

Face/Flesh Detection and Face Recognition

Linda Shapiro

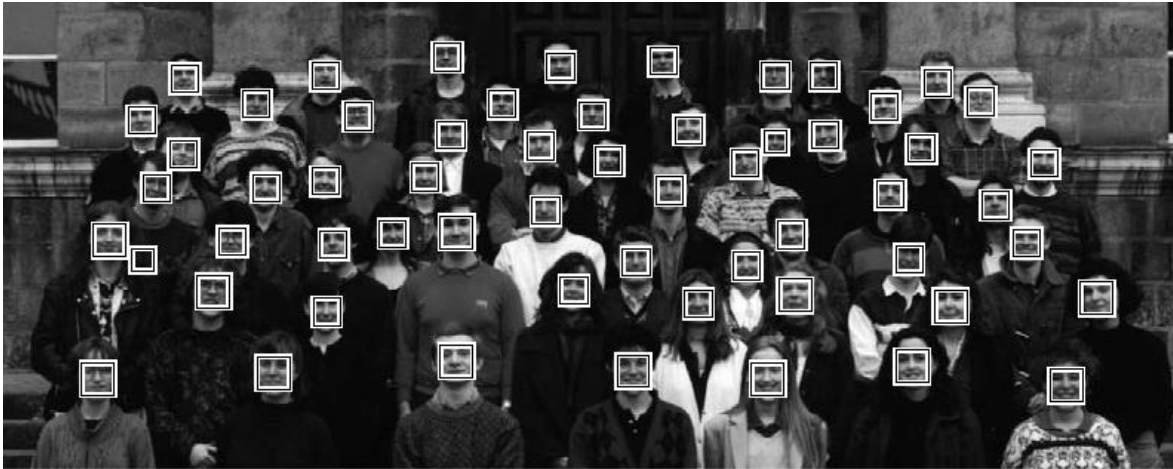
ECE P 596

What's Coming

1. Review of Bakic flesh detector
2. Fleck and Forsyth flesh detector
3. Review of Rowley face detector
4. Overview of Viola Jones face detector with Adaboost
5. Face recognition with PCA

Person Detection

- Example: Face Detection



([Rowley, Baluja & Kanade, 1998](#))

- Example: Skin Detection



([Jones & Rehg, 1999](#))

Review: Bakic Flesh Finder

- Convert pixels to **normalized (r,g)** space
- Train a binary **classifier** to recognize pixels in this space as skin or not skin by giving it lots of examples of both classes.
- On test images, have the classifier **label the skin pixels.**
- Find large **connected components.**

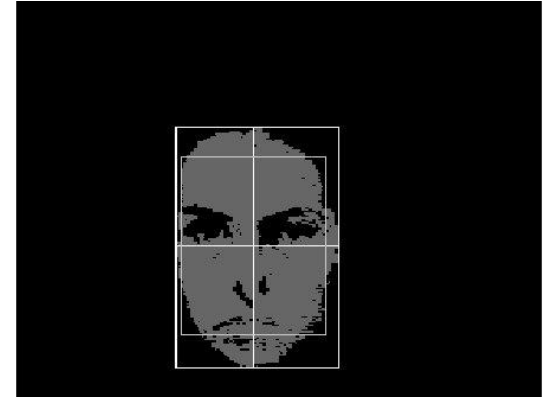
Finding a face in a video frame



input video frame



pixels classified in
normalized r-g space



largest connected
component with aspect
similar to a face

(all work contributed by Vera Bakic)

Fleck and Forsyth's Flesh Detector

- Convert RGB to HSI
- Use the intensity component to compute a texture map
 $\text{texture} = \text{med2} (| I - \text{med1}(I) |)$
- If a pixel falls into either of the following ranges,
it's a potential skin pixel

texture < 5, 110 < hue < 150, 20 < saturation < 60
texture < 5, 130 < hue < 170, 30 < saturation < 130

median filters of
radii 4 and 6

* Margaret Fleck, David Forsyth, and Chris Bregler (1996)
“Finding Naked People,” 1996 **European Conference on
Computer Vision** , Volume II, pp. 592-602.

Algorithm

1. **Skin Filter:** The algorithm first locates images containing large areas whose color and texture is appropriate for skin.
2. **Grouper:** Within these areas, the algorithm finds elongated regions and groups them into possible human limbs and connected groups of limbs, using specialized groupers which incorporate substantial amounts of information about object structure.
3. Images containing sufficiently **large skin-colored groups of possible limbs** are reported as potentially containing naked people.

This algorithm was tested on a database of 4854 images: 565 images of naked people and 4289 control images from a variety of sources. The skin filter identified 448 test images and 485 control images as containing substantial areas of skin. Of these, the grouper identified 241 test images and 182 control images as containing people-like shapes.

Grouping

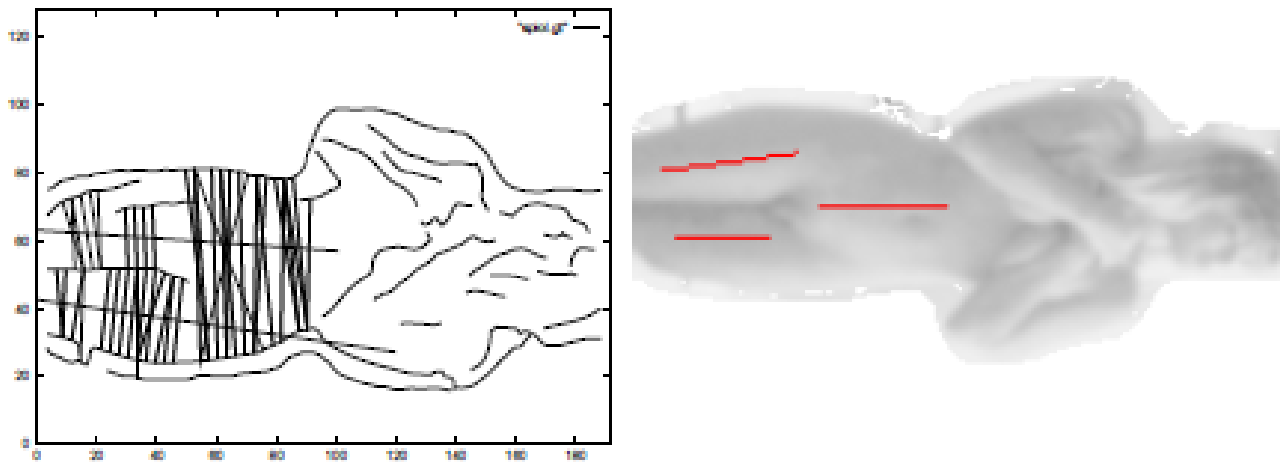
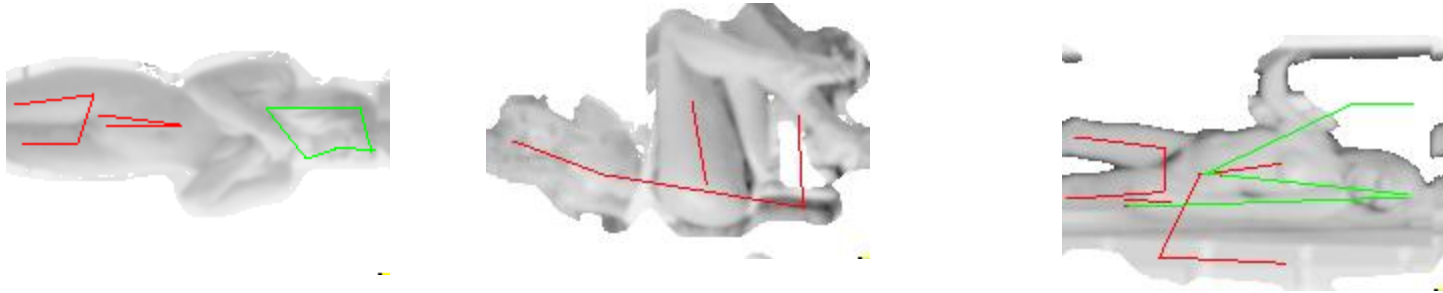


Fig. 2. Grouping a spine and two thighs: *Top left* the segment axes that will be grouped into a spine-thigh group, overlaid on the edges, showing the upper bounds on segment length and the their associated symmetries; *Top right* the spine and thigh group assembled from these segments, overlaid on the image.

Results

	eliminated by skin filter	eliminated by geometrical analysis	marked as containing naked people
test images	13.8% (19)	34.1% (47)	52.2% (72)
control images	92.6% (1297)	4.0% (56)	3.4% (48)

Table 1. Overall classification performance of the system.



