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## Classification aided two stage localization

Hedi Harzallah, Cordelia Schmid, Frédéric Jurie, Adrien Gaidon

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# Classification aided two stage localization

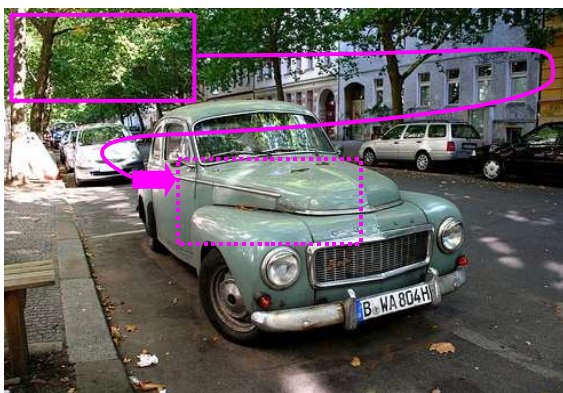
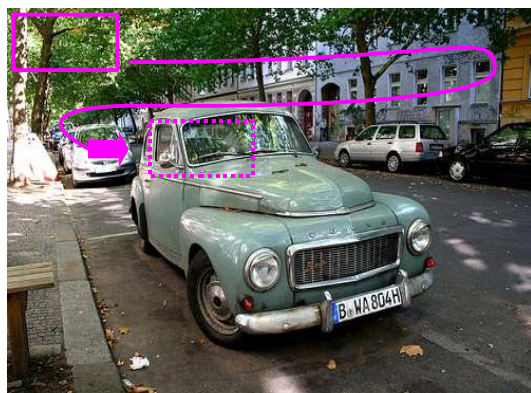
Hedi Harzallah, Cordelia Schmid, Frederic Jurie, Adrien Gaidon

INRIA, LEAR project team

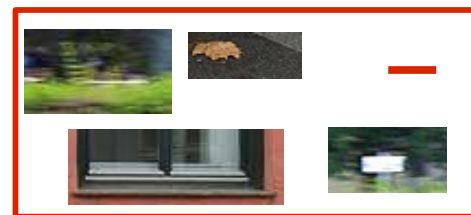
PASCAL VOC2008 challenge workshop

# Introduction

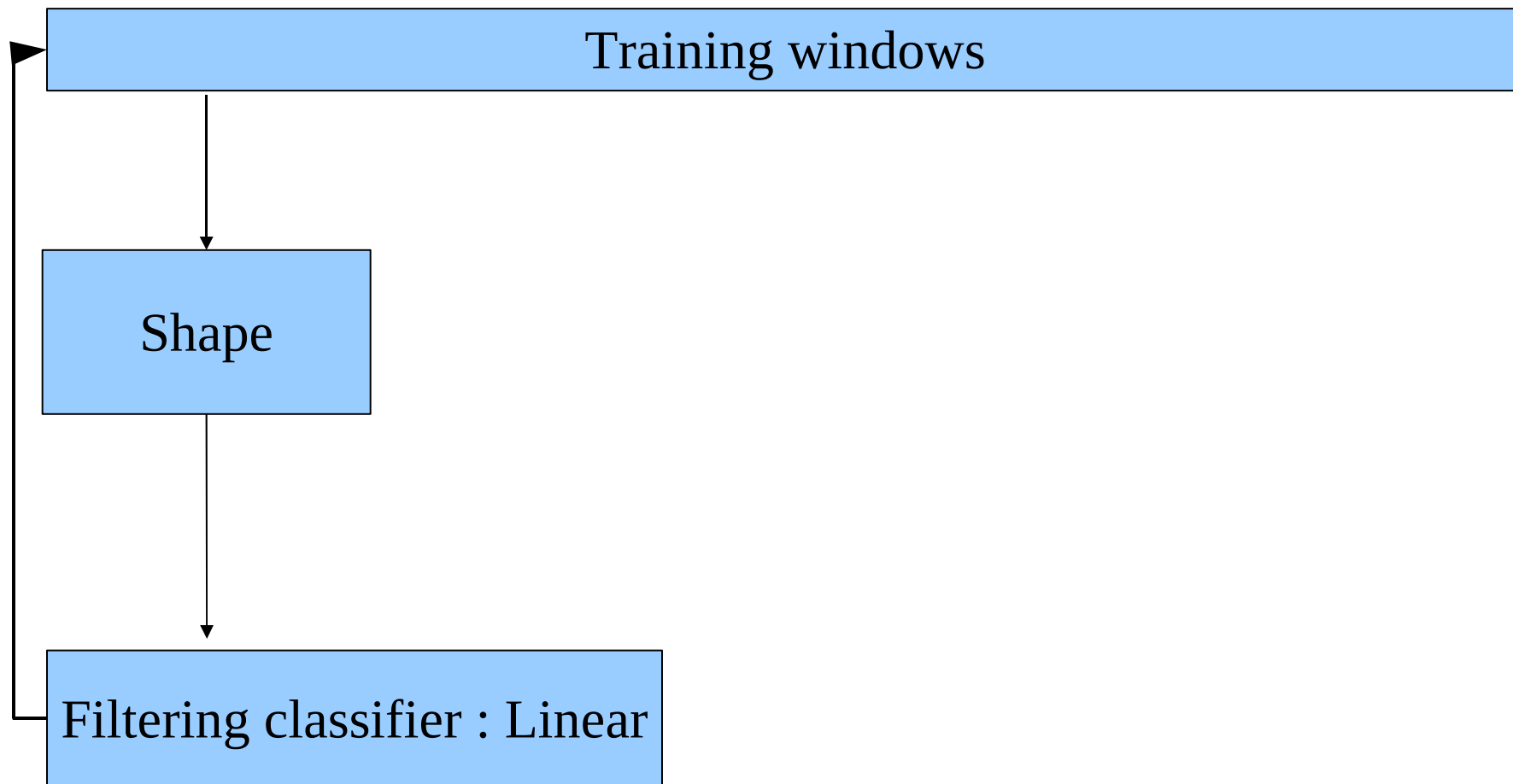
- Detection task on PASCAL VOC2008 challenge
- Method with sliding windows (Each window is classified as containing or not the targeted object)



