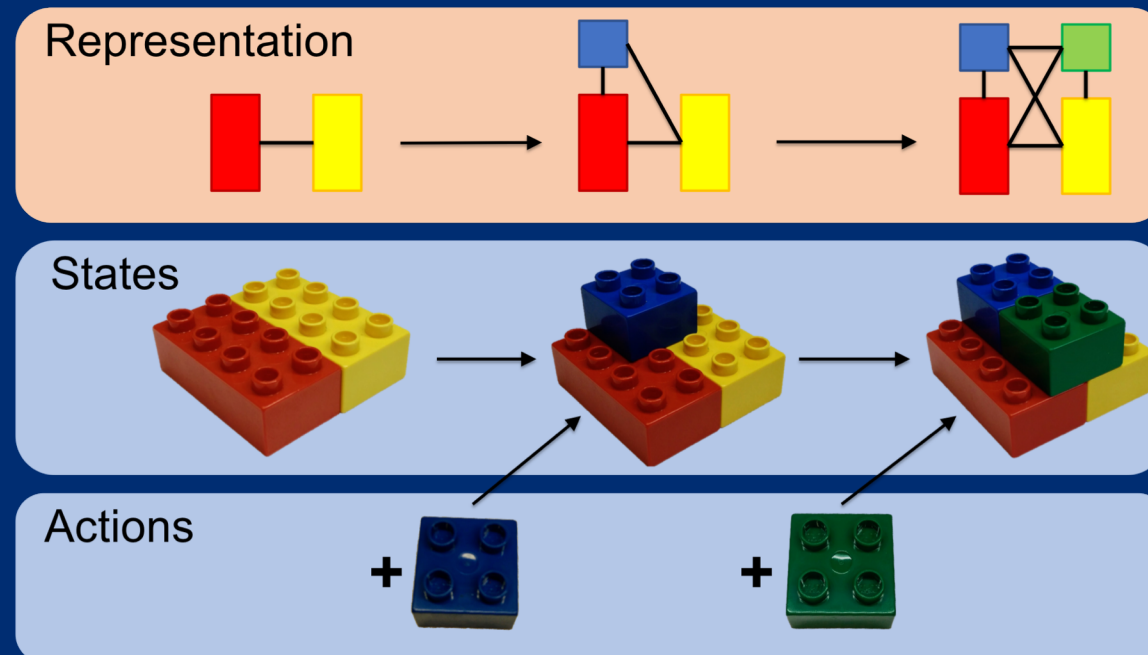
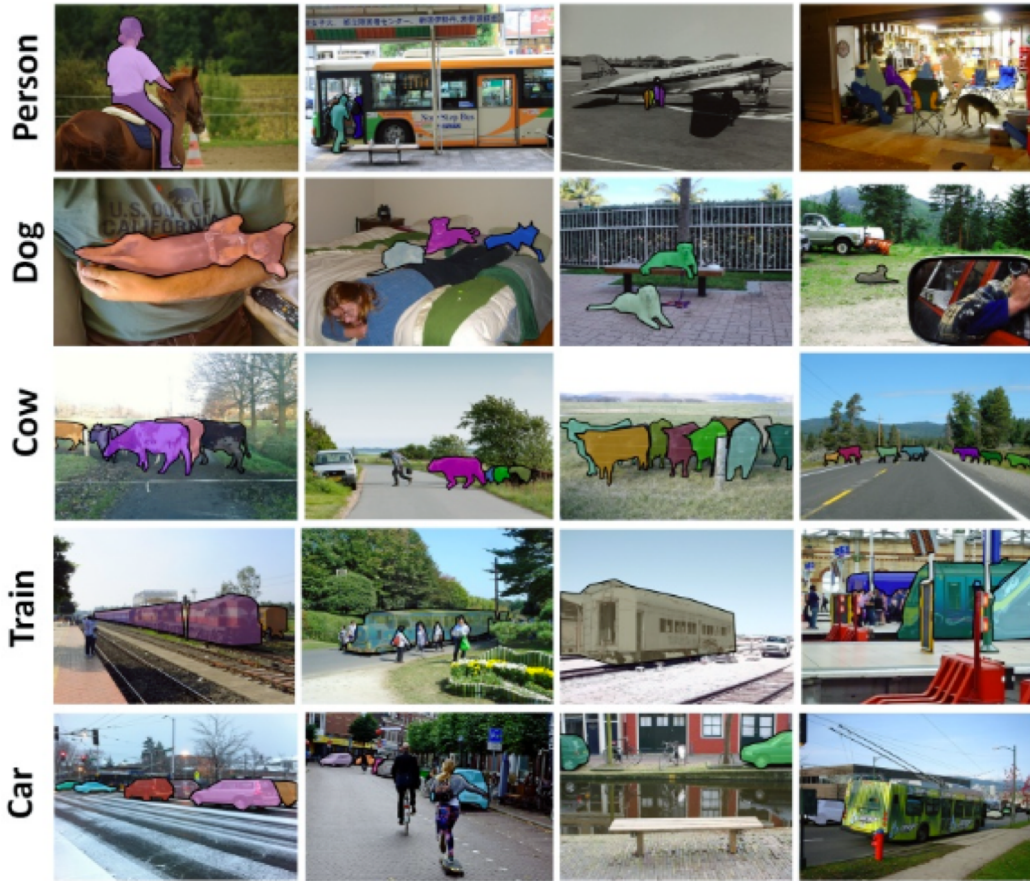


Toward Computer Vision Systems that Understand Real-World Assembly Processes

Jonathan D. Jones, Gregory D. Hager, Sanjeev Khudanpur



Computer vision in dynamic environments



Lin, Tsung-Yi, et al. "Microsoft coco: Common objects in context." *European conference on computer vision*. Springer, Cham, 2014.



