

Discrete Tabu Search for Graph Matching

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Abstract

Graph matching is a fundamental problem in computer vision. In this paper, we propose a novel graph matching algorithm based on tabu search [13]. The proposed method solves graph matching problem by casting it into an equivalent weighted maximum clique problem of the corresponding association graph, which we further penalize through introducing negative weights. Subsequent tabu search optimization allows for overcoming the convention of using positive weights. The method's distinct feature is that it utilizes the history of search to make more strategic decisions while looking for the optimal solution, thus effectively escaping local optima and in practice achieving superior results. The proposed method, unlike the existing algorithms, enables direct optimization in the original discrete space while encouraging rather than artificially enforcing hard one-to-one constraint, thus resulting in better solution. The experiments demonstrate the robustness of the algorithm in a variety of settings, presenting the state-of-the-art results. The code is available at <http://cv.snu.ac.kr/research/~DTSGM/>.

1. Introduction

Graph matching is an important problem in both theoretical computer science, and practical applications of computer vision and machine learning. In computer vision, it has been proven to effectively deal with the problem of matching two sets of visual features making it the approach of choice in shape matching [4], object recognition [8, 25] and tracking [18]. Typically, graph matching is formulated as an integer quadratic program (IQP) with an additional one-to-one constraint. The formulation is popular due to its generality to allow complex but more informative affinity measures between node correspondences such as transfer error [6]. Nonetheless, there are two main theoretical issues with optimizing this graph matching formulation; (1) IQP is generally an NP-hard non-convex problem with multiple local minima; (2) the one-to-one constraint is not straight-

forward to combine into the IQP optimization process. As a result, various methods have been developed to approximate the optimal solution of the graph matching problem based on different approaches, including eigenvector analysis [27, 20], random walk [7], stochastic methods [26] and other optimization techniques [21, 32].

Conventionally, two stage procedure has been used to approximate the solution of IQP: first, solve the optimization problem in continuous domain by relaxing integer constraint, and then project the intermediate solution into the original feasible space of IQP [20, 7, 14]. Nonetheless, recent research [21, 30] devises methods that produce discrete solutions and suggests that post-processing discretization leads to substantial loss in accuracy, especially that the discretization step is independent of the optimization of IQP. The approach to one-to-one constraint is three-fold. The first way, which enforces one-to-one constraint in the post-processing stage, suffers from the above-mentioned post-processing loss [2, 20]. The second approach, bistochastic normalization, in continuous space softly enforces the constraint during the optimization procedure [7, 14]. Finally, incorporating hard one-to-one during optimization results in overly restrictive search of the solution space. [19, 26]

In this work we propose a novel method for the graph matching based on tabu search, which solves the IQP problem effectively incorporating the one-to-one constraint. The contributions of this paper are manifold: (1) It proposes the penalized association graph framework which softly encourages the one-to-one constraint while directly searching in the discrete solution space. (2) Given the above framework, it adopts tabu search as an optimization technique. Tabu search, thanks to its strategic approach to searching the solution space has become a successful tool in optimizing hard combinatorial problems, while not being popular yet in computer vision. (3) It extends the proposed framework to work with repeated structure graph matching, enhancing its usage in practice. (4) Presents experimental results which prove outstanding robustness of the algorithm

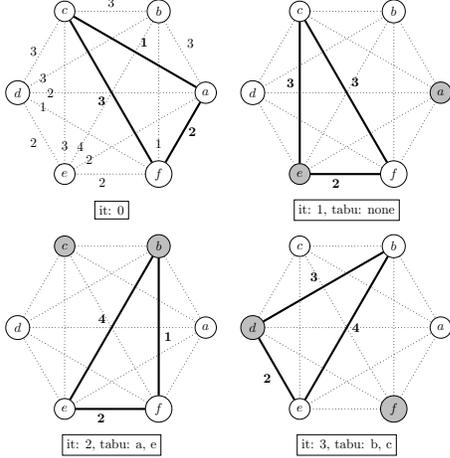


Figure 1. An example of tabu search to find the maximum weighted clique. At each iteration we swap two non-tabu nodes to maximize the objective (1). After being swapped, the nodes (marked as shaded) remain tabu for 1 iteration. (0) initially, $\mathcal{K} = acf$ and $|acf| = 5$; no variables are tabu. (1) e substitutes a , and $|cef| = 8$. (2) tabu variables are e that entered and a that left, we choose between b and d , both choices lower the objective, choose b , $|bcf| = 6$. (3) tabu variables are b and c , choose d to obtain the global optimum $|bed| = 9$.

in practical environment where noise and outliers exist.

2. Related works

The proposed method casts graph matching as a weighted maximum clique problem. In the literature, Horaud et al. [17] first proposed to formulate feature correspondence problem as finding the maximum clique between the nodes representing linear segments in two images. Similarly, Liu et al. [23] formulated graph matching as finding dense subgraphs within the association graph corresponding to local optima. The method was further generalized by allowing subgraph matching [22]. Zhao et al. [31] proposed heuristic label propagation as a post processing step following the initialization by [23]. In contrast, in this work, we redefine the notion of the association graph to incorporate soft one-to-one constraint and further propose tabu search method, which is less initialization dependent, to effectively explore given solution space searching beyond the local maxima, and thus resulting in more accurate solution.

Nevertheless, despite being a flexible and effective tool for solving combinatorial optimization problems [13], tabu search has not been actively applied in computer vision. Sorlin and Solnon [24] and Williams et al. [29] mentioned tabu search for graph matching focusing on simple incomplete synthetic graphs without noise nor outliers, omitting any tests on real world datasets. Moreover, [29] restricts the formulation to simple Bayesian consistency similarity measure and [24] uses cardinality functions.