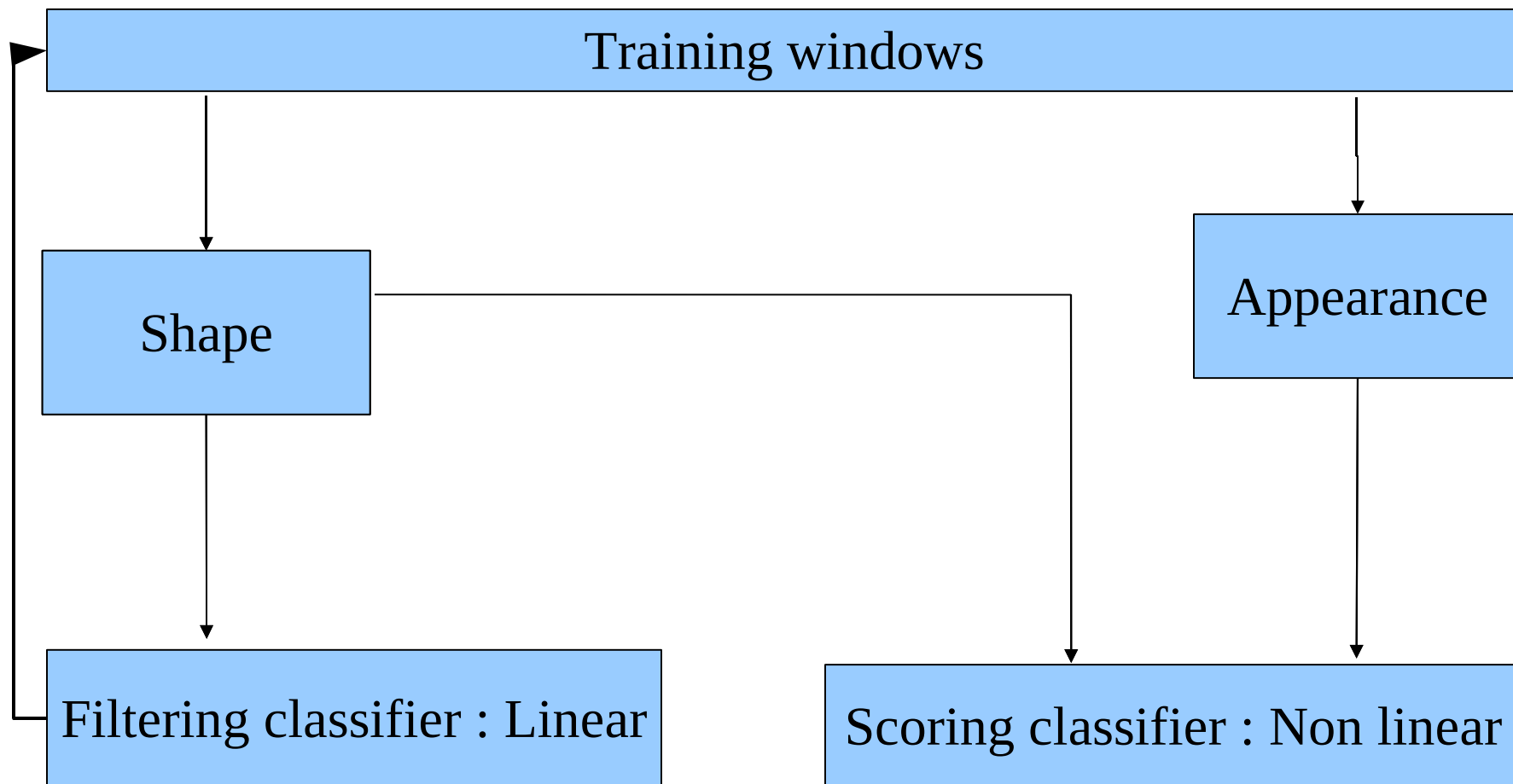
- Learn a classifier by providing positive and negative examples



