co	onstraint-based Elementary Scenario Detection
	in Vision System
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	Abstract. Event detection has advanced significantly in the past decades
	relying on pixel- and feature-level representations of video-clips. Although
	enective those representations have dimcuity on incorporating scene se-
	had scone something but their deterministic nature is susceptible to poice
	from underlying components of vision systems. We propose a proba
	hilistic framework to handle uncertainty on a constraint-based ontol-
	ory framework for event detection. This work focuses on elementary
	event (scenario) uncertainty and proposes probabilistic constraints to
	quantify the spatial relationship between person and contextual objects.
	The uncertainty modeling framework is demonstrated on the detection
	of activities of daily living of participants of an Alzheimer's disease
	study, monitored by a vision system using a RGB-D sensor (Kinect [®] ,
	$\operatorname{Microsoft}^{(\mathbb{C})}$ as input. Two evaluations were carried out: the first, a 3-
	fold cross-validation focusing on elementary scenario detection (n:10 par-
	ticipants); and the second devoted for complex scenario detection (semi-
	probabilistic approach, n:45). Results showed the uncertainty modeling
	improves the detection of elementary scenarios in fecal (e.g., in zone phases 25 to 100 %) and precision indices (e.g., in zone Desding: 54.71
	phone: 85 to 100 %) and precision indices (e.g., in zone nearing, 54.71 to 73 15%) and the recall of Complex scenarios. Future work will extend
	the uncertainty modeling for composite event level
	the uncertainty modeling for composite event level.
	Keywords: Uncertainty Modeling, Ontology, Event Detection, Activi-
	ties of Daily Living, Older People
1	Introduction
Ev€	ent detection has been significantly advancing since the past decade within
the	field of Computer vision giving birth to applications on a variety of domain
like	safety and security $(e.g., crime monitoring [1])$, medical diagnosis and healt
moi	nitoring [2][3], and even as part of a new paradigm of human-machine interfac
in g	gaming and entertainment ($Microsoft^{\mathbb{C}} Kinect^{\mathbb{R}}$).
	Event detection methods in computer vision may be categorized in (adapted
fror	n Lavee et al. [4]): classification methods, probabilistic graphical model
(PC)	GM), and semantic models; which are themselves based on at least one o

the following data abstraction level: pixel-based, feature-based, or event-based.

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Artificial Neural Networks, Support-Vector Machines (SVM), and Indepen-dent Subspace Analysis (ISA) are examples of classification methods. For in-stance. Le *et al.* [5] have presented an extension of the ISA algorithm for event detection, where the algorithm learned invariant spatio-temporal features from unlabeled video data. Wang et al. [6] have introduced new descriptors for dense trajectory estimation as input for non-linear SVMs.

Common examples of PGMs approaches are Bayesian Network (BN). Con-ditional Random Fields, and Hidden Markov Models (HMM). BNs have been evaluated at the detection of person interactions (e.g., shaking hands) [7], left luggage [8], and traffic monitoring [1]. Kitani *et al.* [9] has proposed a Hidden Variable Markov Model approach for event forecasting based on people trajecto-ries and scene features. Despite the advances. PGMs have difficulty at modeling the temporal dynamics of an event. Izadinia and Shah [10] have proposed to detect complex events from by a graph representation of joint the relationship among elementary events and a discriminative model for complex event detec-tion.

Even though the two previous classes of methods have considerably increased the performance of event detection in benchmark data sets, as they rely on pixel-based and feature-based abstractions they have limitations in incorporating the semantic and hierarchical nature of complex events. Semantic (or Descriptionbased) approaches use descriptive language and logical operators to build event representations using domain expert knowledge. The hierarchical nature of these models allow the explicit incorporation of event and scene semantic with much less data than Classification and PGM methods.

