

Parallel Tracking and Verifying: A Framework for Real-Time and High Accuracy Visual Tracking

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1. Siamese networks for verification

1.1. Architecture

Figure 1 shows the detailed architecture of siamese networks. Note that there are only two max pooling layers after conv1-2 and conv2-2 because too many max pooling layers may reduce the spatial information in features. Table 1 demonstrates the parameters of each layer. The source code of PTAV will be released for reproducible research.

1.2. Network training

We use the ALOV dataset [14] to train the siamese networks. Note that we exclude all videos that appear in OTB2013 [17], OTB2015 [18] and TC128 [9]. After removing these sequences, the training dataset and the evaluation datasets have no common objects. As in [15], we generate multiple pairs using every two frames in a video. One element in the pair is the groundtruth bounding box in one frame and the other one is a box sampled in the other frame. The pair is considered to be positive if the sampled box has a intersection-over-union overlap larger than 0.7 with the corresponding groundtruth box and considered to be negative if the overlap is smaller than 0.5. The training pairs and validation pairs are generated from different videos, and therefore from different objects. For training, in total we have sampled 60, 000 pairs of frames from ALOV dataset and each pair has 128 pairs of boxes. For validation, we have gathered 2, 000 pairs of frames and the same as for training each pair of frames contains 128 pairs of boxes.

We use the pre-trained network parameters from VGGNet [13] to initialize the networks. The initial learning rate is 0.001 and the weight decay parameter is 0.001. The learning rate is decreased by a factor of 10 after every 2 epochs. Training stops when the validation loss does not decrease any more.

2. Detailed results on OTB2015 [18]

In this supplementary material, detailed results on OTB2015 [18] with 100 videos are provided. Table 2 shows the per-video distance precisions for all trackers in comparison. Note that table 2 also contains the results on OTB2013 [17]. Figure 2 and Figure 3 show the distance precision plots and overlap successful plots for all 11 attributes, respectively.

3. Detailed results on TC128 [9]

We also present detailed results on the TC128 [9] with 128 videos. The per-video distance precision for all trackers in our comparison are reported in table 3. Figure 4 and Figure 5 show the distance precision plots and overlap successful plots for all 11 attributes, respectively.

4. Detailed results on UAV20L [12]

We present detailed results on the UAV20L [12] with 20 long videos. The shortest video contains 1717 frames, and the longest video contains 5527 frames. The per-video distance precision for all trackers in our comparison are reported in table 4. Figure 6 and Figure 7 show the distance precision plots and overlap successful plots for all 12 attributes, respectively.

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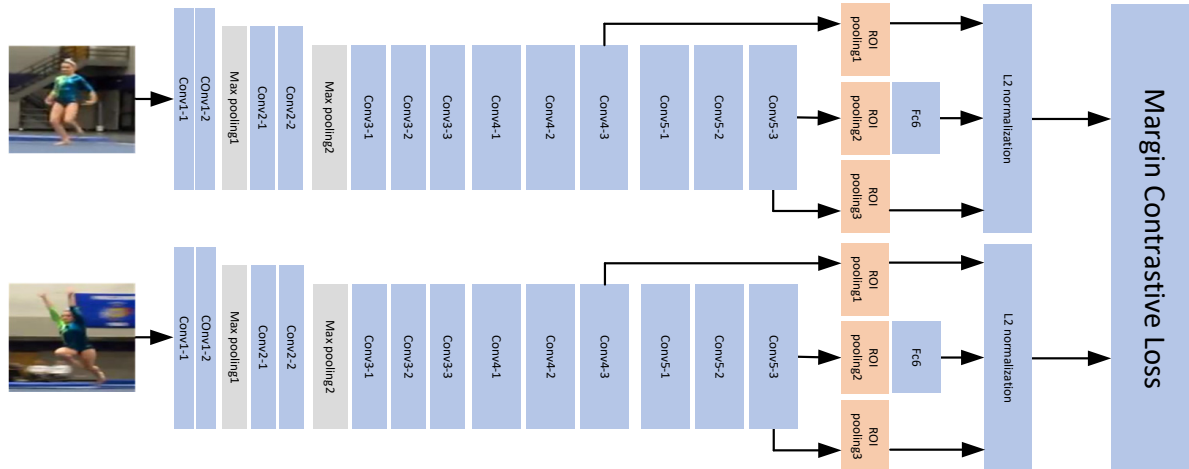


Figure 1. The detailed architecture of siamese networks.

