Progress-Aware Online Action Segmentation for Egocentric Procedural Task Videos

Yuhan Shen, Ehsan Elhamifar

Northeastern University

MCADLAB

CVPR JUNE 17-21, 2024 SEATTLE, WA

Overview

What is Online Action Segmentation?

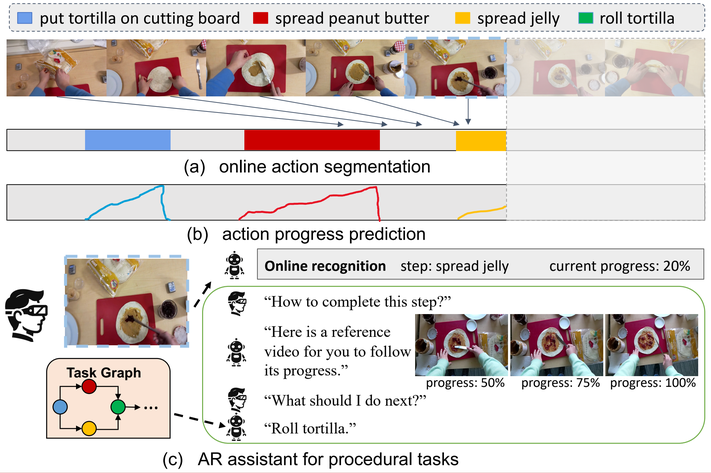
- Recognize and segment actions as frames arrive in real time
- Make predictions without future frame information

Why Online Action Segmentation and Egocentric Videos?

- AR/VR task assistants provide guidance for procedural tasks
- Enable real-time user assistance

How Online Action Segmentation?

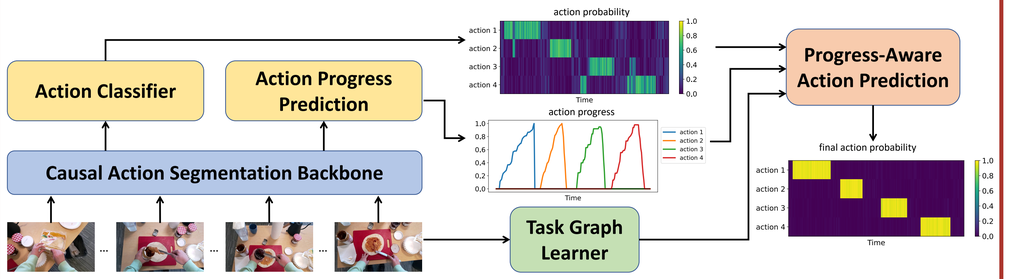
- Remove access to future frames during training
- Estimate action progress and leverage task graphs



Contributions

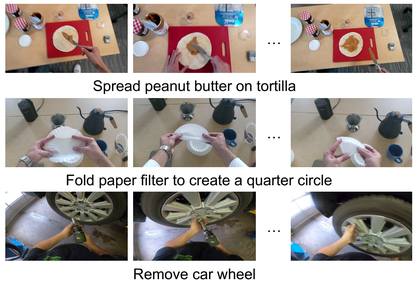
- **PR**ogress-aware **O**nline **T**emporal **A**ction **S**egmentation (**ProTAS**)
  - Address **online action segmentation** in egocentric procedural task videos
- Leverage **task graph learner** for online action segmentation
- Achieve significant improvements on **three datasets**

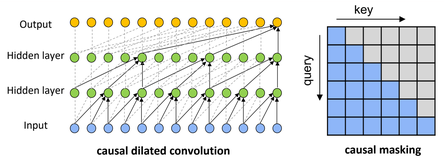
PRogress-aware Online Temporal Action Segmentation (ProTAS)



Causal Action Segmentation (CAS)

- Modify existing architectures (TCN-based and Transformer-based) to make them causal
- CE and smoothing loss: $\mathcal{L}_{\text{cls}} + \lambda_{\text{smo}}\mathcal{L}_{\text{smo}}$





Action Progress Prediction (APP)

- Dynamically estimate progress of ongoing actions via a GRU layer to refine CAS predictions
- Target linear progress: $p^*_{t,k} = \dfrac{t - t_s}{t_e - t_s} \in [0,1]$
- Progress prediction loss:

$$\mathcal{L}_{\text{prog}} = \frac{1}{TK}\sum_{t,k}\left(p_{t,k} - p^*_{t,k}\right)^2$$

