

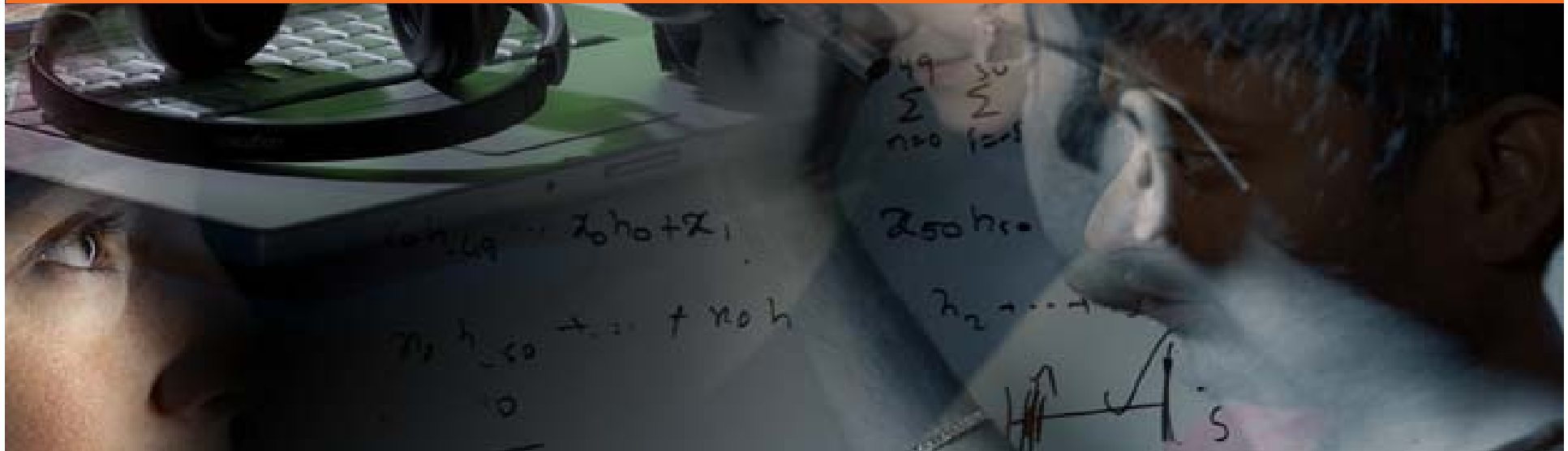


## Learning and Sharing of Semantic Spatial Concepts

Barbara Caputo

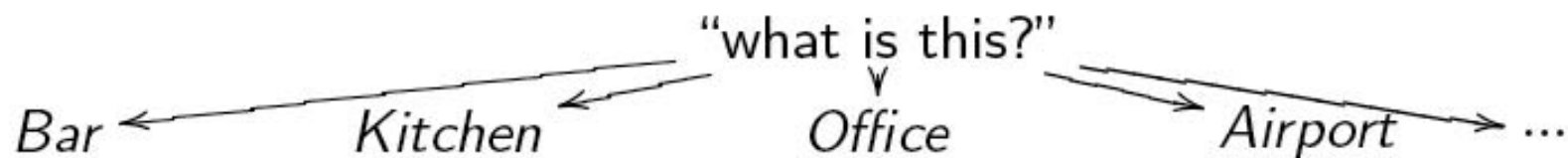
International Advisory Board Meeting, Idiap, September 2, 2011

Research Activities



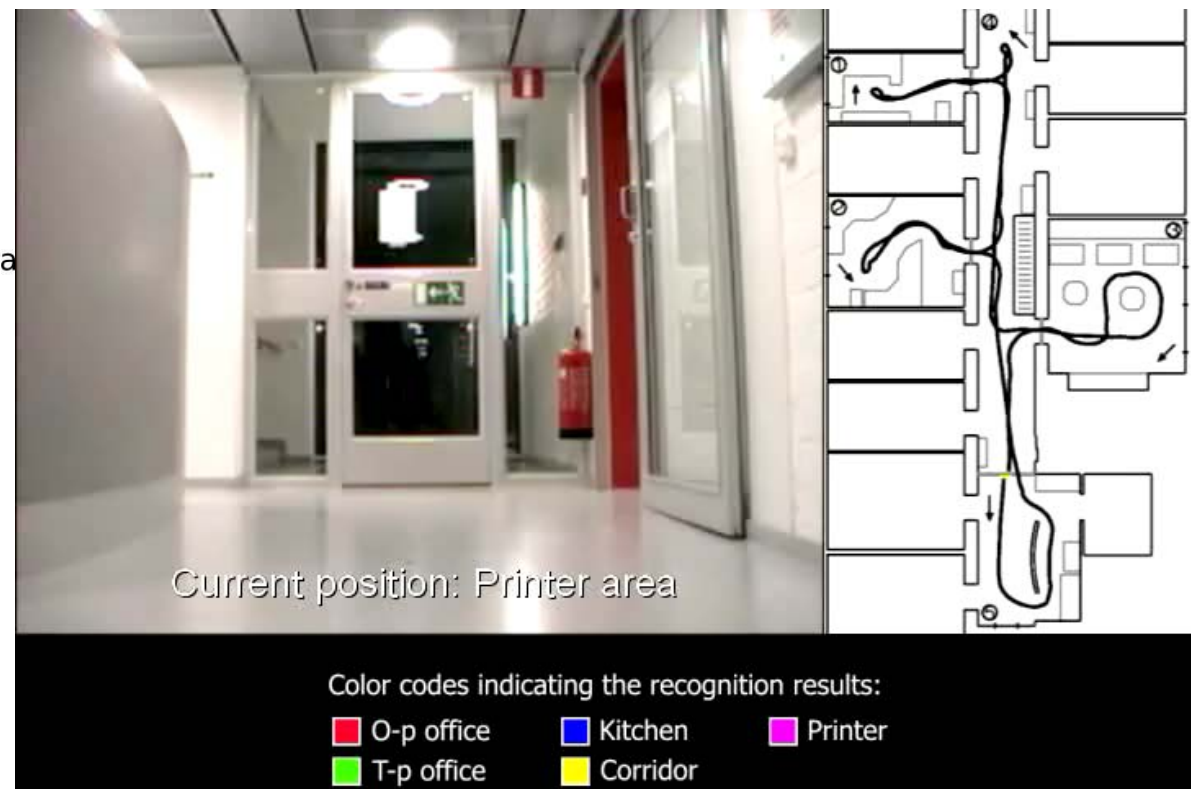
# Goal

- Design a system able to visually categorize indoor places



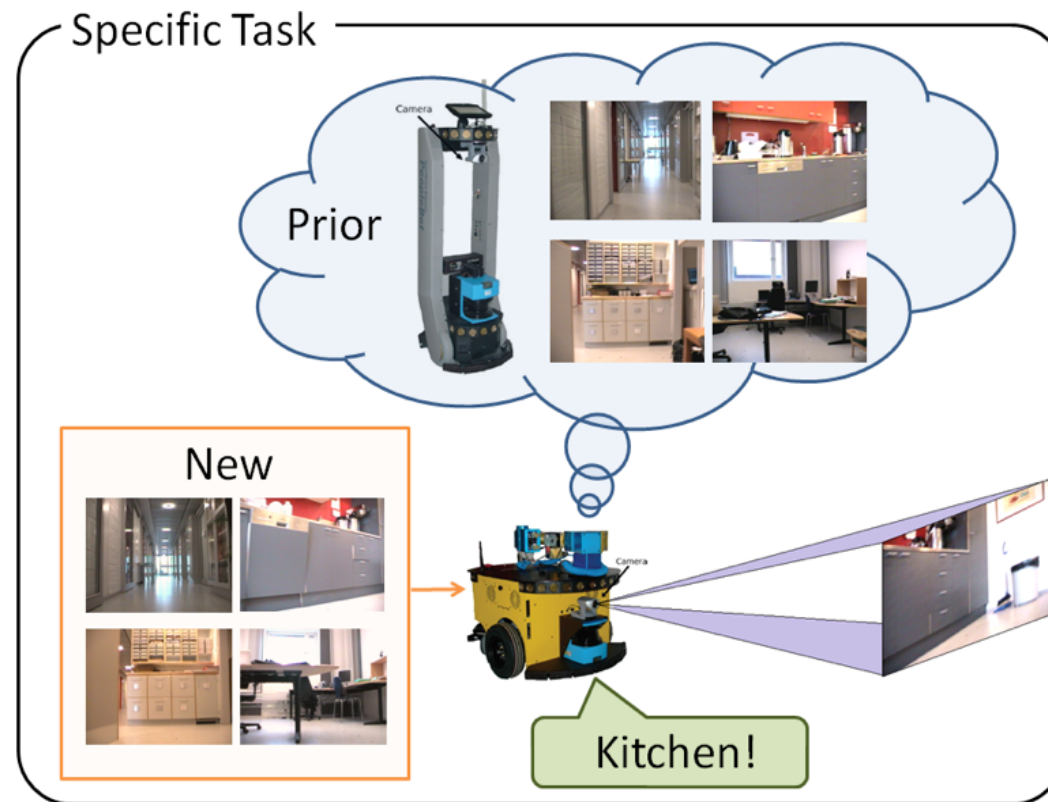
# Why it is useful?