Table 1. Parameters of the siamese networks.

Layer name	Conv1-1	Conv1-2	Max pooling1	Conv2-1	Conv2-2	Max pooling2
Parameters	3x3x64	3x3x64	2x2	3x3x128	3x3x128	2x2
Layer name	Conv3-1	Conv3-2	Conv3-3	Conv4-1	Conv4-2	Conv4-3
Parameters	3x3x256	3x3x256	3x3x256	3x3x512	3x3x512	3x3x512
Layer name	Conv5-1	Conv5-2	Conv5-3	ROI pooling1	ROI pooling2	ROI pooling3
Parameters	3x3x512	3x3x512	3x3x512	7x7	7x7	7x7

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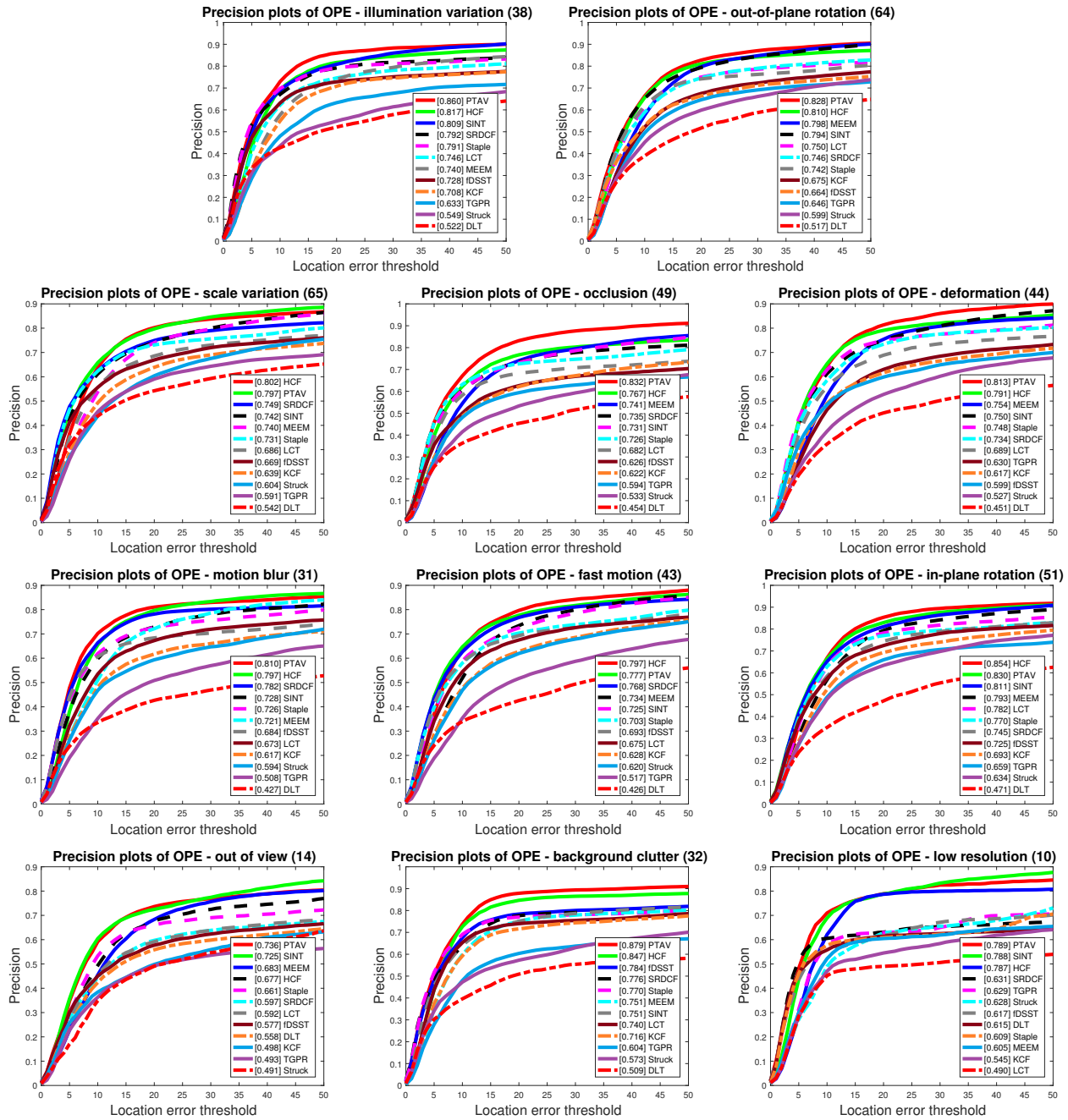


