

Unsupervised Image Segmentation with Spatial Triplet Markov Trees

Hugo Gangloff^{1,2,3} (hugo_gangloff@telecom-sudparis.eu),
Jean-Baptiste Courbot⁴, Emmanuel Monfrini¹, Christophe Collet²

¹Samovar, Télécom SudParis, Institut Polytechnique de Paris, Palaiseau, France

²ICube, Université de Strasbourg, CNRS UMR 7357, Strasbourg, France

³GEPROVAS, Strasbourg, France

⁴IRIMAS UR 7499, Université de Haute-Alsace, Mulhouse, France

International Conference on Acoustics, Speech and Signal Processing 2021

June 06-11, 2021 - Toronto, Canada (virtual conference)

Outline

- ① **Introduction**
- ② Pairwise and Triplet Markov Models
- ③ Spatial Triplet Markov Trees
- ④ Unsupervised image segmentation
- ⑤ Conclusion

Probabilistic graphical models

- Very active research topic

Probabilistic graphical models

- Very active research topic
- Often used for **unsupervised** problems

Probabilistic graphical models

- Very active research topic
- Often used for **unsupervised problems**
- **Sparse models** → fast and exact computations → hugeness some image data (e.g. satellite images)

Probabilistic graphical models

- Very active research topic
- Often used for **unsupervised problems**
- **Sparse models** → fast and exact computations → hugeness some image data (e.g. satellite images)
- **Dense models** → approximating methods → model very complex phenomena (e.g. artifacts on medical images)

Probabilistic graphical models

- Very **active research topic**
- Often used for **unsupervised problems**
- **Sparse models** → fast and exact computations → hugeness some image data (e.g. satellite images)
- **Dense models** → approximating methods → model very complex phenomena (e.g. artifacts on medical images)
- Combined with deep learning → many **top current results** in image processing (e.g. Variational Autoencoders)

Probabilistic graphical models: probabilistic setting

Notations:

- Vectors: \mathbf{x} / Scalars: x

Probabilistic graphical models: probabilistic setting

Notations:

- Vectors: \mathbf{x} / Scalars: x
- Random variables: X ; their realizations: x

Probabilistic graphical models: probabilistic setting

Notations:

- Vectors: \mathbf{x} / Scalars: x
- Random variables: X ; their realizations: x
- For a discrete random variable $X \rightarrow p(\{X = x\})$ is denoted $p(X = x)$, or $p(x)$

Probabilistic graphical models: probabilistic setting

Notations:

- Vectors: \mathbf{x} / Scalars: x
- Random variables: X ; their realizations: x
- For a discrete random variable $X \rightarrow p(\{X = x\})$ is denoted $p(X = x)$, or $p(x)$
- For a continuous random variable Y , $p(y)$ is the density function of Y

Probabilistic graphical models: probabilistic setting

Notations:

- Vectors: \mathbf{x} / Scalars: x
- Random variables: X ; their realizations: x
- For a discrete random variable $X \rightarrow p(\{X = x\})$ is denoted $p(X = x)$, or $p(x)$
- For a continuous random variable Y , $p(y)$ is the density function of Y

Context of **Bayesian segmentation**:

Probabilistic graphical models: probabilistic setting

Notations:

- Vectors: \mathbf{x} / Scalars: x
- Random variables: X ; their realizations: x
- For a discrete random variable $X \rightarrow p(\{X = x\})$ is denoted $p(X = x)$, or $p(x)$
- For a continuous random variable Y , $p(y)$ is the density function of Y

Context of **Bayesian segmentation**:

- Segment an image with values in \mathbb{R} into K classes $\{\omega_k\}_{k \in \{1, \dots, K\}} \triangleq \Omega$

Probabilistic graphical models: probabilistic setting

Notations:

- Vectors: \mathbf{x} / Scalars: x
- Random variables: X ; their realizations: x
- For a discrete random variable $X \rightarrow p(\{X = x\})$ is denoted $p(X = x)$, or $p(x)$
- For a continuous random variable Y , $p(y)$ is the density function of Y

Context of **Bayesian segmentation**:

- Segment an image with values in \mathbb{R} into K classes $\{\omega_k\}_{k \in \{1, \dots, K\}} \triangleq \Omega$
- $\mathbf{X} = (X_s)_{s \in \mathcal{S}}$ with value in $\Omega^{|\mathcal{S}|} \rightarrow$ the **hidden variables**.