- Build a multi-layer representation of space and use it to navigate/interact with it

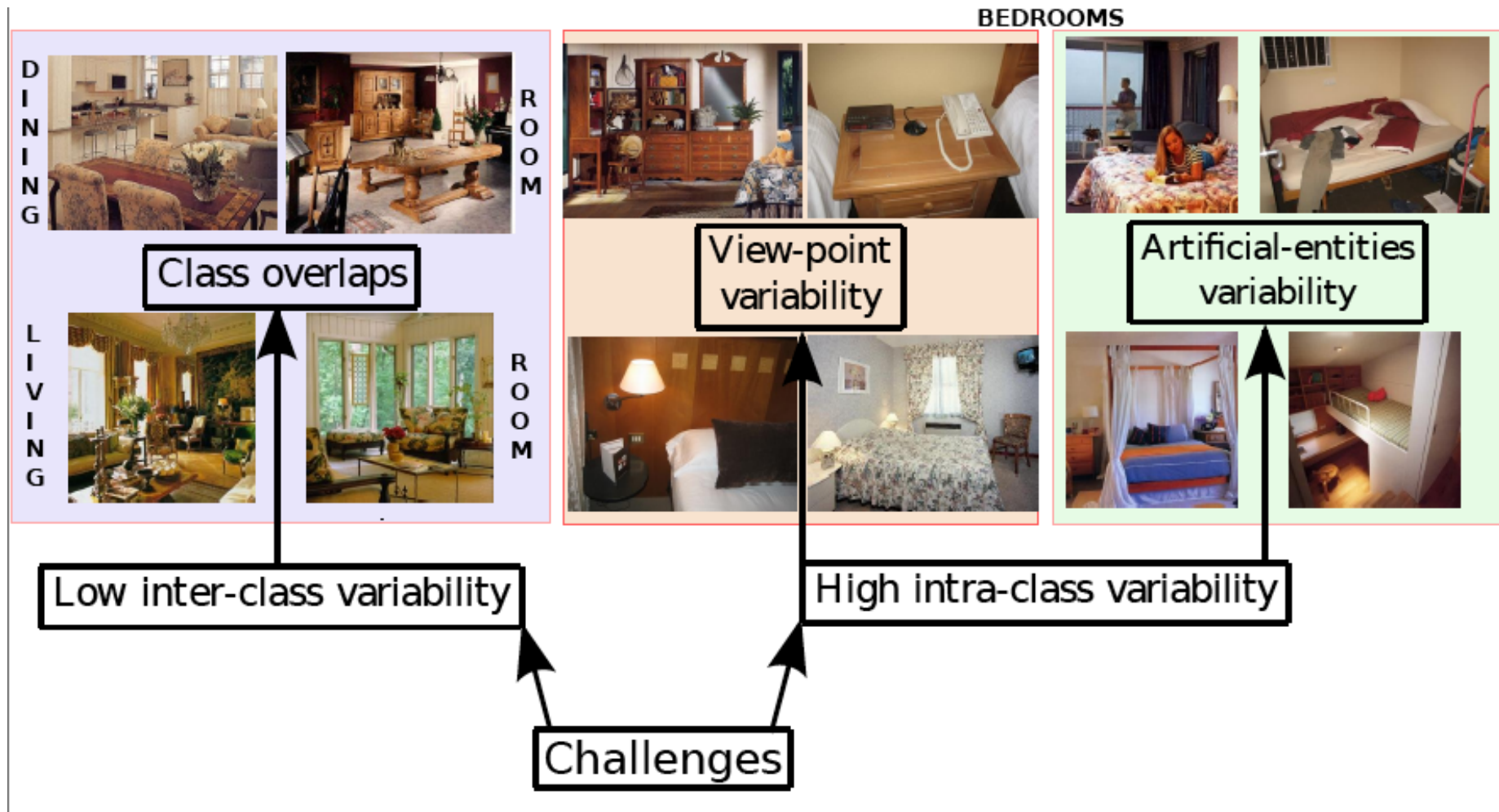


# Why it is useful?

- Use categorical priors for boosting learning of new environments



# Challenges







# Human Visual Perception

- **What do we remember and what do we forget when we recall a scene?**
  - **WE DO REMEMBER:** the gist of a scene, 4-5- landmark objects and their spatial configuration
  - **WE DO NOT REMEMBER:** all the objects in the scene, mid- to fine details

J. M. Wolfe. *Visual memory: what do you know about what you saw?*  
Current Biology, 1998, 8: R303-R304



# Outline of the talk

- **Focus on Gist-like representations**
  - *Visual Place Categorization*
  - *Transfer Learning of Visual Spatial Concepts*



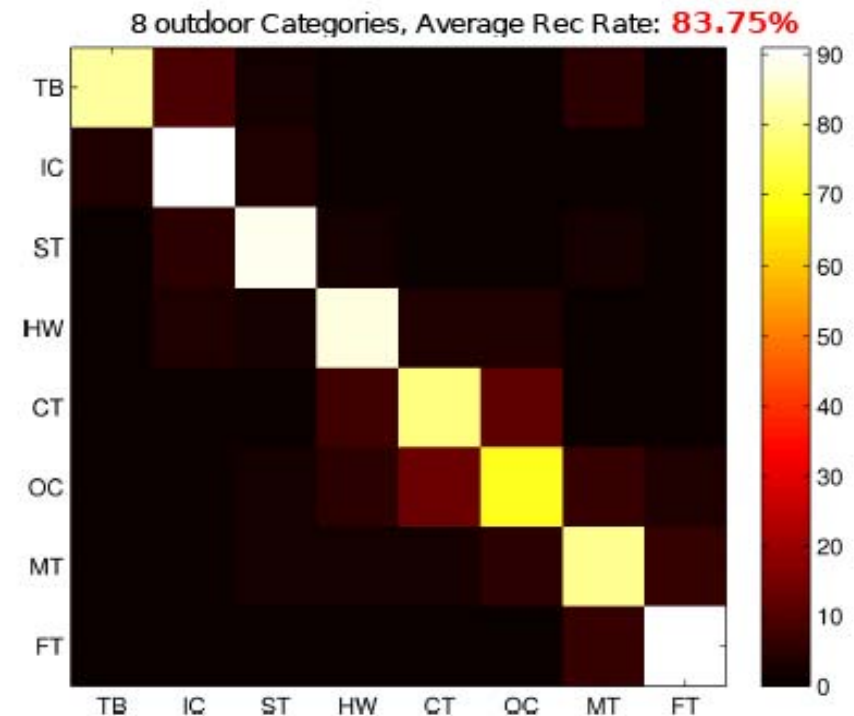
# Outline of the talk

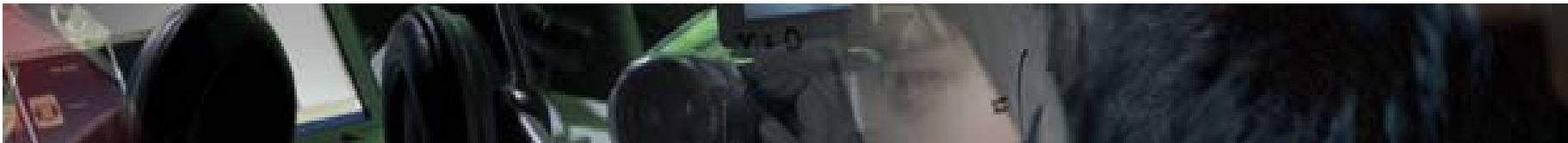
- **Focus on Gist-like representations**
  - *Visual Place Categorization*
  - *Transfer Learning of Visual Spatial Concepts*