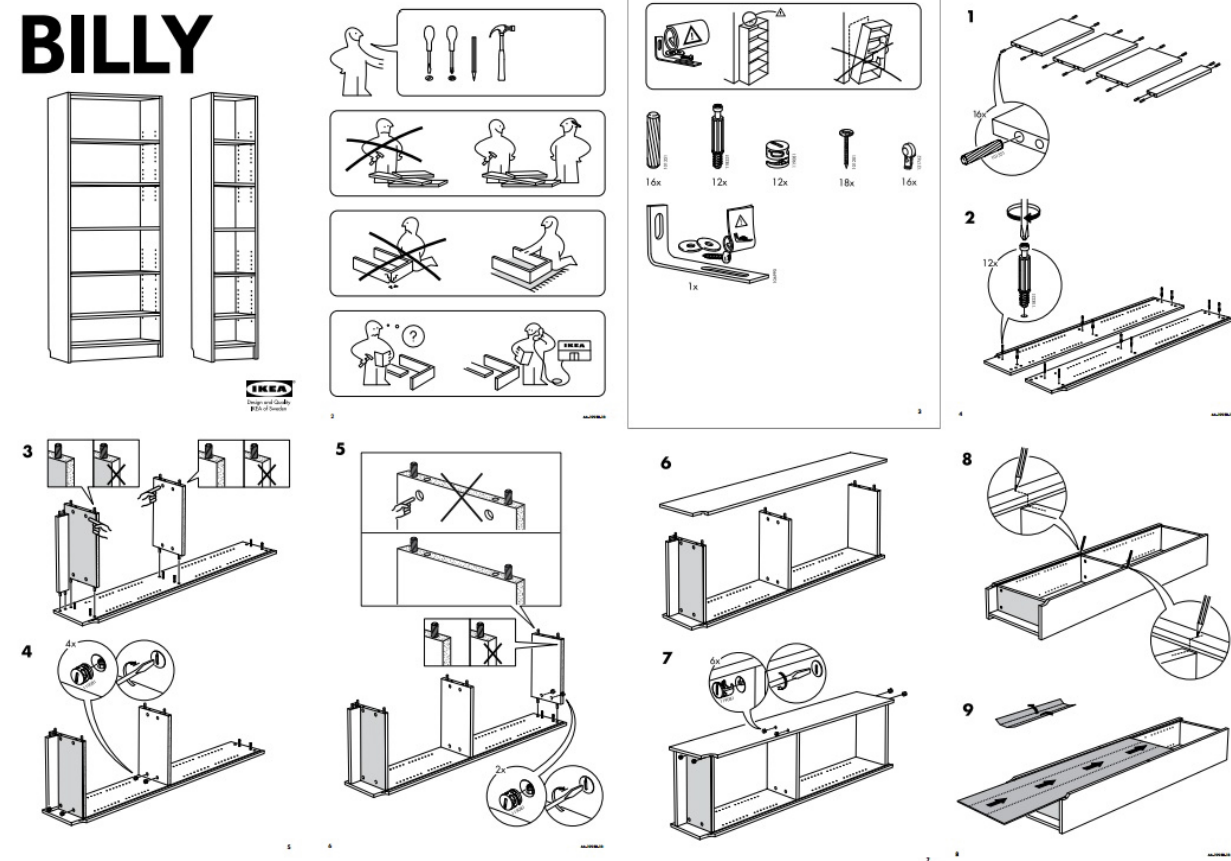
By Steve Jurvetson - Flickr: Tesla Autobots, CC BY 2.0, <https://commons.wikimedia.org/w/index.php?curid=24819239>



Computer vision in dynamic environments

- Environments not always *static*
 - Objects interact with each other
 - Can experience state changes
- Example: *Assembly processes*
 - Collaborative robots
 - Industrial monitoring

BILLY



Billy bookcase instructions, IKEA



Collaborators



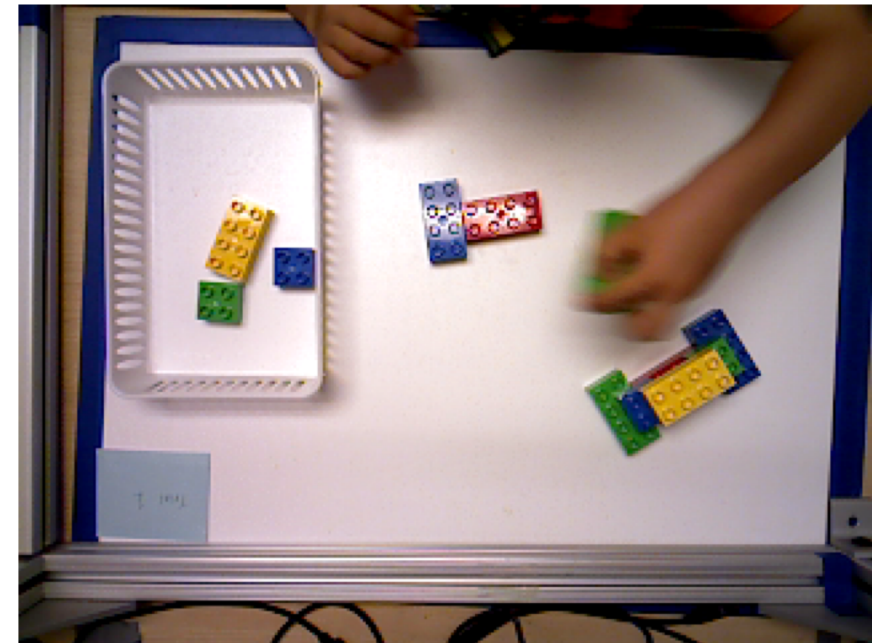
Barbara Landau
Cognitive Science



Amy Shelton
Education



Cathryn Cortesa
Cognitive Science

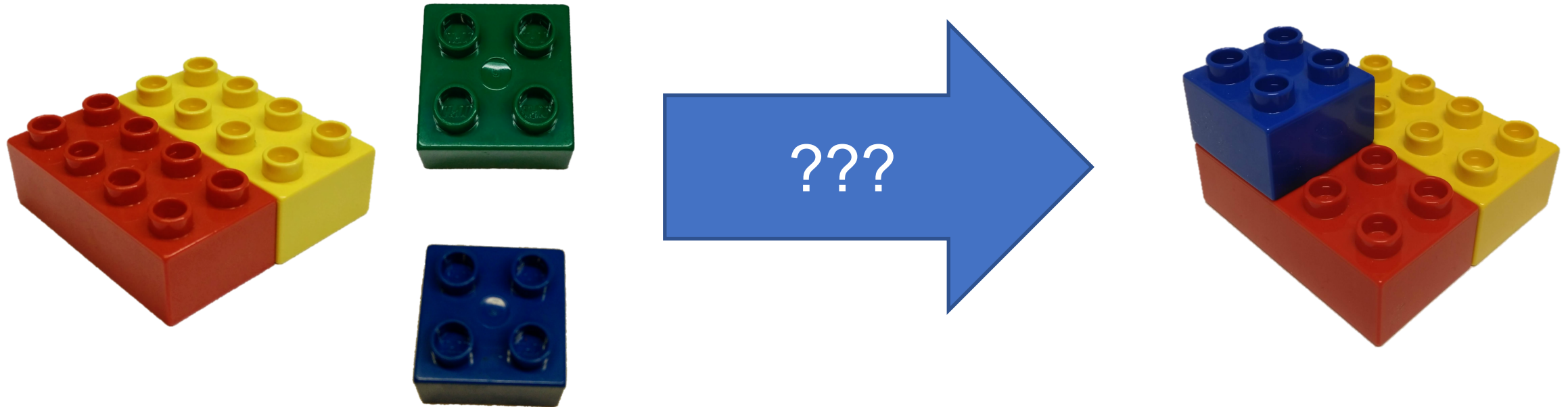


Cortesa, C. S., Jones, J. D., Hager, G. D., Khudanpur, S., Landau, B., & Shelton, A. L. (2018). Constraints and Development in Children's Block Construction. *CogSci 2018 Proceedings*, 246-251.