Ceusters et al. [11] proposes the use of Ontological Realism to provide se-mantic knowledge to high-level events detected by a multi-layer hierarchical and dynamical graphical model in a semi-supervised fashion (human in the loop). Zaidenberg et al. [12] have evaluated a constraint-based ontology language for group behavior modeling and detection in airport, subways, and shopping cen-ter scenes. Cao et al. [13] have proposed an ontology for event context modeling associated to a rule-based engine for event detection in multimedia monitoring system. Similarly, Zouba et al. [2] have evaluated a video monitoring system at the identification of activities of daily living of older people using a hierarchi-cal constraint-based approach. Oltramari and Lebiere [14] presents a semantic infra-structure for a cognitive system devoted for event detection in surveillance videos.

Although Semantic models advantage at incorporating domain expert knowl-edge, the deterministic nature of their constraints makes them susceptible to noise from underlying components - e.a., people detection and tracking com-ponents in a pipeline of computer vision system - as they lack a convenient mechanism to handle uncertainty. Probabilistic reasoning has been proposed to overcome these limitations. Ryoo and Aggarwal [15] [16] have proposed halluci-nation concept to handle uncertainty from low-level components in a context-free grammar approach for complex event detection. Tran and Davis [17] have pro-posed Markov logic networks (MLNs) for event detection in parking lots. Kwak et al. [18] have proposed the detection of complex event by the combination of primitive events using constraint flows. Brendel et al [19] propose probabilistic event logic to extend an interval-based framework for event detection; by adopting a learned weight to penalize the violation of logic formulas.

We present a uncertainty modeling framework to extend the generic constraintbased ontology language proposed by Vu *et al.* [20] by assessing the probability of constraint satisfaction given the available evidence. By combining both frameworks we allow domain expert to provide event models following a deterministic process, while probabilistic reasoning is performed in second plan to cope with the uncertainty in constraint satisfaction. In this paper we focus on handling uncertainty of elementary events.

2 Uncertainty Modeling Framework

Uncertainty may come from different levels of the event modeling task; from failures on the low-level components which provided input-data for the event detection task (*e.g.*, sudden change in person estimated dimension) to the model expressiveness at capturing the real-world event. For instance, constraint violation may be due to person-to-person differences in performing an event (event intra-class variation). In both cases it may be desirable that the event model be still detected even with a smaller probability.

We propose here a framework to handle uncertainty on elementary events. The framework may be decomposed on: event modeling, uncertainty modeling, and inference. In event modeling step domain experts use the constraint-based video event ontology proposed in [20] to devise event models based on attributes of tracked physical objects (e.g., a person) and scene semantics (contextual ob-*iects*). In uncertainty modeling step we learn the conditional probability dis-tributions about the constraints using annotation on the events and the event models provided by domain experts. The inference step is performed by the tem-poral algorithm of Vu et al. [20] adapted to also compute event probability. The probability computation sub-step infers how likely a model is given the avail-able evidence based on pre-learned conditional probabilities about the evaluated constraints.

2.1 Video Event Ontology

The constraint-based framework is composed of a temporal scenario (event) recognition algorithm and a video event ontology for event modeling. The video event ontology is based on natural terminology to allow end users (e.g., medical experts) to easily add and change event models of a system. The models take into account *a priori* knowledge of the experimental scene, and attributes of objects (herein called Physical Objects, e.g., a person, a car, etc.) detected and tracked by the vision components. A priori knowledge consists of the decomposition of a 3D projection of the scene floor plan into a set of spatial zones which carry semantic information about the monitored scene (e.g., zones like "TV",

"armchair", "desk", "coffee machine"). The temporal algorithm is responsible for the inference task, where it takes as input low-level data from underlying vision components, and evaluates whether these objects (or their properties) satisfy the constraints defined in the modeled events. An event model is composed of (up to) five parts [20]:

- - Physical Objects refer to real-world objects involved in the detection of the modeled event. Examples of physical object types are: mobile objects (e, a, ..., a)person, or vehicle in another application), contextual objects (equipment) and contextual zones (chair zone)
- - **Components** refer to sub-events of which the model is composed.
- Constraints are conditions that the physical objects and/or the components should hold. These constraints could be logical, spatial and temporal. - Alert define the level of importance of the event model, and
- - Action is an optional clause which works in association with the Alert type describes a specific course of action which should be performed in case the event model is detected. (e.g., send a SMS to a caregiver responsible to check a patient over a possible falling down).