# History: the CV Perspective

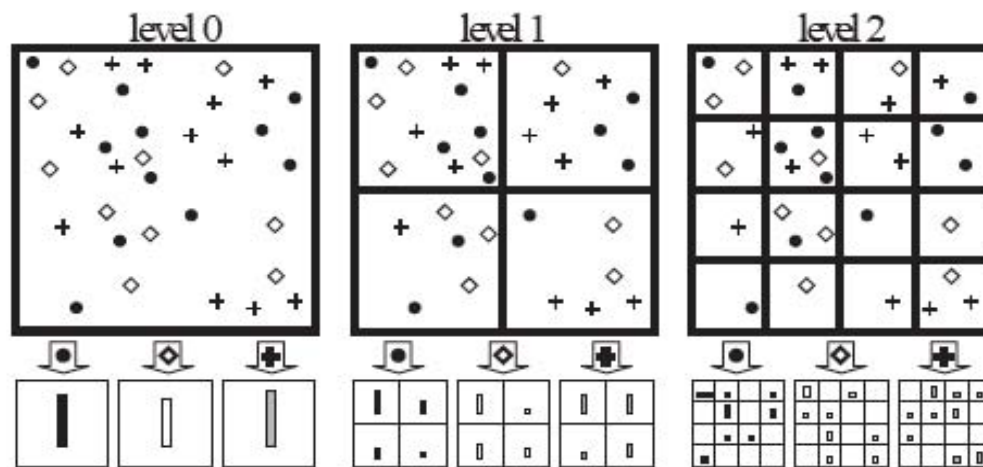
2001 A. Oliva and A. Torralba. Modeling the shape of the scene: A holistic representation of the spatial envelope. IJCV





# History: the CV Perspective

2006 S. Lazebnik, C. Schmid, and J. Ponce. Beyond bags of features: Spatial pyramid matching for recognizing natural scene categories. CVPR

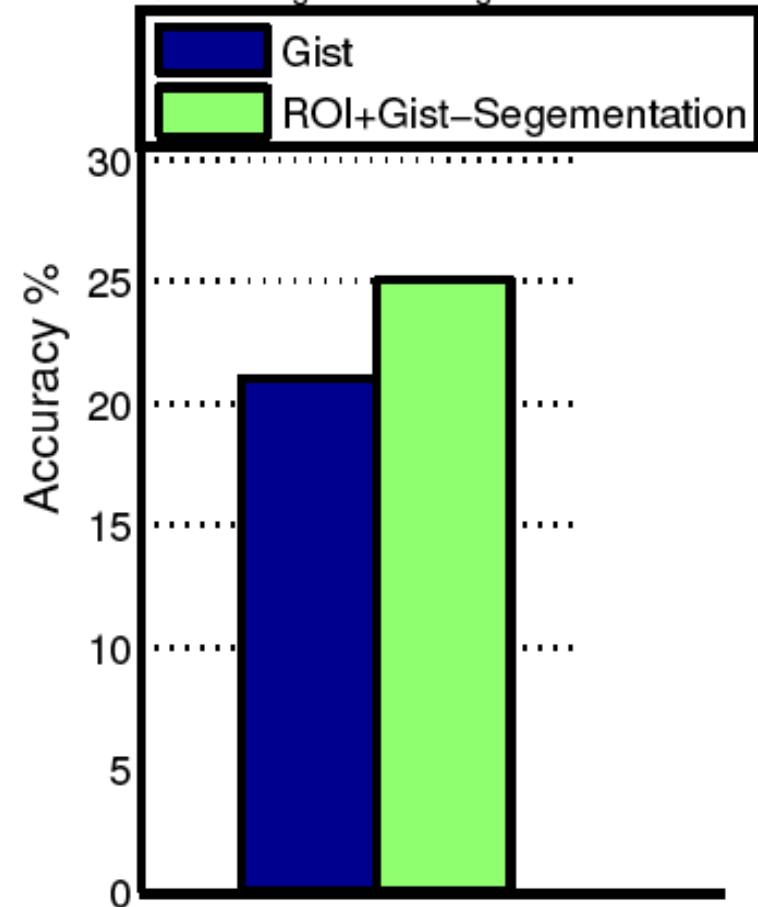


*"Not surprisingly, confusion occurs between the indoor classes"*

# History: the CV Perspective

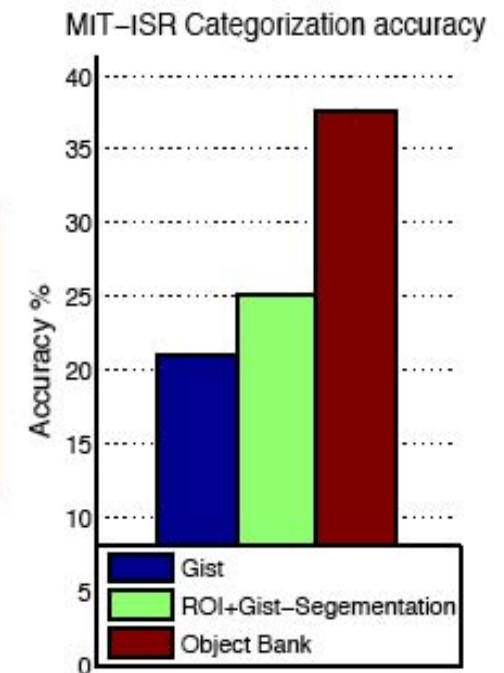
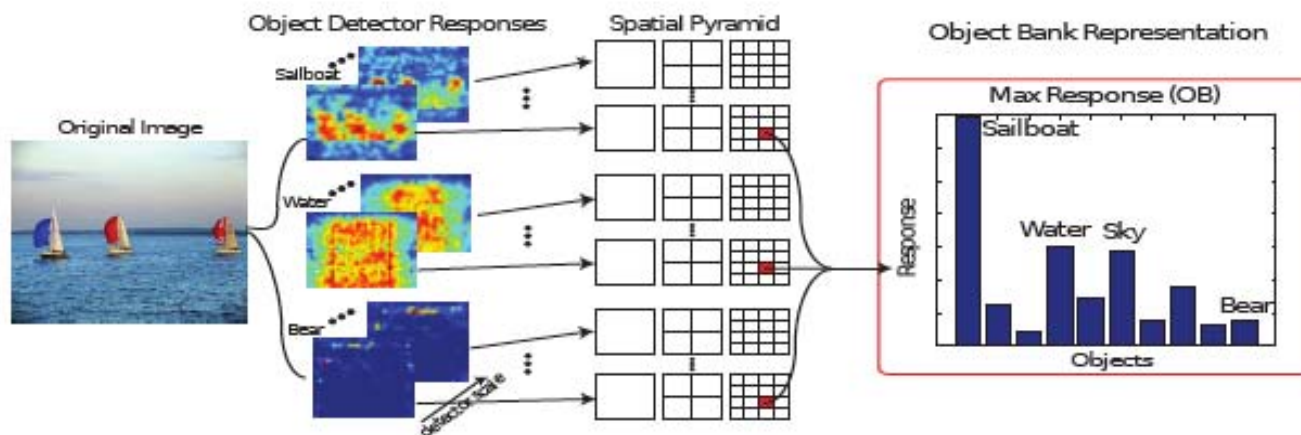
2009 A. Quattoni and A. Torralba. Recognizing Indoor Scenes. CVPR

67 Indoor Categories Average Rec. Rate **25%**



# History: the CV Perspective

2010 Li-Jia Li et al. Object Bank: A High-Level Image Representation for Scene Classification and Semantic Feature Sparsification. NIPS