Probabilistic graphical models: probabilistic setting

Notations:

- Vectors: \mathbf{x} / Scalars: x
- Random variables: X ; their realizations: x
- For a discrete random variable $X \rightarrow p(\{X = x\})$ is denoted $p(X = x)$, or $p(x)$
- For a continuous random variable Y , $p(y)$ is the density function of Y

Context of **Bayesian segmentation**:

- Segment an image with values in \mathbb{R} into K classes $\{\omega_k\}_{k \in \{1, \dots, K\}} \triangleq \Omega$
- $\mathbf{X} = (X_s)_{s \in \mathcal{S}}$ with value in $\Omega^{|\mathcal{S}|} \rightarrow$ the **hidden variables**.
- $\mathbf{Y} = (Y_s)_{s \in \mathcal{S}}$ with value in $\mathbb{R}^{|\mathcal{S}|} \rightarrow$ the **observed variables**.

Probabilistic graphical models: probabilistic setting

Notations:

- Vectors: \mathbf{x} / Scalars: x
- Random variables: X ; their realizations: x
- For a discrete random variable $X \rightarrow p(\{X = x\})$ is denoted $p(X = x)$, or $p(x)$
- For a continuous random variable Y , $p(y)$ is the density function of Y

Context of **Bayesian segmentation**:

- Segment an image with values in \mathbb{R} into K classes $\{\omega_k\}_{k \in \{1, \dots, K\}} \triangleq \Omega$
- $\mathbf{X} = (X_s)_{s \in \mathcal{S}}$ with value in $\Omega^{|\mathcal{S}|} \rightarrow$ the **hidden variables**.
- $\mathbf{Y} = (Y_s)_{s \in \mathcal{S}}$ with value in $\mathbb{R}^{|\mathcal{S}|} \rightarrow$ the **observed variables**.
- Segmentation criteria: \rightarrow Maximum A Posteriori (MAP)
 \rightarrow Maximum Posterior Mode (MPM)

Hidden Markov Models (HMM)

- Hidden Markov Models (HMM) (Baum and Petrie 1966) are the most popular type of probabilistic models

Hidden Markov Models (HMM)

- Hidden Markov Models (HMM) (Baum and Petrie 1966) are the most popular type of probabilistic models
- Applications in many contexts: image segmentation, speech processing, stock index forecasting, gene prediction, ...

Hidden Markov Models (HMM)

- Hidden Markov Models (HMM) (Baum and Petrie 1966) are the most popular type of probabilistic models
- Applications in many contexts: image segmentation, speech processing, stock index forecasting, gene prediction, ...
- Different models belong to the HMM family:

Hidden Markov Models (HMM)

- Hidden Markov Models (HMM) (Baum and Petrie 1966) are the most popular type of probabilistic models
- Applications in many contexts: image segmentation, speech processing, stock index forecasting, gene prediction, ...
- Different models belong to the HMM family:
 - Hidden and observed random variables

Hidden Markov Models (HMM)

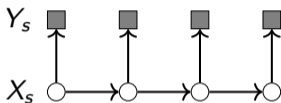
- Hidden Markov Models (HMM) (Baum and Petrie 1966) are the most popular type of probabilistic models
- Applications in many contexts: image segmentation, speech processing, stock index forecasting, gene prediction, ...
- Different models belong to the HMM family:
 - Hidden and observed random variables
 - Generative models $\rightarrow p(\mathbf{x}, \mathbf{y})$ is modeled

Hidden Markov Models (HMM)

- Hidden Markov Models (HMM) (Baum and Petrie 1966) are the most popular type of probabilistic models
- Applications in many contexts: image segmentation, speech processing, stock index forecasting, gene prediction, ...
- Different models belong to the HMM family:
 - Hidden and observed random variables
 - Generative models $\rightarrow p(\mathbf{x}, \mathbf{y})$ is modeled
 - \mathbf{X} is a Markovian process and $p(\mathbf{y}|\mathbf{x}) = \prod_{s \in \mathcal{S}} p(y_s|x_s)$