The physical object types depend on the domain of application. Two disjoint default types are presented. Mobile and Contextual Objects, with one extensions each, respectively, Person and Contextual Zone. Mobile is a generic class which defines the basic set of attributes for any moving object detected in the scene (e.g., 3D position, width, height, depth). Person is an extension of Mobile class whose attributes are body posture and appearance signature(s). Contextual Ob-ject (CO) type refer to a priori knowledge of the scene. Contextual zone is an extension of CO commonly used to define a set of vertices in the ground plane which corresponds to a region with semantic information (e, q), eating table, ty, desk) for an event model. Contextual objects may be defined at the deployment of the system by the domain experts or by launching an object detection algo-rithm for scene description at system installation, and specific times where object displacement is identified. Physical object types can be expanded accordingly to describe all types of objects in the scene.

Constraints define conditions that physical object properties and/or compo-nents must satisfy. They can be non-temporal, such as spatial (person->position in a contextual zone; or displacement(person1) >1 m) and appearance con-straints (person1->AppearanceSignature = person2->ApperanceSignature); or temporal to capture specific duration patterns or time ordering between a model sub-events (components). Temporal relation are defined following Allen's in-terval algebra (e.g., before, and, meet, overlaps). Fig. 1 describes the model Person changing from zone1 to zone 2: which is defined in terms of a tempo-ral relationship between two sub-events: e.g., c1, Person in zone 1 before c2, Person in zone 2.

The ontology hierarchically categorizes event models according to their com-plexity as (in ascending order):

- **Primitive State** models an instantaneous value of a property of a physical object (person posture, or person inside a semantic zone).

CompositeEvent(Person changing from zone1 to zone 2,	180
PhysicalObjects((per:Person), (z1: Zone), (z2: Zone))	181
Components (182
(c1: PrimitiveState Person_in_zone_1 (p1,z1)	183
(c2: PrimitiveState Person_in_zone_2 (pi,zi)	184
(constraints((c1 before c2)))	185
Alert(NOTURCENT)	186
	100
,	107
	100
Fig. 1: Person changing from zone 1 to zone 2	109
	190
	191
- Composite State refers to a composition of two or more primitive states.	192
– Primitive Event models a change in a value of physical object property	193
(e.g., person changes from sitting to standing posture), and	194
- Composite Event refers to the composition of two previous event models	195
which should hold a temporal relationship (person changes from sitting to	196
standing posture before person in corridor zone).	197
	198
2.2 Uncontainty Modeling for Flomentary Scongrigs	199
2.2 Oncertainty modering for Elementary Scenarios	200

For uncertainty modeling purposes we divided the constraint-based ontology event models into two categories: elementary and composite scenarios. The term scenario is used to differentiate the modeling and inference tasks. Elementary Scenario have a direct correspondence to the primitive state type of the on-tology, and the Composite Scenario represents all other ontology event types (Primitive Event, Composite States and Composite Events). This simplification is performed since these ontology event categories were devised to help domain experts at devising models in a modular fashion and then reduce model com-plexity and increase its re-usability. But, none difference exists for the inference algorithm while processing these event categories besides to the hierarchy depth of the sub-events they define a relationship for.

The uncertainty modeling framework is based on the following concepts:

- Elementary Scenario(ES) is composed of physical objects and constraints.
 This scenario constraints are only related to instantaneous values (*e.g.*, current frame) of physical object(s) attribute(s).
- Composite Scenario(CS) is composed of physical objects, sub-scenarios
 (components) and constraints; where the latter generally refer to composition
 and/or temporal relationships among model sub-scenarios.
- Constraint is a condition that physical object(s) or sub-scenarios must
 satisfy, and refer to the constraint types presented on the constraint-based
 ontology section.
- Attributes correspond to the properties (characteristics) of real world ob jects measured by the underlying components of the event detection task
 (e.g., vision system).