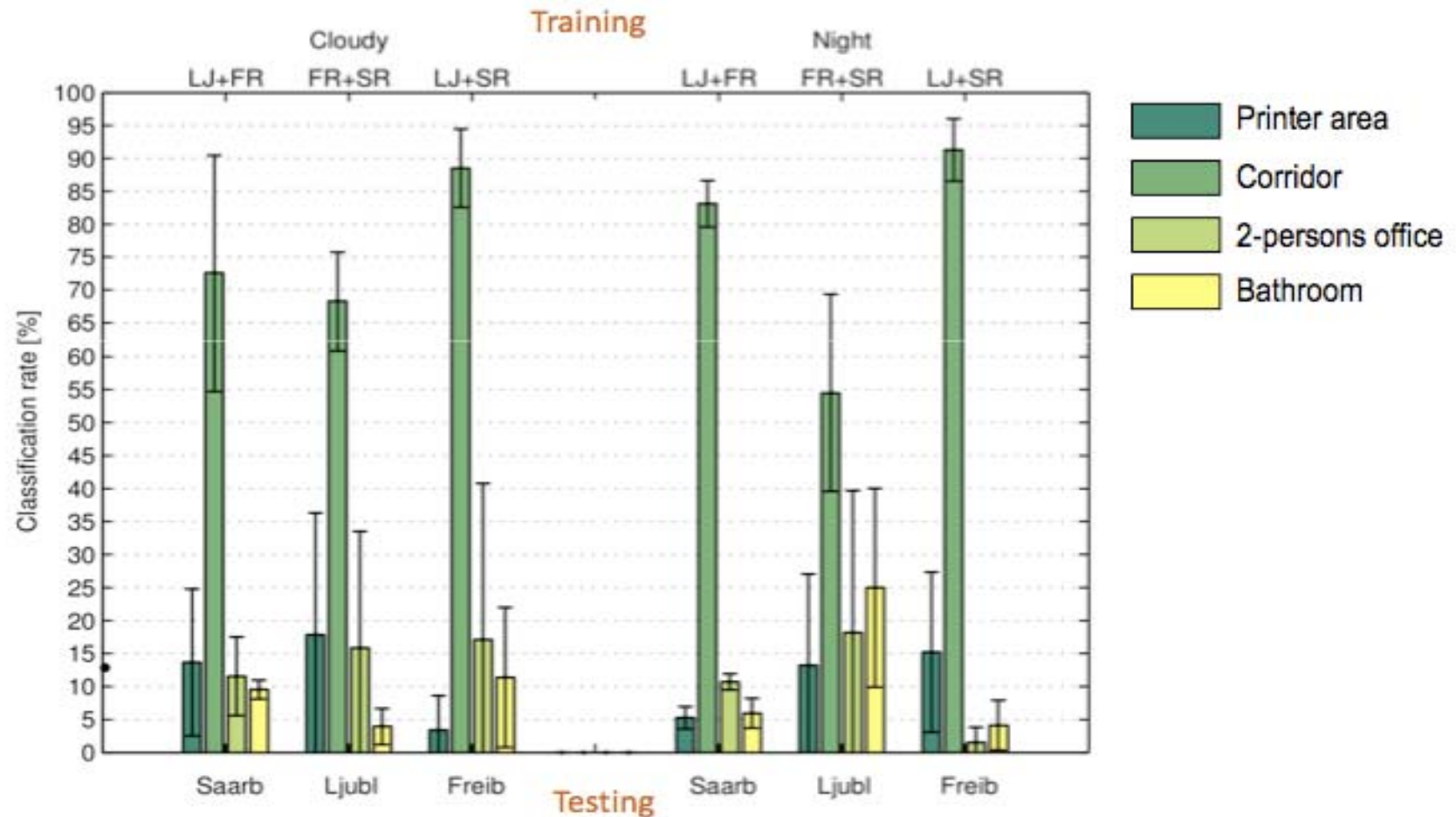
# History: the Robotics Perspective



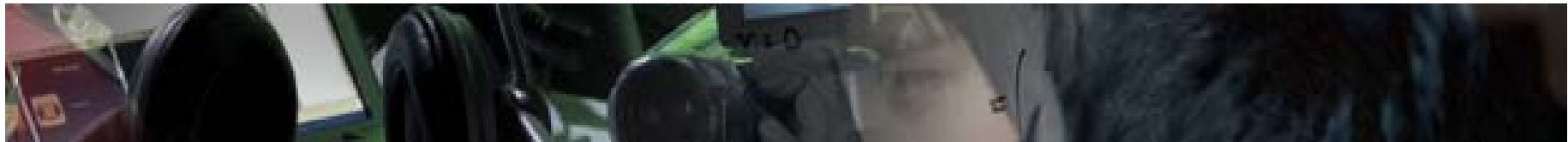
- A. Pronobis, B. Caputo. COLD: the Cosy Localization Database. IJRR 2009



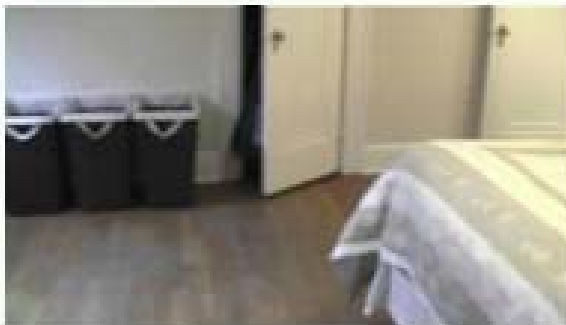
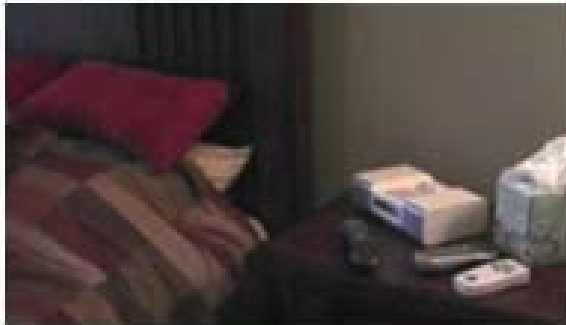
# Place Categorization



- Rec Rate SOTA: 27.57%

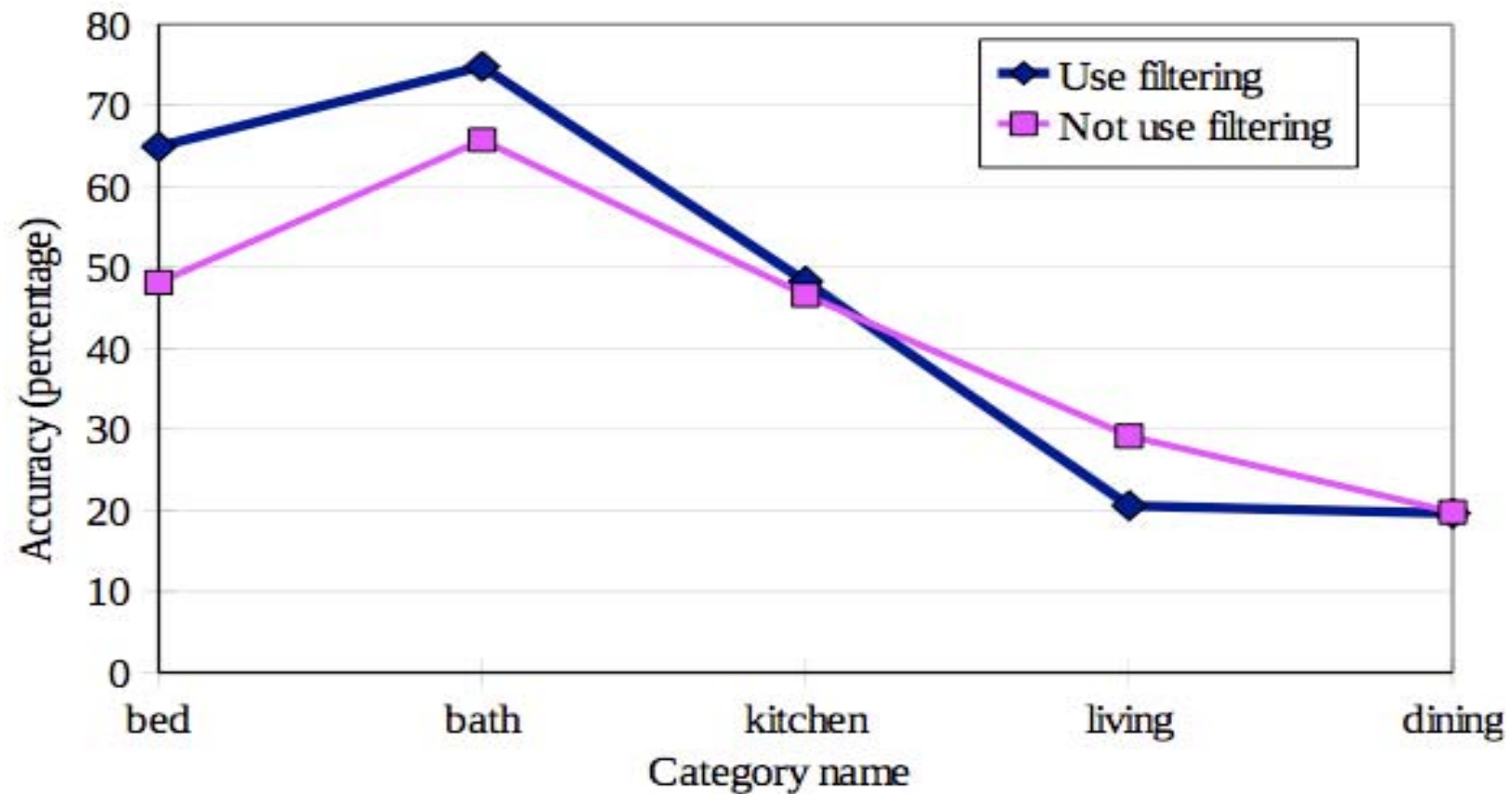


# Place Categorization



- J. Wu, H. Christensen, J. Rehg. Visual place categorization: problem, dataset, and algorithms.
- Proc of ICRA 2009.