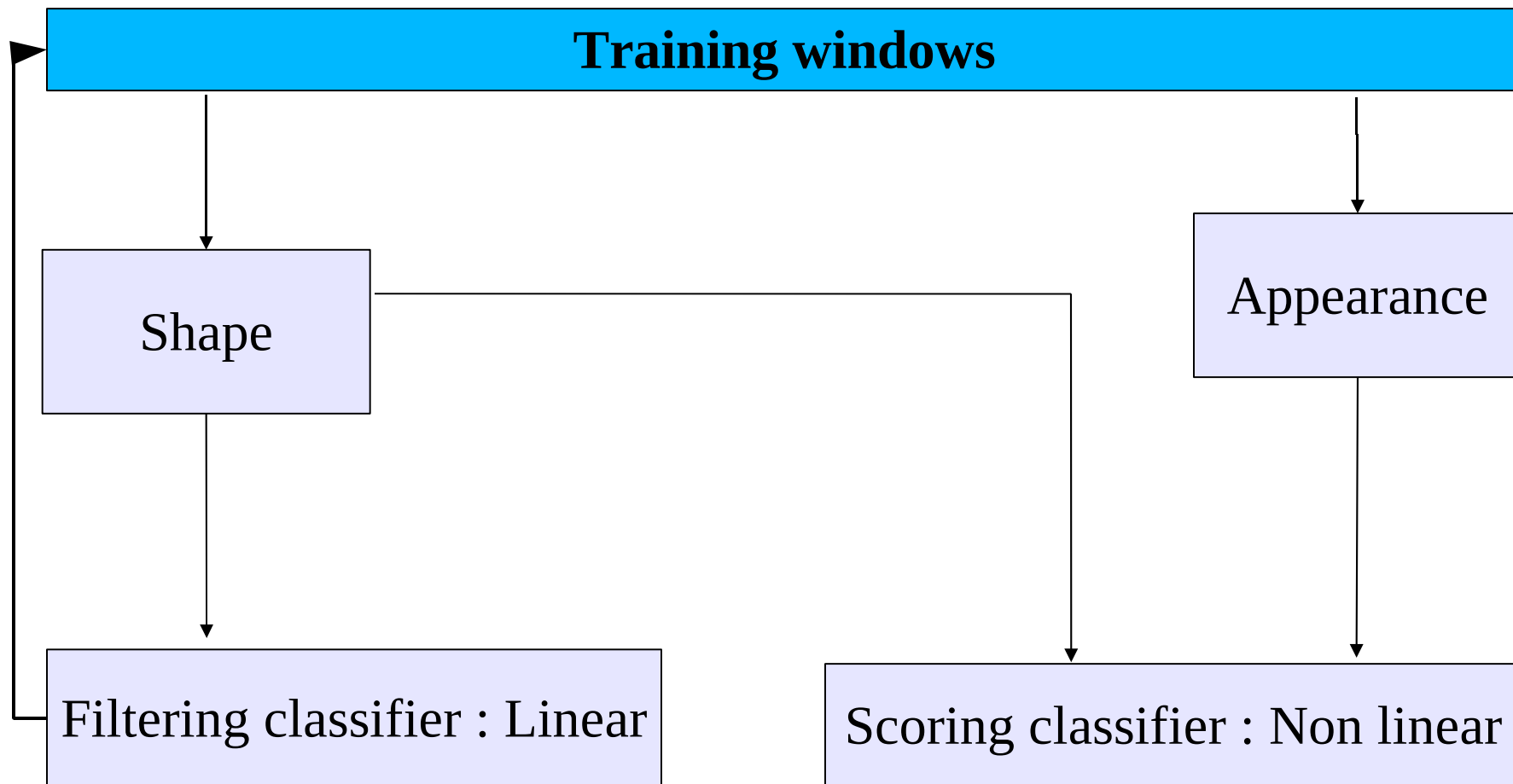
# Training outline



# Training outline

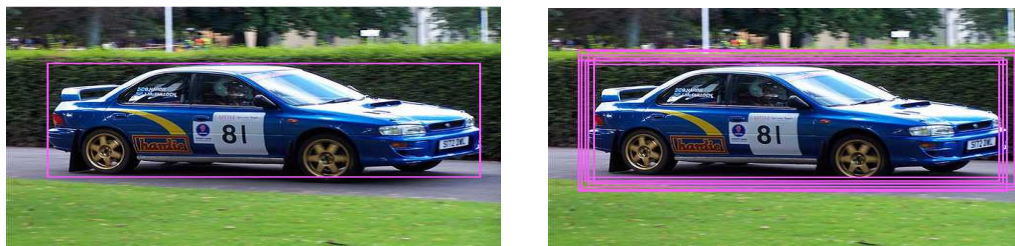


# Generating training windows

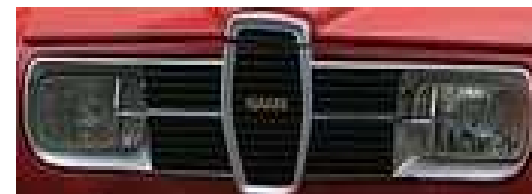
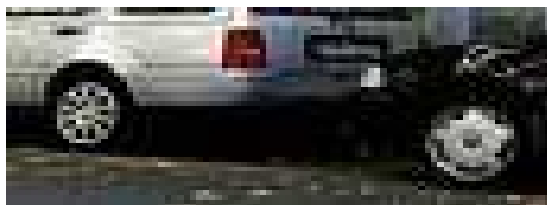


# Generating training windows

- Adding positive training examples by shifting and scaling the original annotations [Laptev06]