Some True Positives

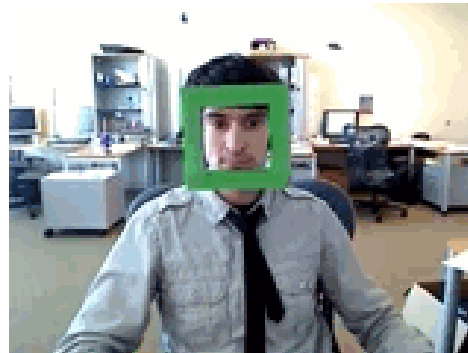


False Negatives



True Negative

Face detection



State-of-the-art face detection demo
(Courtesy [Boris Babenko](#))

Face detection

Where are the faces?



Face Detection

What kind of features?

- Rowley: 32 x 32 subimages at different levels of a pyramid
- Viola/Jones: rectangular features

What kind of classifiers?

- Rowley: neural nets
- Viola/Jones: Adaboost over simple one-node decision trees (stumps)

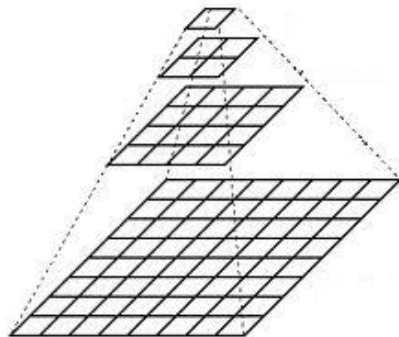
Object Detection: Rowley's Face Finder

1. convert to gray scale
2. normalize for lighting
3. histogram equalization
4. apply neural net(s)
trained on 16K images



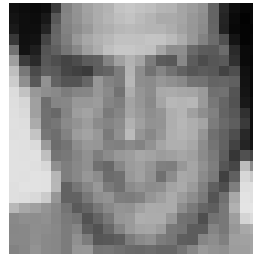
What data is fed to
the classifier?

20 x 20 windows in
a pyramid structure



Viola/Jones: Image Features

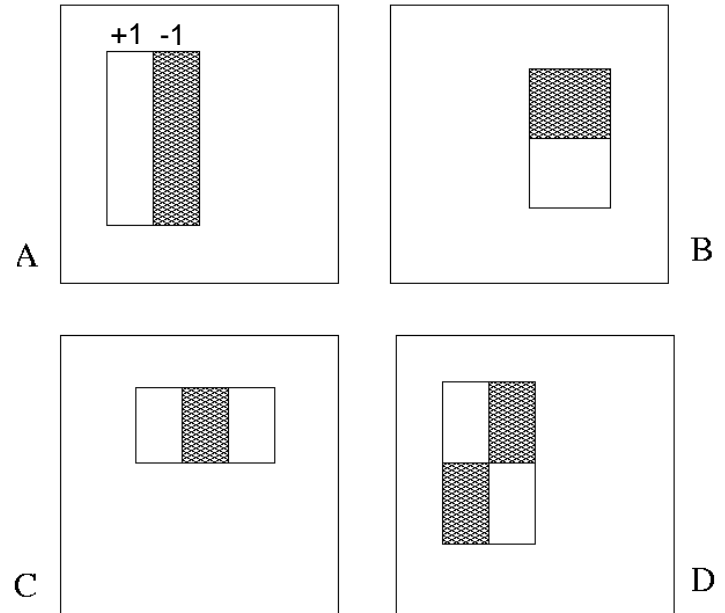
“Rectangle filters”



People call them Haar-like features, since similar to 2D Haar wavelets.

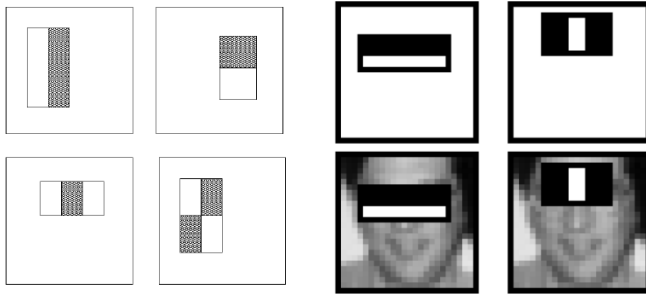
Value =

$$\sum (\text{pixels in white area}) - \sum (\text{pixels in black area})$$



Feature extraction

“Rectangular” filters

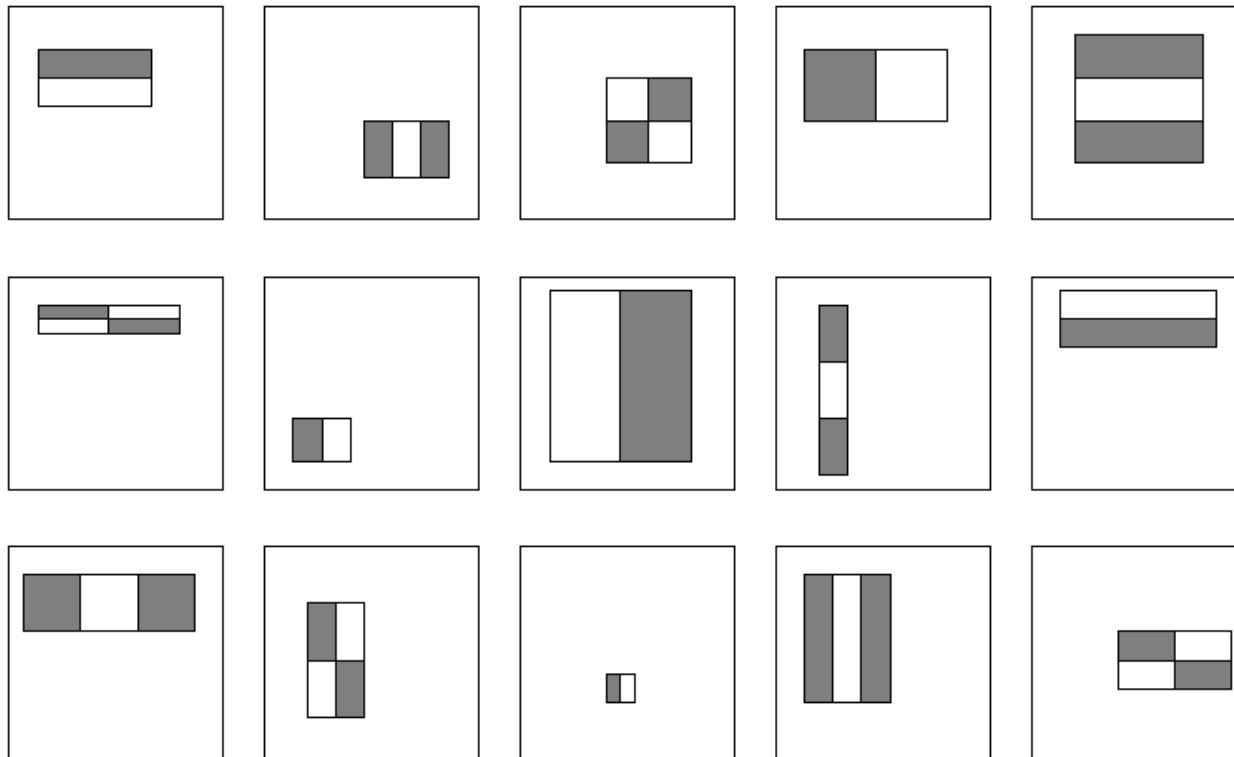


- Filters can be different sizes.
- Filters can be anywhere in the box being analyzed.
- Feature output is very simple convolution.
- Requires sums of large boxes.

Efficiently computable
with **integral image**: any
sum can be computed
in constant time

Avoid scaling images
scale features directly
for same cost

Large library of filters



Considering all possible filter parameters:
position, scale,
and type:

160,000+
possible features
associated with
each 24 x 24
window

Use **AdaBoost** both to select the informative features and to form the classifier

Feature selection

- For a 24x24 detection region, the number of possible rectangle features is ~160,000!
- At test time, it is impractical to evaluate the entire feature set
- Can we create a good classifier using just a small subset of all possible features?
- How to select such a subset?