This work is written in the spirit of recent research that

advocates the importance of discretization in the course of the algorithm. Leordeanu et al. [21] iterates between maximizing linearly approximated objective in discrete domain and maximizing along the gradient direction in continuous domain. Moreover, Zhou et al. [32] induces discrete solution by gradually changing weights of concave and convex relaxations of the original objective. Although these methods mitigate the artifact of continuous relaxation, they still phase through the continuous solution space during the optimization.

On the other hand, few algorithms have been proposed to directly explore the feasible space of IQP without any relaxation. Yan et al. [30] propose discrete method for hyper graph matching. Lee et al. [19] built Markov chain Monte Carlo based algorithm and Suh et al. [26] used Sequential Monte Carlo sampling to deal with the exponentially large and discrete solution space. Though they circumvent the issue of relaxation mentioned above, instead, they suffer from inefficient exploration, because the one-to-one constraint significantly limits the possible moves in their approach.

3. Graph Matching Problem

A graph \mathcal{G} is represented as a quadruple $\mathcal{G} = (\mathcal{V}, \mathcal{E}, \mathcal{W}^{\mathcal{V}}, \mathcal{W}^{\mathcal{E}})$. The elements $\mathcal{V}, \mathcal{E}, \mathcal{W}^{\mathcal{V}}, \mathcal{W}^{\mathcal{E}}$ respectively denote a set of nodes, a set of edges (which represent pairwise relations between the nodes), attributes of nodes and attributes of edges. In feature correspondence, a node attribute describes a local appearance of a feature in an image, and an edge geometrical relationship between features.

The objective of graph matching is to find the correct correspondences between nodes of two graphs \mathcal{G}_1 and \mathcal{G}_2 with n_1 and n_2 nodes, respectively. In this work, ‘‘one-to-one’’ constraint is assumed, which requires one node in \mathcal{G}_1 to be matched to at most one node in \mathcal{G}_2 and vice versa. The case when a node is not matched can be interpreted as the node being an outlier.

The compatibility between nodes and edges of two graphs \mathcal{G}_1 and \mathcal{G}_2 is commonly encoded in the nonnegative affinity matrix $\mathbf{A} \in \mathbb{R}^{n_1 n_2 \times n_1 n_2}$. A diagonal entry $\mathbf{A}_{ii', ii'}$ ¹ represents an affinity between attributes of $v_i \in \mathcal{V}_1$ and $v_{i'} \in \mathcal{V}_2$. A non-diagonal entry $\mathbf{A}_{ii', jj'}$ is a quantified information how well a match between $v_i \in \mathcal{V}_1$ and $v_{i'} \in \mathcal{V}_2$ corresponds to another match $v_j \in \mathcal{V}_1$ and $v_{j'} \in \mathcal{V}_2$. In subsequent sections for simplicity of notation, we will use superscript v_i^1 to denote the i -th node of graph \mathcal{G}_1 .

3.1. Formulation

The goal of graph matching problem is to find the set of matches between nodes of two graphs \mathcal{G}_1 and \mathcal{G}_2 that maxi-

¹For ease of understanding, in this paper we use notation $\mathbf{A}_{ii', jj'}$ to refer actually to the affinity matrix entry $\mathbf{A}_{(i'-1)n_1+i, (j'-1)n_1+j}$.

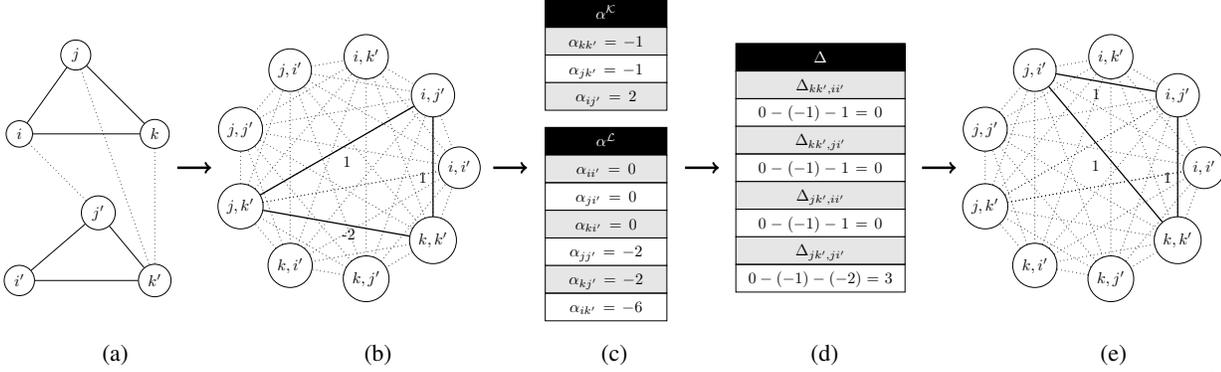


Figure 2. An example of using penalty to enforce one-to-one constraint through local search for (a) graph matching between \mathcal{G}_1 and \mathcal{G}_2 with initial matching ij', jk', kk' violating the constraint. (b) the corresponding association graph. The weights for non-conflicting matches are 1 and for conflicting matches -2 (for clarity, only the weights for the subgraph \mathcal{K} are shown). (c) affinity value of each node to \mathcal{K} given by Eq.(5) (d) The change Δ_{ab} to the IQP objective for interchanging top two matches from (c) according to Eq.(6). (e) Resulting subgraph with matches satisfying one-to-one constraint (one of the two possible results).

