Vehicle Classification from Profile Measures

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Vehicle Classification Problem

Goal: Classify vehicles from point clouds in two configurations



Non-metric configuration



Metric configuration

State of the art: VoxNet

CNN with 3-dimensional convolutional layers

Advantages

- Extraction of rich (shape) features
- Works in both configurations

Disadvantages

- Lack of metric information
- Low voxel resolution $(16 \times 48 \times 16)$
- High network complexity



State of the art: VoxNet architecture



State of the art: PointNet

CNN with *pointwise* convolutions **Advantages**

- Extraction of metric features
- No resolution problem
- Low network complexity

Disadvantages

- Works in metric configuration only
- Can't extract neighbourhood information well



State of the art: PointNet architecture



Our proposal

A CNN which is able to extract metric information from x and zcoordinates, and non-metric one over y axis

The input is modified from point cloud to structured point cloud, reordering it in a tensor of shape (number of slices) x (number of points per slice) x 2



Our proposal: SliceNet



Combination of PointNet and VoxNet Advantages

- Extraction of metric features over x and z axis
- Extraction of neighbour information over *y* axis
- Low network complexity
- Works in both configurations

Disadvantages

• In metric configuration y coordinate is not exploited

Our proposal: SliceNet architecture



Our proposal: SliceNet GAP architecture





Experiments: Datasets

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Non-metric			~6900				18			
Metric			~2500				8			
car										
suv										
van										
truck										
road tractor	-									
s-truck closed		Wile	NAME							
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Experiments: Results



(a) Van, misclassified as truck.





(b) Truck, misclassified as van.



(c) Bus, misclassified as coach.

	Accuracy						
	Non-metric	Metric					
VoxNet	96.6	99.3					
PointNet	96.7	99.4					
SliceNet	97.2	99.4					
SliceNet GAP	97.1	99.2					



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Thank you for your attention!