Basic AdaBoost Review

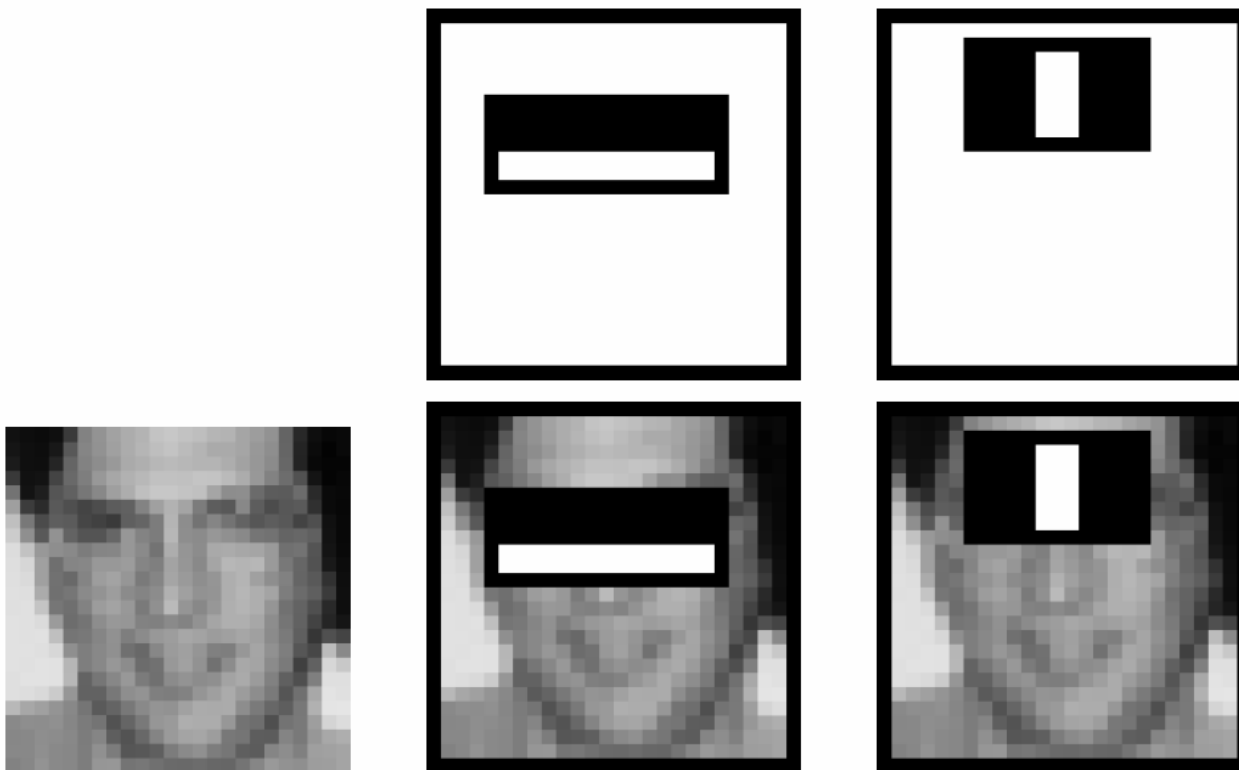
- **Input** is a set of training examples (X_i, y_i) $i = 1$ to m .
- We train a **sequence of weak classifiers**, such as decision trees, neural nets or SVMs. Weak because not as strong as the final classifier.
- The training examples will have **weights**, initially all equal.
- At each step, we use the current weights, train a new classifier, and use its performance on the training data to produce **new weights** for the next step (normalized).
- But we **keep ALL** the weak classifiers.
- When it's time for testing on a new feature vector, we will **combine the results from all of the weak classifiers**.

Weak Classifiers

- Each weak classifier works on exactly **one rectangle feature**.
- Each weak classifier has 3 associated variables
 1. its threshold θ
 2. its polarity p
 3. its weight α
- The polarity can be 0 or 1
- The weak classifier computes its one feature f
 - When the polarity is 1, we want $f > \theta$ for face
 - When the polarity is 0, we want $f < \theta$ for face
- The weight will be used in the final classification by AdaBoost.

Boosting for face detection

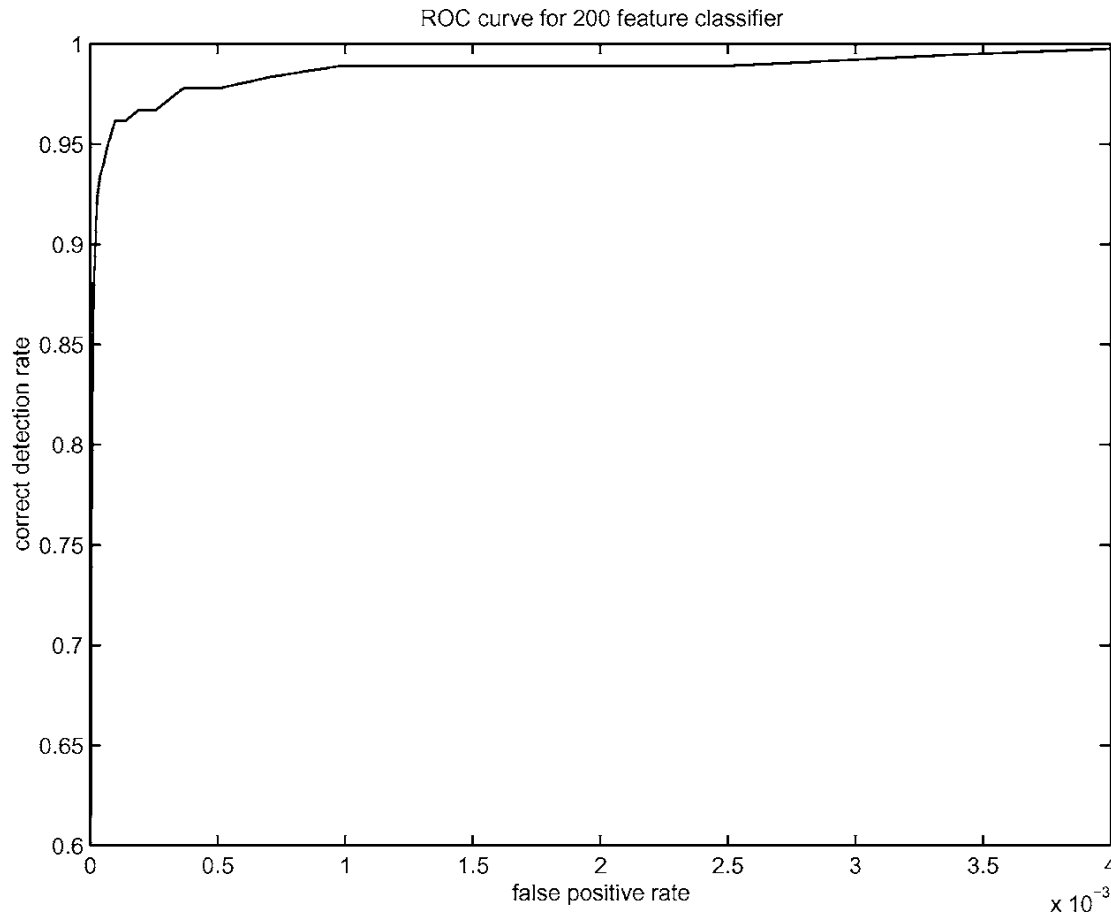
- First two features selected by boosting:



This feature combination can yield 100% detection rate and 50% false positive rate

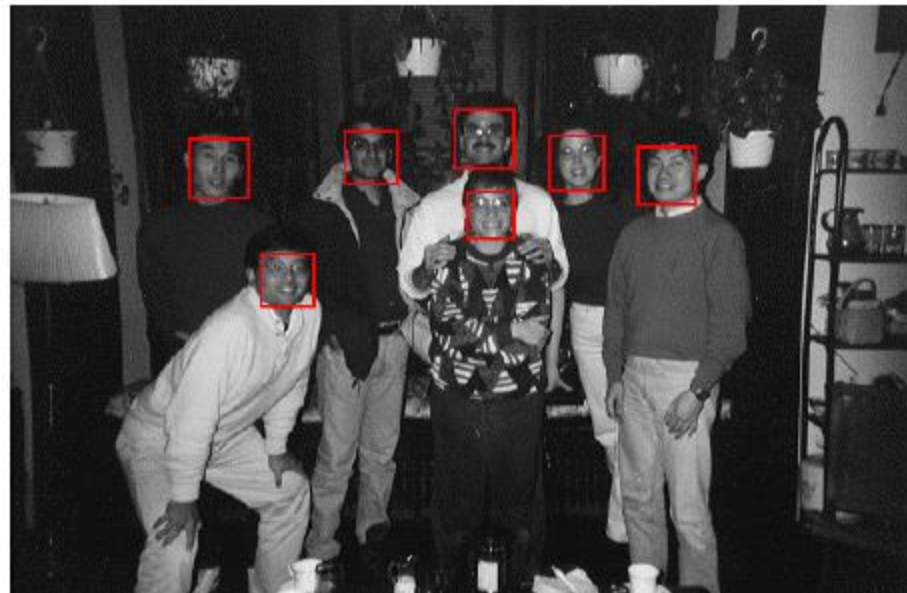
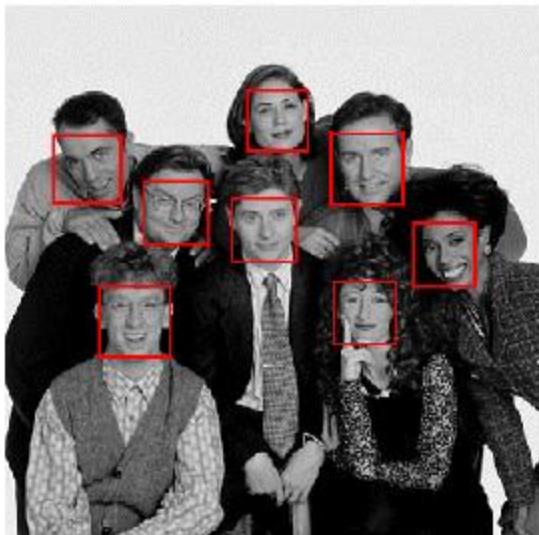
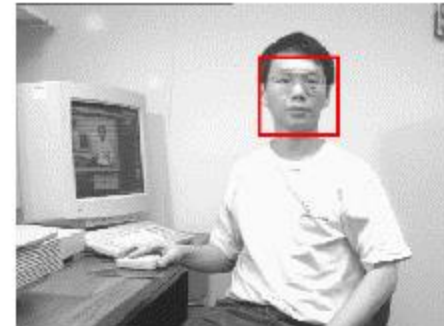
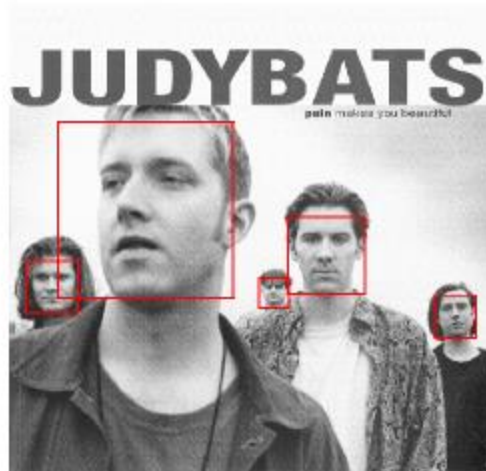
Boosting for face detection

