Self-supervised Learning of Geometrically Stable Features Through Probabilistic Introspection

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Abstract

One of the most promising directions of deep learning is the development of self-supervised methods that can substantially reduce the quantity of manually-labeled training data required to learn a model. Several recent contributions, in particular, have proposed self-supervision techniques suitable for tasks such as image classification. In this work, we look instead at self-supervision for geometrically-oriented tasks such as semantic matching and part detection. We develop a new approach that combines the strength of recent methods to discover object landmarks automatically. This approach learns dense distinctive visual descriptors that are invariant to synthetic image transformations from an unlabeled dataset of images of object categories. It does so by means of a robust probabilistic formulation that can introspectively determine which image regions are likely to result in stable matching. We show empirically that a network pre-trained in this manner requires significantly less supervision to learn semantic object parts compared to numerous pre-training alternatives. We also show that the pre-trained representation is excellent for semantic object matching.

1. Introduction

One factor that limits the applicability of deep neural networks to many problems is the difficulty and cost of procuring enough supervised data. This explains the increasing interest in techniques that can learn good feature representations without the use of manual supervision. Methods that rely on self-supervision [7, 25, 29], for example, can be used to initialize (pre-train) deep neural networks from large unlabeled data collections. Such pre-trained networks can then be fine-tuned to solve a target task with far less manual annotation than would otherwise be needed.

While several authors have looked at self-supervision for tasks such as image classification and segmentation, less work has been done on tasks that involve understanding the geometric properties of object categories. In this paper, therefore, we propose and develop a self-supervised pre-training technique that obtains image representations suitable for geometry-oriented tasks. We consider in particular two representative problems: semantic part detection and semantic matching. Parts capture the detailed semantic structure of objects and semantic matching establishes analogies between them, helping to characterize object categories.

Our specific goal is to pre-train convolutional neural networks suitable for such geometry oriented tasks on a dataset of images of one or more object categories with no bounding box, part or other types of geometric annotations. Our approach is based on three ideas. First, we configure the network to compute a dense field of visual descriptors and aim at using those to characterize different object parts. These descriptors are learned to match corresponding object points in different images using a pairwise loss formu-
lation. However, since no labels are given, correspondences between images are also unknown. Thus, the second idea is to generate image pairs for which correspondences are known by means of synthetic warps [16, 30, 33, 34]. Learning from them results in visual descriptors that are invariant to image deformations, but not necessarily characteristic of specific object parts. The authors of [34] address a similar problem by constraining the descriptor dimensionality, which strongly encourages them to generalize and anchor to object landmarks. However, compared to recent techniques such as AnchorNet [26] that also learn unsupervised landmarks, this geometric approach was found to be too fragile to handle complex 3D object categories, particularly when many landmarks can be occluded in different views.

Seeking to retain the robustness of methods such as AnchorNet while incorporating a geometric prior such as [34], we propose to trade-off robustness for a higher dimensionality of the descriptors. We further improve robustness by casting learning into a probabilistic formulation. This formulation allows the network to explicitly learn, along with the visual descriptors, an estimate of their expected matching reliability. As a consequence, the network is able to learn failure modalities, arising for example from extracting descriptors in correspondence of background regions instead of the object, from occlusions, or from matches that are inherently difficult for the model.

The resulting formulation is able to pre-train excellent networks for semantic matching and semantic part detection. This is demonstrated empirically by means of thorough experiments against a range of baselines on standard benchmark datasets. For semantic matching, our results outperform [26] and [34] that use a comparable level of supervision and are on par with the fully supervised method of [10]. For part detection, we consider a few-shot keypoint detection task and show that our method performs better than all competitors when few annotations are available.

The rest of the manuscript is organized as follows. Section 2 discusses related work, section 3 presents the technical details of our method, section 4 conducts the experimental evaluation, and section 5 summarizes our findings.

2. Related Work

Learning features for geometric tasks. Hand-crafted features such as SIFT [23], DAISY [40], or HOG [5], initially designed for geometrical tasks such as matching-based retrieval [32], stereo matching [28], or optical flow [13] formed the gold standard until very recently due to their appealing properties such as repeatability.