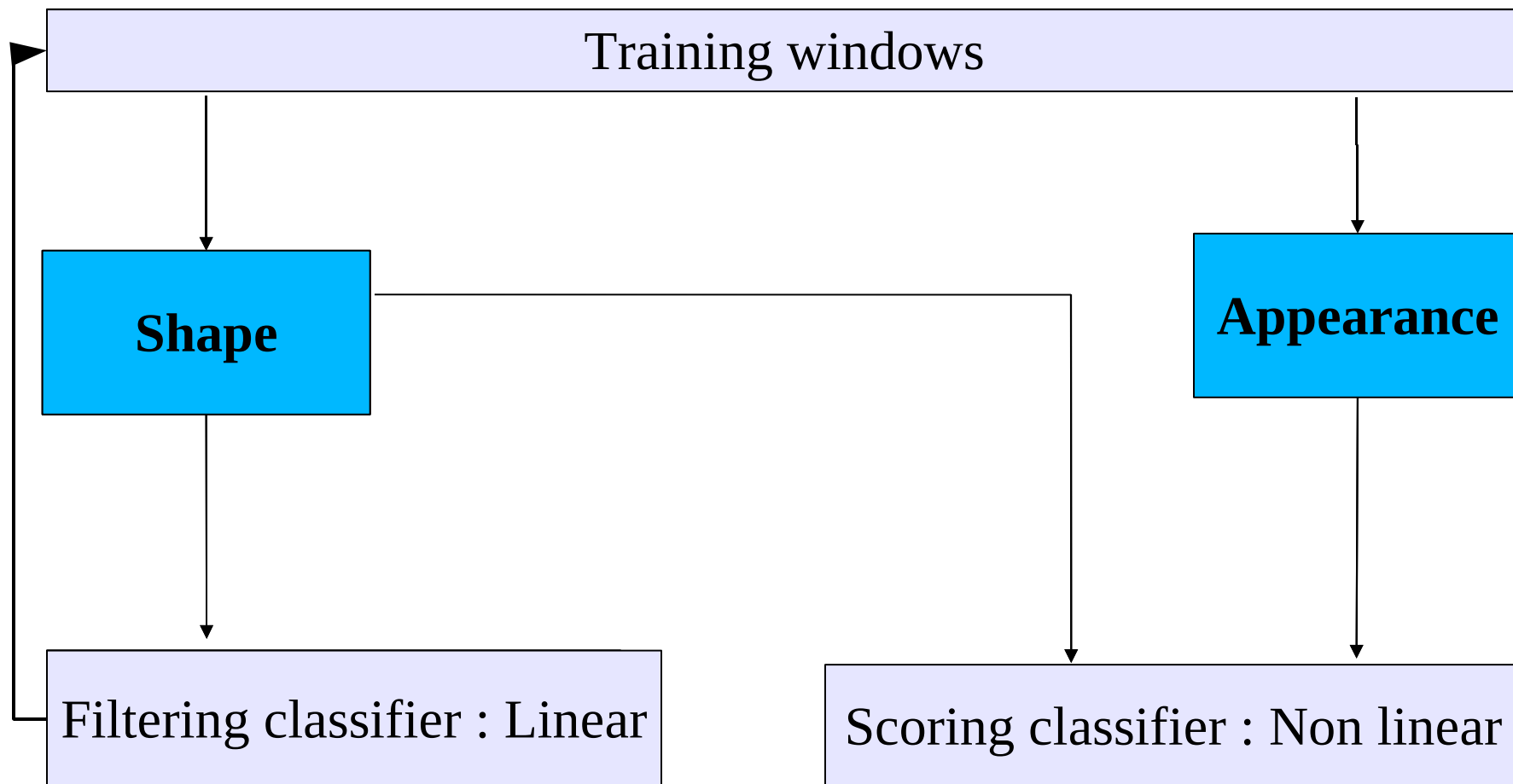


- Negative examples randomly extracted from background
- Training an initial classifier
- Retraining 4 times by adding false positives