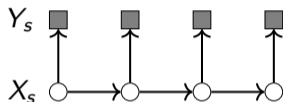
Hidden Markov Models: classical models

Hidden Markov Chain (HMC) (Baum, Petrie, et al. 1970)



Hidden Markov Models: classical models

Hidden Markov Chain (HMC) (Baum, Petrie, et al. 1970)

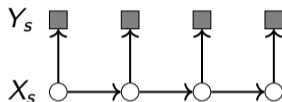


$p(\mathbf{x})$ is a Markov chain

$$p(\mathbf{x}, \mathbf{y}) = p(x_r)p(y_r|x_r) \prod_{s \in \bar{\mathcal{S}}} p(x_s|x_{s-})p(y_s|x_s)$$

Hidden Markov Models: classical models

Hidden Markov Chain (HMC) (Baum, Petrie, et al. 1970)

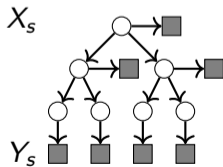


$p(\mathbf{x})$ is a Markov chain

$$p(\mathbf{x}, \mathbf{y}) = p(x_r)p(y_r|x_r) \prod_{s \in \bar{\mathcal{S}}} p(x_s|x_{s-})p(y_s|x_s)$$

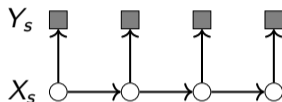
Hidden Markov Tree (HMT) (Laferté et al. 2000)

→ a generalization of HMCs



Hidden Markov Models: classical models

Hidden Markov Chain (HMC) (Baum, Petrie, et al. 1970)

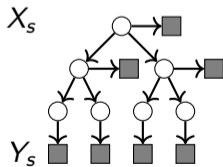


$p(\mathbf{x})$ is a Markov chain

$$p(\mathbf{x}, \mathbf{y}) = p(x_r)p(y_r|x_r) \prod_{s \in \bar{\mathcal{S}}} p(x_s|x_{s-})p(y_s|x_s)$$

Hidden Markov Tree (HMT) (Laferté et al. 2000)

→ a generalization of HMCs

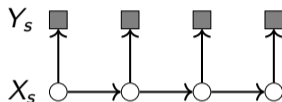


$p(\mathbf{x})$ is a Markov tree

$p(\mathbf{x}, \mathbf{y}) \rightarrow$ same as an HMC

Hidden Markov Models: classical models

Hidden Markov Chain (HMC) (Baum, Petrie, et al. 1970)

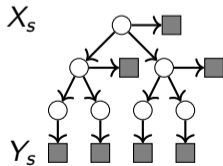


$p(\mathbf{x})$ is a Markov chain

$$p(\mathbf{x}, \mathbf{y}) = p(x_r)p(y_r|x_r) \prod_{s \in \mathcal{S}} p(x_s|x_{s-})p(y_s|x_s)$$

Hidden Markov Tree (HMT) (Laferté et al. 2000)

→ a generalization of HMCs



$p(\mathbf{x})$ is a Markov tree

$p(\mathbf{x}, \mathbf{y}) \rightarrow$ same as an HMC

inference → **direct, exact computations** with Forward-Backward based algorithms

Outline

- ① Introduction
- ② Pairwise and Triplet Markov Models**
- ③ Spatial Triplet Markov Trees
- ④ Unsupervised image segmentation
- ⑤ Conclusion

Motivations

How could we introduce richer direct dependencies in HMMs ?

Motivations

How could we introduce richer direct dependencies in HMMs ?

→ Strong restrictions classically made in HMMs:

Motivations

How could we introduce richer direct dependencies in HMMs ?

- Strong restrictions classically made in HMMs:
 - X is constrained to be a Markov chain / tree

Motivations

How could we introduce richer direct dependencies in HMMs ?

→ Strong restrictions classically made in HMMs:

- \mathbf{X} is constrained to be a Markov chain / tree
- The independent noise assumption $p(\mathbf{y}|\mathbf{x}) = \prod_{s \in \mathcal{S}} p(y_s|x_s)$

Motivations

How could we introduce richer direct dependencies in HMMs ?