Cortesa, C. S., Jones, J. D., Hager, G. D., Khudanpur, S., Shelton, A. L., & Landau, B. (2017). Characterizing spatial construction processes: Toward computational tools to understand cognition. *CogSci 2017 Proceedings*, 246-251.



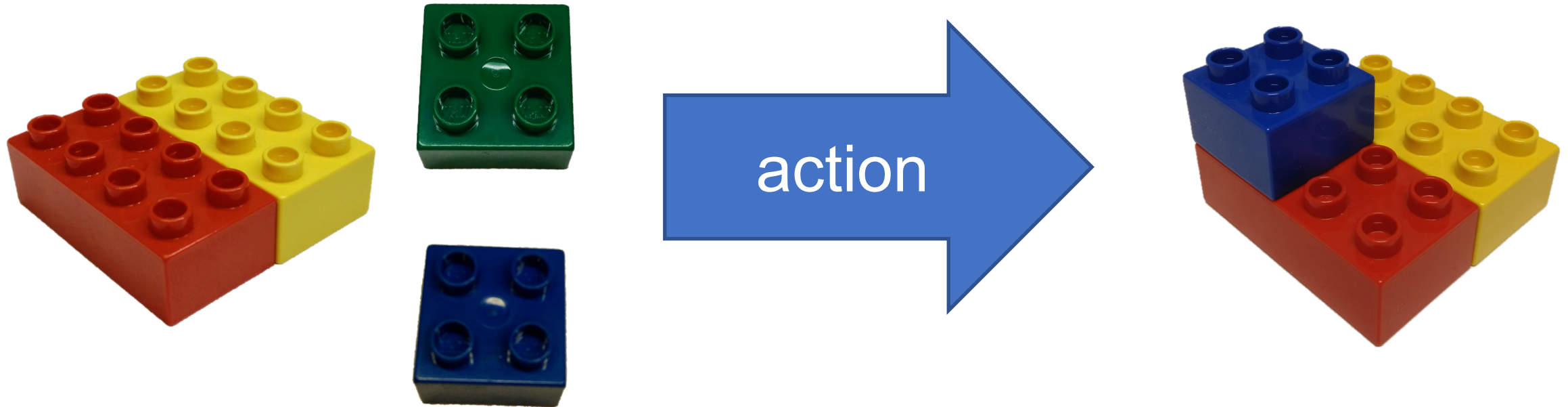
Representing assembly processes



1. Choose the right block
2. Make the right connections
3. Connect in the right way



Representing assembly processes

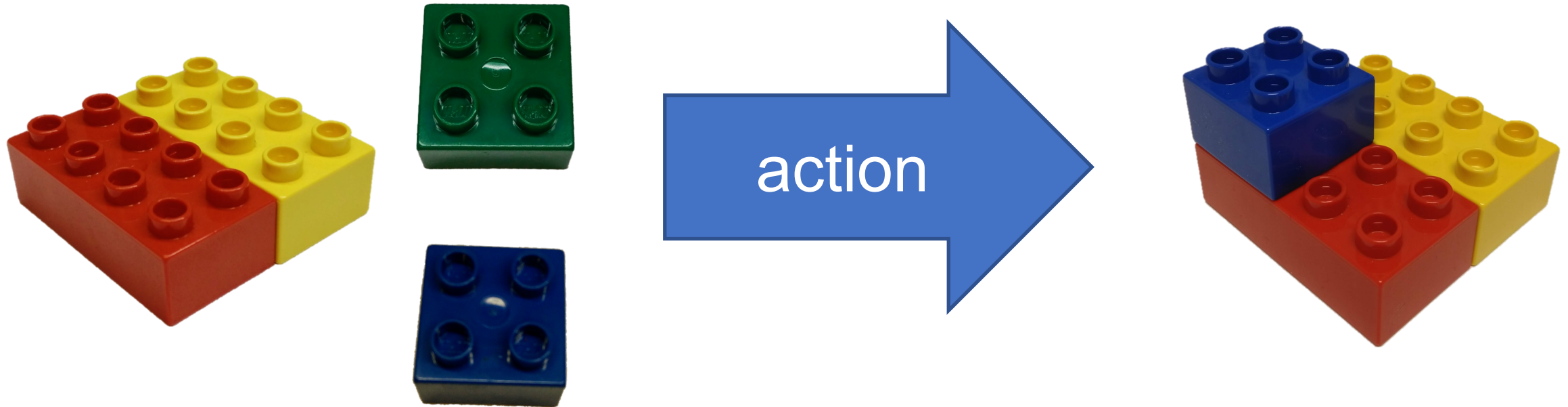


1. Choose the right block
2. Make the right connection
3. Connect in the right way


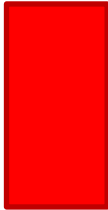
connect ( , , ,)