225	- Observation corresponds to the amount of evidence on a constraint or a	225
226	scenario model.	226
227	- Instance refers to an individual detection of a given scenario.	227
228		228
229	Fig. 2 presents a description for the elementary scenario <i>Person in zone Tea</i> .	229
230	This scenario is based on the physical objects <i>Person</i> and the semantic zone	230
231	zone lea. For instance, zone lea would be polygon drawn on the noor - close or	231
232	around the table where the kitchen tools to prepare tea are commonly placed	232
233	- <i>a priori</i> defined by a domain expert during system instanation of automati-	233
234	that the target zone is zone Tea: and a spatial constraint called In which verifies	234
235	whether the person position lies inside the given zone. Fig. 3 illustrates an ex-	235
236	ample of a scene where semantic zones were manually drawn on the floor plane	236
237	where contextual objects are located	237
238	where contentual objects are recarded.	238
239		239
240	ElementaryScenario(Person_in_zone_Tea,	240
241	PhysicalObjects((per:Person), (zT: Zone))	241
242	Constraints(242
243	(per-Prosition in ZI-Vertices) (zT-Sname = "zoneTea")	243
244	(displacement(per->Position) < stopConstant)	244
245)	245
246)	246
247		247
248		248
249	Fig. 2: Elementary Scenario Person in zone Tea	249
250		250
251		251
252		252
253	2.3 Computation of Elementary Scenario Uncertainty	253
204		204
256	The uncertainty of an Elementary Scenario is formalized as function of the	255
257	tramework confidence on the satisfaction of the Elementary Scenario constraints.	250
258	Equation 1 presents an formalization of Elementary Scenario Uncertainty using	258
259	Bayes Rule.	250
260	$P(C_i E_i) * P(E_i)$	260
261	$P(E_i C_i) = \frac{-(C_i) - (C_i)}{P(C_i)} $ (1)	261
	(\sub{i})	

where,

- $P(E_i|C_i)$: Conditional Probability of Event E_i given its observed constraints C_i ;
- $P(C_i|E_i)$: Probability of constraints which intervene on E_i at the current frame; and
- $P(E_i)$: Prior Probability of Event.



Fig. 3: Scene semantic zones

The conditional probability of event E_i given its set of observed constraints C_i is given by the multiplication of the individual conditional probabilities of its constraints. We assumed all constraints contribute equally to the event model detection and are conditionally independent (see Equation 2).

$$P(C_i|E_i) = \prod_{c_{i,j} \in C_i}^{N_j} P(C_{i,j}|E_i)$$
(2)

where $C_{i,j}$:

- Conditional probability of Constraint j of given event i.

To avoid computing $P(C_i)$ which can become costly as the number of constraints increase, we opted to use the non-normalized probability of $P(E_i|C_i)$ as described in Equation 3.

$$\tilde{P}(E_i|C_i) = P(E_i) \prod_{c_{i,j} \in C_i}^{N_j} P(C_{i,j}|E_i)$$
(3)

In its final form the proposed formula for elementary scenario uncertainty (Equation 3) addresses small violations of constraints from noise coming from underlying components and due to event intra-class variations.

2.4 Probabilistic Constraints

The uncertainty of a scenario model or its conditional probability given the evidence is addressed by associating each of its constraints to a Probability Density 314

Function (PDF) responsible for quantifying how likely the constraint would be satisfied given the available evidence. The use of PDFs provide a modular and flexible way to model and change the uncertainty process that governs the condi-tional probability distribution of a constraint given the available evidence - e.g., by modeling the variation of the low level data the constraint is conditioned on during the targeted event execution - and allowing us to avoid the fully speci-fication of the set of assignments of a conditional probability table. Moreover, different constraints may use different PDFs according to the low-level data, and the PDF may be easily changed without any other changes to the event model.

Besides to selecting the fitting PDF to a given constraint it is also important to how we evaluate the constraint goal in a probabilistic fashion. In the case of the spatial operator In its deterministic version is susceptible to different sources of uncertainty; firstly, from the estimated position of the person which may be influenced by noise from low-level computer vision components: and secondly. from the semantic zone *zone Tea* - a priori defined by an expert - which may not accommodate the complete floor surface where people may stand to prepare tea. Its probabilistic counter-part should quantify how likely is the person position to be inside the zone of interest given these sources of noise. We here propose two probabilistic alternatives to the deterministic constraint In: the fully probabilistic In (FPIn) and the semi-probabilistic In (SPIn).