Figure 2. Distance precision plots on OTB2015 [18] for 11 attributes, which are background cluttered (BC), deformation (DEF), fast motion (FM), in-plane rotation (IPR), illumination variation (IV), low resolution (LR), motion blur (MB), occlusion (OCC), out-of-plane rotation (OPR), out-of-view (OV) and scale variation (SV). The distance precision (DP) score is shown in the legend. Our PTAV ranks top 2 on all 11 attributes.

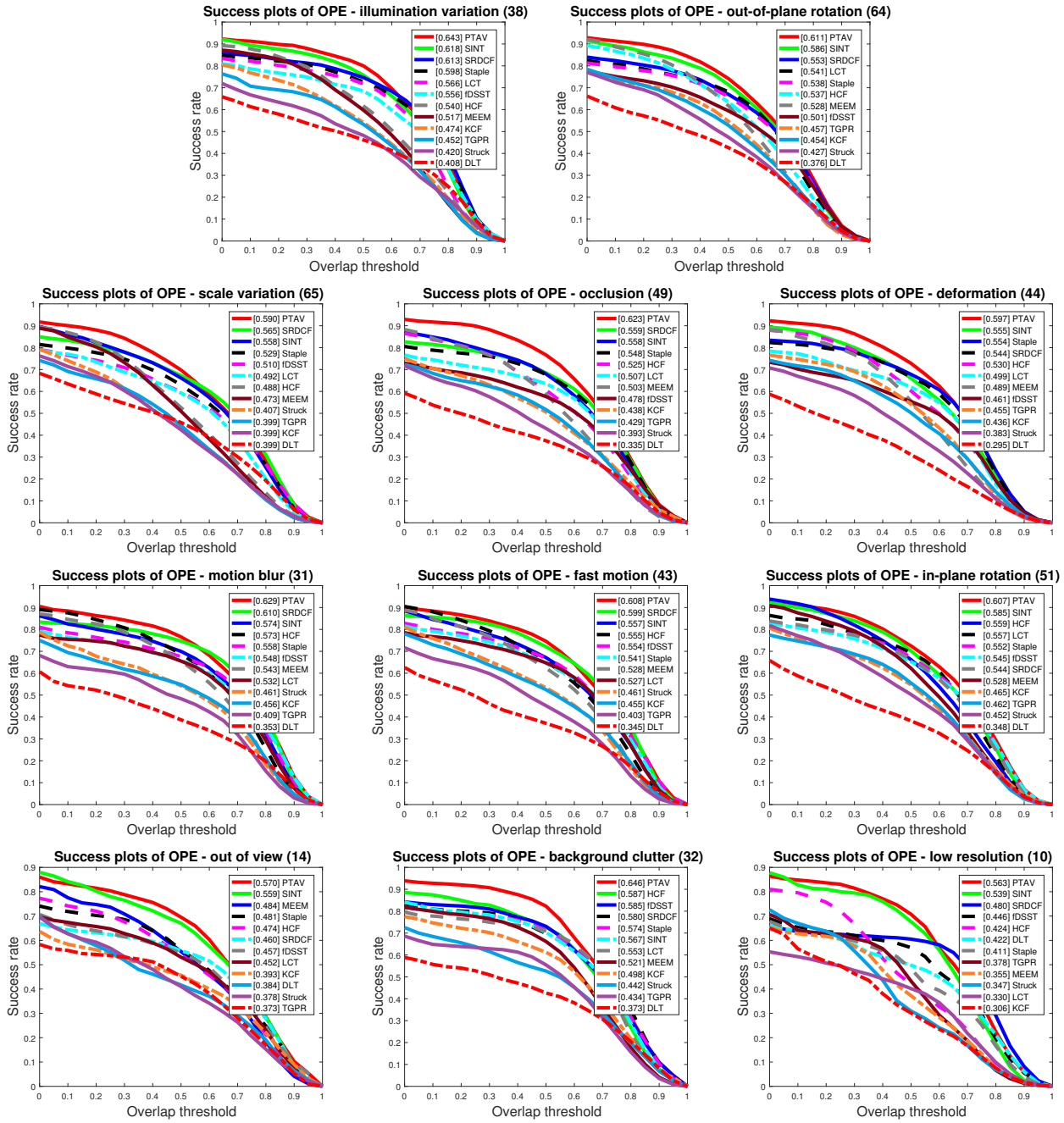


Figure 3. Overlap success plots on OTB2015 [18] for 11 attributes, which are background cluttered (BC), deformation (DEF), fast motion (FM), in-plane rotation (IPR), illumination variation (IV), low resolution (LR), motion blur (MB), occlusion (OCC), out-of-plane rotation (OPR), out-of-view (OV) and scale variation (SV). The title of each attribute plot contains the name of the attribute and the number of videos associated with it. The overlap success (OS) score is shown in the legend. Our PTAV ranks top 2 on all 11 attributes.