minimize the sum of affinity values of corresponding nodes and edges given by the affinity matrix \mathbf{A} . This formulation can be compactly represented by means of Integer Quadratic Programming (IQP):

$$\mathbf{x} = \arg \max_{\mathbf{x}} \mathbf{x}^T \mathbf{A} \mathbf{x} \quad (1)$$

$$s.t. \quad \mathbf{x} \in \{0, 1\}^{n_1 n_2}, \quad (2)$$

where the resulting matches are represented by a column vector \mathbf{x} , where $x_{ii'} = 1$ if node v_i^1 is matched with $v_{i'}^2$ and 0 otherwise². In accordance with the IQP graph matching conventional formulation, we assume the one-to-one constraint:

$$\forall i, \sum_{i'=1}^{n_2} x_{ii'} \in \{0, 1\} \text{ and } \forall i', \sum_{i=1}^{n_1} x_{ii'} \in \{0, 1\}. \quad (3)$$

3.2. Equivalent weighted maximum clique problem

In this section we build a graph matching framework based on the notion of the association graph, and incorporate graph matching constraints in an intuitive yet powerful way. Let us consider the association graph $\mathcal{A} = (\mathcal{V}_{\mathcal{A}}, \mathcal{E}_{\mathcal{A}}, \mathcal{W}_{\mathcal{A}}^{\mathcal{V}}, \mathcal{W}_{\mathcal{A}}^{\mathcal{E}})$ constructed from two input graphs, \mathcal{G}_1 and \mathcal{G}_2 , which is a fully connected graph with real valued attributes for both node and edges. Each node represents a possible node correspondence between input graphs, i.e., $v \in \mathcal{V}_{\mathcal{A}}$ stands for $(v_i^1, v_{i'}^2) \in \mathcal{V}_1 \times \mathcal{V}_2$ and each edge $e \in \mathcal{E}_{\mathcal{A}}$ represents a relationship between the two node correspondences. The nodes and edges are respectively characterized by its weights $w_v \in \mathcal{W}_{\mathcal{A}}^{\mathcal{V}}$ and $w_e \in \mathcal{W}_{\mathcal{A}}^{\mathcal{E}}$. Then, denote \mathcal{K} as the corresponding fully connected induced subgraph of \mathcal{A} such that the subset of nodes $\mathcal{V}_{\mathcal{K}} \subset \mathcal{V}_{\mathcal{A}}$. Choosing the

²In a similar manner to the convention used for \mathbf{A} , we use $x_{ii'}$ to denote the entry $x_{(i-1)n_2+i'} = 1$

subset $\mathcal{V}_{\mathcal{K}}$ is equivalent to selecting a set of node correspondences between the original graphs (see Fig. 2(a,b)). Analogously, we let $\mathcal{L} = \mathcal{A} \setminus \mathcal{K}$. Thus, we represent the selection of nodes in \mathcal{A} with a binary indicator vector $\mathbf{x} \in \{0, 1\}^{|\mathcal{V}_{\mathcal{A}}|}$, where $x_a = 1$ if a -th node is selected, that is $v_a \in \mathcal{K}$ and $x_a = 0$ if $v_a \in \mathcal{L}$. Let us note, that vector \mathbf{x} in this form satisfies the graph matching integer constraint and belongs to the feasible solution set of the constrained IQP (1).

Now, we can construct a graph $\mathcal{A}^{\mathcal{P}}$, whose maximum clique problem is equivalent to the graph matching problem. The weighted maximum clique problem is to find a subgraph \mathcal{K} , also referred to as a clique, in the graph $\mathcal{A}^{\mathcal{P}}$ which maximizes its potential, where the potential is the sum of all weights of included nodes and edges, i.e.,

$$\sum_{v \in \mathcal{V}_{\mathcal{K}}} w_v + \sum_{e \in \mathcal{E}_{\mathcal{K}}} w_e. \quad (4)$$

We assign the attributes as follows: $w_v = \mathbf{A}_{ii';ii'}$, where $v = (v_i^1, v_{i'}^2)$, and $w_e = \mathbf{A}_{ii';jj'} + p$, where $e = (v, u)$, $v = (v_i^1, v_{i'}^2)$, $u = (v_j^1, v_{j'}^2)$ and the term $p < 0$ when $i = j$ or $i' = j'$, which is a conflicting match, and 0 otherwise. If $p = 0$, then finding the vector \mathbf{x} that maximizes the sum of the affinities values in \mathcal{K} is equivalent to maximizing the QP with the integer constraint. If $p = -\infty$, then it becomes equivalent to maximizing the IQP with one-to-one constraint.

In this work, we propose to incorporate the penalty term p into the association graph framework which enforces the one-to-one constraint in soft way. As our objective is to maximize the sum of affinities in the clique \mathcal{K} , choosing a match that violates one-to-one constraint, (which is equivalent to selecting an edge penalized negatively) lowers the objective function. The subsequent section describes the local search optimization which utilizes above framework to enforce the one-to-one constraint.

4. Discrete Tabu Search for Graph Matching

In this section, we propose a tabu search based graph matching algorithm that optimizes the framework built in the previous section. Tabu search solves the original optimization problem Eq.(1-3) by solving the equivalent weighted maximum clique problem (3.2) in the penalized association graph $\mathcal{A}^{\mathcal{P}}$. Tabu search, also called adaptive memory programming, has been introduced to deal with hard optimization problems through economical search in the solution space exploiting the search history [11, 12]. It has been widely applied in various fields including engineering, economics and finance spanning the application ranging from pattern classification, VLSI design, investment planning, energy policy, biomedical analysis and environmental conservation [13] due to its flexibility and excellent performance, though it has not been widely applied yet in computer vision. In this work, we use tabu search to explore the space of all possible cliques of the association graph.