Dense semantic matching methods, pioneered by SIFT Flow [20] are designed to deal with more variability in appearance and create dense correspondences across different scenes. Following the success of CNN architectures for recognition tasks like image classification [19], these architectures have been used as feature extractors for other tasks, including semantic matching. Yet, without any further training, they have been shown not to improve over hand-engineered features for geometric tasks [22, 9] and most approaches still combine hand-crafted features and spatial regularization [3, 14, 18, 20, 44]. To overcome this, deep features have been retrained for geometric tasks [4, 44, 10]. Choy et al. [4] combine a fully convolutional architecture with a contrastive loss and train with a large number of annotations. Zhou et al. [45] require 3D models to link correspondences between images and rendered views. Han et al. [10] follow Proposal Flow [9] and replace the hand-crafted features with features trained end-to-end with a large amount of annotations.

Training geometry-aware features without costly annotations such as keypoints or 3D models has only been seldom studied [26, 33, 34]. The AnchorNet approach [26] builds discriminative parts that match different object instances as well as different object categories using only image-level supervision. Other methods have proposed to replace costly manual annotations by synthetically generating image pairs [33, 34, 30]. Thewlis et al. [33] show that placing constraints on matching builds object landmarks that are not only consistently detected across the deformation of a current instance, but also across instances. This work was extended to a dense formulation [34], embedding objects on a sphere. Although this works well for faces, such an approach seems less appropriate for objects with a complex 3D shape. Rocco et al. [30] propose a Siamese CNN architecture for geometric matching, composed of a feature extraction part and a matching architecture that is used to predict the parameters of a synthetic transformation applied to the input image. Artificial correspondences were also used in [16] for a fine-grained task.

Keypoint detection. Keypoint detection has been extremely well studied for the case of humans [15, 41, 8, 1] and recent approaches have considered deep architectures [36, 35]. Only a few works have considered keypoint detection for generic categories [12, 22, 39, 37]. These methods require large training sets and none of them has considered a few-shot learning scenario.

3. Method

Given an image \( x \in \mathbb{R}^{H \times W \times 3} \) from a certain collection of object categories, the aim is to learn a neural network that can localize the object’s parts and produce a semantic match between that image and another instance of its category. Furthermore, we make the assumption that only a small number of images annotated with information relevant to these tasks is available, but the images labeled only with the presence of a given object category are plentiful [6]. Thus, our main goal is to develop a self-supervised
method to use the weakly labeled images to pre-train the model as well as possible.

Formally, let $X = \{x_1, \ldots, x_N\}$ be a collection of $N$ unlabeled images of one or more object categories and let $\phi : \mathbb{R}^{H \times W \times 3} \rightarrow \mathbb{R}^{H \times W \times C}$ be a deep neural network extracting dense image features. Furthermore, let the symbol $\phi(x)_u \in \mathbb{R}^C$ denote the feature column extracted at location $u \in \{1, \ldots, H\} \times \{1, \ldots, W\}$:

$$\forall c \in \{1, \ldots, C\} : \left[\phi(x)_u\right]_c = \left[\phi(x)\right]_{uc}. \quad \text{(1)}$$

Each vector $\phi(x)_u$ can be thought of as a descriptor of the image content around location $u$. As our aim is to learn to recognize and match object parts, we would like such descriptors to be characteristic of specific object landmarks or structures.

In a supervised setting, one is given the identity of the object part found at each location $u$ and can use this to learn corresponding descriptors. However, in our case this information is not available, so we must resort to a different supervisory signal. We do so by constraining descriptors to be invariant (section 3.1) and discriminative (section 3.2) with respect to synthetic image transformations, and make this robust using a form of probabilistic introspection (section 3.3). The resulting learning objective is given in section 3.4 and further discussed in section 3.5. Figure 2 provides an overview of the overall approach.