# Place Categorization



- Rec Rate SOTA: 45.62%

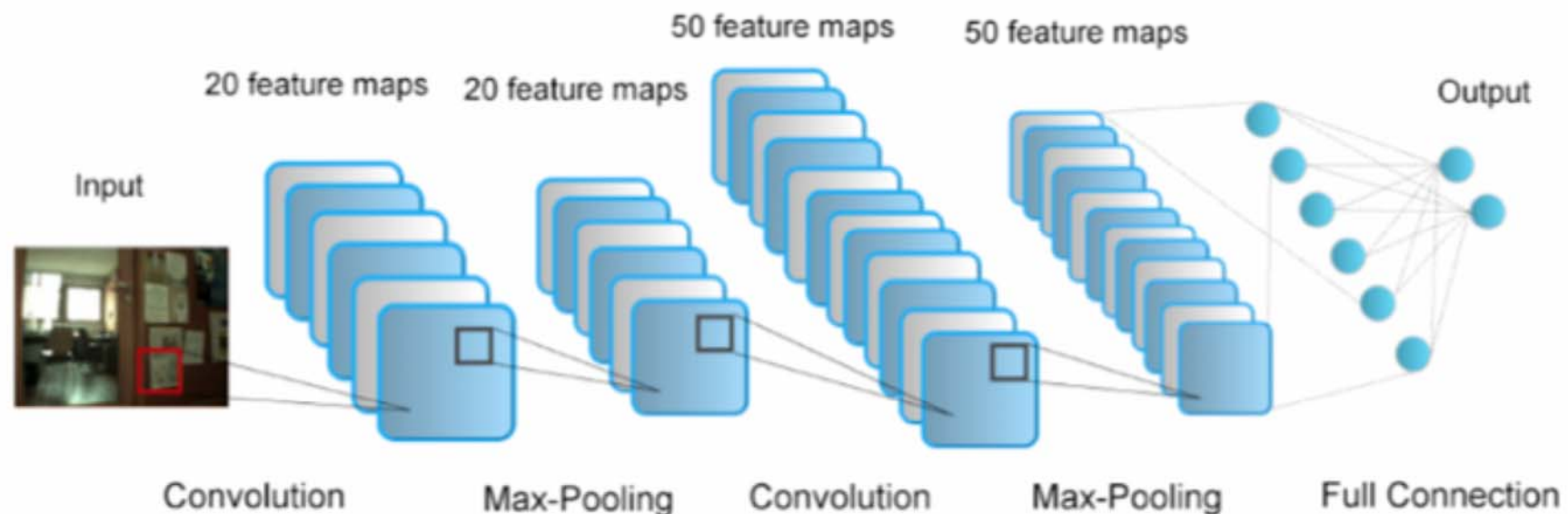


# Place Categorization

Gist representations  
do not work.....  
or do they?

# Place Categorization

M. Mirza, M. Forni, R. Collobert, B. Caputo. *On Learning Visual Features for Indoor Scenes*. ICRA12, submitted



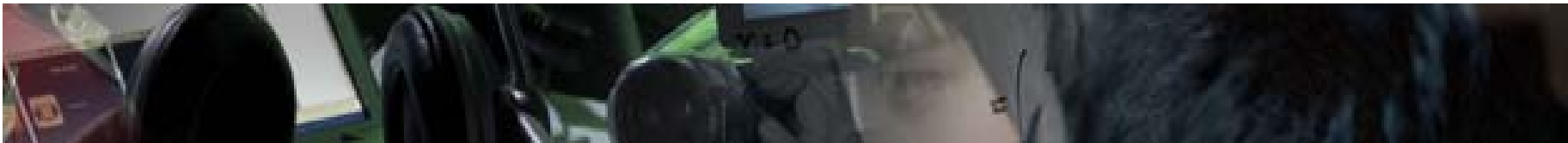
***We learn the gist as opposed to designing it!***





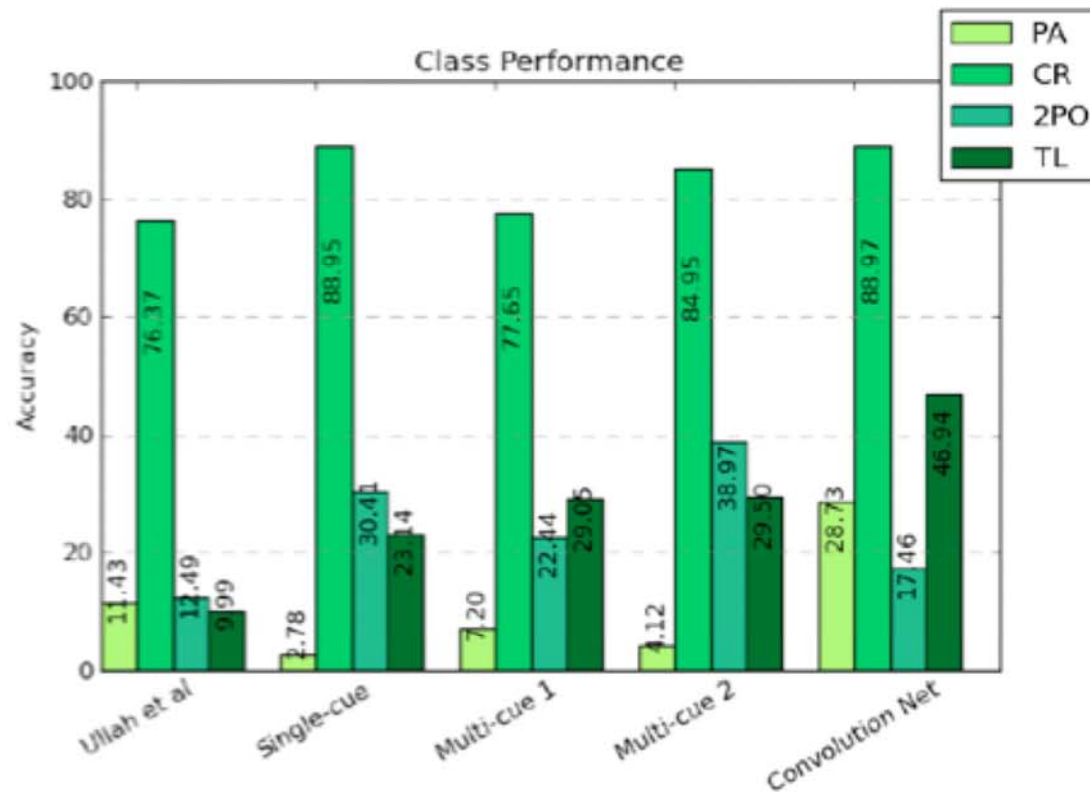
# Place Categorization

- We follow the approach outlined in [Jarret et al, ICCV09] for object recognition benchmarks
- **We use a two stages architecture for feature extraction, with each stage composed by:**
  - 20/50 filter banks of size  $(10 \times 10)$ ,  $(4 \times 4)$ / $(2 \times 2)$  shaped max pooling, rectification and non-linearity
- **Third stage:** hidden layer with 1,000 nodes, connected to an output layer of the same dim of the number of classes