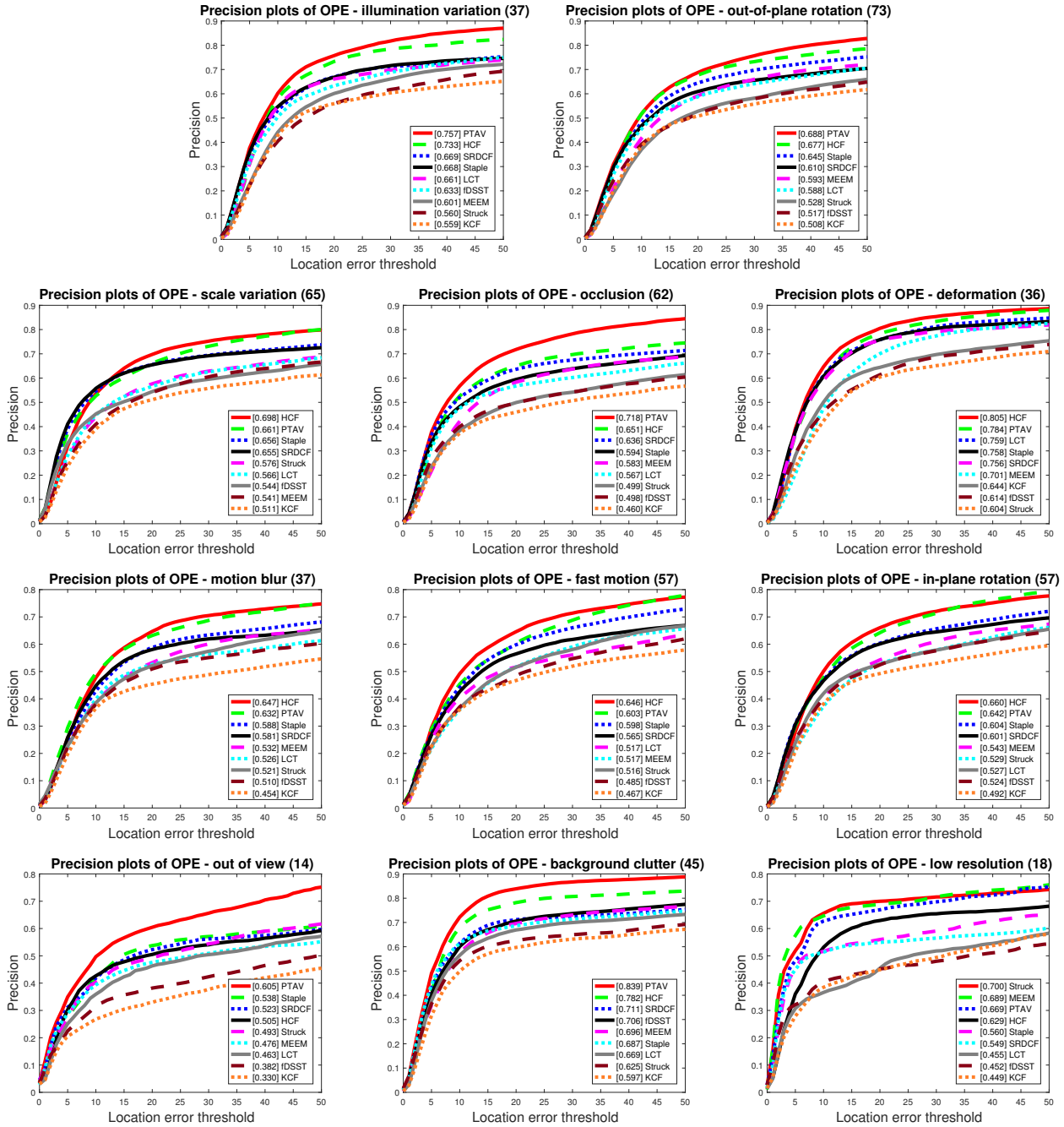


Figure 4. Distance precision plots on TC128 [9] for 11 attributes, which are background cluttered (BC), deformation (DEF), fast motion (FM), in-plane rotation (IPR), illumination variation (IV), low resolution (LR), motion blur (MB), occlusion (OCC), out-of-plane rotation (OPR), out-of-view (OV) and scale variation (SV). The distance precision (DP) score is shown in the legend. Our PTAV ranks top 2 on all 10 of 11 attributes.