Examples of false positives

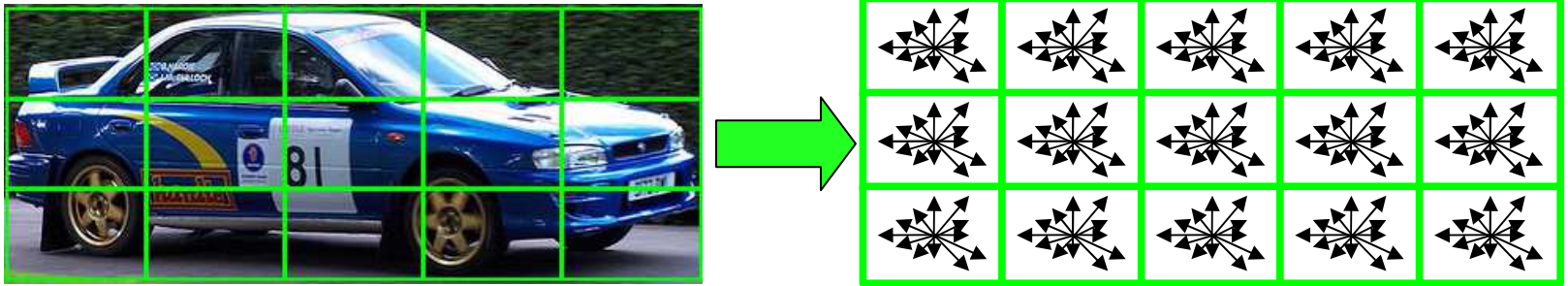
# Image representation



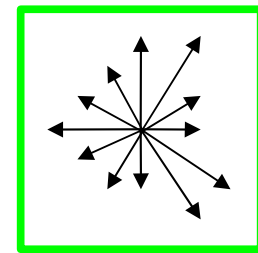


# Image representation: Histogram-of-gradients (HOG)

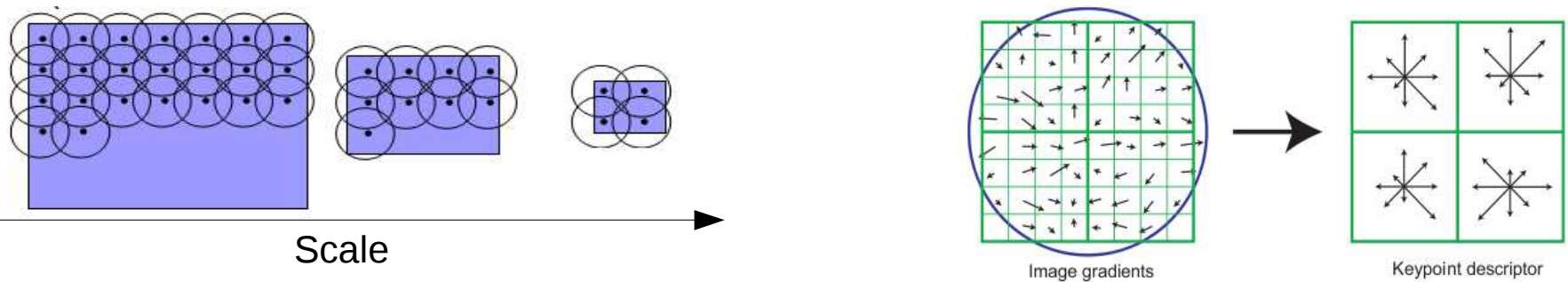
- Tiling optimized per class (around 100 overlapping tiles)



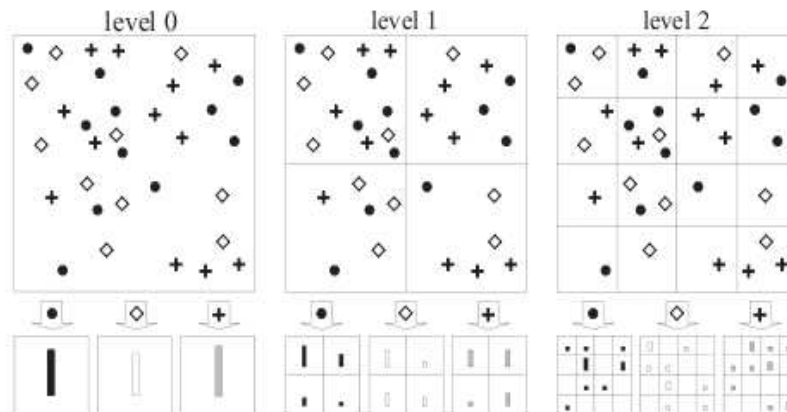
- Computed with integral histograms
- With 16 orientations



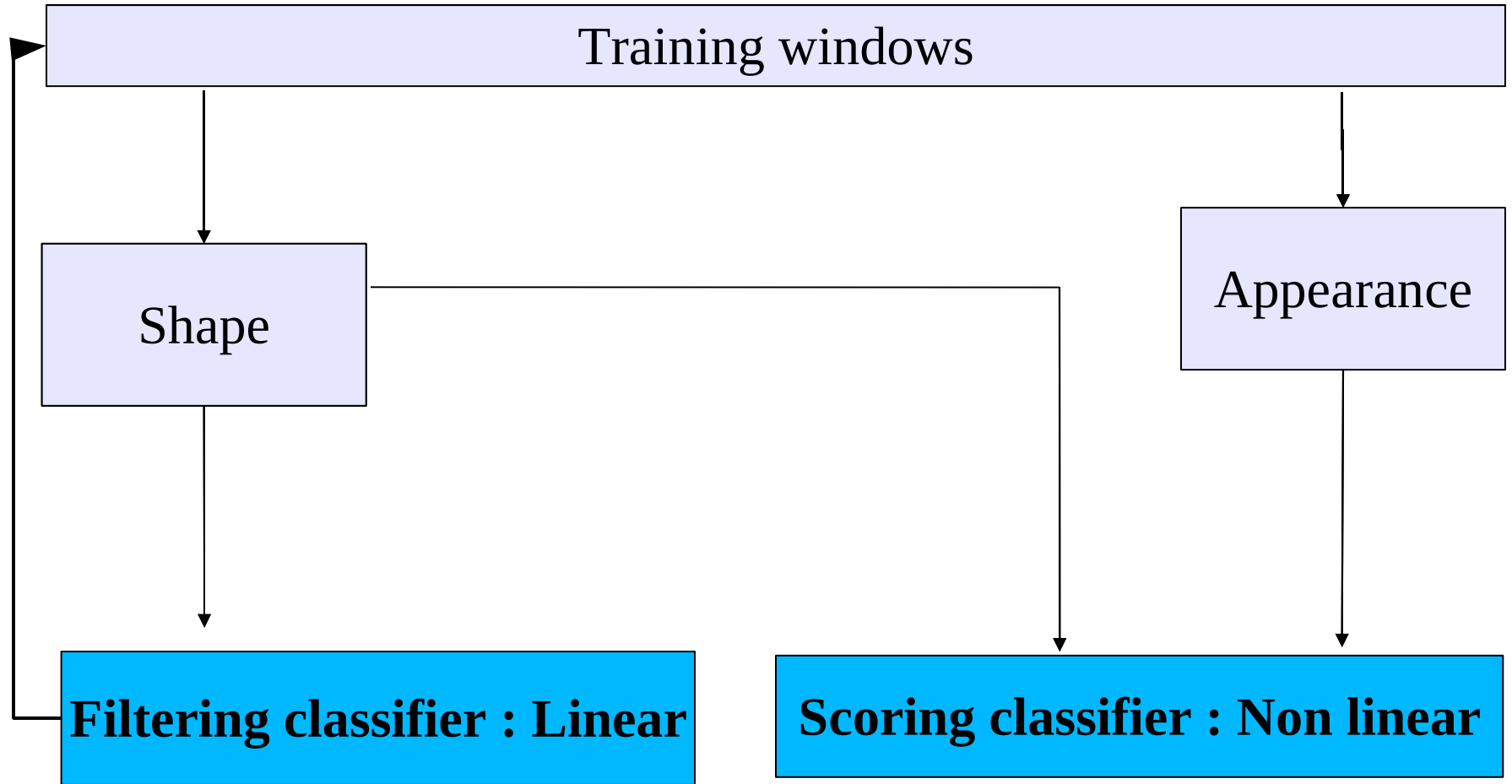
# Image representation : Dense SIFT



- Computed over dense patches (shift step 6 pixels, scale step 1.2)
- Discretized into 100 visual words using k-means
- Used as BOW with a spatial pyramid [Lazebnik06]