→ Strong restrictions classically made in HMMs:

- \mathbf{X} is constrained to be a Markov chain / tree
- The independent noise assumption $p(\mathbf{y}|\mathbf{x}) = \prod_{s \in \mathcal{S}} p(y_s|x_s)$
- More complex noise models: special cases of pairwise and triplet models

Motivations

How could we introduce richer direct dependencies in HMMs ?

→ Strong restrictions classically made in HMMs:

- \mathbf{X} is constrained to be a Markov chain / tree
- The independent noise assumption $p(\mathbf{y}|\mathbf{x}) = \prod_{s \in \mathcal{S}} p(y_s|x_s)$
- More complex noise models: special cases of pairwise and triplet models

→ Pairwise and Triplet (Hidden) Markov Models are richer models:

Motivations

How could we introduce richer direct dependencies in HMMs ?

- Strong restrictions classically made in HMMs:
 - \mathbf{X} is constrained to be a Markov chain / tree
 - The independent noise assumption $p(\mathbf{y}|\mathbf{x}) = \prod_{s \in \mathcal{S}} p(y_s|x_s)$
 - More complex noise models: special cases of pairwise and triplet models

- Pairwise and Triplet (Hidden) Markov Models are richer models:
 - Strict generalizations of HMMs (Gorynin et al. 2018)

Motivations

How could we introduce richer direct dependencies in HMMs ?

→ Strong restrictions classically made in HMMs:

- \mathbf{X} is constrained to be a Markov chain / tree
- The independent noise assumption $p(\mathbf{y}|\mathbf{x}) = \prod_{s \in \mathcal{S}} p(y_s|x_s)$
- More complex noise models: special cases of pairwise and triplet models

→ Pairwise and Triplet (Hidden) Markov Models are richer models:

- Strict generalizations of HMMs (Gorynin et al. 2018)
- Conservation of the good properties of inference

Motivations

How could we introduce richer direct dependencies in HMMs ?

→ Strong restrictions classically made in HMMs:

- \mathbf{X} is constrained to be a Markov chain / tree
- The independent noise assumption $p(\mathbf{y}|\mathbf{x}) = \prod_{s \in \mathcal{S}} p(y_s|x_s)$
- More complex noise models: special cases of pairwise and triplet models

→ Pairwise and Triplet (Hidden) Markov Models are richer models:

- Strict generalizations of HMMs (Gorynin et al. 2018)
- Conservation of the good properties of inference
- Naturally encompass extended HMMs models from the literature

Motivations

How could we introduce richer direct dependencies in HMMs ?

→ Strong restrictions classically made in HMMs:

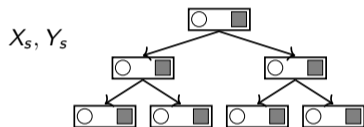
- \mathbf{X} is constrained to be a Markov chain / tree
- The independent noise assumption $p(\mathbf{y}|\mathbf{x}) = \prod_{s \in \mathcal{S}} p(y_s|x_s)$
- More complex noise models: special cases of pairwise and triplet models

→ Pairwise and Triplet (Hidden) Markov Models are richer models:

- Strict generalizations of HMMs (Gorynin et al. 2018)
- Conservation of the good properties of inference
- Naturally encompass extended HMMs models from the literature
- Triplet models integrate **auxiliary random variables** → link with deep learning models

Pairwise and triplet assumptions

Pairwise Markov Tree (Peczynski 2002)

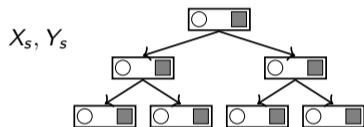


$p(\mathbf{x}, \mathbf{y})$ is a Markov tree

$$p(\mathbf{x}, \mathbf{y}) = p(x_r, y_r) \prod_{s \in \bar{S}} p(x_s, y_s | x_{s-}, y_{s-})$$

Pairwise and triplet assumptions

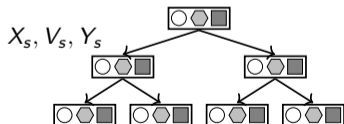
Pairwise Markov Tree (Pieczyński 2002)



$p(\mathbf{x}, \mathbf{y})$ is a Markov tree

$$p(\mathbf{x}, \mathbf{y}) = p(x_r, y_r) \prod_{s \in \bar{S}} p(x_s, y_s | x_{s-}, y_{s-})$$