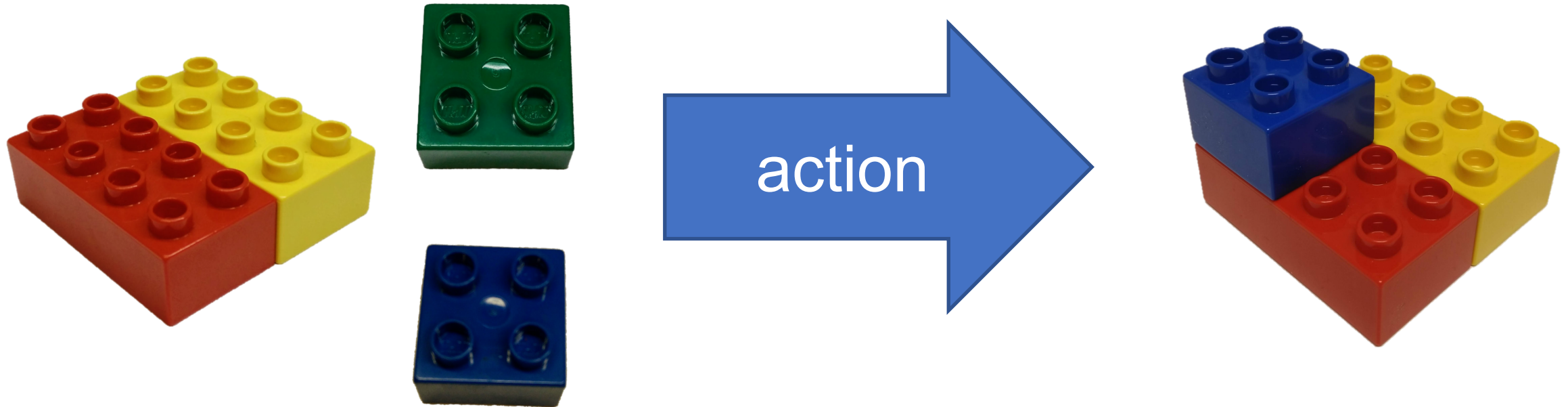
Representing assembly processes




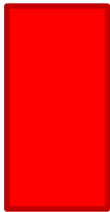
1. Choose the right block
2. Make the right connection
3. Connect in the right way

connect ( ,  , ,)

Representing assembly processes



1. Choose the right block
2. Make the right connection
3. Connect in the right way

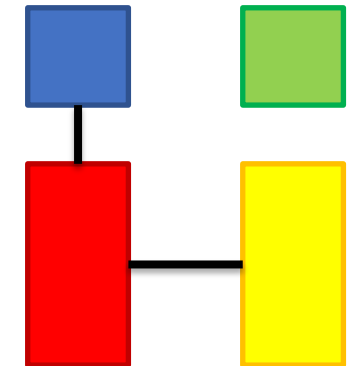
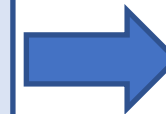
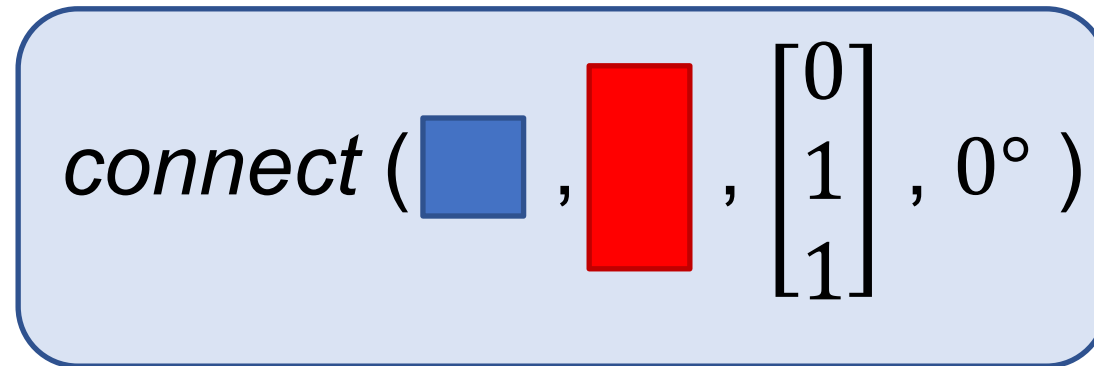
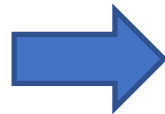
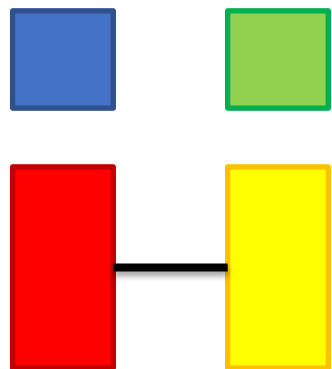
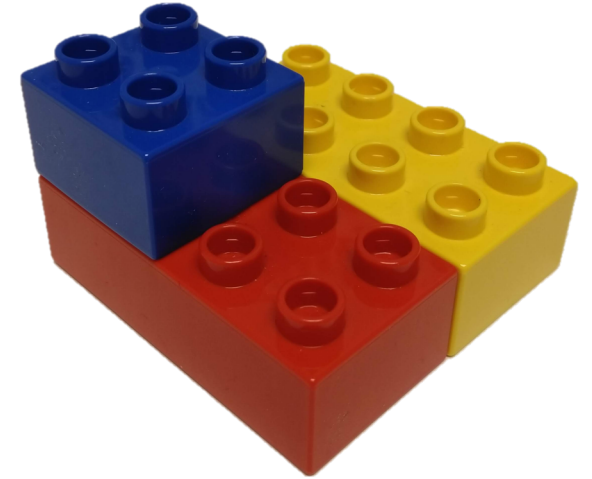
connect ( ,  , $\begin{bmatrix} 0 \\ 1 \\ 1 \end{bmatrix}$, 0°)



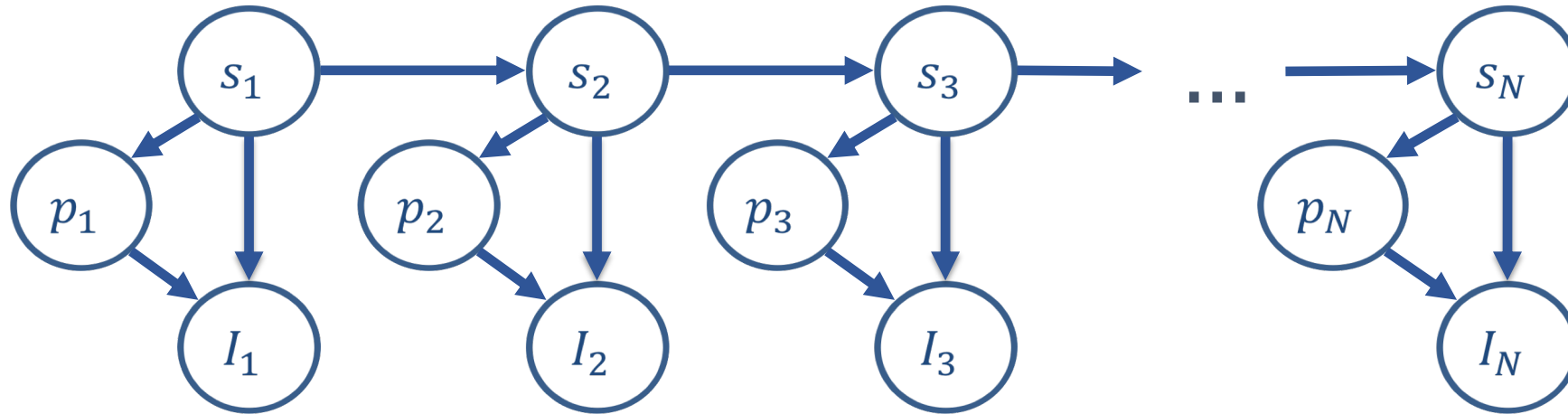
Representing assembly processes



- State is a graph
- Vertices are blocks
- Edges are block connections
- Edges are labeled with a block's relative pose in the coordinate frame of its neighbor