### 3.1. Invariant description

If $u$ and $u'$ are projections of the same object point in images $x$ and $x'$ (or of analogous points such as the right eye of two different cats), then the descriptors

$$\phi(x)_u = \phi(x')_{u'} \quad \text{(1)}$$

should be identical. This *invariance* condition states that the descriptors computed at corresponding image locations $u$ and $u'$ should be identical despite differences in the appearance of the points.

While correspondences are not known for arbitrary images in the database $X$ (short of providing manual annotations), we can at least synthetically generate such examples. To this end, let $g : \mathbb{R}^2 \rightarrow \mathbb{R}^2, u \mapsto u' = g(u)$ be a random image warp and let $x' = x \circ g^{-1}$ be the image obtained by warping $x \in X$ accordingly.\(^2\) Then, constraint (1) can be rewritten as:

$$\forall g, u : \phi(x)_u = \phi(x \circ g^{-1})_{g(u)} \quad \text{(2)}$$

While any sensible descriptor extractor $\phi$ should satisfy this constraint, this is clearly insufficient as a specification. In fact, the constraint is trivially satisfied by any constant function $\phi$, or even by the identity mapping $\phi(x)_u = x(u)$. The ingredient that is missing is that the descriptors should also be a unique characterization of a specific object point. Building this additional constraint into the model is discussed in the next section.

### 3.2. Informative invariant description

Invariance (2) must be paired with the fact that descriptors should be able to robustly distinguish between different object points. To encode such a constraint, we note first that it does not make sense to check for exact descriptor equality or inequality as literally suggested by eq. (2). Instead, descriptors are compared continuously by considering a *matching score*: their rectified inner product

$$s_{xx'}^{uu} = \max \{0, \langle \phi(x)_u, \phi(x')_{u'} \rangle\}. \quad \text{(3)}$$

In order to guarantee that this score is maximum when a descriptor is compared to itself ($s_{xx}^{uu} \leq 1, s_{xx}^{uu} = 1$), de-
The model has several options for decreasing the loss: (1) increasing the similarity while keeping confidence unchanged, (2) decreasing the confidence while keeping similarity and (3) increasing both similarity and confidence.

In order to handle difficult or impossible matches in the background, or the match may just be too difficult for the object point may be occluded, a pixel may belong to the next section.

Illustration of the probabilistic loss. The plot shows values of the loss for positive pairs ($y_{uu'} = 1$, bluer means a smaller loss) as a function of the similarity between the pixel representations $s_{uu'}$ and the uncertainty $\sigma_{uu'}$ who’s inverse $\sigma_{uu'}^{-1}$ corresponds to the confidence. The model has several options for decreasing the loss: (1) increasing the similarity while keeping confidence unchanged, (2) decreasing the confidence while keeping similarity and (3) increasing both similarity and confidence.

However, $\ell$ cannot be satisfied for all possible choices of image and pixel pairs $(x, x')$ and $(u, u')$. For example, an object point may be occluded, a pixel may belong to the background, or the match may just be too difficult for the model to express adequately. This problem is addressed in the next section.

**3.3. Probabilistic introspection**

In order to handle difficult or impossible matches in the loss function, we do not resort to heuristics such as using robust versions of the loss (4), but rather task the neural network with predicting when descriptors are unreliable. In order to do so, inspired by [27, 17], the network is modified to compute an additional scalar value $\sigma_{uu'}^x \in \mathbb{R}^+$ for each pixel expressing uncertainty about the quality of the descriptor extracted at $u$ and its consequent ability of establishing a reliable match. Importantly, this belief is estimated from each image independently before matching occurs. In this manner, $\sigma_{uu'}^x$ can be interpreted as an assessment of the informativeness of the image region that is used to compute the descriptor.