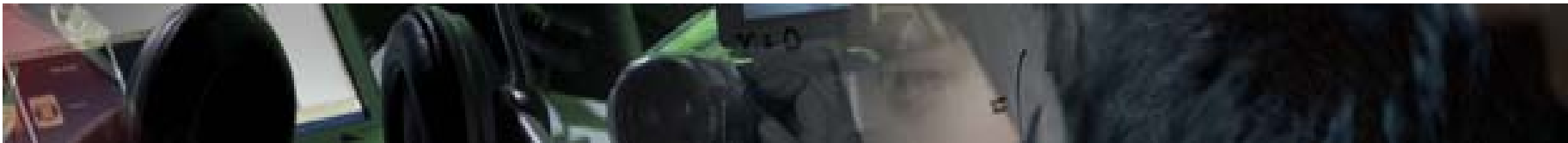


# Place Categorization

## Results: COLD database

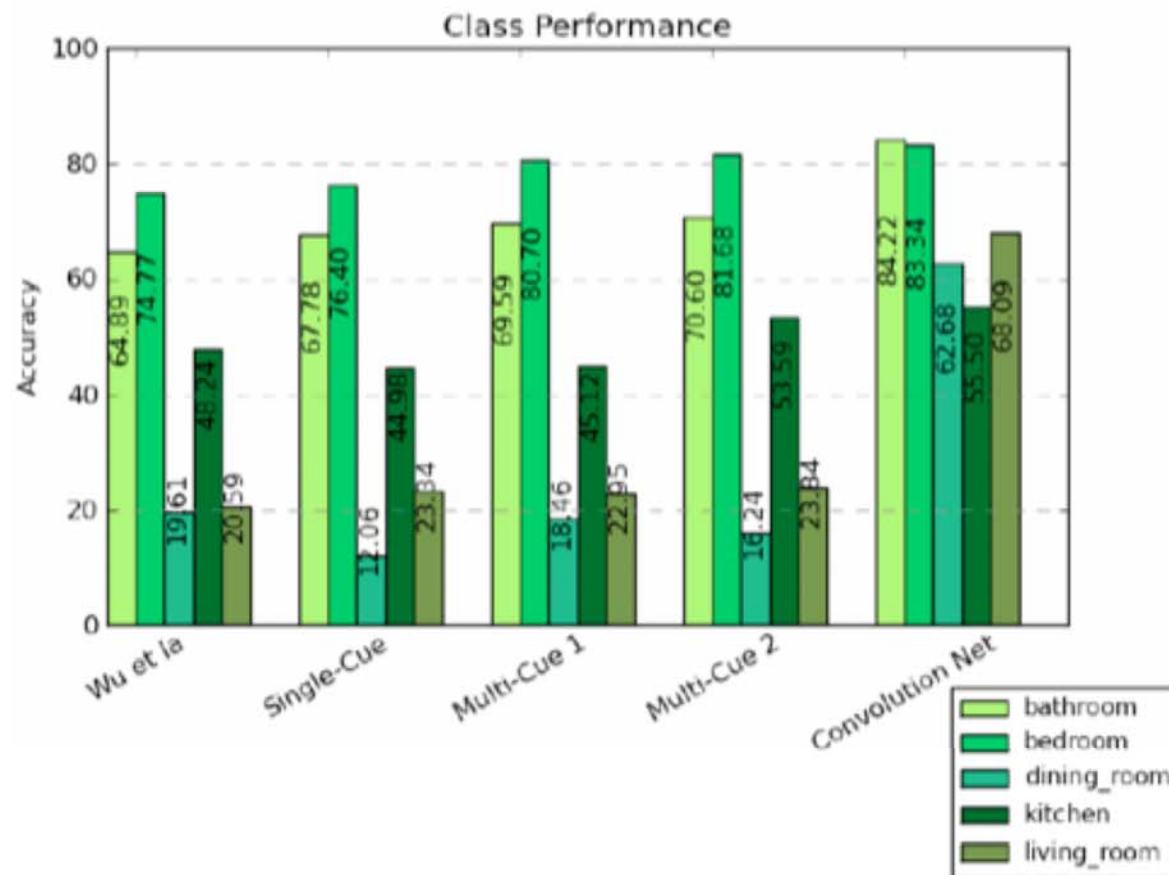


rec rate sota: 27.57%  
rec rate dcn: 45.52%



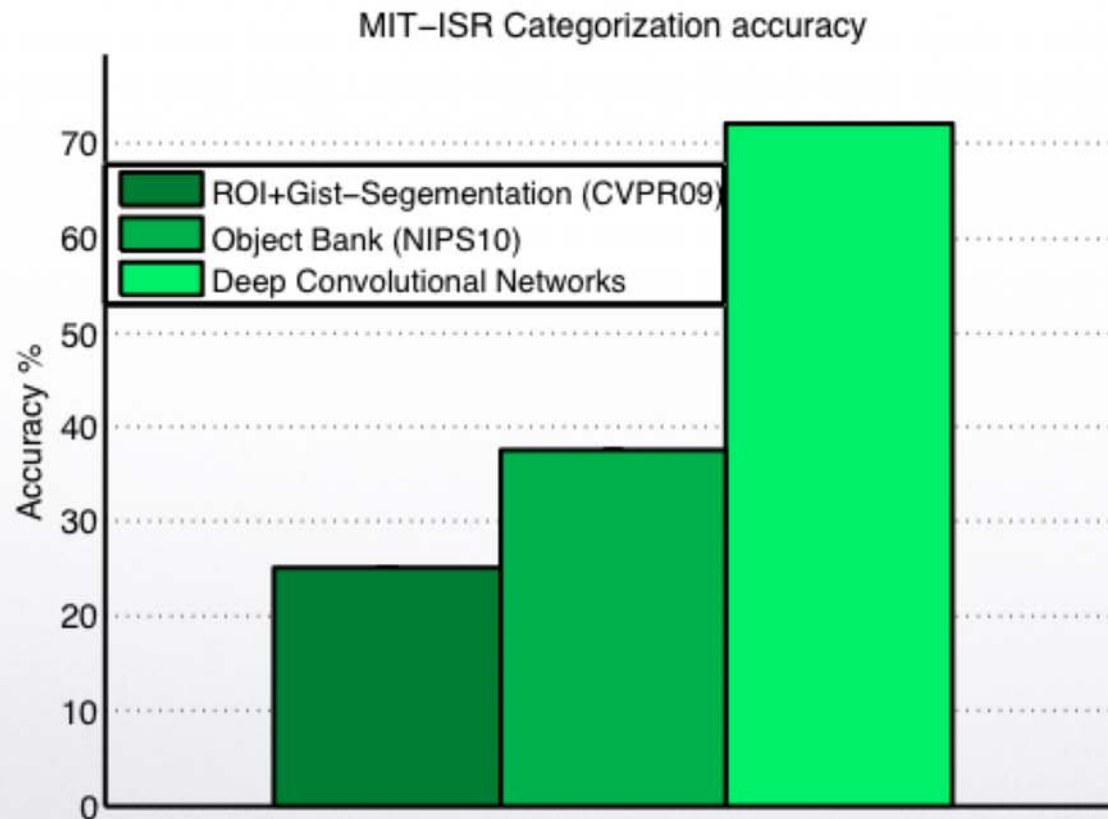
# Place Categorization

## Results: VPC database



rec rate sota: 45.62%  
rec rate dcn: **70.76%**

# Place Categorization



rec rate sota:37%  
rec rate dcn: **72%**



# Outline

- **Focus on Gist-like representations**
  - *Visual Place Categorization*
  - *Transfer Learning of Visual Spatial Concepts*





# Transfer Learning

## Learning Categories from few examples

- Basic Intuition

**IF** a system has already learnt  $k$  categories  
**THEN** learning the  $(k + 1)^{\text{th}}$  should be easier.

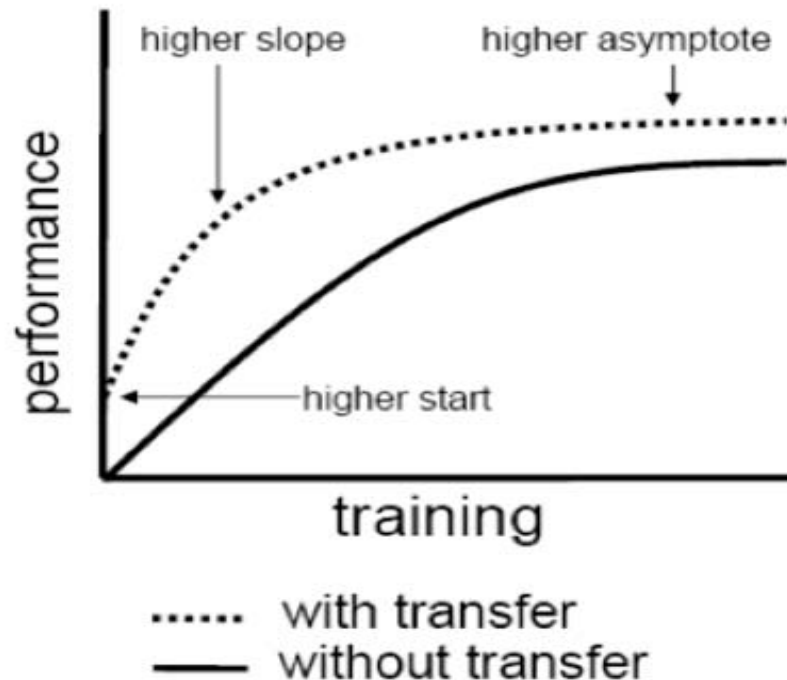


**Transfer information from prior knowledge**

- **Hypothesis:** the more familiar the new category is to prior knowledge, the easier the learning process is.

# Transfer Learning

## Advantages



- + performance higher than that of an ignorant agent;
- + less time needed than learning from scratch;
- + heigher asymptotic performance than using only train data.



# Transfer Learning

## Transfer Learning: key questions

- **How to transfer:** using Least-Square Support Vector Machine.
- **What to transfer:** we define the prior knowledge as the hyperplanes of the classifiers  $\mathbf{w}'_j$ ,  $j=1 \dots k$  of the  $k$  classes already learned.
- **When/How much to transfer:** using the Leave One Out error on the training set. It is an unbiased estimator of the classifier generalization error.

