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# Techniques for Image Classification, Object detection and Object Segmentation

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paper co-authored with

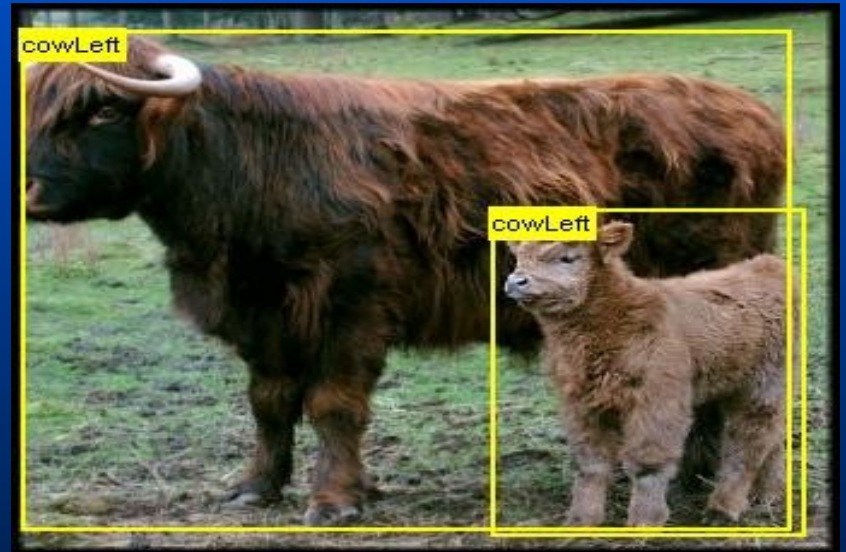
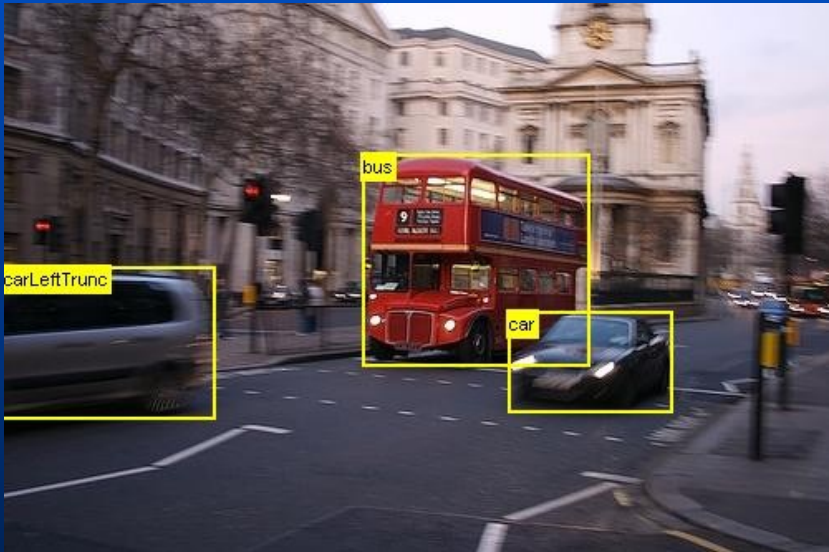
Jorma Laaksonen

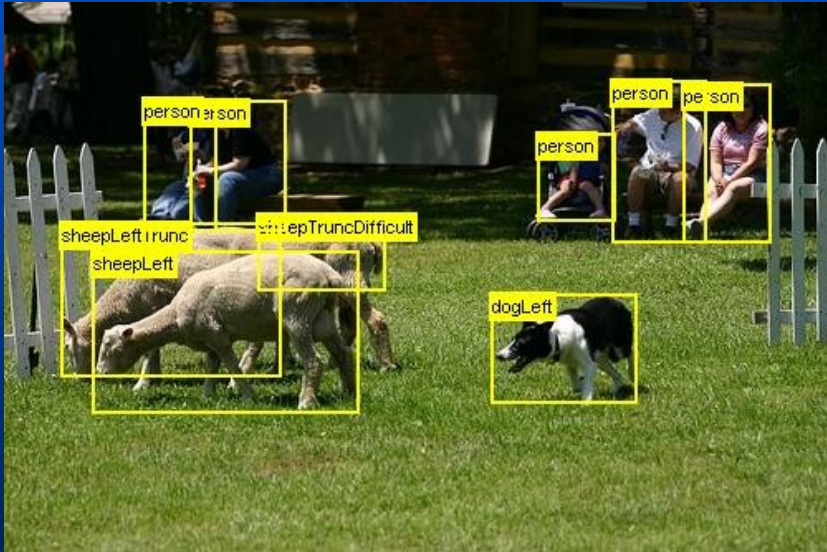
# Talk contents

- aim: document and discuss the system we used for participating the VOC 2007 image analysis benchmark contest
  - 1) The VOC 2007 benchmark
  - 2) Our approach
    - image classification
    - object detection
    - object segmentation
  - 3) Results & conclusion

# VOC 2007 benchmark competition

- Visual Object Classes challenge: a yearly benchmark competition organised by PASCAL Network of Excellence
  - nowadays ~ 20 participating groups
- ~ 10k photographic images
- annotated for 20 classes of objects
  - aeroplane, bicycle, bird, bottle, boat, bus, car, cat, chair, cow, dining table,...