- A 200-feature classifier can yield 95% detection rate and a false positive rate of 1 in 14084

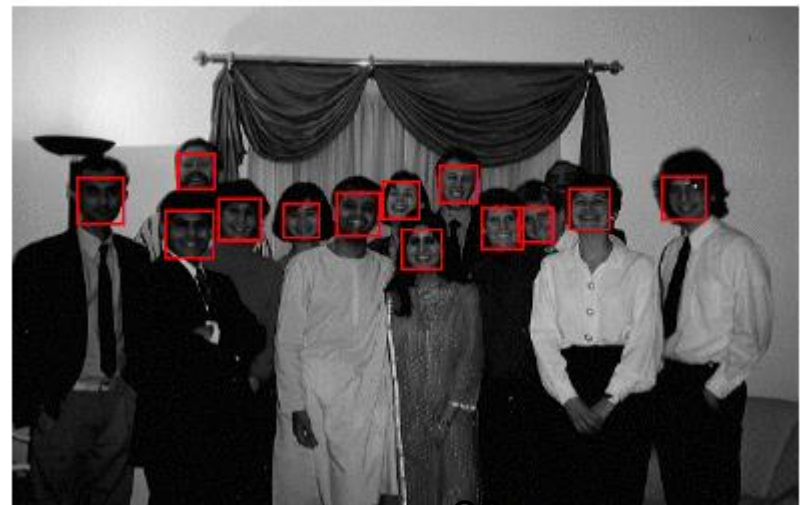
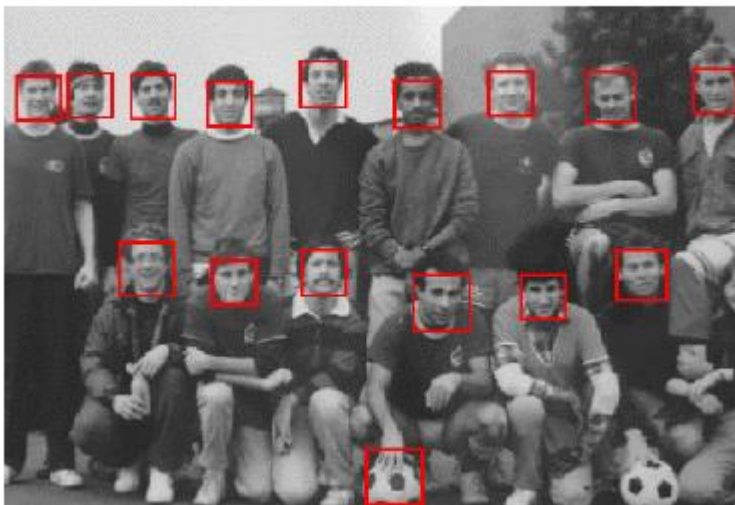
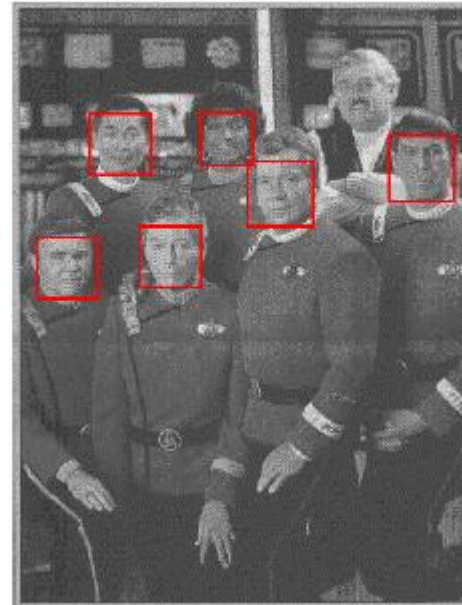
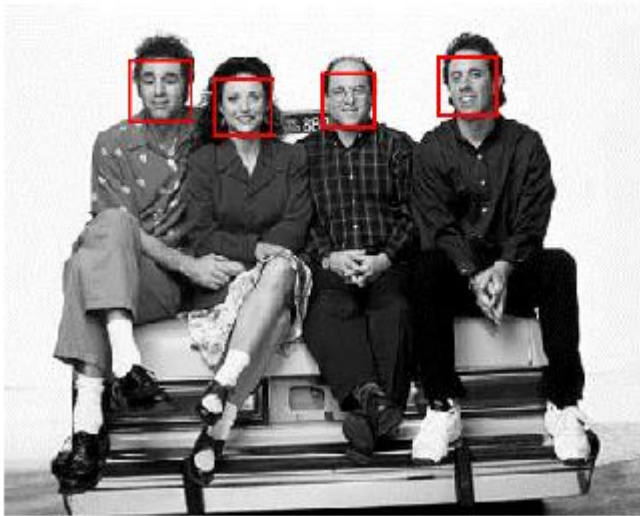


Receiver operating characteristic (ROC) curve

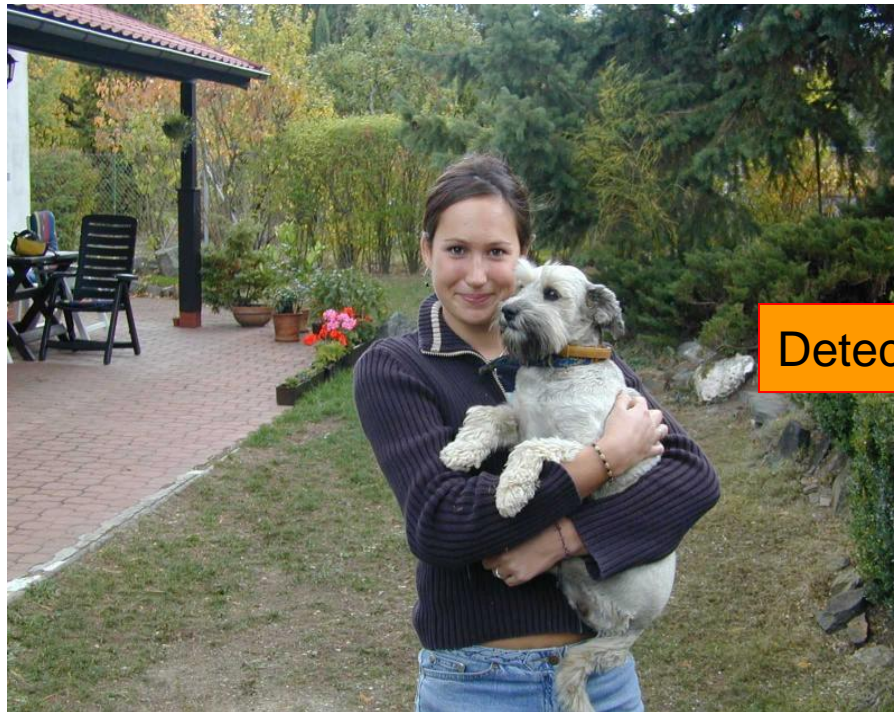
Viola-Jones Face Detector: Results



Viola-Jones Face Detector: Results



Face recognition: once you've detected and cropped a face, try to recognize it



Detection



Recognition

"Sally"

Face recognition: overview

Typical scenario: few examples per face, identify or verify test example

What's hard: changes in expression, lighting, age, **occlusion**, **viewpoint**

Basic approaches (all nearest neighbor)

1. Project into a new subspace (or kernel space) (e.g., “Eigenfaces”=PCA)
2. **Measure face features**

Typical face recognition scenarios

Verification: a person is claiming a particular identity;
verify whether that is true

- E.g., security

Closed-world identification: assign a face to one person
from among a known set

General identification: assign a face to a known person
or to “unknown”

What makes face recognition hard?