Tabu search is a meta-algorithm and constitutes of two components. The first one is the base algorithm which describes the general mechanism how we iterate between solutions (Section. 4.1). The second part consists of the criteria which solutions are allowed and which ones are forbidden at any given iteration (Section. 4.2). The overall algorithm is described as Alg. 1. The subsequent section describes the local search, where we propose how to utilize discrete solution space to iterate between solutions.

4.1. Local search and search space

Local search is an optimization technique which searches for the optimal solution among the set of candidate solutions. In our case, the set of candidate solutions is the neighborhood $N(\mathbf{x})$. The basic idea behind local search is to advance from one candidate solution \mathbf{x} to another solution \mathbf{x}' by an operation called a *move*. The movement occurs in the neighborhood $N(\mathbf{x})$ which we define as the set of solutions that differ with the candidate solution \mathbf{x} by one node:

$$N(\mathbf{x}) = \{\mathbf{x}' | \mathbf{x}' \cdot \mathbf{x} = k - 2, \|\mathbf{x}\| = \|\mathbf{x}'\| = k\}.$$

Since the goal of the graph matching is to maximize the affinity sum between the matches, local search moves from one solution to another in such a way to encounter a solution that maximizes the objective (1). To this aim, we need to make appropriate change to the composition of \mathcal{K} , that is to remove the nodes that have little affinity to the rest of the subgraph and substitute them with the nodes which have high affinity with the rest of the subgraph.

Let α_a be the sum of affinity values between a node v_a and all the nodes in \mathcal{K} :

$$\alpha_a = \sum_{b|v_b \in \mathcal{K}} \mathbf{A}_{ab} \quad (5)$$

Then change in the objective (1) when interchanging $v_a \in \mathcal{K}$ and $v_b \in \mathcal{L}$ is equal to:

$$\Delta_{ab} = \alpha_b - \alpha_a - \mathbf{A}_{ab}. \quad (6)$$

For simplicity, we denote $\alpha_a^{\mathcal{K}}$ if $v_a \in \mathcal{K}$ and respectively $\alpha_a^{\mathcal{L}}$ if $v_a \in \mathcal{L}$. Computing affinity values and the affinity change are illustrated in Fig. 2(c,d) and in Alg. 1 lines 7-8.

4.1.1 Decreasing the size of local search space

Note that for a single solution \mathbf{x} , the search space contains $|\mathcal{K}| \cdot |\mathcal{L}|$ possible moves and as the search space of local search is large, we attempt to decrease the scope of the search to the movements which are most likely to cause the large positive change Δ in the objective. To this aim similarly to the method in [28], we select the pairs of nodes from \mathcal{K} and \mathcal{L} which are likely to result in the largest positive change in the objective. To do so, we sort values $\alpha_a^{\mathcal{K}}$ in the increasing order and $\alpha_a^{\mathcal{L}}$ in the decreasing order and identify the top t nodes in each of the list for which we compute the change in the objective (Alg.1, line 8). Thus, we narrow the search space from $|\mathcal{K}| \cdot |\mathcal{L}|$ to t^2 where $t^2 \ll |\mathcal{K}| \cdot |\mathcal{L}|$. Define the narrowed space as $\tilde{N}(\mathbf{x})$. Let us note that swapping top nodes from each of the list may not be optimal if the affinity between two nodes we swap is large. Subsequently, among t^2 candidate pairs we choose the pair of nodes that results in the highest gain and swap the two nodes.

Once the move is done and a node v_a in \mathcal{K} is replaced by a node v_b , then and therefore the node affinity values for each node in both \mathcal{K} and \mathcal{L} must be updated accordingly:

$$\alpha_c := \alpha_c - \mathbf{A}_{ca} + \mathbf{A}_{cb}. \quad (7)$$

Note two special cases when $c = a$ and $c = b$. The affinity \mathbf{A}_{cc} is 0 for all c , and therefore when v_a is replaced by v_b in the subgraph, the sum of affinities of v_a to the new subgraph increases by its affinity to the new node in the subgraph, v_b . The case for the new node v_b is analogous.

$$\begin{aligned} \alpha_c &= \alpha_b + \mathbf{A}_{ab}, \text{ if } c = a \\ \alpha_c &= \alpha_b - \mathbf{A}_{ab}, \text{ if } c = b. \end{aligned} \quad (8)$$

4.2. Tabu search

The local search algorithm is a vanilla algorithm which forms the base for the tabu search. Local search defines the general direction of the search by aiming to choose the move which maximizes the change in the objective. On the other hand, tabu search defines the criteria whether a move proposed by local search can be executed or not.