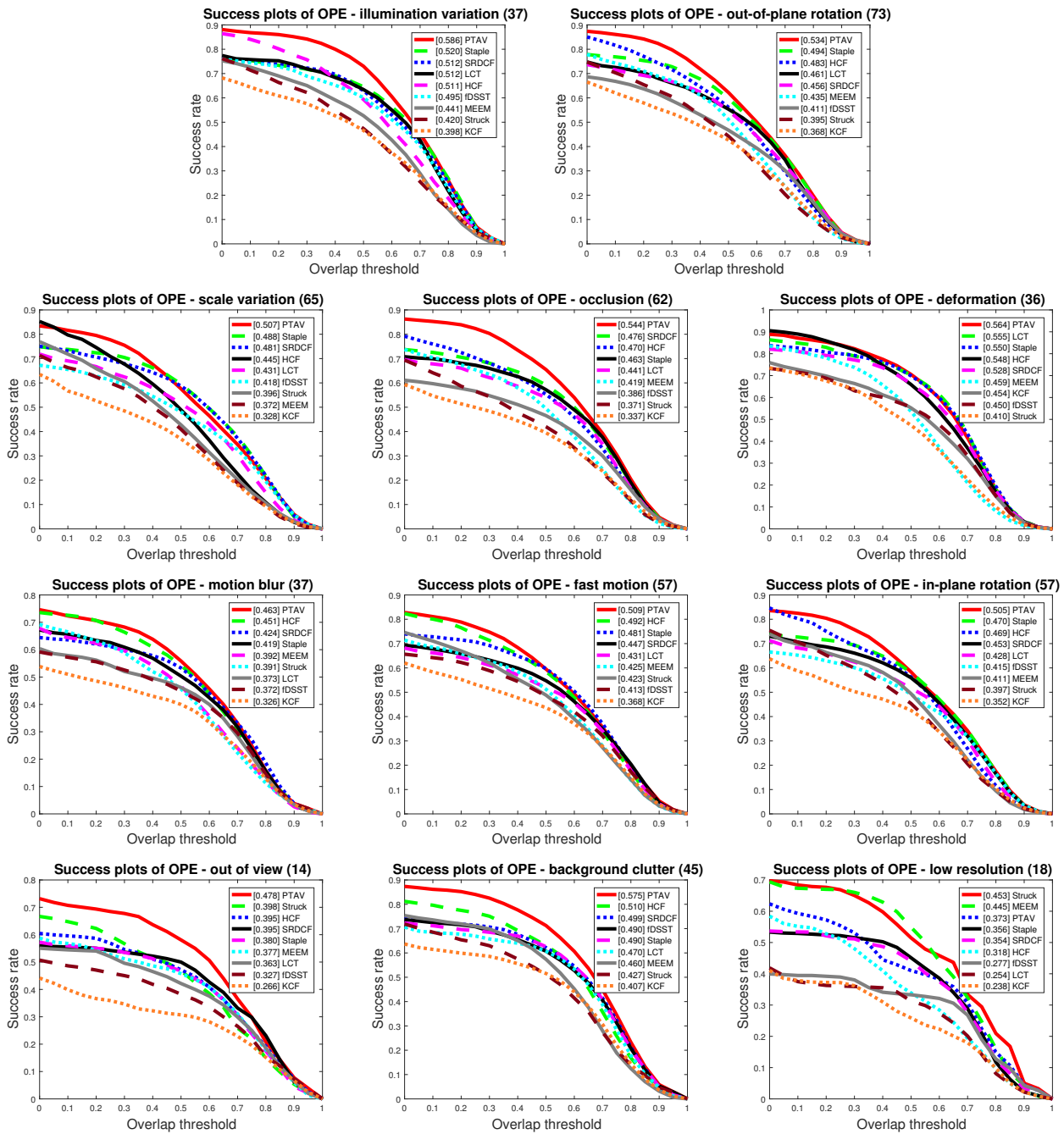


Figure 5. Overlap success plots on TC128 [9] for 11 attributes, which are background cluttered (BC), deformation (DEF), fast motion (FM), in-plane rotation (IPR), illumination variation (IV), low resolution (LR), motion blur (MB), occlusion (OCC), out-of-plane rotation (OPR), out-of-view (OV) and scale variation (SV). The title of each attribute plot contains the name of the attribute and the number of videos associated with it. The overlap success (OS) score is shown in the legend. Our PTAV ranks top 2 on all 10 of 11 attributes.

Table 4. A per-video comparison on the UAV20L [12]. The best two results are highlighted with red and blue fonts (last row of table).

	PTAV	MUSTer [7]	SRDCF [3]	HCF [10]	MEEM [19]	SAMF [8]	Struck [5]	fDSST [2]	LCT [11]	KCF [6]
Bike1	0.456	0.406	0.330	0.579	0.576	0.395	0.156	0.449	0.349	0.138
Bird1	0.439	0.436	0.436	0.435	0.441	0.436	0.461	0.439	0.436	0.435
Car1	0.830	0.657	0.657	0.618	0.385	0.615	0.569	0.657	0.618	0.382
Car3	1.000	0.981	1.000	1.000	1.000	1.000	0.912	1.000	1.000	0.837
Car6	0.369	0.350	0.117	0.118	0.098	0.175	0.158	0.148	0.124	0.125