- The fully probabilistic *In* is fully based on a PDF with respect to the relative
 distance between the centroid of the person projected onto the floor and
 the central position of the given semantic zone.
- The semi-probabilistic In is a hybrid implementation which provides maximum probability (100 %) when the person is anywhere inside the semantic zone, and a probability proportional to the distance of the person to the closest zone edge otherwise.

To model the conditional probability distribution of the distances between the person position and the semantic zone we have used Equation 4. Briefly, this equation converts the observed distance among objects into the corresponding value in an uniform Gaussian distribution using expected parameters pre-learned per semantic object. The corresponding value is then applied to an exponential function to obtain the probability of the constraint given the evidence, e.g., a specific low-level data value for elementary scenario. The resulting PDF provides a probability curve with maximum value around the mean parameter and a monotonically decreasing behavior is observed as the observed value distances from the mean.

$$P(C_{i,j}) = \exp(\frac{1}{2} * (\frac{observed_value - \bar{x}}{s})^2)$$
(4)

where, \bar{x} : learned mean of constraint value, and s: standard deviation of \bar{x}

2.5 Learning Constraint Conditional Probabilities

The conditional probability distribution of the elementary constraints were obtained by a learning step based on the event models provided by domain experts 359

- using the constraint-based ontology - and annotated RGB-D recordings of the targeted events. The learning step was performed as follows: firstly, an event detection process was performed using the deterministic event models. Each time the deterministic In was evaluated the relative distance used by the prob-abilistic counterparts was stored independent of whether the current constraint is satisfied. Secondly, using the event annotation we collect the distance val-ues frequently assumed by the In variants when elementary scenario annotation is present for the given RGB-D recording. Thirdly and finally, we computed statistics about the collected values of the attribute the constraint was con-ditioned on. By performing the learning step using event models combined with event annotation (both provided by domain experts) we aim at capturing the Conditional Probability Distribution (CPD) of the constraints according to the event model semantics and maybe reduce the semantic gap between the event model and the real-world event.

Elementary Scenarios are assumed to be equally probable as their evidence is mainly related to a single time unit (e.g., a frame). The Temporal aspect of scenario models such as instance filtering is currently performed by a threshold method which removes low-probability events. The influence of previous instances probabilities into the evaluated time unit will be evaluated in the future in conjunction with uncertainty modeling at Composite Scenario level (Composite Event).

3 Evaluation

The proposed framework has been evaluated at modeling the uncertainty of ac-tivities of daily living of participants of a clinical protocol for Alzheimer's disease study. Two evaluations were performed, firstly on the detection of elementary scenarios, and secondly on the detection of complex events by using uncertainty framework for elementary scenarios as basis for the deterministic complex event models. The latter evaluation intends to assess the improvement brought to the detection of high-level scenario by low-level uncertainty modeling. For both eval-uations contextual objects were defined a priori by domain experts and mostly refer to static furniture in the scene.

Concerning the learning step necessary to obtain the parameters for the constraint conditional probabilities, in the first evaluation the parameters were computed following the rules of the 3-fold cross-validation procedure. For the second evaluation, the 10 videos involved in the 3-fold cross-validation procedure were used for the learning procedure, and the complex detection performance was evaluated on a set of recordings of 45 participants new to the system, which were only annotated in terms of Composite Events.