Input: Affinity matrix $\mathbf{A} \in \mathbb{R}^{n_1 n_2 \times n_1 n_2}$
Output: Solution vector $\mathbf{x}^* \in \{0, 1\}^{n_1 n_2 \times 1}$

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1 penalize conflicting matches in  $\mathbf{A}$  with penalty  $p$ ;
2  $\mathbf{S} \leftarrow \{\}$  // stores multiple solutions
3 for  $i=1$  to  $sol$  do
4    $it \leftarrow 0; nonImpIt \leftarrow 0; bestTabu \leftarrow$ 
    $-\infty, bestnTabu \leftarrow -\infty; tabuIt[] \leftarrow 0[];$ 
5   while  $NonImpIter > endIt$  do
6     initialize subgraph  $\mathcal{K}$  with random nodes from
     affinity graph  $\mathcal{A}$ ;
7      $\alpha_a \leftarrow$  compute subgraph affinity for  $v_a \in \mathcal{V}_{\mathcal{A}}$ ;
8      $\Delta_{ab} \leftarrow$  compute the change (6) in the
     objective for exchanging top  $t$  nodes from
     sorted  $\alpha_a^{\mathcal{K}}$  (increasingly) and  $\alpha_a^{\mathcal{L}}$ 
     (decreasingly);
9      $\mathbf{x}_{tabu}, \mathbf{x}_{nontabu}, \mathbf{x}_{nontabu2} \leftarrow$  choose tabu
     ( $tabuIt > it$ ), best non-tabu and second best
     tabu solution with highest  $\Delta_{ab}$ ;
10    if  $f(\mathbf{x}_{tabu}) > f(\mathbf{x}_{nontabu})$  and  $f(\mathbf{x}_{tabu}) >$ 
     $f(\mathbf{x}^*)$  then
11       $\mathbf{x}_{cur} \leftarrow \mathbf{x}_{tabu}$ 
12    else
13       $\mathbf{x}_{cur} \leftarrow \mathbf{x}_{nontabu}$  // can lower objective.
14    end
15     $tabuIt(a), tabuIt(b) \leftarrow rand([q, r]) + it$ 
16     $\alpha_a \leftarrow$  recompute subgraph affinity for
     $v_a \in \mathcal{V}_{\mathcal{A}}$  for new solution  $\mathbf{x}_{cur}$  using (7)&(8);
17    if  $f(\mathbf{x}_{cur}) > f(\mathbf{x}_{cur}^*)$  then
18       $\mathbf{x}_{cur}^* \leftarrow \mathbf{x}_{cur}$ 
19    else
20       $nonImpIt = nonImpIt + 1;$ 
21    end
22    if  $f(\mathbf{x}_{cur}) > f(\mathbf{x}_{cur}^*)$  then
23       $\mathbf{x}_{cur}^* \leftarrow \mathbf{x}_{cur}$ 
24    end
25  end
26  if  $f(\mathbf{x}_{cur}^*) > f(\mathbf{x}^*)$  then
27     $\mathbf{x}^* \leftarrow \mathbf{x}_{cur}^*$ 
28  end
29 end

```

Algorithm 1: Tabu search for Graph Matching

In other words, the purpose of tabu search is to modify neighborhood $N(\mathbf{x})$ (usually by removing solutions) in such a way as to encourage or discourage certain moves in order to find the global solution. The advantages of the tabu search follow. Tabu search overcomes the shortcomings of simple descent method, which looks within the static neighborhood for the solutions that improve the objective, but terminates at a local optimum when no improving solution can be found. In contrast, the tabu search by redefining the neighborhood and forbidding certain moves, allows the

objective to worsen in order to leave the current neighborhood in the search for more optimal solutions. As a result, optimization via tabu search is less dependent on the initialization as the tabu search has capability of moving away from the undesired states. Finally, the distinct feature of tabu search is its use of the history of search in making strategic changes to $N(\mathbf{x})$. The set of rules behind modification of search space are called *adaptive memory* and are described in detail in the following sections. The proposed method adapts two types of adaptive memory, short-term memory and long-term memory.

4.2.1 Short term memory

The main component of tabu search is *short-term memory* which uses recent search history to modify the neighborhood of the current solution. Short-term memory is a selective memory that keeps track of solutions visited in the past to forbid revisiting them in the future. Fig. 1 describes a simple example of short-term memory mechanism on a graph, which, in this work, is the penalized association graph $\mathcal{A}^{\mathcal{P}}$.

In the proposed algorithm, the search history of the optimization process of the objective (1) relies on a sequence of swaps between two nodes, $v_a \in \mathcal{K}$ and $v_b \in \mathcal{L}$. Thus, we consider a solution \mathbf{x} to be characterized by two nodes v_a and v_b that participate in the swap. The short-term memory is implemented to keep track of nodes that have been swapped and forbid them to participate in the swap within certain span of time in the future. Thus, the result of the short-term mechanism is a modified neighborhood $\tilde{N}(\mathbf{x}_{cur})$ which is the subset of the original neighborhood $N(\mathbf{x})$.