A probabilistic model



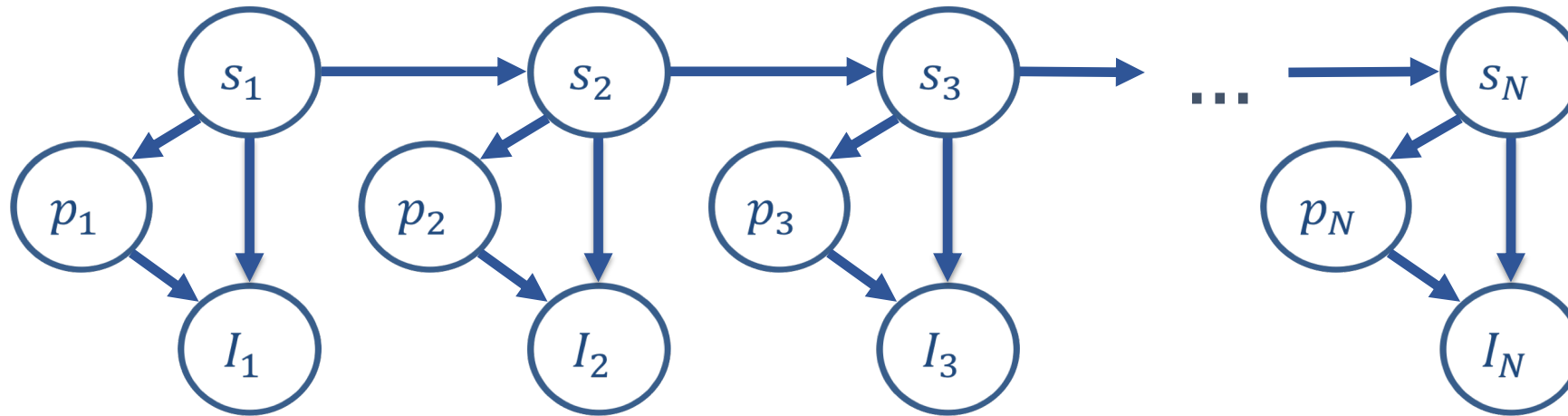
s_t : state of block model

p_t : pose of block model

I_t : video keyframe



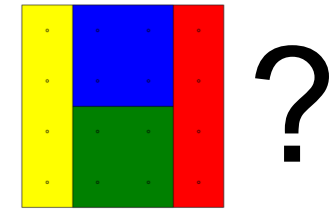
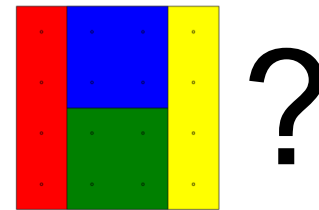
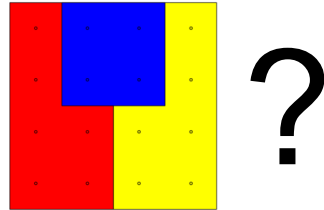
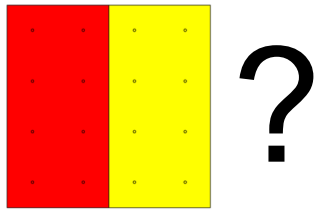
A probabilistic model



$$p_{1:N}^*, s_{1:N}^* = \underset{p_{1:N}, s_{1:N}}{\operatorname{argmax}} P(p_{1:N}, s_{1:N} \mid I_{1:N})$$