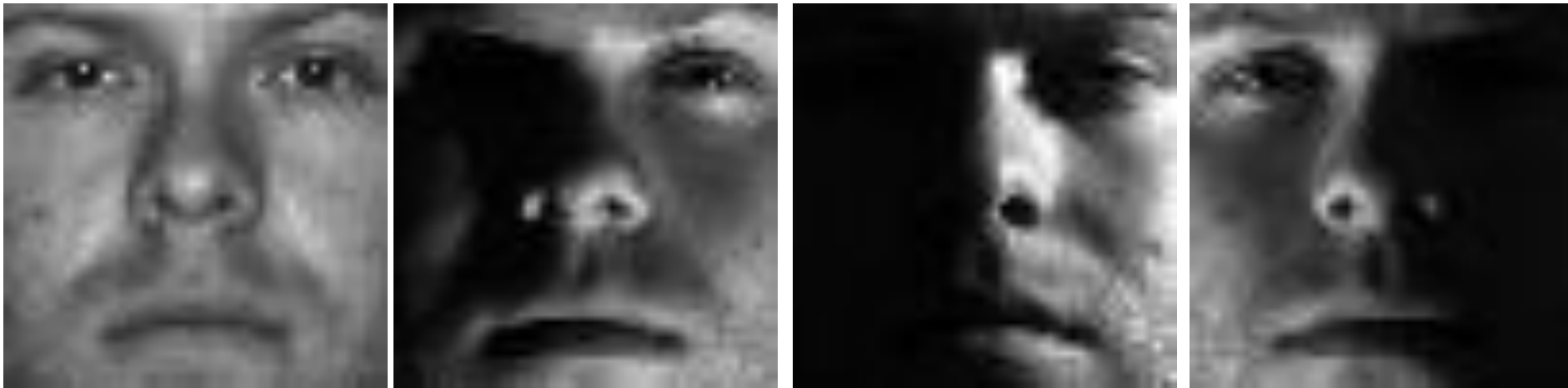
Expression





What makes face recognition hard?

Lighting



What makes face recognition hard?

Occlusion



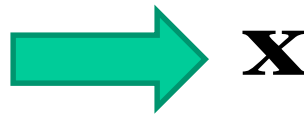
What makes face recognition hard?

Viewpoint



Simple idea for face recognition

1. Treat face image as a vector of intensities



\mathbf{x}

2. Recognize face by nearest neighbor in database



$\mathbf{y}_1 \cdots \mathbf{y}_n$

$$k = \underset{k}{\operatorname{argmin}} \|\mathbf{y}_k - \mathbf{x}\|$$

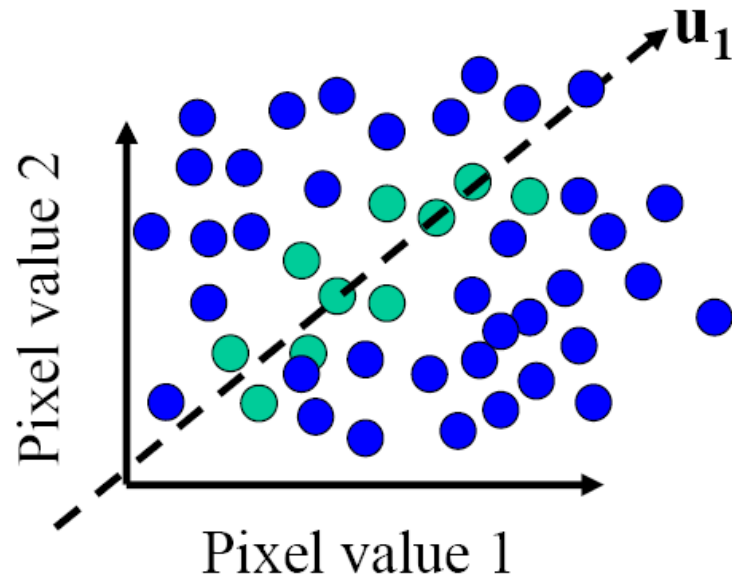
The space of all face images

- When viewed as vectors of pixel values, face images are extremely high-dimensional
 - 100x100 image = 10,000 dimensions
 - Slow and lots of storage
- But very few 10,000-dimensional vectors are valid face images
- We want to effectively model the subspace of face images



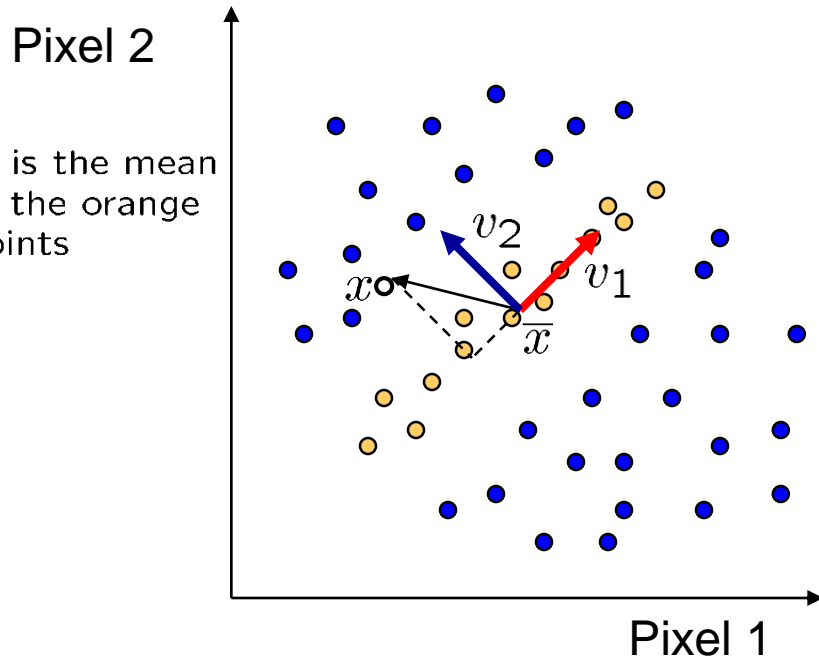
The space of all face images

- Eigenface idea: construct a **low-dimensional linear subspace** that best explains the variation in the set of face images



- A face image
- A (non-face) image

Linear subspaces



\mathbf{v}_1 is the major direction of the orange points and \mathbf{v}_2 is perpendicular to \mathbf{v}_1 .

Convert \mathbf{x} into $\mathbf{v}_1, \mathbf{v}_2$ coordinates

$$\mathbf{x} \rightarrow ((\mathbf{x} - \bar{\mathbf{x}}) \cdot \mathbf{v}_1, (\mathbf{x} - \bar{\mathbf{x}}) \cdot \mathbf{v}_2)$$

What does the \mathbf{v}_2 coordinate measure?

- distance to line
- use it for classification—near 0 for orange pts

What does the \mathbf{v}_1 coordinate measure?