Short-term memory is implemented via a list, called *tabu list* which keeps track of the nodes that are forbidden to participate in the swap at the current iteration. After every swap a node v_i that was swapped (there are two of them) is assigned a positive integer, s_i , randomly selected from the interval $[q, r]$ which prevents the variable to participate in swap for s_i subsequent iterations. Originally, all the values s_a are initialized to 0. These nodes which cannot participate in the swap are called *tabu variables*. Clearly, at subsequent iterations only *non-tabu* variables can be swapped.

Table 1. Parameters used in Alg. 1

p	penalty for conflicting matches. ($-4 \cdot \max \mathcal{A}$)
$q-r$	lower and upper bound of the possible tabu tenure. (2-4)
t	number of nodes in \mathcal{K} and \mathcal{L} which are considered for move in a given iteration. (5)
$endIt$	number of iterations that do not improve the objective to terminate. (1500)
sol	number of runs of the algorithm. (20)

4.2.2 Implementation details

In the proposed algorithm, at any given time we maintain pointers to three main solutions, \mathbf{x}_{cur} , the solution which indicates the point in solution space where the algorithm currently stands, \mathbf{x}_{cur}^* , the maximum solution in the current run of the tabu search and \mathbf{x}^* , the overall maximum solution of the objective (1). At every iteration, a subset of solutions given by parameter t is used for candidate moves from \mathbf{x}_{cur} .

Non-tabu solutions are computed from $\tilde{N}(\mathbf{x}_{cur})$ according to Eq.(6). Then the non-tabu solution with highest change Δ in the objective becomes the incumbent solution \mathbf{x}_{cur} (Alg. 1, line 14). Notice that the algorithm is designed in such a way that \mathbf{x}_{cur} changes after every iteration and we are never stuck in one place in the solution space. Thus, the tabu search algorithm explores the solution space in a way that the objective function value (1) may fluctuate. For instance, if all the potential moves have negative value, then the objective function will decrease. The solution \mathbf{x}_{cur}^* is updated when the new solution is larger. The proposed algorithm also incorporates the exception, called *aspiration criterion* which allows tabu move to take place. The tabu solution becomes current solution if it is strictly bigger than the maximum solution \mathbf{x}_{cur}^* (Alg. 1, line 10).

4.2.3 Long term memory

Long-term memory, in contrast to short-term memory, takes into account the extended search history and is activated when the short-term criterion fails to improve the objective function. Long-term memory maintains a list of useful but suboptimal solutions visited in the past (while using only short-term memory criteria to move between the solutions) which can be used as a new solution from which local search may proceed. The search is restarted when the solution \mathbf{x}^* is not improved for the given number of iterations (for brevity the loop not included in the Alg. 1). The rationale behind the criterion is that the current region is not promising for finding a more optimal solution and the mechanism chooses to relocate to a more promising region.

4.2.4 Implementation details

Various criteria can be adopted to make the long-term memory list. We implement long term memory as a list of “second” solutions S_{sec} [3] which consists of solutions that at every iteration landed just behind the current solution \mathbf{x}_{cur} , called the “second” solution list. Therefore, in the algorithm we also maintain pointers to a secondary solution \mathbf{x}_{sec} which, if better, replaces the worst solution in the list of secondary solutions. When the long-term termination criterion is activated, a search is restarted from the solution $\mathbf{x} \in S_{sec}$ with the highest objective. In the subsequent section, we present the experimental results of both short-term and long-term mechanism compared to the existing graph matching methods.

5. Experiments

This section presents extensive evaluation of the proposed method through three sets of experiments in both synthetic and real-world setting.

5.1. Synthetic random graph matching

The experiments perform an evaluation on the randomly synthesized graphs which simulate the practical environment where deformation noise and outliers obfuscate the underlying matching. In this experiment, we construct two graphs, \mathcal{G}_1 and \mathcal{G}_2 , each with n nodes such that $n = n_{in} + n_{out}$ where n_{in} and n_{out} denote the number of inlier and outlier nodes, respectively. First, we construct \mathcal{G}_1 such that its edge attributes \mathbf{w}_{ij} are generated from the uniform distribution $[0, 1]$. Subsequently, \mathcal{G}_2 is created by perturbing the attributes of \mathcal{G}_1 with Gaussian noise $\epsilon \sim N(0, \sigma_s^2)$. Generated in similar manner, outliers are added in \mathcal{G}_2 from the uniform distribution and then perturbed. The affinity matrix values between two potential matches v_i^1 with v_j^2 and v_i^1 with $v_{j'}^2$, is computed using the negative exponential of $\mathcal{A}_{i i': j j'} = \exp(-\|\mathbf{w}_{ij} - \mathbf{w}_{i' j'}\|/\sigma^2)$, where $\sigma^2 = 0.1$. The node attributes are all set to 0.