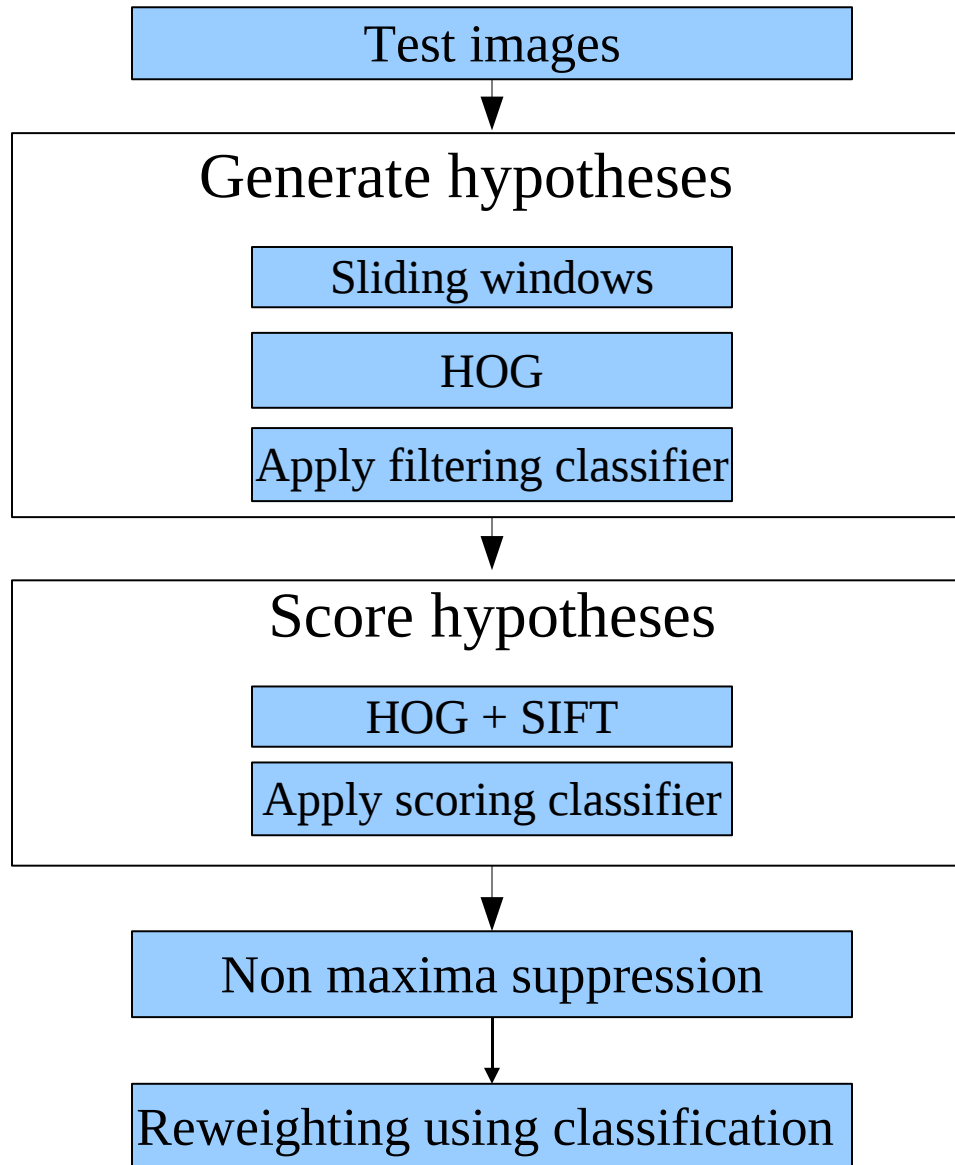
# Learning procedure



# Learning procedure

- Training one classifier per view (Side, Front/Rear, Unspecified)
- Linear SVM classifier
  - HOG only (combining with SIFT gives minor gain at high cost)
- Non Linear SVM classifier
  - We use non linear  $X^2$  kernel SVM [Zhang et al 2007]
  - Training with:
    - Examples used in the linear case (positives + shifted positives + hard false positives)
    - Additional random 70K negative examples