Parsing assembly processes

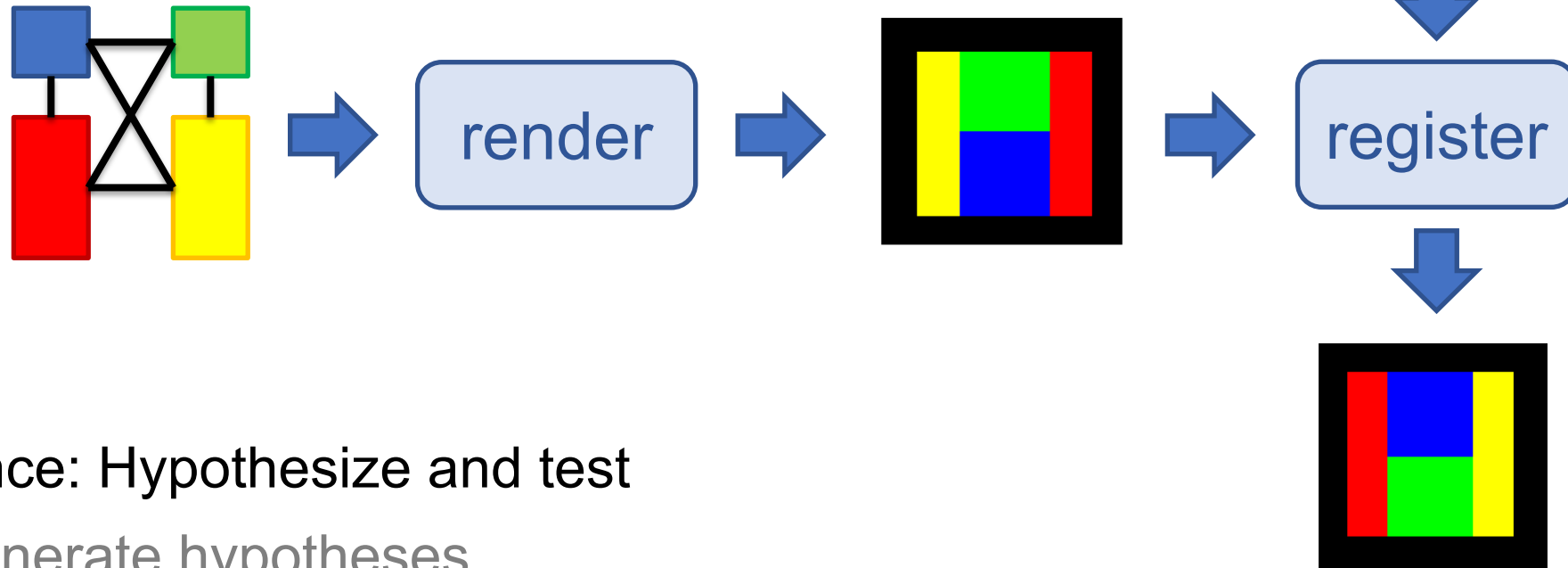


Inference: Hypothesize and test

1. Generate hypotheses
2. Test hypotheses locally (render & register template)
3. Decode best state sequence globally



Parsing assembly processes

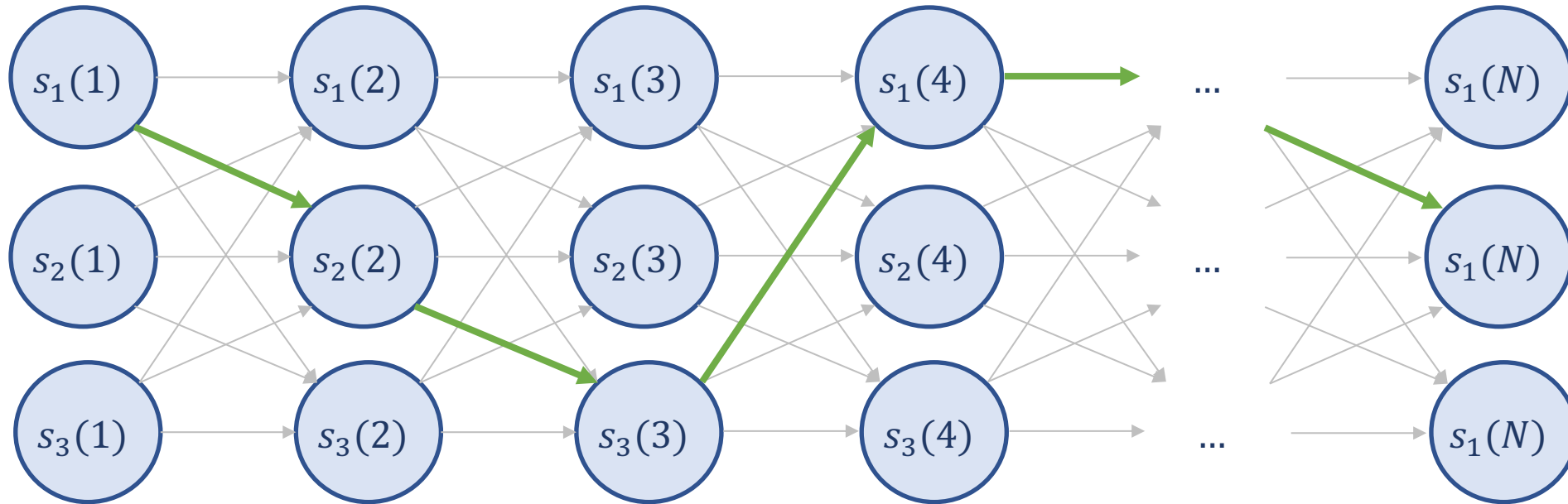


Inference: Hypothesize and test

1. Generate hypotheses
2. Test hypotheses locally (render & register template)
3. Decode best state sequence globally



Parsing assembly processes

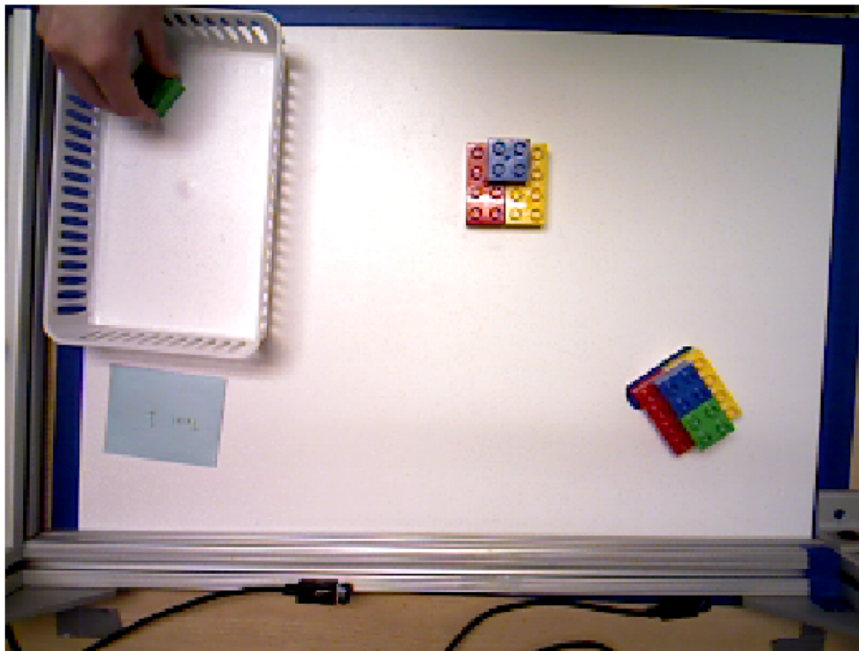


Inference: Hypothesize and test

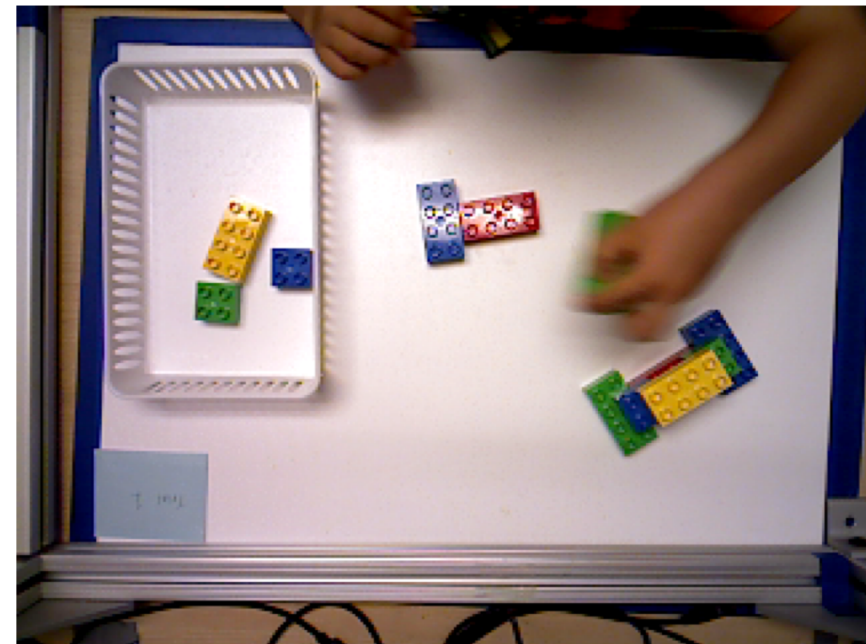
1. Generate hypotheses
2. Test hypotheses locally (render & register template)
3. Decode best state sequence globally