Triplet Markov Tree (TMT) (Courbot et al. 2018)



$p(\mathbf{x}, \mathbf{v}, \mathbf{y})$ is a Markov tree

$$p(\mathbf{x}, \mathbf{v}, \mathbf{y}) = p(x_r, v_r, y_r) \prod_{s \in \bar{S}} p(x_s, v_s, y_s | x_{s-}, v_{s-}, y_{s-})$$

Triplet assumptions

- Neither $p(\mathbf{x})$, $p(\mathbf{y})$, $p(\mathbf{v})$, $p(\mathbf{x}, \mathbf{y})$, $p(\mathbf{y}, \mathbf{v})$, nor $p(\mathbf{x}, \mathbf{v})$ are necessarily Markovian distributions

Triplet assumptions

- Neither $p(\mathbf{x})$, $p(\mathbf{y})$, $p(\mathbf{v})$, $p(\mathbf{x}, \mathbf{y})$, $p(\mathbf{y}, \mathbf{v})$, nor $p(\mathbf{x}, \mathbf{v})$ are necessarily Markovian distributions
- But $p(\mathbf{x}, \mathbf{v}|\mathbf{y})$ (and the others...) are Markovian distributions
 - Inference can be done as in classical HMMs
 - Original hidden states:

$$p(\mathbf{x}|\mathbf{y}) = \sum_{\mathbf{v}} p(\mathbf{x}, \mathbf{v}|\mathbf{y})$$

Triplet assumptions

- Neither $p(\mathbf{x})$, $p(\mathbf{y})$, $p(\mathbf{v})$, $p(\mathbf{x}, \mathbf{y})$, $p(\mathbf{y}, \mathbf{v})$, nor $p(\mathbf{x}, \mathbf{v})$ are necessarily Markovian distributions
- But $p(\mathbf{x}, \mathbf{v}|\mathbf{y})$ (and the others...) are Markovian distributions
 - Inference can be done as in classical HMMs
 - Original hidden states:

$$p(\mathbf{x}|\mathbf{y}) = \sum_{\mathbf{v}} p(\mathbf{x}, \mathbf{v}|\mathbf{y})$$

We now present the Spatial Triplet Markov Tree model:

- It takes advantage of the increased modeling possibilities
- It enhances the spatial correlations between random variables

Outline

- ① Introduction
- ② Pairwise and Triplet Markov Models
- ③ Spatial Triplet Markov Trees**
- ④ Unsupervised image segmentation
- ⑤ Conclusion

Spatial Triplet Markov Trees (STMTs)

Distribution of STMTs (Gangloff et al. 2020) (this paper):

$$p(\mathbf{x}, \mathbf{v}, \mathbf{y}) = p(x_r, \mathbf{v}_r, y_r) \prod_{s \in \bar{\mathcal{S}}} p(x_s, \mathbf{v}_s, y_s | x_{s^-}, \mathbf{v}_{s^-}, y_{s^-})$$

Spatial Triplet Markov Trees (STMTs)

Distribution of STMTs (Gangloff et al. 2020) (this paper):

$$p(\mathbf{x}, \mathbf{v}, \mathbf{y}) = p(x_r, \mathbf{v}_r, y_r) \prod_{s \in \bar{\mathcal{S}}} p(x_s, \mathbf{v}_s, y_s | x_{s^-}, \mathbf{v}_{s^-}, y_{s^-})$$

- Special design of \mathbf{V} to improve spatial correlations in the classical HMT model.