Car8	0.434	0.419	0.750	0.087	0.407	0.250	0.388	0.434	0.106	0.078
Car9	0.988	0.979	0.424	0.109	0.396	0.423	0.115	0.423	0.151	0.225
Car16	0.712	0.118	0.356	0.666	0.349	0.125	0.408	0.440	0.093	0.112
Group1	0.356	0.548	0.895	0.939	0.930	0.798	0.672	0.356	0.490	0.212
Group2	0.899	0.350	0.114	0.114	0.114	0.114	0.143	0.114	0.114	0.114
Group3	0.399	0.130	0.362	0.363	0.366	0.367	0.365	0.352	0.349	0.365
Person2	0.881	1.000	1.000	1.000	1.000	1.000	1.000	0.881	1.000	0.996
Person4	0.298	0.266	0.937	0.877	0.457	0.294	0.450	0.299	0.298	0.299
Person5	0.742	1.000	0.980	1.000	1.000	1.000	0.709	0.683	0.660	0.508
Person7	0.885	0.321	0.330	0.352	0.357	0.196	0.505	0.203	0.186	0.143
Person14	0.976	0.801	0.063	0.064	0.063	0.064	0.064	0.064	0.064	0.064
Person17	0.994	0.406	0.605	0.999	0.993	0.996	0.894	0.994	0.605	0.605
Person19	0.138	0.233	0.297	0.303	0.221	0.301	0.201	0.138	0.173	0.156
Person20	0.236	0.474	0.376	0.228	0.173	0.480	0.217	0.236	0.445	0.317
Uav1	0.443	0.411	0.115	0.154	0.319	0.107	0.361	0.122	0.108	0.110
Average	0.624	0.514	0.507	0.500	0.482	0.457	0.437	0.422	0.368	0.311