# Transfer Learning

## Transfer Learning from Multiple Classes

### Weighted LS-SVM + Adaptation

$$\min_{\mathbf{w}, b} \frac{1}{2} \left\| \mathbf{w} - \sum_{j=1}^k \beta_j \mathbf{w}'_j \right\|^2 + \frac{C}{2} \sum_{i=1}^n \zeta_i$$

**Leave-One-Out Error :**  $\mathbf{r}_i^{(-i)} = f(\mathbf{w}'_{1\dots j}, b_{1\dots j})$

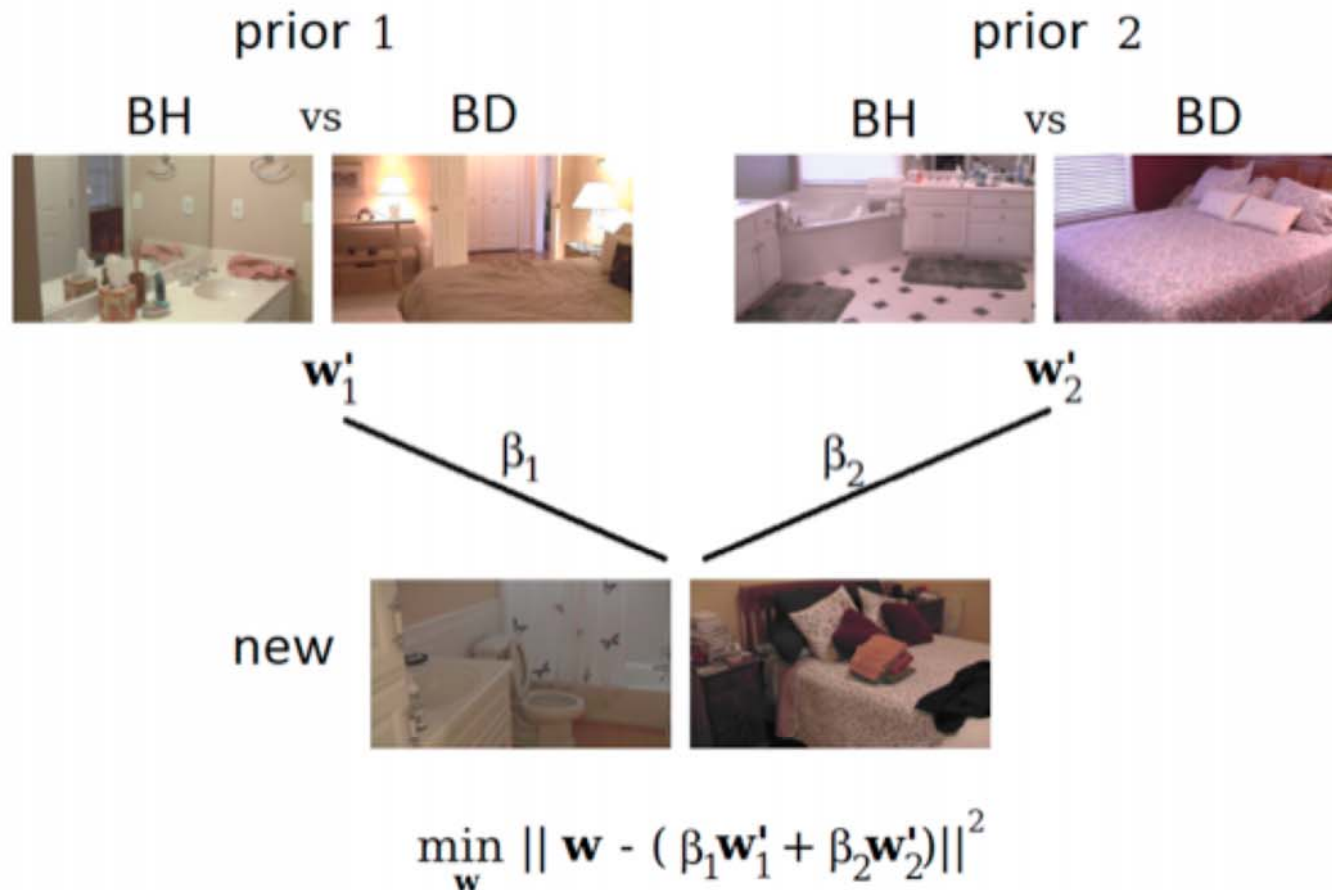
**Leave-One-Out Prediction:**  $\mathbf{y} = g(\mathbf{r}_i^{(-i)})$

**Loss Function:**  $l(y_i, \tilde{y}_i) = \zeta_i \max[1 - y_i \tilde{y}_i, 0]$

**Objective Function:**  $J = \sum_{i=1}^n l(y_i, \tilde{y}_i) \quad \text{s.t.} \quad \|\boldsymbol{\beta}\|_2 \leq 1$

**Find the best  $\mathbf{b}_j$  minimizing  $J$**

# Transfer Learning



T. Tommasi, F. Orabona, B. Caputo. *Safety in numbers: learning categories from few examples with multi model knowledge transfer*. Proc CVPR 2010



# Transfer Learning

S. P. Elango, T. Tommasi, B. Caputo. *Transfer learning of visual concepts across robots: a discriminative approach*. IEEE T on Robotics, under review, 2011

**IDOL DB**



prior

PA

CR

TO

OO

KT



cloudy

new



cloudy

new



sunny

new

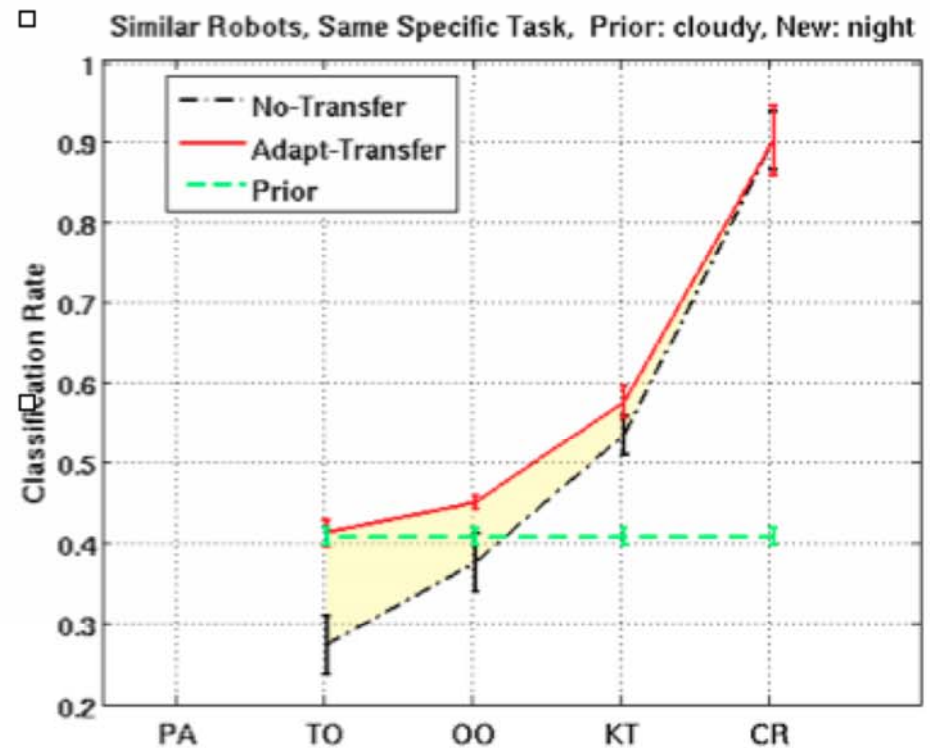
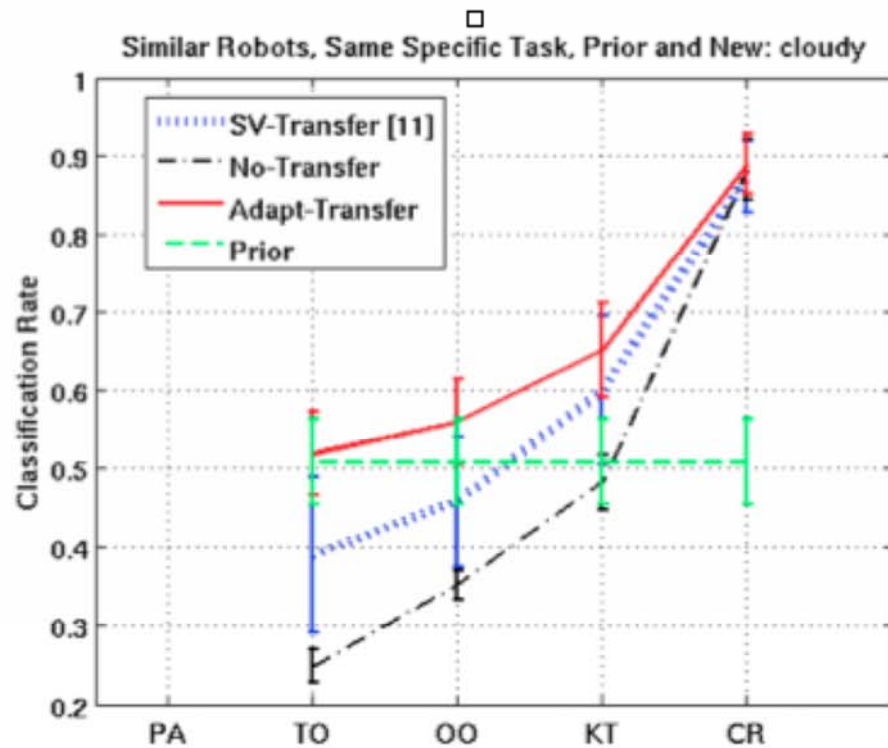