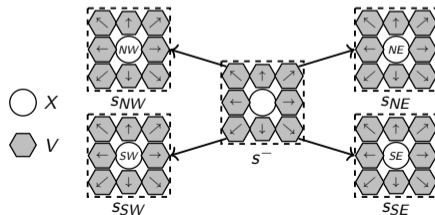
$$\forall s \in \mathcal{S} : \mathbf{V}_s = (V^{\leftarrow}, V^{\swarrow}, V^{\uparrow}, V^{\nearrow}, V^{\rightarrow}, V^{\searrow}, V^{\downarrow}, V^{\swarrow})$$

Spatial Triplet Markov Trees (STMTs)

Distribution of STMTs (Gangloff et al. 2020) (this paper):

$$p(\mathbf{x}, \mathbf{v}, \mathbf{y}) = p(x_r, \mathbf{v}_r, y_r) \prod_{s \in \bar{\mathcal{S}}} p(x_s, \mathbf{v}_s, y_s | x_{s^-}, \mathbf{v}_{s^-}, y_{s^-})$$

- Special design of \mathbf{V} to improve spatial correlations in the classical HMT model.
 $\forall s \in \mathcal{S} : \mathbf{V}_s = (V^{\leftarrow}, V^{\nwarrow}, V^{\uparrow}, V^{\nearrow}, V^{\rightarrow}, V^{\searrow}, V^{\downarrow}, V^{\swarrow})$
- Quadrees: each site s^- has four sons ($s^{NW}, s^{NE}, s^{SE}, s^{SW}$) (except for last layer):

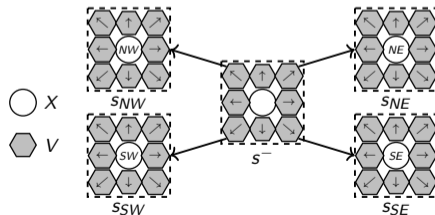


Spatial Triplet Markov Trees (STMTs)

Distribution of STMTs (Gangloff et al. 2020) (this paper):

$$p(\mathbf{x}, \mathbf{v}, \mathbf{y}) = p(x_r, \mathbf{v}_r, y_r) \prod_{s \in \bar{\mathcal{S}}} p(x_s, \mathbf{v}_s, y_s | x_{s^-}, \mathbf{v}_{s^-}, y_{s^-})$$

- Special design of \mathbf{V} to improve spatial correlations in the classical HMT model.
 $\forall s \in \mathcal{S} : \mathbf{V}_s = (V^{\leftarrow}, V^{\swarrow}, V^{\uparrow}, V^{\nearrow}, V^{\rightarrow}, V^{\searrow}, V^{\downarrow}, V^{\swarrow})$
- Quadtrees: each site s^- has four sons ($s^{NW}, s^{NE}, s^{SE}, s^{SW}$) (except for last layer):



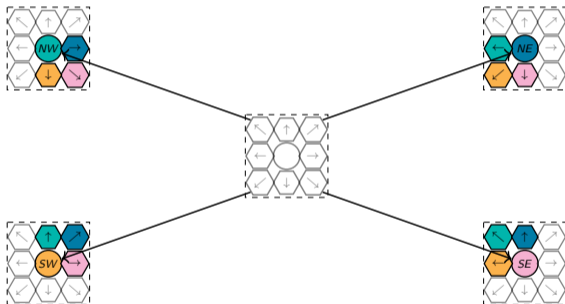
- We consider only observations Y_s at the finer resolution.

Designing the auxiliary process in STMTs



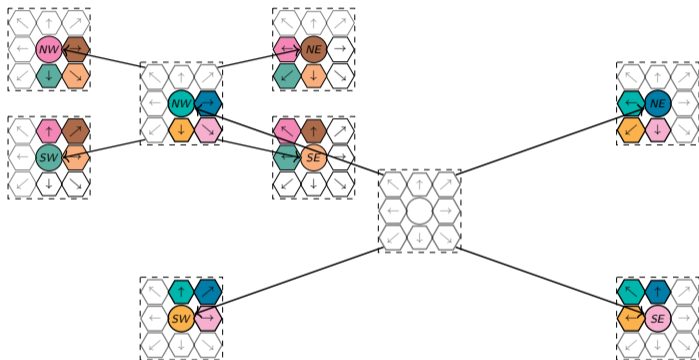
Propagation of spatial information: the same color indicates the same probability law