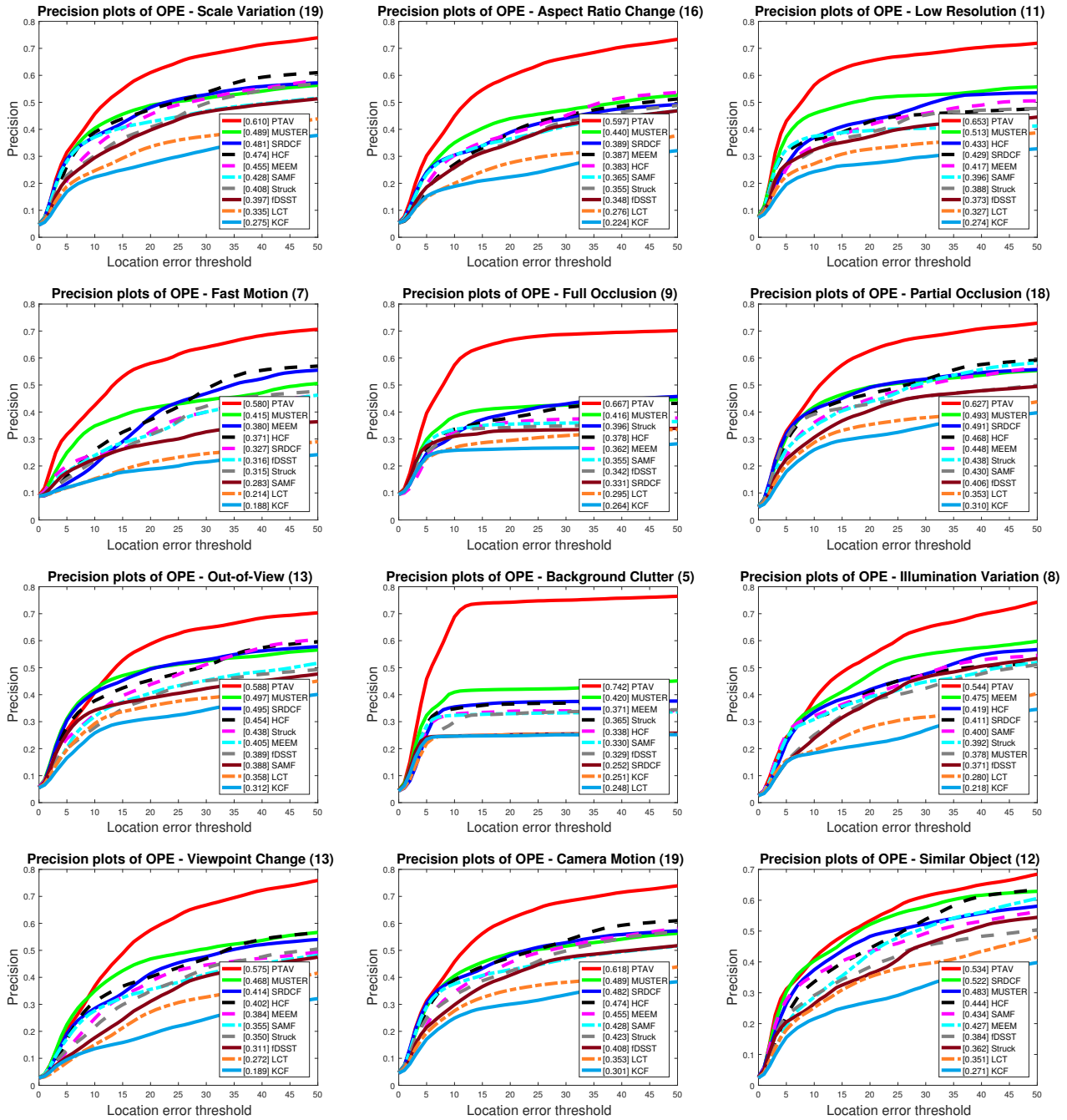


Figure 6. Distance precision plots on UAV20L [12] for 12 attributes, which are scale variation (SV), aspect ratio change (ARC), low resolution (LR), fast motion (FM), full occlusion (FOC), partial occlusion (POC), out-of-view (OV), background clutter (BC), illumination variation (IV), viewpoint change (VC), camera motion (CM) and similar object (SOB). The distance precision (DP) score is shown in the legend. Our PTAV ranks top 1 on all 12 attributes.