In more detail (and dropping the superscript $xx'$ for simplicity), we define a distribution over matching scores $p(s_{uu'} | y_{uu'}, \sigma_{uu'})$ conditioned on the average predicted uncertainty $\sigma_{uu} = (\sigma_u + \sigma_u')/2$ and on whether pixels are in correspondence or not. The distribution is given by:

$$p(s_{uu'} | y_{uu'}, \sigma_{uu'}) = \frac{1}{C(\sigma_{uu})} \exp \left(1 - \frac{\ell_{uu'}(s_{uu'}, y_{uu'})}{\sigma_{uu'}} \right)$$

where $C(\sigma_{uu})$ is a normalization constant ensuring that $p(s_{uu'} | y_{uu'}, \sigma_{uu'})$ integrates to one.

To understand expression (5), note that, due to the fact that $s_{uu'} \in [0, 1]$ and to the particular form (4) of the function $\ell_{uu'}$, $C(\sigma_{uu})$ is finite and does not depend on $y_{uu'}$. When the model is confident in the quality of both descriptors $\phi(x, u)$ and $\phi(x', u')$, the value $\sigma_{uu}$ is small. In this case, the distribution (5) has a sharp peak around 1 or 0, depending on whether pixels $(u, u')$ are in correspondence or not. On the other hand, when the model is less certain about the quality of the descriptors, the score distribution is more spread.

**3.4. Learning objective**

It is now possible to describe the overall learning objective for our method. The models $\phi$ and $\sigma$ are learned by minimizing the negative logarithm of the probability $p(s_{uu'} | y_{uu'}, \sigma_{uu'})$ averaged over images, random transformations, and point pairs. Formally, the learning objective is given by:

$$\mathcal{L}(\phi, \sigma) = \frac{1}{|X|} \sum_{x \in X} \mathbb{E}_{g,u,u'} \left[ -\log p(s_{xx'g^{-1}}(\phi) | y_{uu'}, \sigma_{uu'} + \sigma_{uu'}^{-1}) \right]$$

Here the score $s$ depends on the neural network $\phi$ as shown in eq. (3). The function $\sigma$ is implemented as a small neural network branching off $\phi$ and is also learned with it. The labels $y_{uu'}$ are easily obtained as

$$y_{uu'} = \begin{cases} 
1, & \|u' - g(u)\|_2 \leq \tau_1, \\
0, & \tau_1 < \|u' - g(u)\|_2 \leq \tau_2 \\
-1, & \text{otherwise}.
\end{cases}$$

where $\tau_1 < \tau_2$ are matching thresholds (we set $\tau_1 = 1$ and $\tau_2 = 30$ pixels). The value of the probabilistic loss $\mathcal{L}$ as a function of the similarity $s_{xx'}$ and the predicted uncertainty $\sigma_{uu'}$ is illustrated in Figure 3.
mirror-pad each image enlarging its size by a factor of two while biasing the sampled transformations towards zooming into the padded image. In order to avoid potential trivial solutions due to keeping the first image $x$ unwarped, we sample two transformations $\hat{g}, \hat{g}'$ and then warp the original input image $\hat{x}$ twice to form the input image pair $x = \hat{x}\hat{g}^{-1}$ and $x' = \hat{x}\hat{g}'^{-1}$. The pairwise transformation $g = \hat{g} \circ \hat{g}'^{-1}$ is a straightforward composition of $\hat{g}$ and $\hat{g}'$. In order to sample pairs of pixels $(u, u')$, we first randomly pick 700 points $U = \{u_i\}_{i=1}^{700}$ from the first image. For each $u_i$, we then sample $u'_i = g(u_i)$ from the second image and evaluate the loss $\mathcal{L}$ on all possible pairs $(u_i, u'_j) \in \mathcal{U} \times \mathcal{U}'$. We then follow a hard negative mining strategy by selecting the 30 negative samples $u'_i$ from the second image (out of 700 potential samples) that contribute to $\mathcal{L}$ the most. Backpropagation is then performed only through these “hard negative” examples and all the positive examples while equally balancing the overall weights of the two sets.

### Appearance transformations.
While random affine warping makes our features invariant to the geometric transformations, a successful representation should be also invariant to intraclass appearance variations caused by e.g. color and illumination changes. Hence, besides warping the input image, we apply a random color transformation $c(\hat{g}(\hat{x}))$ after the geometric transformation $\hat{g}(\hat{x})$. The color transformations are generated following the approach of [21]. We increase the intensity of the color shifts in order to introduce substantial appearance changes required to boost the invariance properties of the representation. Examples of the original images and their geometry-appearance transformations are in Figure 4.