- position along line
- use it to specify which orange point it is

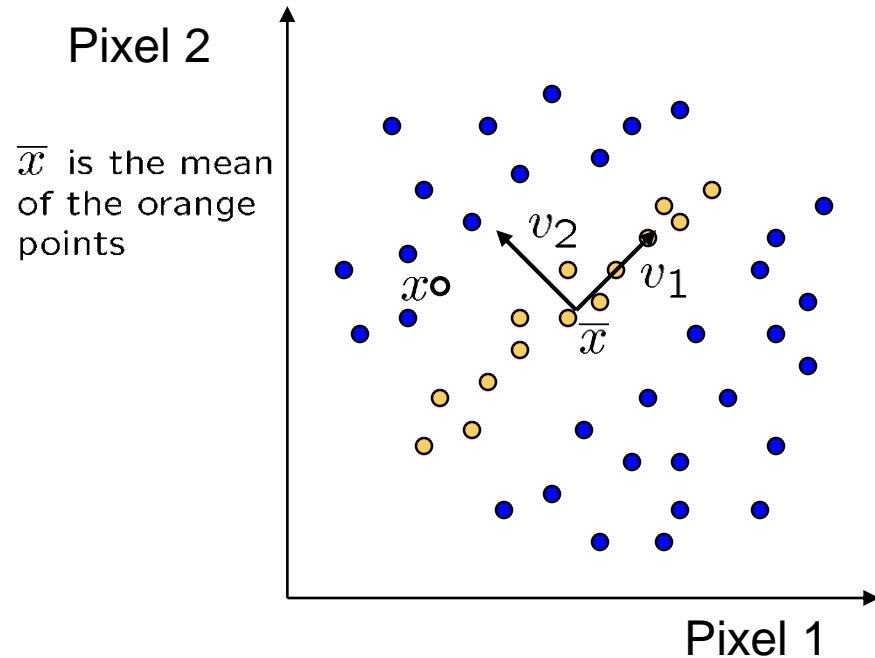
Classification (to what class does \mathbf{x} belong) can be expensive

- Big search problem

Suppose the data points are arranged as above

- Idea—fit a line, classifier measures distance to line

Dimensionality reduction



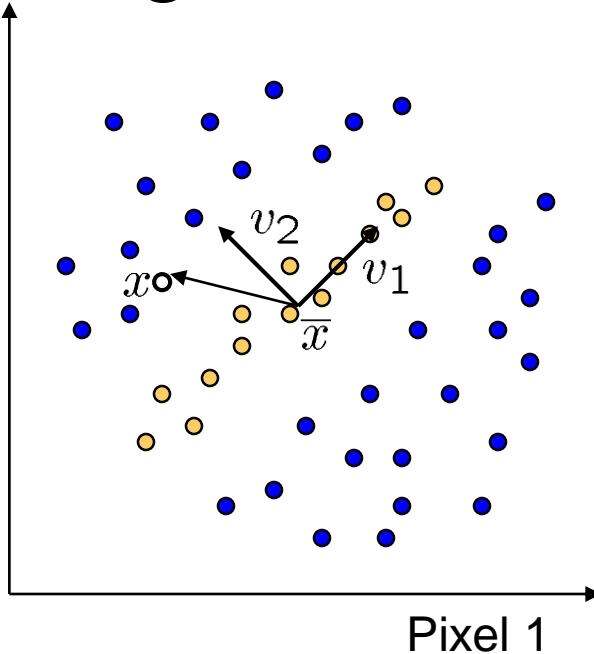
Dimensionality reduction

- We can represent the orange points with *only* their \mathbf{v}_1 coordinates
 - since \mathbf{v}_2 coordinates are all essentially 0
- This makes it much cheaper to store and compare points
- A bigger deal for higher dimensional problems (like images!)

Eigenvectors and Eigenvalues

Pixel 2

\bar{x} is the mean
of the orange
points



Consider the variation along a direction \mathbf{v}
among all of the orange points:

$$var(\mathbf{v}) = \sum_{\text{orange point } \mathbf{x}} \|(\mathbf{x} - \bar{\mathbf{x}})^T \cdot \mathbf{v}\|^2$$

What unit vector \mathbf{v} minimizes var ?

$$\mathbf{v}_2 = \min_{\mathbf{v}} \{var(\mathbf{v})\}$$

What unit vector \mathbf{v} maximizes var ?

$$\mathbf{v}_1 = \max_{\mathbf{v}} \{var(\mathbf{v})\}$$

$$\begin{aligned} var(\mathbf{v}) &= \sum_{\mathbf{x}} \|(\mathbf{x} - \bar{\mathbf{x}})^T \cdot \mathbf{v}\|^2 \\ &= \sum_{\mathbf{x}} \mathbf{v}^T (\mathbf{x} - \bar{\mathbf{x}}) (\mathbf{x} - \bar{\mathbf{x}})^T \mathbf{v} \\ &= \mathbf{v}^T \left[\sum_{\mathbf{x}} (\mathbf{x} - \bar{\mathbf{x}}) (\mathbf{x} - \bar{\mathbf{x}})^T \right] \mathbf{v} \\ &= \mathbf{v}^T \mathbf{A} \mathbf{v} \quad \text{where } \mathbf{A} = \sum_{\mathbf{x}} (\mathbf{x} - \bar{\mathbf{x}}) (\mathbf{x} - \bar{\mathbf{x}})^T \end{aligned}$$

\mathbf{A} = **covariance matrix** of data
points (if divided
by no. of points)

Solution: \mathbf{v}_1 is eigenvector of \mathbf{A} with *largest* eigenvalue
 \mathbf{v}_2 is eigenvector of \mathbf{A} with *smallest* eigenvalue

Principal component analysis (PCA)

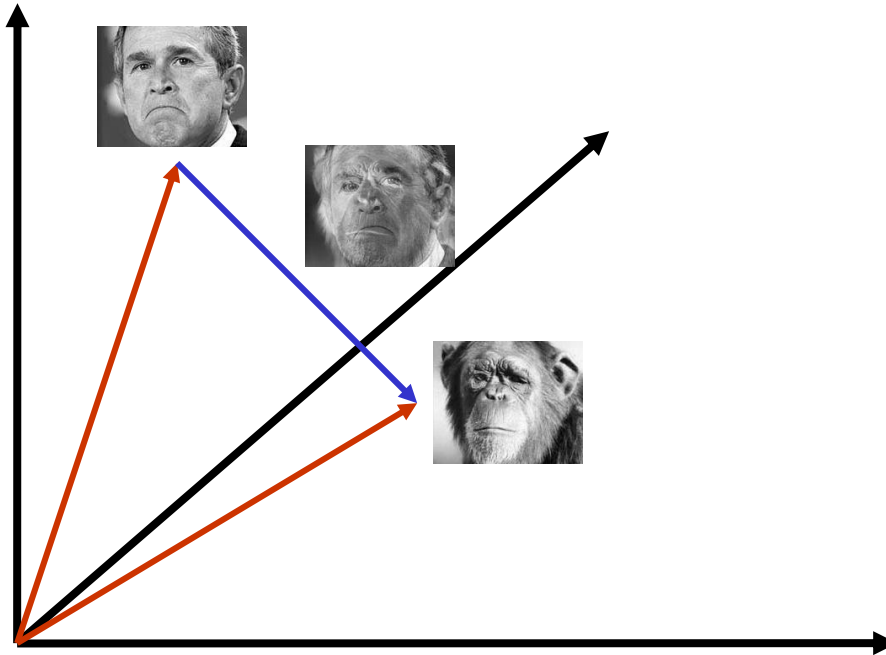
Suppose each data point is N-dimensional

- Same procedure applies:

$$\begin{aligned} var(\mathbf{v}) &= \sum_{\mathbf{x}} \|(\mathbf{x} - \bar{\mathbf{x}})^T \cdot \mathbf{v}\|^2 \\ &= \mathbf{v}^T \mathbf{A} \mathbf{v} \quad \text{where } \mathbf{A} = \sum_{\mathbf{x}} (\mathbf{x} - \bar{\mathbf{x}})(\mathbf{x} - \bar{\mathbf{x}})^T \end{aligned}$$

- The eigenvectors of **A** define a new coordinate system
 - eigenvector with largest eigenvalue captures the most variation among training vectors **x**
 - eigenvector with smallest eigenvalue has least variation
- We can compress the data by only using the top few eigenvectors
 - corresponds to choosing a “linear subspace”
 - » represent points on a line, plane, or “hyper-plane”
 - these eigenvectors are known as the **principal components**

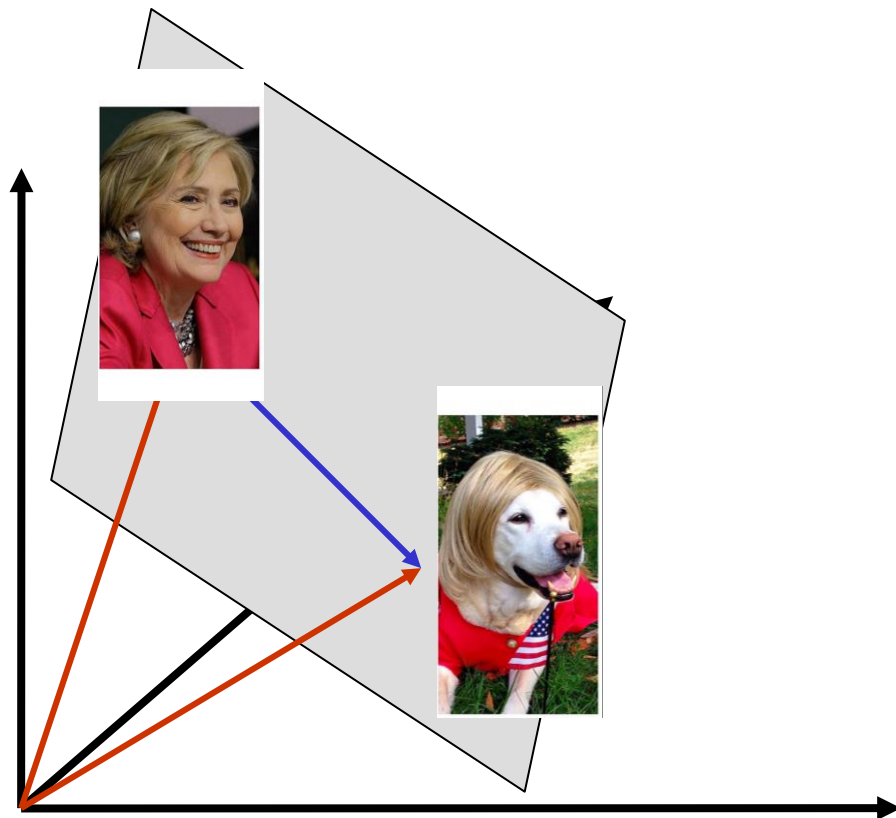
The space of faces



An image is a point in a high dimensional space

- An $N \times M$ image is a point in \mathbb{R}^{NM}
- We can define vectors in this space as we did in the 2D case