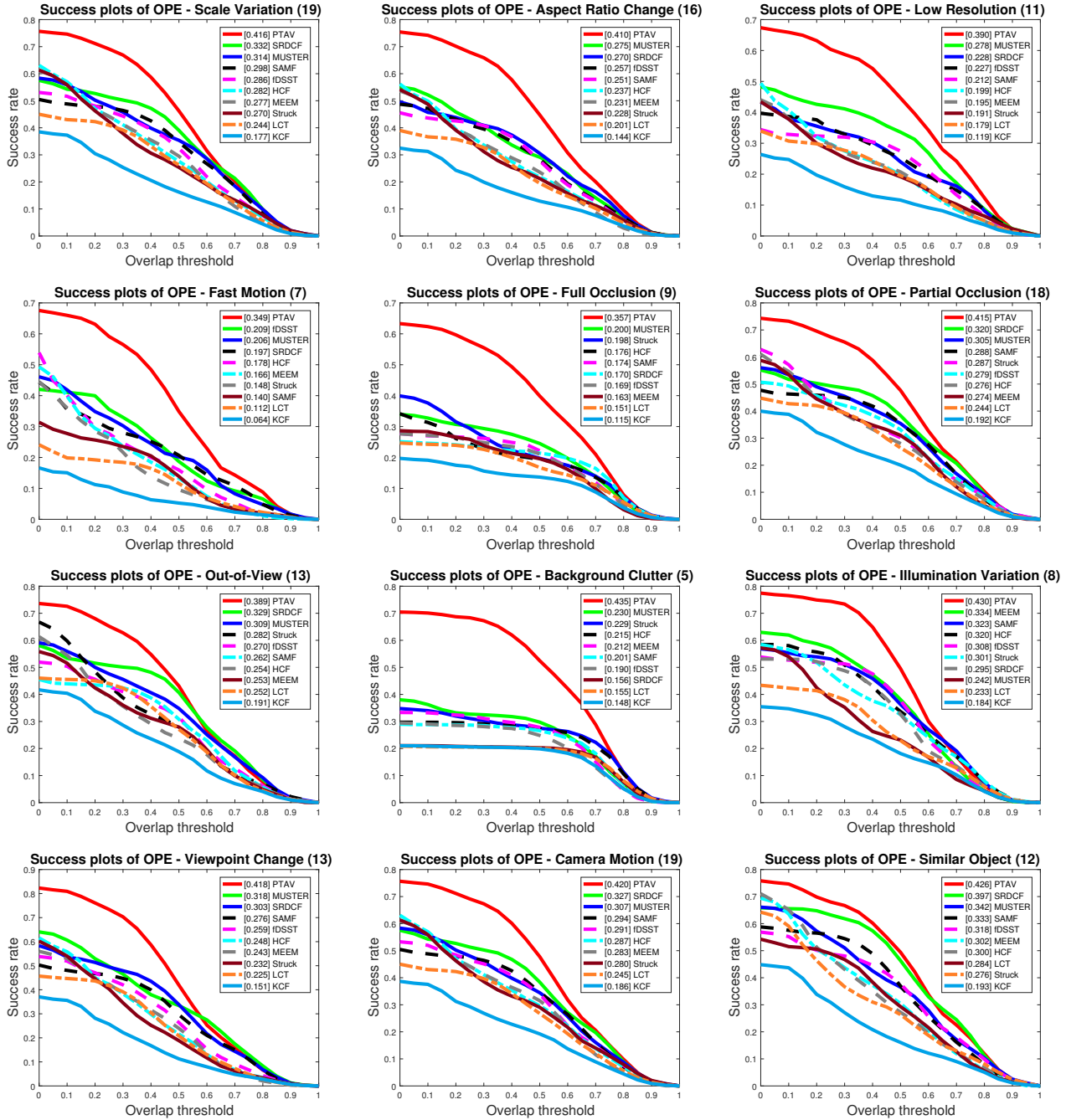


Figure 7. Overlap success plots on UAV20L [12] for 12 attributes, which are scale variation (SV), aspect ratio change (ARC), low resolution (LR), fast motion (FM), full occlusion (FOC), partial occlusion (POC), out-of-view (OV), background clutter (BC), illumination variation (IV), viewpoint change (VC), camera motion (CM) and similar object (SOB). The title of each attribute plot contains the name of the attribute and the number of videos associated with it. The overlap success (OS) score is shown in the legend. Our PTAV ranks top 1 on all 12 attributes.