#### 3.5. Discussion

Besides its robust nature, the formulation so far can be seen as learning discriminative viewpoint invariant features. This does not guarantee per se that the learned descriptors are characteristics of particular object parts. For example, since the model is only trained against synthetic warps of individual images, the descriptors computed for analogous parts in different object instances (e.g. the eyes in two different cats) may still differ. Even out-of-plane rotations are in principle sufficient to throw off the model.

Recently, the authors of [34] have suggested to constrain the descriptor capacity to favor generalization. In particular, they argue that using two dimensional descriptors strongly encourages them to attach to specific points on the surface of an object, and thus to generalize across different object instances.

Nevertheless, the method of [34] was found to be too fragile to work well in challenging data where significant occlusions may be present. Our approach trades off descriptor generality for robustness. As we will see in the experiments, this pays off as, ultimately, the representation is fine-tuned with a small amount of supervised data which is sufficient to bridge most of the gaps.

#### 3.6. Learning details

We learn our representation using the training images of the 12 rigid PASCAL classes from the ImageNet dataset (but we test it on all the classes, including non-rigid ones). As a preprocessing step, we apply a weakly supervised detector [2] and use the resulting image crops instead of the full images. This detector only requires image-level labels and no further supervision is used. This is exactly the same level of supervision used in [26, 30] and weaker than in [33] where bounding box annotations are required.

The representation predictor $\phi(x)$ is a deep convolutional neural network whose architecture is based on the ResNet-50 model [11] due to its good compromise between speed and capacity. We remove the two topmost layers and base the rest of our model on the rectified res5c features. In order to increase the spatial resolution of the produced representation, following [43] we dilate all res5 convolutional filters by the factor of 2 while decreasing their stride to 1. Finally, we attach a $1 \times 1$ convolutional layer that produces raw embedding vectors that, after $\ell_2$ normalization applied at every spatial location, form the embedding $\phi(x) \in \mathbb{R}^{H \times W \times C}$.

Our network is optimized using the AdaGrad solver. Learning rate, weight decay and momentum were set to 0.001, 0.0005 and 0.9 respectively. We decay learning rate by the factor of 10 once the loss plateaus and optimize network until no further loss improvement is observed. Learning converges within 36 hours on a single GPU.

### 4. Experiments

We first show qualitative results of our self-learning approach (section 4.1). Then, we quantitatively evaluate for the semantic matching (section 4.2) and for the keypoint detection (section 4.3) tasks.
4.1. Qualitative analysis

We first qualitatively analyze the nature of the learned feature representation. Figure 5 considers six categories and shows, for four images of each category, the confidence maps $\sigma^{-1}$ along with example rectified responses $\max([\phi(x)]_c, 0)$ for several feature channels $c$ of the learned representation. It can be observed that the responses resemble distinct keypoint detectors that fire consistently across different instances of a category, even in the presence of large intra-class variations. Furthermore, the confidence predictor $\sigma(x)^{-1}$ can be interpreted as a generic detector of distinct areas of the image foreground.

4.2. Semantic matching

We first assess our method on the problem of semantic matching and compare it to other unsupervised and weakly-supervised approaches for learning geometry-aware representation. In particular, we follow the dataset and experimental protocol of [9] and consider the problem of establishing correspondences between bounding box proposals and keypoints extracted in pairs of images.