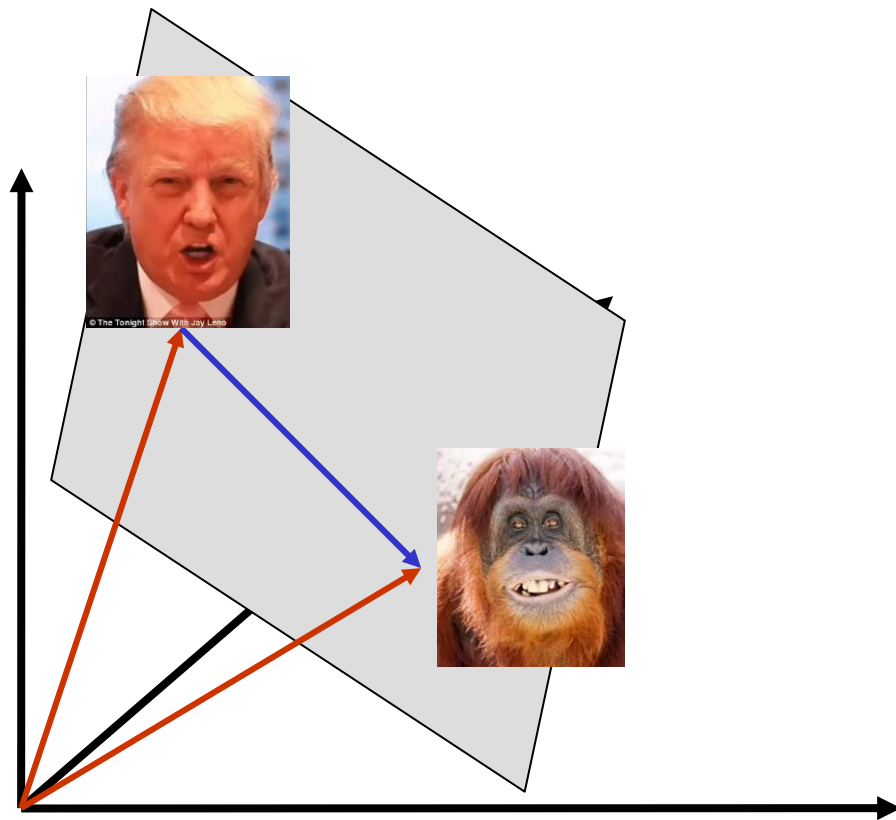
Dimensionality reduction



The set of faces is a “subspace” of the set of images

- Suppose it is K dimensional
- We can find the best subspace using PCA
- This is like fitting a “hyper-plane” to the set of faces
 - spanned by vectors $\mathbf{v}_1, \mathbf{v}_2, \dots, \mathbf{v}_K$
 - any face $\mathbf{x} \approx \bar{\mathbf{x}} + a_1\mathbf{v}_1 + a_2\mathbf{v}_2 + \dots + a_k\mathbf{v}_k$

Dimensionality reduction



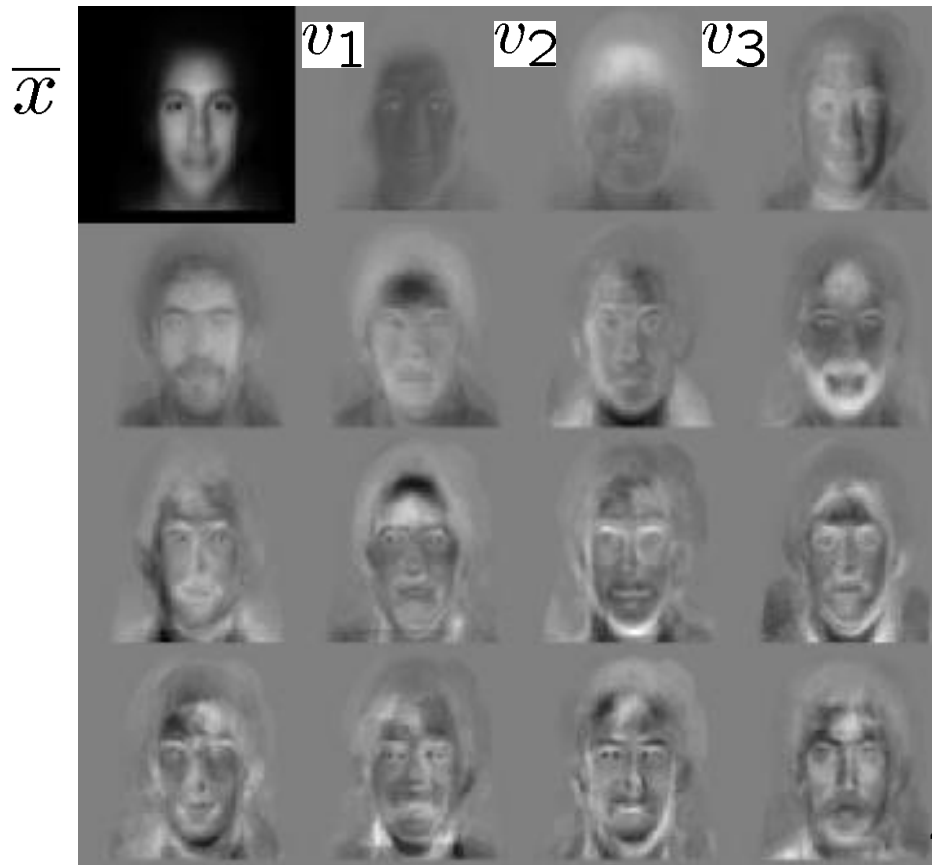
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Eigenfaces

PCA extracts the eigenvectors of **A**

- Gives a set of vectors $\mathbf{v}_1, \mathbf{v}_2, \mathbf{v}_3, \dots$
- Each one of these vectors is a direction in face space
 - what do these look like?



Visualization of eigenfaces

Principal component (eigenvector) u_k



$\mu + 3\sigma_k u_k$



$\mu - 3\sigma_k u_k$



Projecting onto the eigenfaces

The eigenfaces $\mathbf{v}_1, \dots, \mathbf{v}_K$ span the space of faces

- A face is converted to eigenface coordinates by

$$\mathbf{x} \rightarrow \underbrace{((\mathbf{x} - \bar{\mathbf{x}}) \cdot \mathbf{v}_1)}_{a_1}, \underbrace{((\mathbf{x} - \bar{\mathbf{x}}) \cdot \mathbf{v}_2)}_{a_2}, \dots, \underbrace{((\mathbf{x} - \bar{\mathbf{x}}) \cdot \mathbf{v}_K)}_{a_K}$$

$$\mathbf{x} \approx \bar{\mathbf{x}} + a_1\mathbf{v}_1 + a_2\mathbf{v}_2 + \dots + a_K\mathbf{v}_K$$



\mathbf{x}



$a_1\mathbf{v}_1 \quad a_2\mathbf{v}_2 \quad a_3\mathbf{v}_3 \quad a_4\mathbf{v}_4 \quad a_5\mathbf{v}_5 \quad a_6\mathbf{v}_6 \quad a_7\mathbf{v}_7 \quad a_8\mathbf{v}_8$