In the synthetic setting, we evaluate the proposed discrete tabu search algorithm in two forms. The first contains only the short-term mechanism described in section 4.2.1 while the second includes also long-term memory described in section 4.2.3. The proposed methods are evaluated along with seven state-of-the-art methods, Graduate assignment (GA) [14], Shrinking and expansion algorithm (SEA) [22], Integer projected fixed point method (IPFP) [21], Spectral matching (SM) [20], Re-weighted random walk matching (RRWM) [7], and Factorized graph matching (FGM) [32].

We evaluate the methods in four experimental settings which reflect the possible combinations of variation of the two factors: the amount of deformation noise σ and the number of outliers n_{out} : (1) varying deformation noise with no outliers, (2) varying deformation noise with some outliers, (3) varying the number of outliers with no deformation noise (4) varying the number of outliers with some deformation noise. In each setting the number of inliers n_{in} is fixed to be 20. For every setting, we generate independently 50 graph matching problems as defined in the previous paragraph and report the average accuracy and objective score. Fig. 3 presents the results. In the first and second setting (Fig. 3a and 3b), the deformation noise σ varies between 0 and 0.4 by 0.05 increments while we fix the number of outliers to 0 and 10. In the third and fourth setting (Fig. 3c and 3d), the number of outliers varies between 0 and 20 by increments of 4, while the noise levels are fixed to be $\sigma = 0$ and $\sigma = 0.1$.

Under varying condition the proposed methods perform outstandingly well, noting the better performance of tabu

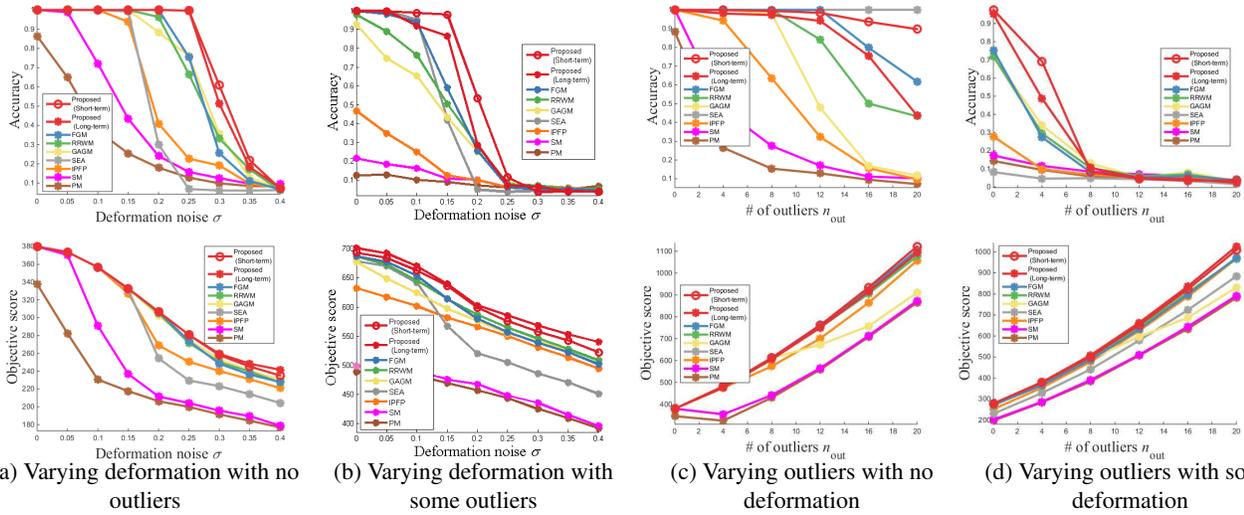


Figure 3. Accuracy and score curves are plotted for four different conditions: varying the amount of deformation noise with fixed number of outliers (a) $n_{out} = 0$ and (b) $n_{out} = 10$, and varying the number of outliers with fixed deformation noise (c) $\sigma = 0$ (d) $\sigma = 0.15$

Table 2. SNU Dataset Average Accuracy (%)

Alg	SEA	GAGM	RRWM	IPFP	Ours
Accuracy(%)	56.3	70.3	73.6	74.1	79.0
Time(s)	3.33	1.78	0.22	0.10	0.69

Table 3. Willow Object Dataset Average Accuracy (%)

Class	Car	Duck	Face	Motor bike	Wine bottle	avg
SEA	30.3	26.5	72.9	32.4	45.4	41.4
GAGM	38.6	35.4	79.4	38.3	53.9	49.1
RRWM	38.0	35.7	78.3	40.4	53.7	49.2
IPFP	37.6	36.9	80.4	40.4	56.0	50.3
Ours	39.5	36.1	80.2	44.0	57.9	51.5

search which includes only short-term memory. As the only evaluated method, it achieves 100% accuracy given high levels of noise ($\sigma = 0.2$ and $\sigma = 0.25$ with no outliers and $\sigma = 0.1$ $\sigma = 0.15$ with outliers). While varying outliers, the method slightly falls short to SEA, whose performance, however, considerably deteriorates when noise appears. The proposed method proves to be particularly robust in more practical settings where both outliers and noise are present. Given choice of parameters from Table 4.2.1 and varying $endIt$ and sol , it obtains superior solutions in the presence of noise and outliers in 1.0-4.4 sec.; FGM - 23.5, RRWM - 0.2, IPFP - 0.2, GAGM - 0.4 and SEA - 1.1 (averaged results for results in Fig. 3b,d).

5.2. Real image feature correspondence

In this section, we evaluate the proposed method for feature correspondence task on two datasets: SNU dataset [7] and Willow Object Class dataset [5]. RRWM, IPFP,

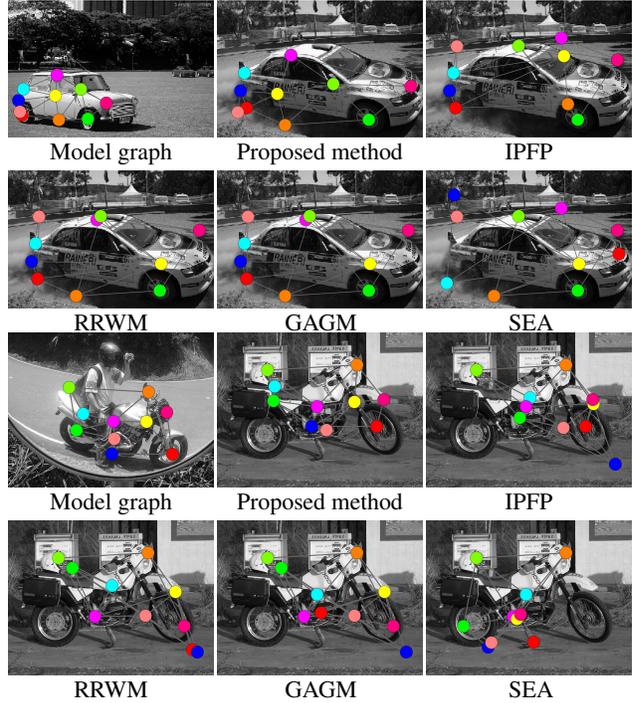


Figure 4. Example results of the real image matching on Willow Object dataset. Keypoints are distinguished by different colors in the model image and the matched locations are depicted for each algorithm

GAGM, and SEA are compared with the proposed method³.

SNU dataset consists of 30 pairs of images most of which are collected from Caltech-101 [10] and MSRC [1] dataset. Each pair of images have similar viewpoints with large

³FGM is not compared because it cannot be applied in the experimental setting of [7], which uses initial candidate matches.

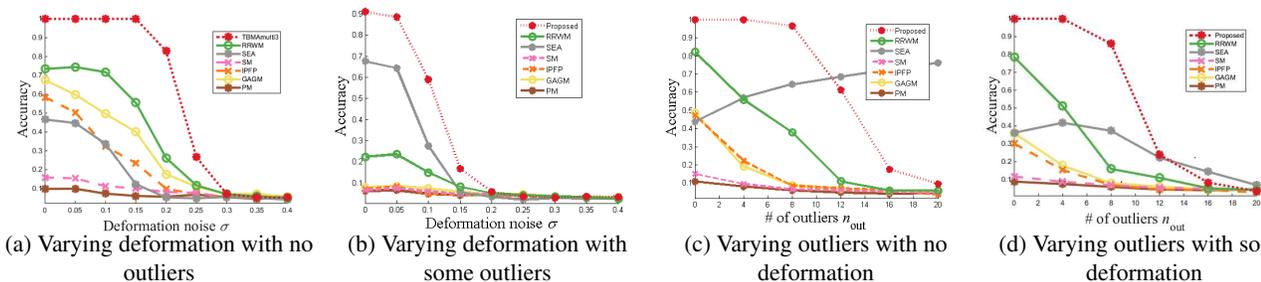


Figure 5. Accuracy and score curves are plotted for four different conditions: varying the amount of deformation noise with fixed number of outliers (a) $n_{out} = 0$ and (b) $n_{out} = 10$, and varying the number of outliers with fixed deformation noise (c) $\sigma = 0$ (d) $\sigma = 0.1$.