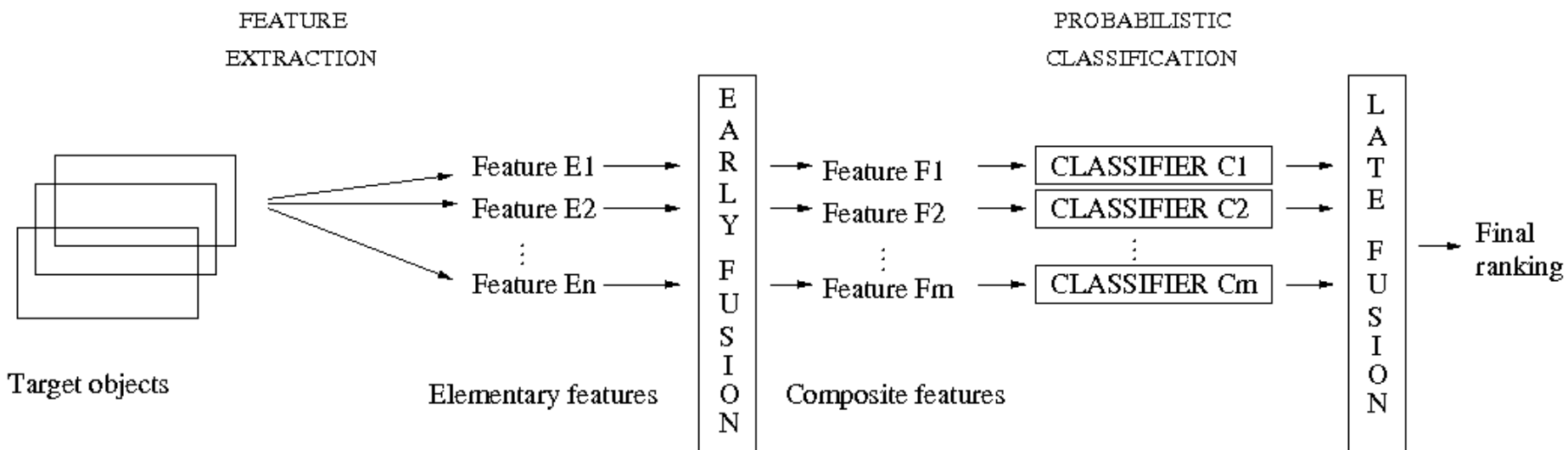




# VOC 2007 tasks

- we consider three (out of four defined) supervised tasks:
  - 1) image classification: determine whether or not a certain class (e.g. cow) of object is present in the images
  - 2) object detection: find bounding boxes of objects
  - 3) object segmentation: find pixel-level segmentation masks for partitioning the area of the images among the 20 object classes

# Framework for visual object classification



# VOC 2007 classification task

- framework used with images as target objects
- large set of global image features -> 141 composite features
- 141 separate SVM classifiers
- SVM-based fusion

# Detection task

- segmentation on images with a region merging type segmentation algorithm
- for each image segment  $s$

$$p(I_s = 1 | c_i, c_s) \approx p(I_s = 1 | I_i = 1, c_s) p(I_i = 1 | c_i).$$

- latter probability directly from classification task
- the first probability calculated using the framework with image segments as target objects
  - feature set somewhat reduced but otherwise similar to classification task

# Segmentation task

- the bounding boxes from detection task automatically converted to segmentation masks

# Results and conclusions

- Classification: relatively good (4<sup>th</sup> out of 19)
  - our individual features probably not as good as the best ones,
  - the fusion aspect of the system more developed
- detection: quite modest, although not hopelessly bad
- segmentation: best among the participants
  - solutions of the participants obviously not yet well-developed
  - why our segmentations better than automatic segmentations converted from better detections?
  - segmentation has been markedly improved [3] after the challenge by re-segmenting our bounding boxes

- A more detailed version of the paper available on-line as a technical report [4] at <http://www.cis.hut.fi/projects/cbir/>