# Testing outline



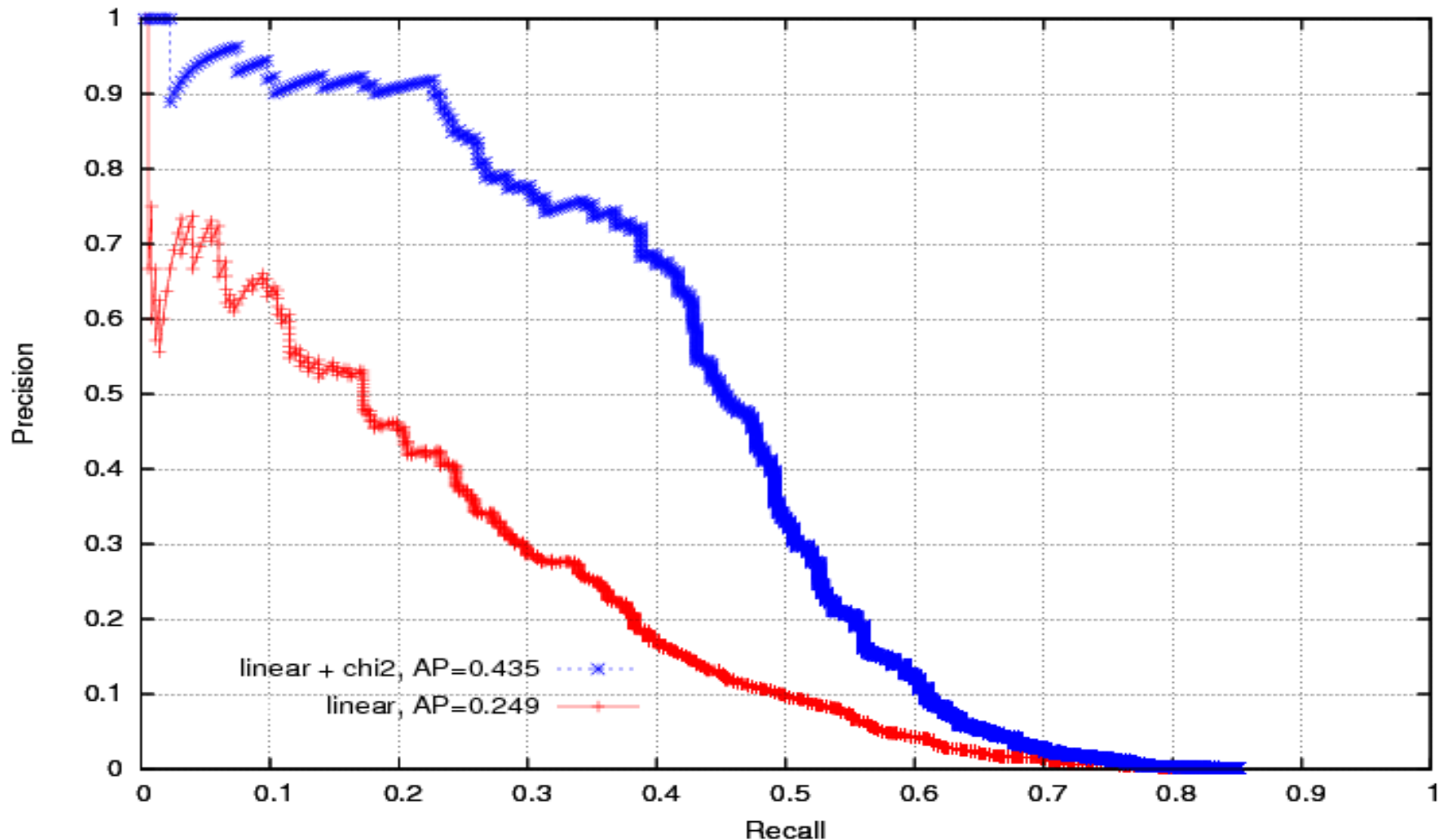
# Evaluation of linear/non linear SVM

- Using HOG only to learn the non linear classifier
- Linear classifier used not only for filtering but also for scoring

	Linear	Linear + $X^2$
<b>All classes</b>	<b>0.139</b>	<b>0.220</b>
aeroplane	0.039	0.184
horse	0.249	0.435
diningtable	0.096	0.108
pottedplant	0.100	0.118