Controlled dataset



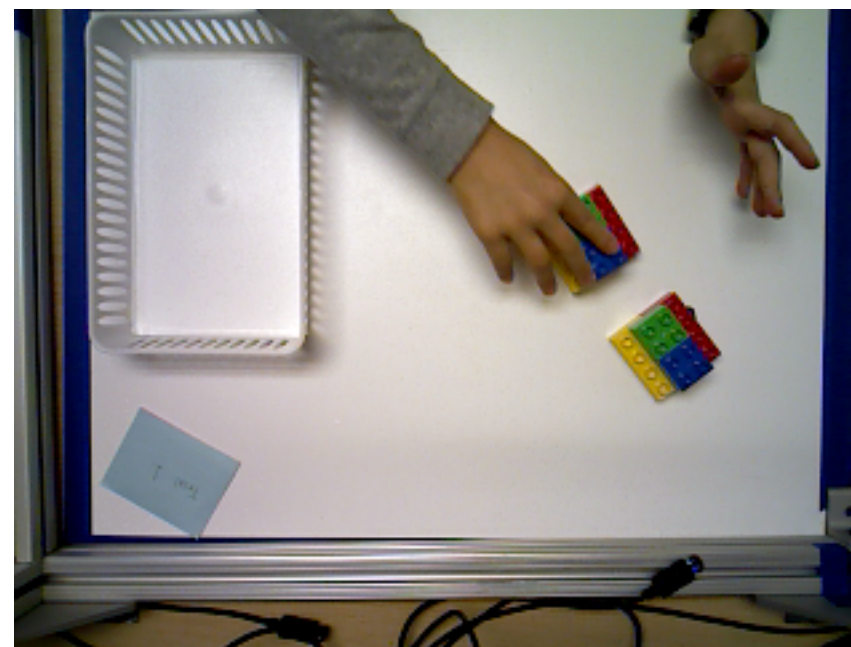
“Child’s play” dataset



“Child’s play” dataset

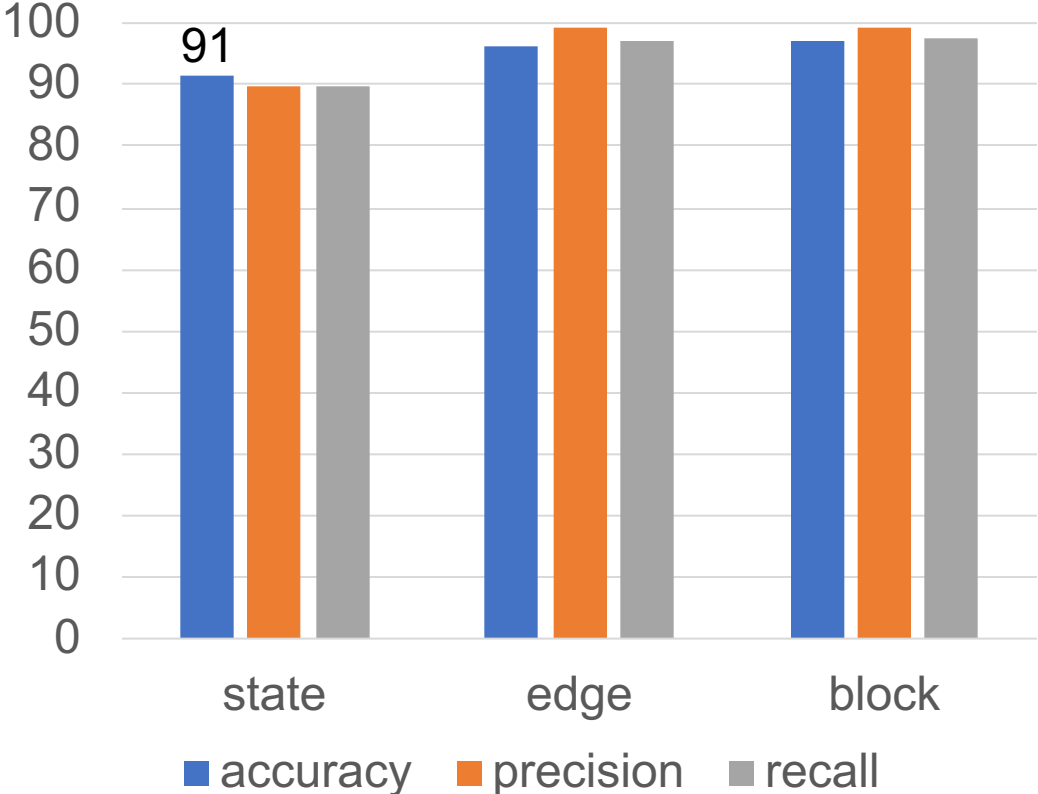


assembly out of view

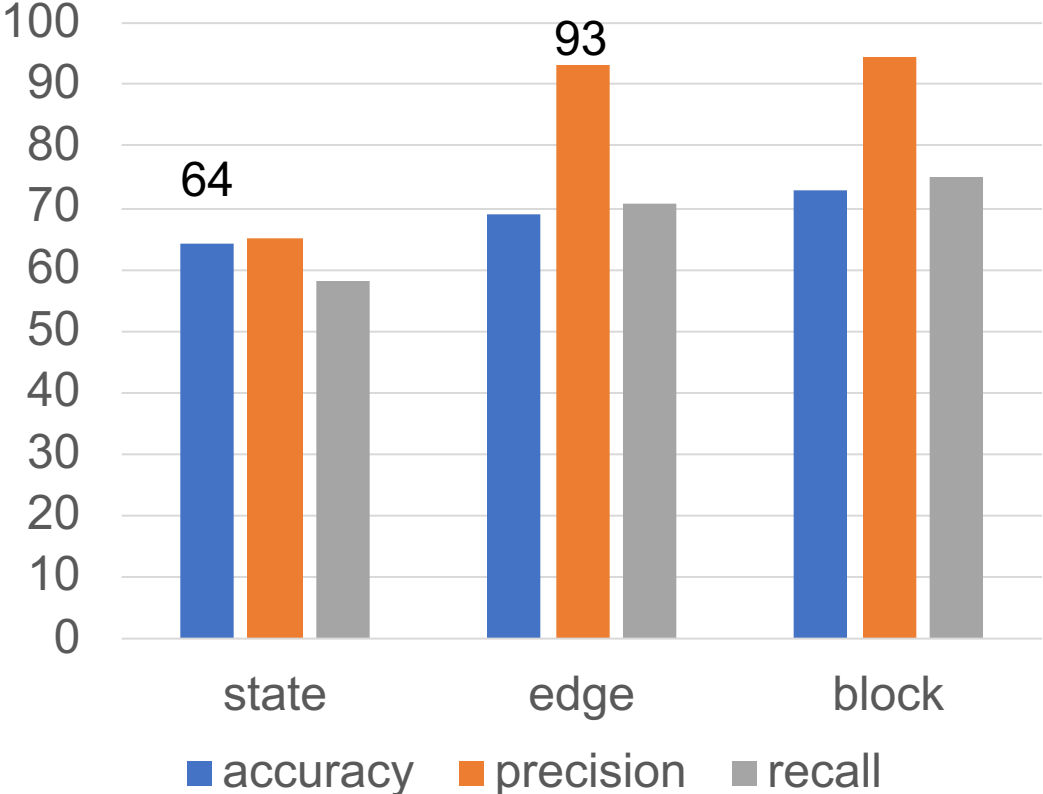


assembly occluded

Controlled dataset

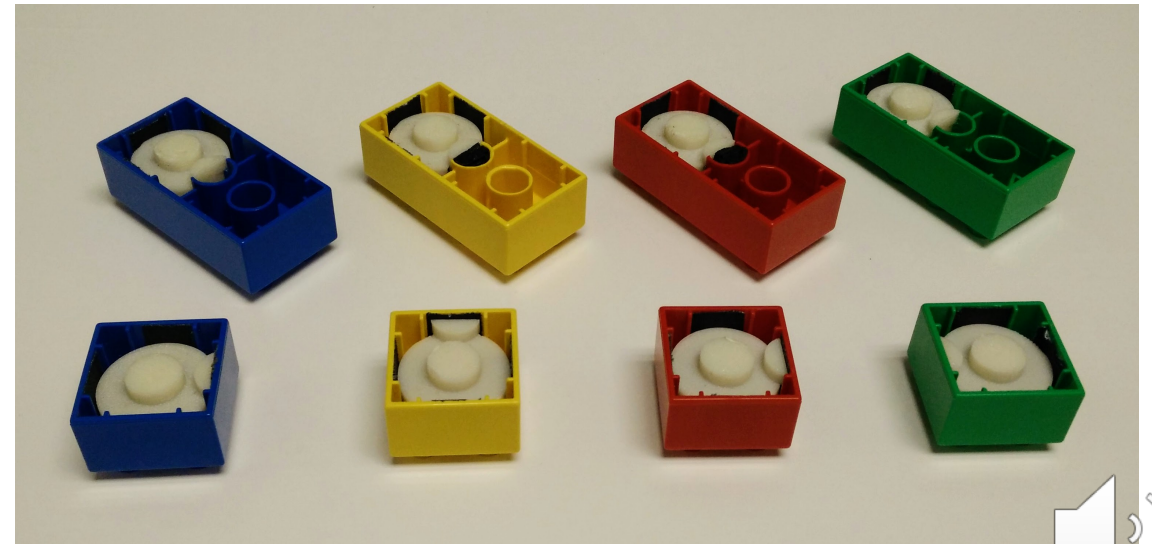
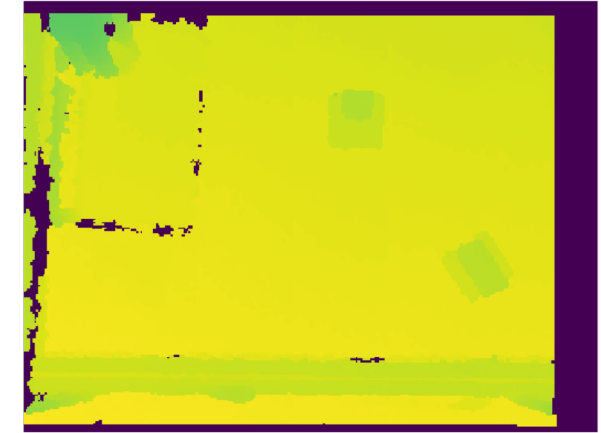
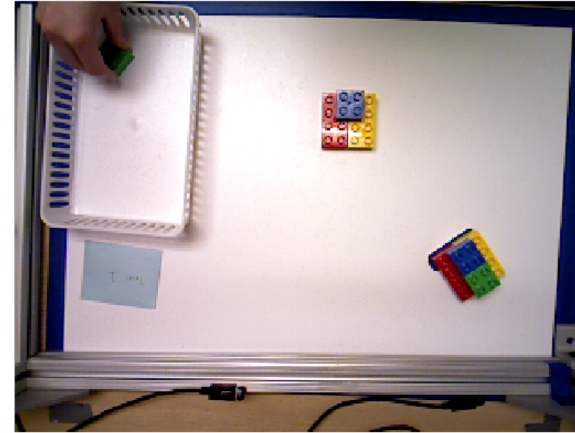


Child's play dataset



Future work

- Multimodal inference
 - RGB-depth
 - acceleration, angular velocity
- Handling occlusion
- Modeling actions



Acknowledgements



Barbara Landau
Cognitive Science



Amy Shelton
Education



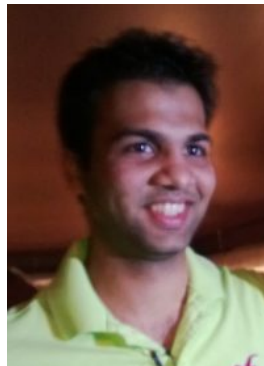
Greg Hager
*Computer
Science*



Sanjeev Khudanpur
*Electrical
Engineering*



Cathryn Cortesa
Cognitive Science



Anand Malpani
*Computer
Science*



Jonathan Jones
*Electrical
Engineering*