Recognition with eigenfaces

Algorithm

1. Process the image database (set of images with labels)
 - Run PCA—compute eigenfaces
 - Calculate the K coefficients for each image
2. Given a new image (to be recognized) \mathbf{x} , calculate K coefficients

$$\mathbf{x} \rightarrow (a_1, a_2, \dots, a_K)$$

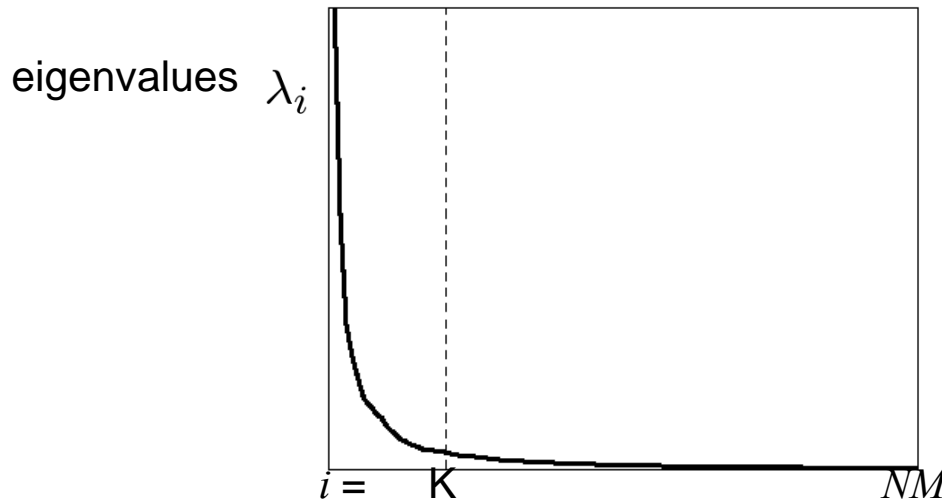
3. Detect if \mathbf{x} is a face

$$\|\mathbf{x} - (\bar{\mathbf{x}} + a_1\mathbf{v}_1 + a_2\mathbf{v}_2 + \dots + a_K\mathbf{v}_K)\| < \text{threshold}$$

4. If it is a face, who is it?

- Find closest labeled face in database
- Nearest-neighbor in K -dimensional space

Choosing the dimension K



How many eigenfaces to use?

Look at the decay of the eigenvalues

- the eigenvalue tells you the amount of variance “in the direction” of that eigenface
- ignore eigenfaces with low variance

PCA

- General dimensionality reduction technique
- Preserves most of variance with a much more compact representation
 - Lower storage requirements (eigenvectors + a few numbers per face)
 - Faster matching
- What other applications?

Enhancing gender



more

same

original

androgynous

more oppos

D. Rowland and D. Perrett, ["Manipulating Facial Appearance through Shape and Color,"](#) IEEE CG&A, September 1995

Slide credit: A. Efros

Changing age

Face becomes
“rounder” and “more
textured” and “grayer” original



shape

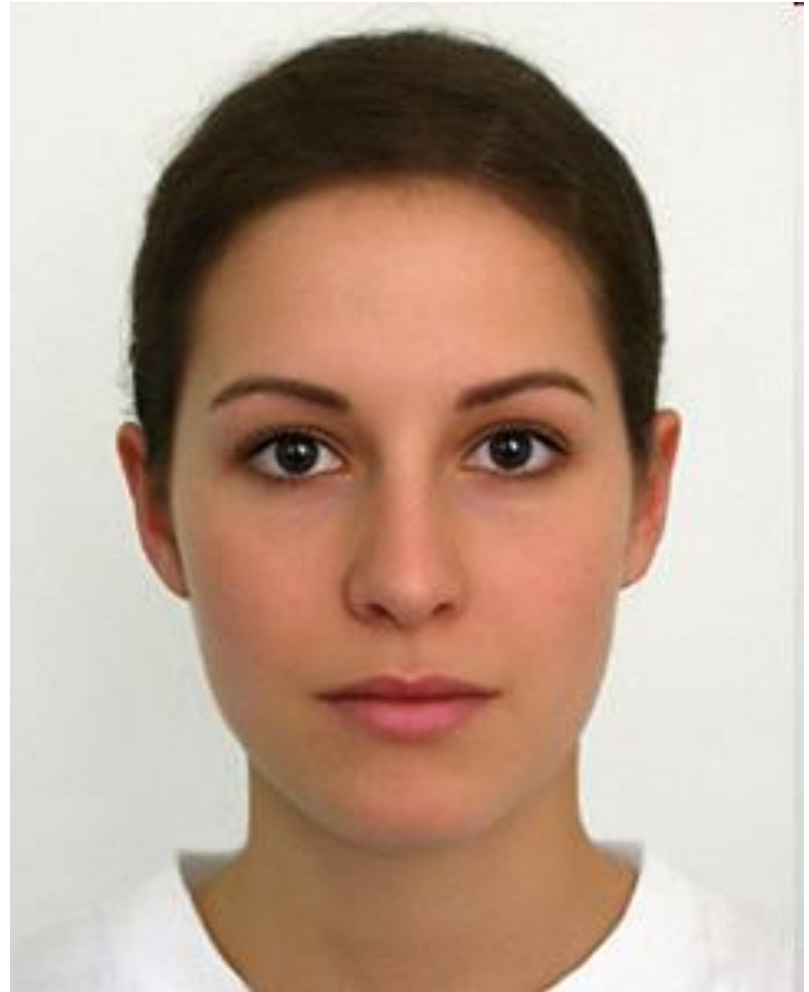
color

both

D. Rowland and D. Perrett, [“Manipulating Facial Appearance through Shape and Color,”](#) IEEE CG&A, September 1995

Slide credit: A. Efros

Which face is more attractive?



Use in Cleft Severity Analysis

We have a large database of normal 3D faces.

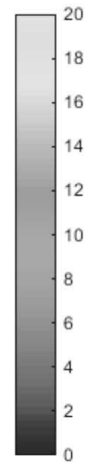
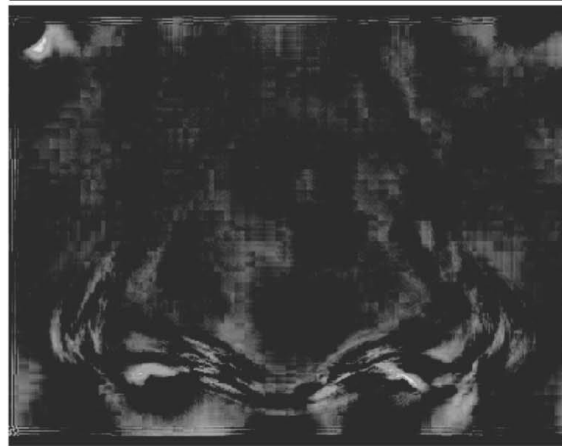
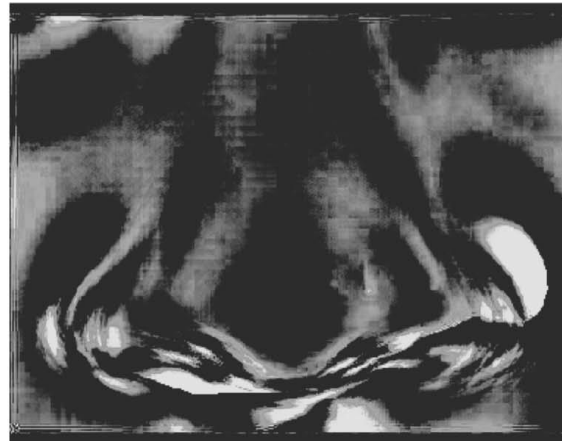
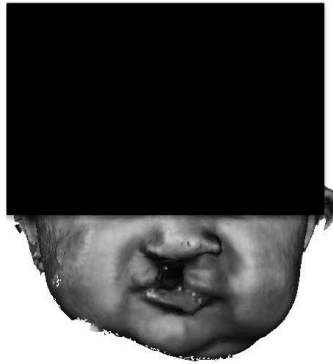
We construct their principal components.

We can reconstruct any normal face accurately using these components.

But when we reconstruct a cleft face from the normal components, there is a **lot of error.**

This error can be used to measure the **severity** of the cleft.

Use of PCA Reconstruction Error to Judge Cleft Severity



Aligned head mesh

Error map from PCA reconstruction

Extension to 3D Objects

- Murase and Nayar (1994, 1995) extended this idea to 3D objects.
- The training set had **multiple views of each object**, on a dark background.
- The views included **multiple (discrete) rotations** of the object on a turntable and also **multiple (discrete) illuminations**.
- The system could be used first to **identify** the object and then to determine its (approximate) **pose** and illumination.

Sample Objects

Columbia Object Recognition Database

COLUMBIA UNIVERSITY IMAGE LIBRARY (COIL-20)



Significance of this work

- The extension to 3D objects was an important contribution.
- Instead of using brute force search, the authors observed that

All the views of a single object, when transformed into the eigenvector space became points on a manifold in that space.
- Using this, they developed fast algorithms to find the closest object manifold to an unknown input image.
- Recognition with pose finding took less than a second.

Appearance-Based Recognition

- Training images must be representative of the instances of objects to be recognized.
- The object must be well-framed.
- Positions and sizes must be controlled.
- Dimensionality reduction is needed.
- It is not powerful enough to handle general scenes without prior segmentation into relevant objects.
- * The newer systems that use “parts” from interest operators are an answer to these restrictions.