intra-class variation. In addition to the original experimental setting [7], which did not use unary score, WHO [16] and their inner product are used as feature descriptor and unary score to enhance the overall performance. The average accuracy over 10 experiments is shown in Table 2. The proposed algorithm outperforms all the other methods.

Willow dataset consists of 5 classes, whose images are collected from Caltech-256 [15] and PASCAL VOC2007 dataset [9] with 10 manual keypoint annotation for each image. Each class contains 40 to 108 images taken from various viewpoints with clutter, making feature correspondence extremely challenging. Therefore, we restricted the graph constructed from one side image to have only keypoints without outliers. WHO [16] and HARG [5] are used as node and edge descriptors, respectively. The average accuracy over 100 random pairs is shown in Table 3. Classes with low intra-class variation (face and winebottle) show high accuracy overall, while the performance of the classes with large intra-class variation (car, duck, and motorbike) is relatively low. The proposed algorithm outperforms the other algorithms in car, motorbike and winebottle classes, while is comparable in face and duck classes. Some qualitative example results are shown in Fig. 4. The average running times are following: proposed - 0.93s, RRWM - 0.04s, IPFP - 0.03s, GAGM - 0.08s, SEA - 0.49s.

5.3. Repeated Structure Matching

In this set of experiments, we present particular suitability of tabu search method to multiple graph matching, attempting to discover repeated structures or multiple instances of an object. The advantage is due to the fact that the method produces multiple solutions (Alg. 1, line 2-3), each of which is a set of matches between two regions in two graphs. The multiple solutions may or may not correspond to the same regions in the original graphs. This setting makes graph matching more useful in practical applications. E.g., in feature correspondence, it overcomes the conventional restriction to allow one object per image.

In this set of experiments, we simulate the multiple object environment. We construct \mathcal{G}_1^{mult} and \mathcal{G}_2^{mult} according to the procedure in Section (5.1) where $|\mathcal{G}_1^{mult}| = n$ and

$|\mathcal{G}_2^{mult}| = 2|\mathcal{G}_1^{mult}| = 2n$ in such a way that \mathcal{G}_1^{mult} consists of two independently perturbed copies of \mathcal{G}_1^{mult} . The affinity matrix \mathbf{A}_{mult} has size $2n^2 \times 2n^2$. We subsequently perform tabu search optimization on the penalized association graph \mathcal{A}_{mult}^P obtained from \mathbf{A}_{mult} .

We compare our method to SEA which also produces multiple solutions and the remaining methods evaluated in Section (5.1) (with the exception of FGM whose running time is too large for this set of experiments) adapted to multiple matching setting by means of the following sequential matching procedure. We perform matching m times (where $m = 2$ in our case) after each stage removing matched nodes and performing the subsequent round on the remaining nodes. The methods are evaluated in the same settings as in Section (5.1) where we vary deformation noise and the number of outliers. The results are presented in Fig. 5. The proposed method outperforms the existing methods by large margin when noise is varied. The improving accuracy of SEA with the increasing number of outliers is noteworthy. The proposed method again performs very robustly in a mixed environment with both noise and outliers present.

6. Conclusion

In this work, we propose graph matching algorithm which adapts tabu search to search discrete solution space directly and effectively. First, we build the framework based on penalized association graph to move between its subgraphs by forbidding certain solutions and encouraging others. As a result unlike any of the existing works, this method works both in discrete space (by itself discrete graph matching optimization is rare) and incorporates one-to-one constraint softly into the optimization process with no post-processing step. The proposed method is suitable for multiple graph matching as it produces different solutions that potentially correspond to repeated instances of an object. The algorithm proves to be outstandingly robust achieving superior results to the existing algorithms (in some cases over 40 percentage points, which given a long history of graph matching research, is notable) in the extensive combination of experiments where noise and outliers are present.

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