# Evaluation of linear/non linear SVM

Precision recall curve for the class horse using HOG features



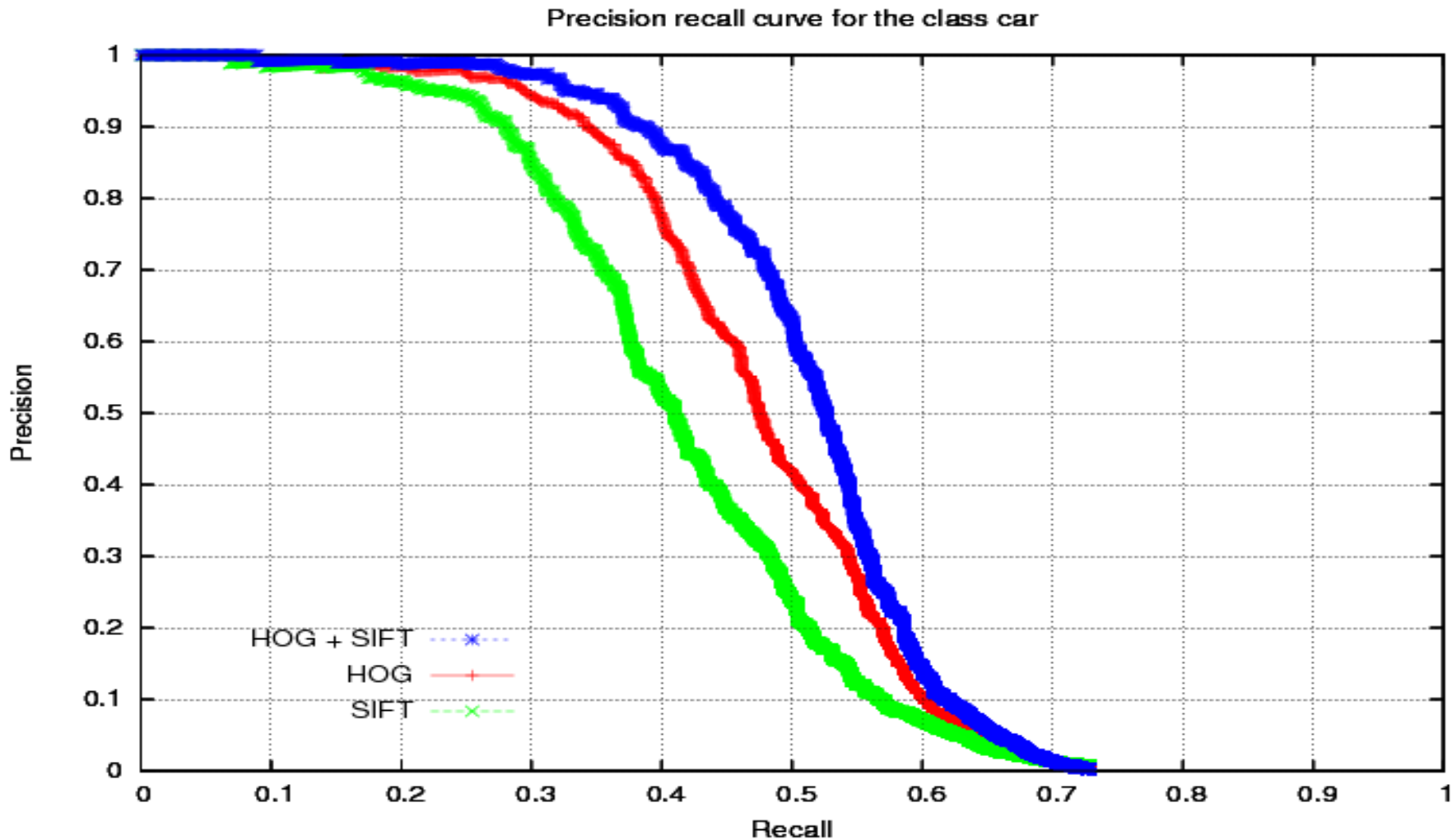
# Evaluation of descriptors

- Scoring classifiers learned with different features
- Applied on the same hypotheses

	HOG	SIFT	HOG+SIFT
<b>All classes</b>	<b>0.220</b>	<b>0.231</b>	<b>0.264</b>
aeroplane	0.184	0.298	0.338
car	0.475	0.425	0.511
train	0.318	0.344	0.291
bus	0.432	0.397	0.423



# Evaluation of descriptors



# Combining localization and image classification

- Provides contextual information
- Results are more reliable in image classification
- Transform scores into probabilities
- New score =  $P(\text{det}) * P(\text{cls})$

# Influence of the use of image classification score

- We use the Lear\_flat submission [Gaidon and Marszalek]

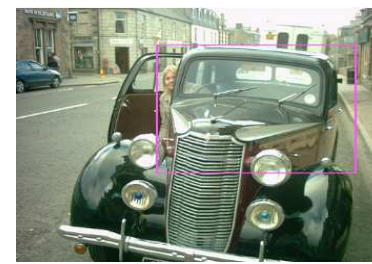
	HOG+SIFT	HOG+SIFT plusclass
<b>All classes</b>	<b>0.264</b>	<b>0.290</b>
cow	0.240	0.309
sheep	0.212	0.273
car	0.511	0.518
motorbike	0.417	0.427

# Example of results: cars

Top true positives



First false positives



Missed

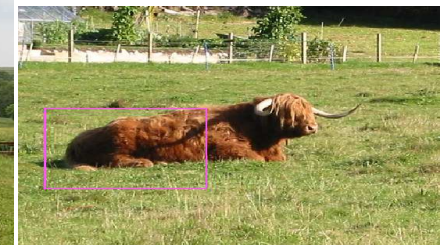
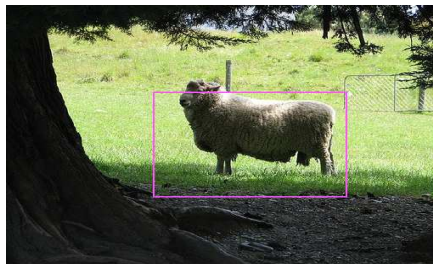


# Example of results: cow

Top true positives



First false positives



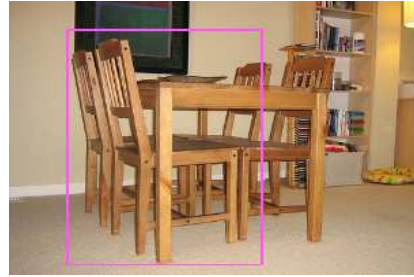
Missed





# Example of results: chair

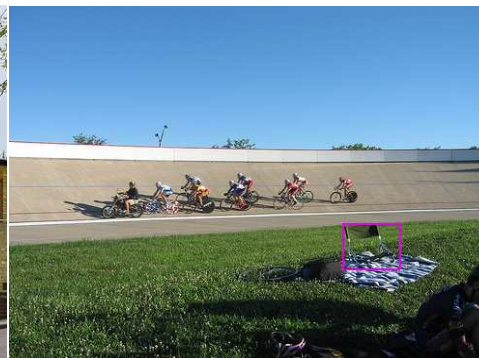
Top true positives



First false positives



Missed



# Summary

- Two stage classification (hypotheses prediction, hypotheses verification)
- Image representation combination
- Reweighting with classification score
- Worse performance on some articulated classes (part models more suited)
- Outperform other competitors on most of the rigid classes

**Thank you**