401 3.1

Data set

Participants of 65 years and over were recruited by the Memory Center (MC) of
 a collaborating Hospital. Inclusion criteria of the Alzheimer Disease (AD) group

405	are: diagnosis of AD according to NINCDS-ADRDA criteria and a Mini-Mental	405
406	State Exam (MMSE) 35 score above 15. AD participants who have significant	406
407	motor disturbances (per the Unified Parkinson's Disease Rating Scale) are ex-	407
408	cluded. Control participants are healthy in the sense of behavioral and cognitive	408
409	disturbances. The clinical protocol asks the participants to undertake a set of	409
410	physical tasks and Instrumental Activities of Daily Living in a Hospital obser-	410
411	vation room furnished with home appliances [21]. Experimental recordings used	411
412	a RGB-D camera (Kinect [®] , Microsoft [©]). The activities of the clinical protocol	412
413	are divided into three scenarios: Guided, Semi-guided, and Free activities. With	413
414	the guided-activities (10 minutes) the protocol intends to assess kinematic pa-	414
415	rameters of the participant gait profile $(e.g., static and dynamic balance test,$	415
416	walking test); while in semi-guided activities (15 minutes) the aim is to evaluate	416
417	the level of autonomy of the participant by organizing and carrying out a list of	417
418	instrumental activities of daily living (IADL).	418
419	For the framework evaluation we have focused only on the recordings of	419
420	patients in the semi-guided scenario. In these recordings the participant enters	420
421	the observation room alone with a list of activities to perform, and he/she is	421
422	advised to leave the room only when he/she has felt the required tasks are	422
423	completed. The list of semi-guided activities is composed as follows:	423
424	Wetch TV	424
425	- Watch IV,	425
426	- Trepare rea/collee, Write the shopping list for the lunch ingradients	426
427	- write the shopping list for the funch ingredients,	427
428		428

- 428 Read the newspaper/magazine,
- Water the plant,
- Organize the prescribed drugs inside the drug box according to the daily/
 weekly intake schedule,

- Write a check to pay the electricity bill,
 - Call a taxi,

- Get out of the room.

3.2 RGB-D Monitoring System

The framework for uncertainty modeling was evaluated using a RGB-D sensorbased monitoring system, built on the event detection framework proposed by
Vu et al. [20], and later evaluated on the detection of daily living activities of
older people by Crispim-Junior et al. [3] using a 2D-RGB camera as the input
sensor.

The evaluation monitoring system can be composed into three main steps: people detection, people tracking, and event detection. People detection step is performed by a depth-based algorithm proposed in Nghiem *et al.* [22], since we have replaced the 2D-RGB camera by a RGB-D sensor. The depth-based algorithm performs as follows: first, background subtraction is employed on the depth image provided by the RGB-D camera to identify moving regions. Then, region pixels are clustered in objects based on their depth and neighborhood

information. Finally, head and shoulder detectors are employed to detect peopleamongst other types of detected objects.

The set of people detected by the previous algorithm is then evaluated by a multi-feature tracking algorithm proposed in Chau *et al.* [23], which employs as features the 2D size, the 3D displacement, the color histogram, and the dominant color to discriminate among tracked objects.

Event detection step has as input the set of tracked people generated in the previous step and *a priori* knowledge of the scene provided by a domain expert. This step was evaluated for two different components for comparison purposes: the proposed framework for uncertainty modeling, and the deterministic event modeling framework proposed by Vu *et al.* [20] and evaluated by Crispim-Junior *et al.* [3]. Both components frameworks used the same underlying components.

3.3 Performance Measurement

The framework performance on event detection is evaluated using the indices of Recall (Rec.) and Precision (Prec.) described in Equations 5 and 6, respectively in comparison to ground-truth events annotated by domain experts.

$$Recall = \frac{TP}{TP + FN} \tag{5}$$

$$Precision = \frac{TP}{TP + FP} \tag{6}$$

where TP: True Positive rate, FP: False Positive rate and FN: False Negative rate.

4 Results and Discussion

Table 1 presents the performance of the uncertainty modeling framework on elementary scenario (primitive state) detection in a 3-fold cross-validation scheme.
The cross-validation scheme used 10 RGB-D recordings of participants of the
clinical protocol data set. "Deterministic" stands for the deterministic constraintbased approach. Results are reported as the average performance on the frameworks on the validation sets.

The proposed probabilistic constraints outperformed the deterministic approach on the recall index in all cases except for the detection of "In zone reading" event with *FPIn* constraint, where a slightly inferior performance is observed for this probabilistic constraint. In the precision index the *FPIn* constraint alternates with the deterministic approach as the constraint with highest performance among elementary scenarios; while a worse performance is observed for the *SPIn* constraint .