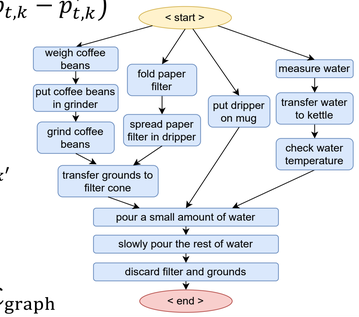
Task Graph (TG)

- Calculate penalty for an action using the completion state of its predecessors and successors:

$$\alpha^p_{t,k} = \sum_{k' \in Predecessor(k)}\left(1 - c_{t,k'}\right),\ \alpha^s_{t,k} = \sum_{k' \in Sucessor(k)} c_{t,k'}$$

- Encourage predictions aligned with task graph:

$$\mathcal{L}_{\text{graph}} = \frac{1}{TK}\sum_{t,k}\left(\alpha^p_{t,k} + \alpha^s_{t,k}\right) \cdot y_{t,k}$$



Training Loss: $\mathcal{L} = \mathcal{L}_{\text{cls}} + \lambda_{\text{smo}}\mathcal{L}_{\text{smo}} + \lambda_{\text{prog}}\mathcal{L}_{\text{prog}} + \lambda_{\text{graph}}\mathcal{L}_{\text{graph}}$

Experimental Results

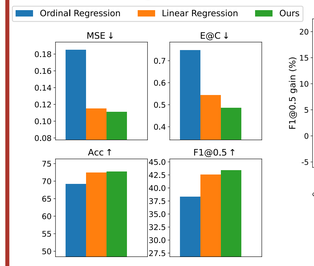
Results on three datasets, MSTCN and ASFormer as backbones

Method	Inference	GTEA			EgoProceL			EgoPER		
		Acc	Edit	F1@0.5	Acc	Edit	F1@0.5	Acc	Edit	F1@0.5
Use MSTCN as backbone										
Base	Offline	76.3	79.0	69.8	69.2	56.9	45.9	83.0	85.9	77.3
Base	Online	47.0	58.8	38.7	18.3	19.9	8.8	20.2	31.0	11.9
CAS	Online	74.0	64.4	56.0	64.5	42.5	33.0	71.8	48.9	39.4
CAS+APP	Online	**76.0**	67.0	57.9	66.3	47.1	35.2	**72.7**	55.0	43.4
CAS+APP+TG	Online	74.3	**69.2**	**59.7**	**67.8**	**48.8**	**35.7**	70.2	**60.7**	**46.3**
Use ASFormer as backbone										
Base	Offline	83.4	84.6	78.9	69.5	59.8	48.8	81.8	88.8	79.9
Base	Online	36.2	48.2	28.3	13.2	17.6	5.4	19.8	24.3	8.8
CAS	Online	77.2	73.3	65.0	64.8	48.1	35.4	70.3	60.6	44.7
CAS+APP	Online	**77.3**	74.0	65.4	66.7	50.7	36.1	70.6	61.2	46.9
CAS+APP+TG	Online	77.0	**74.1**	**66.1**	**68.5**	**52.1**	**36.8**	**71.7**	**62.4**	**48.6**

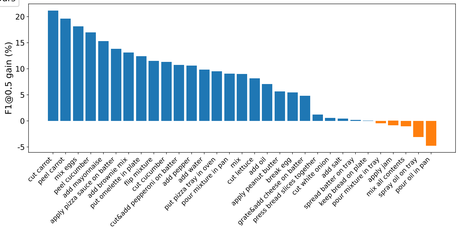
Comparison of different ways of constructing task graph

Task Graph	GTEA			EgoProceL			EgoPER		
	Acc	Edit	F1@0.5	Acc	Edit	F1@0.5	Acc	Edit	F1@0.5
transcript	74.3	69.2	59.7	67.8	48.8	**35.7**	70.2	60.7	46.3
manual	—	—	—	—	—	—	70.4	61.0	46.5
learnable	**74.5**	**69.3**	**60.2**	**68.0**	**48.9**	34.8	**70.6**	**61.4**	**47.1**

Model designs for APP



Action-wise performance gain



Qualitative results