Compared approaches. We compare our learned dense features to five existing feature representations. First, in order to demonstrate the improvement of our self-learning approach over the pre-trained (using only image-level labels) ResNet-50 model, we consider ResNet-50-HC which is a hypercolumn architecture that pools features from the res3c, res4c, res5c layers and separately upsamples them to a common spatial size. In order to demonstrate the benefits of the probabilistic introspection, we also present results of Ours w/o conf. which is our method trained by optimizing the non-probabilistic loss function from eq. (4). Then, to provide a direct comparison with approaches that tackle the geometric feature learning task, we report the results of [26] and [33]. For AnchorNet [26], we use their public class-agnostic model. To provide a fair comparison with the method of Thewlis et al. [33], we train their method on the same dataset as used for our features. To establish a baseline, we explore three variants of the base architecture proposed in [33]: a model with 10 landmarks (as proposed in the original work), a model with 64 landmarks (to increase model capacity) and finally a modified, class specific architecture which learns a set of 64 landmarks per-class. In practice, we found the second design to be most effective, and we therefore report performance for only this option in each of our experiments.

The last baseline are pool4 features from the Vgg16 architecture [31] pre-trained on the ImageNet image classification task. We selected these features, since they are the basis of current state-of-the-art semantic matching approaches [30, 10, 9]. Alongside other unsupervised and weakly supervised methods, we also compare against the fully supervised SCNet-A architecture introduced in [10].

For our approach, matching descriptors are produced by
exploiting the confidence prediction capacity of our model, scaling the outputs of the final layer by the inverse of the predicted uncertainty $\sigma$. We then follow the simple approach developed in [10], by applying ROI-pooling with bin size $7 \times 7$ to each proposal region resulting in a feature vector comprising these scaled representations. We further pool and concatenate res4c features from a lower layer of our network. In order to produce a dense warping field for keypoint matching we employ the sd-filtering as done in [9, 10]. For keypoint matching, following other approaches [9, 30, 10], we modify our original ResNet50-based architecture by replacing the network trunk with the Vgg16 architecture truncated after the pool4 features and terminated as described in section 3.6. This network was trained on all 20 PASCAL classes of the imagenet dataset according to the same learning schedule as described in section 3.6. For this architecture, instead of res4c features we pool and concatenate the pool4 features.

Since our objective is to assess feature quality, we evaluate each method without using any spatial regularization (such as e.g., Local Offset Matching [9], joint warp estimation [30], or MRFs with geometric potentials [38]).

### Dataset
We evaluate our approach on the PF-PASCAL dataset [9] which contains pairs of images which have been fully annotated with keypoints for 20 object classes. Each method is evaluated with a set of 1000 object proposals per image, generated with the Randomized Prim (RP) method [24]. Following [10], performance is reported on the test partition, which comprises 302 image pairs.

![Figure 6. Region matching performance on PF-Pascal. Features are matched directly without any spatial regularization. Left: region matching precision (PCR). Right: region matching accuracy (mIoU@k). Note that unlike all other reported approaches, SCNet-A [10] is a fully supervised method.](image)

<table>
<thead>
<tr>
<th>Method</th>
<th>PCK</th>
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<tr>
<td>AnchorNet</td>
<td>66.3</td>
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<tr>
<td>Vgg16 [9]</td>
<td>61.4</td>
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<tr>
<td>Ours w/o conf.</td>
<td>60.6</td>
</tr>
<tr>
<td>Ours</td>
<td>66.5</td>
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Table 1. Keypoint matching performance on PF-Pascal reporting PCK@0.1 for our method and existing approaches.

### Evaluation
We report results under the standard PCR (probability of correct regions) and mIoU@k (mean intersection over union of the best $k$ matches) metrics introduced in [9]. PCR aims to capture the accuracy of overall assignment, while mIoU@k reflects the reliability of matching scores. Following the common practice on this dataset, keypoint matching is assessed by reporting PCK@$\alpha$ with the misalignment sensitivity threshold $\alpha$ set to 0.1. All evaluations are conducted using the public implementation provided by the authors of [10].

### Results
The region matching results are shown in Figure 6. First, we observe that our approach significantly outperforms previous representations trained with a comparable amount of supervision: AnchorNet [26], the method of Thewlis et al. [33], and Vgg16 [31]. Second, we see that, interestingly, our self-supervised features perform on par with the model SCNet-A of [10] which is in fact fully supervised with keypoint annotations. These observations are encouraging also due to the fact that our representation was trained only on rigid classes while the PF-Pascal dataset also contains a large portion of the non-rigid ones.