491Table 2 presents the results of the framework on Composite Event Detection.491492Here an hybrid strategy is adopted where the uncertainty modeling is used on492493elementary scenarios and the deterministic constraint-based framework is used493494on composite event modeling.494

495	Table 1: Average Performance of Framework on Elementary Scenario Detection on a
106	3-fold-cross-validation scheme

	I	Deterministic			SPIn				FPIn	
IADL	Rec.	Р	rec.	Rec.	ec.			Rec.	Prec.	
In zone Pharmacy	100±	0 8	3.33 ± 28.87	100±0		85 ± 13	.23	100 ± 0	85.71 ± 24.7	
In zone Phone	85.2±	15. 8	8.89 ± 11.11	91.9 ± 7	.3	85.5 ± 1	17.1	100 ± 0	93.33 ± 11.5	
In zone Plant	100±	0 6	8.59 ± 35.06	100 ± 0		20.44±	-5.93	100 ± 0	55.56 ± 13.88	
In zone Tea	$100\pm$	0 8	1.02 ± 22.92	100 ± 0		$37.58 \pm$	-28.11	100 ± 0	79.17 ± 26.02	
In zone Read	80 ± 3	4.64 5	4.71 ± 21.11	100 ± 0		$33.96 \pm$	12.92	72.38 ± 24	73.15 ± 27.82	
$N: 10 \ participant$	ts; 15 n	nin. e	ach; Total	: 150 m	iin					
Table 2: Fra	amewo	rk Pei	rformance o	on Comp	\mathbf{pos}	ite Ev€	ent Det	ection Le	vel	
Deterministic					SPIn F			PIn		
IADL	Rec.	Prec.	Rec.	P	rec.	Rec.	Prec.			
Talk on Phone	89.6	86.7	90.8	72	2.5	88.5	80.2			
Preparing Tea/ Co	89.4	72.0	97.0	36	5.8	95.4	50.8			
Using Pharmacy B	95.4	95.4	97.7	93	3.5	97.7	93.5			
	74.1	69.0	100.0	21	1.6	100.0	23.1			
Watering plant					_					
$\frac{\text{Watering plant}}{N: 45 \text{ participant}}$	ts; 15	min. e	each; Tota	l: 675m	iin					
$\frac{\text{Watering plant}}{N: 45 \text{ participant}}$	<i>s</i> ; 15	min. e	each; Tota	l: 675m	ıin					

The results on complex event detection showed SPIn and FPIn had similar performance and outperformed the deterministic approach in the recall index. In contrast *FPIn* outperformed *SPIn* in the precision index but was still worse than the deterministic approach in two out of for cases.

In general, the worse performance on this event level may be attributed to the fact that other model constraints, which play a key-role on the detection of the modeled events and did not have their uncertainty addressed, have degenerated the performance of the framework. But, in the case of watering plant event the observed low precision may be due to the learned parameters of this semantic zone were not appropriate to model its uncertainty probability distribution.

Given the presented results we have chosen the *FPIn* as the probabilistic alternative for the deterministic spatial constraint In in our future work. Further work will investigate new methods to model the uncertainty of elementary scenarios as well as extending the framework for Composite Scenario level.

Conclusions

We have presented a uncertainty modeling framework to handle uncertainty from low-level data in the form of constraints of elementary scenarios (low-level events). The framework successfully improves the recall performance of the event detection task in elementary scenarios, and in some cases the recall in-dex on detection of Composite Scenarios (semi-probabilistic approach). Further development will investigate new methods to model the condition distribution of constraints for which the univariate Gaussian distribution is not appropriate.

Currently, a supervised learning step is necessary to compute the conditional probabilities associated to the event model constraints. To improve the usability of the framework in a system-wise approach, future work would also investigate possible alternatives to allow small deviations to the scenario constraint with-out the need of a learning step. Finally, an investigation will be carried out to extend the current framework to composite scenario models by proposing tech-niques to handle uncertainty related to composite and temporal relations among sub-scenarios.

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