night



# Transfer Learning

## Results: IDOL database



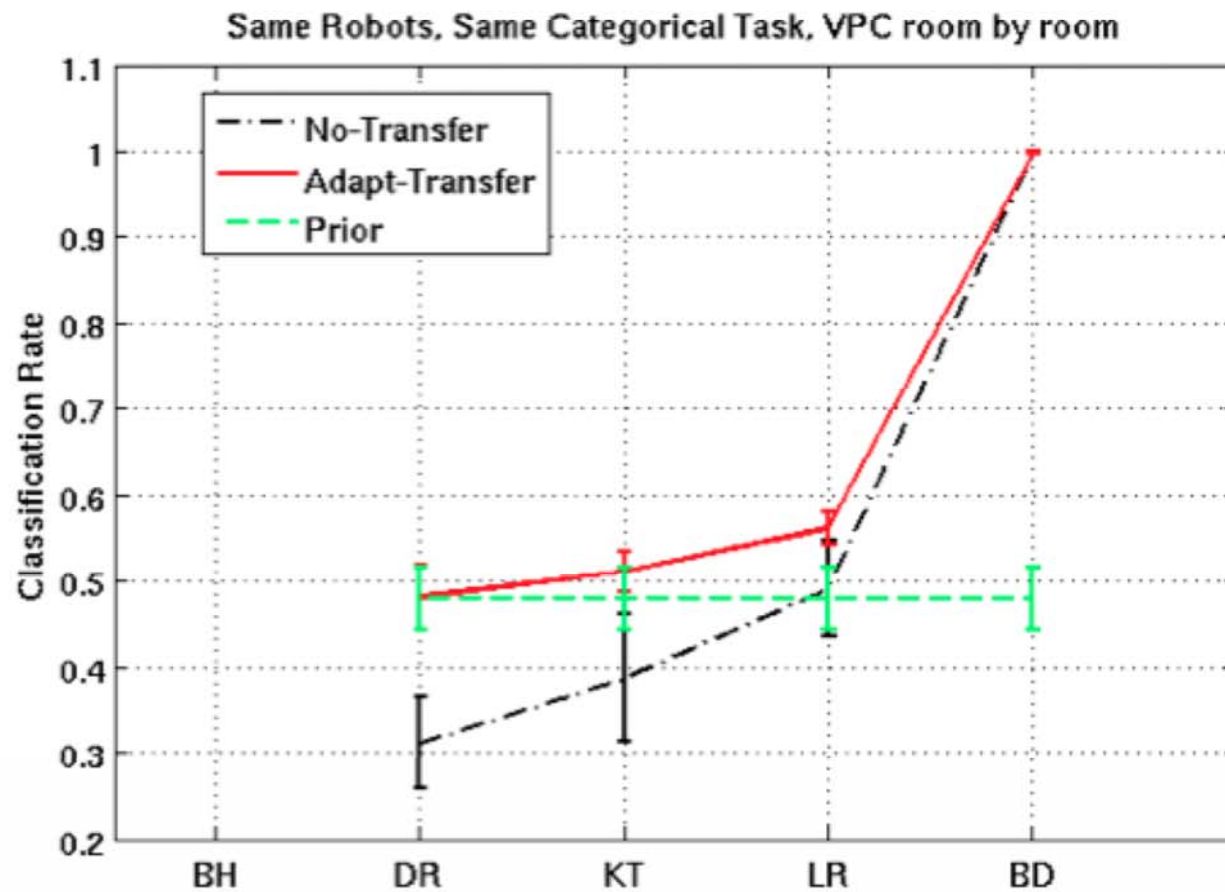
# Transfer Learning

## VPC database



# Transfer Learning

## Results: VPC database





# Transfer Learning

## COLD database



prior

CR



PA



KT



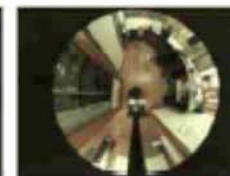
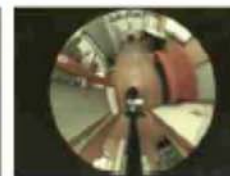
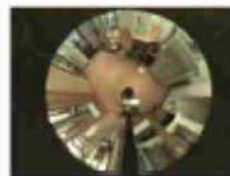
TO



BH



new



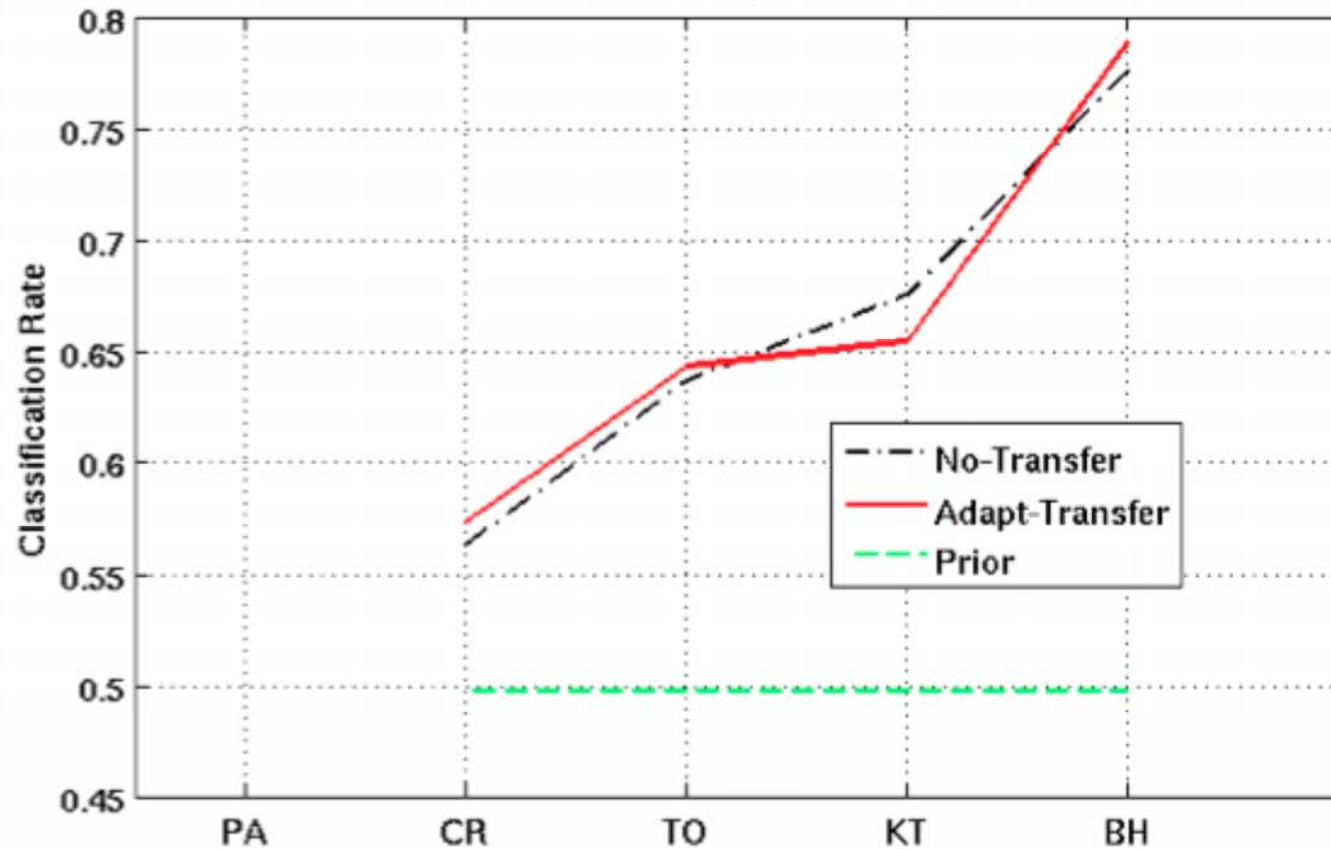
new



# Transfer Learning

## Results: COLD database

Similar Robots, Same Categorical Task, Prior: perspective cam., New: omnidirectional cam.







# Wrapping up

- **Focus on Gist-like representations**
  - Visual Place Categorization: shows big promise by learning the gist representation from the data
  - Transfer Learning of Visual Spatial Concepts: works as long as the prior is informative



# Acknowledgments

- DIRAC EU Integrated Project (FP6)
  - Work on transfer learning (T. Tommasi, F. Orabona)
- ICS-SNSF
  - Work on learning perceptual features (M. Fornoni, M. Mizra)
- SS2-Rob, EU NoE PASCAL Pump Priming
  - Work on transfer learning across heterogeneous robot platforms (S. P. Elango)