Results on the keypoint matching task are present in Table 1. Similar to region matching, we observe improvements over other approaches trained with comparable level of supervision. Furthermore, our results are again on par

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Figure 7. Keypoint prediction on Pascal3D. We report the area under the PCK-over-alpha curve as a function of the number of training annotations.

with the fully supervised SCNet-A [10]. We observe a decrease in matching performance with Ours w/o conf. which validates the contribution of our method.

4.3. Few-shot keypoint detection

In section 4.1 we have observed that the learned features often correspond to distinctive object parts. Those do not necessarily have a semantic meaning, as demonstrated in [33], but they can still be used as anchors that facilitate the detection of semantic parts. Following [33], in this section we tackle the task of semantic keypoint detection where our learned representation as well as competitors is used as input features for a keypoint predictor. The keypoint detection performance then serves as an estimate of how well the respective representations encode the geometrical structure of visual categories. We depart from [33] and we consider a significantly more challenging setting with out-of-plane rotations and large appearance variations.

Furthermore, an important feature of successful geometric representations is how well they facilitate transfer of information from a very limited number of annotated samples. Hence, here we consider keypoint detection with few-shot supervision where a training set of object keypoint annotations is gradually extended with new training samples while monitoring the performance on a held-out test set.

Dataset. We use the keypoint annotations from the original Pascal3D dataset [39]. The few-shot keypoint predictors are trained on the “train” set of Pascal3D and evaluated on the held-out “val” set. Following common practice [37], knowledge of a ground truth bounding box as well as the depicted object’s class is assumed during both training and testing. The task is evaluated using the probability of correct keypoint measure (PCK) introduced in [42]. A keypoint prediction is regarded as correct if its distance from the corresponding ground truth annotation is lower than $\alpha \times \max\{w, h\}$, where $w, h$ are the object bounding box dimensions and $\alpha$ controls the sensitivity of the measure to misalignments. For each class, PCK corresponds to the ratio between the number of correct predictions and the total number of keypoint annotations. Similar to the PCR metric, we integrate the measure over all possible $\alpha$ values and report the average over the 12 Pascal3D object classes.

Keypoint predictor. Our keypoint predictor consists of a 512-channel $3 \times 3$ convolutional layer with stride 1 followed by batch normalization, ReLU and a final $3 \times 3$ convolutional layer with stride 1 terminated by the sigmoid activation function. Each channel of the final layer then serves as a response map of the corresponding keypoint class. The loss minimizes the weighted $\ell_2$ distance between the ground truth heatmap and the corresponding prediction as proposed in [37]. The evaluation process alternates between training the keypoint detector, evaluating its performance and adding a new set of training annotations consisting of an equal number of randomly sampled images per class. For each round, the detector is trained for 3 epochs making sure that at least 500 training steps are performed for each epoch. Detector parameters are initialized with the model from the previous round. The experiment is run three times with different random seeds and we report an average over PCKs.

Results. Results of the few-shot detection experiments are reported in Figure 7. Our method surpasses all the compared approaches when a small percentage of the training annotations is available, and in particular the methods of [26], [33], and [30], while performing on par with the best competitor on this task (Vgg16 [31]) when the full training set is used. Similar to the semantic matching experiments section 4.2, we observe significant drop in performance of the method from [33]. Ours w/o conf. obtains similar results to the proposed method. This is likely due to the fact that the detection dataset does not contain a large quantity of background clutter because the evaluated instances are always cropped using a tight ground truth bounding box.

5. Conclusions

In this paper, we have presented a self-supervised method that can pre-train features useful to reason about the geometry of object categories in tasks such as part localization and semantic matching. The method combines the robustness of recent approaches such as AnchorNet with the geometric prior induced by invariance to synthetic image transformations. This allows to train features that excel at these geometric tasks using only images with class-level annotations. We have shown that these features outperform all other pre-training methods in semantic matching and part localization. In the case of the first task, our features per-
form on par with a fully-supervised approach.

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