Designing the auxiliary process in STMTs



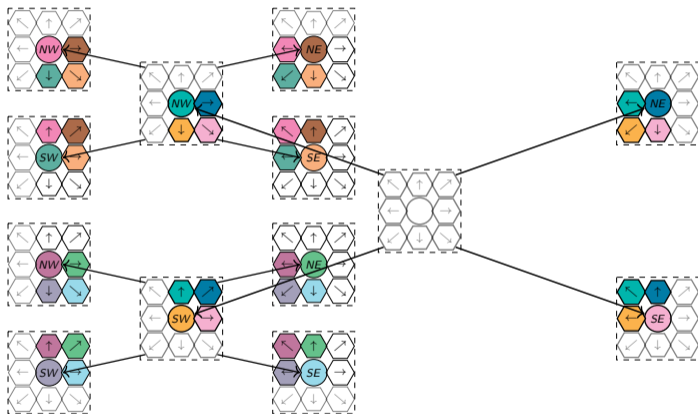
Propagation of spatial information: the same color indicates the same probability law

Designing the auxiliary process in STMTs



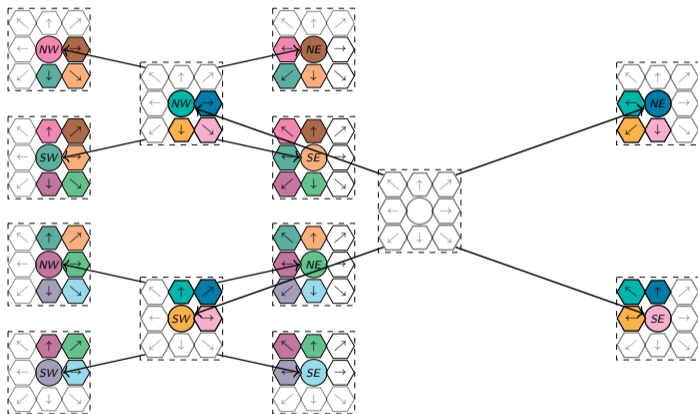
Propagation of spatial information: the same color indicates the same probability law

Designing the auxiliary process in STMTs



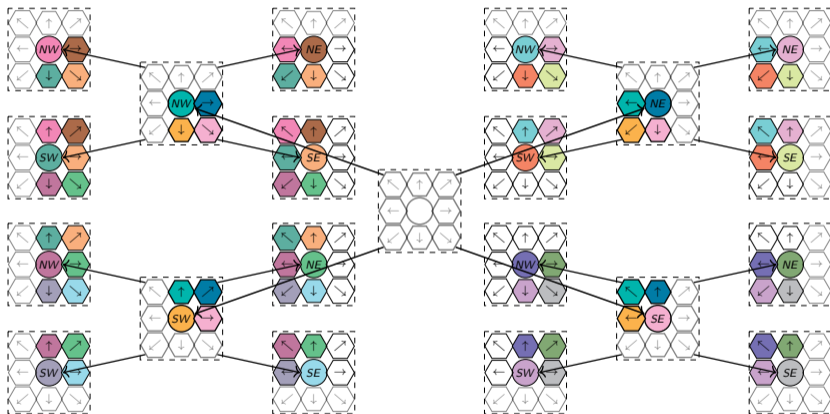
Propagation of spatial information: the same color indicates the same probability law

Designing the auxiliary process in STMTs



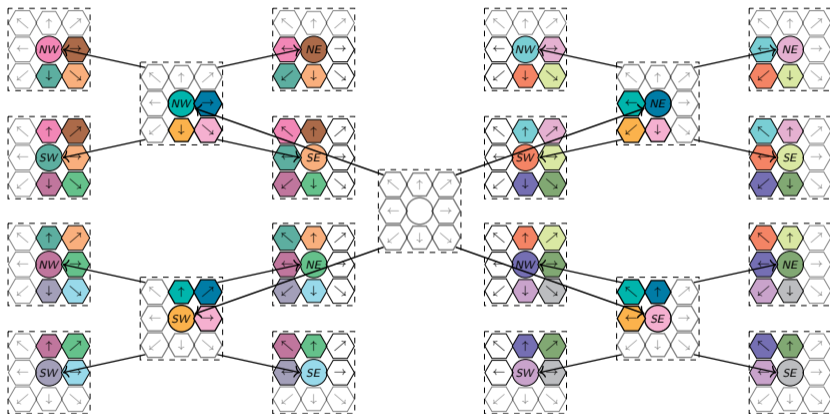
Propagation of spatial information: the same color indicates the same probability law

Designing the auxiliary process in STMTs



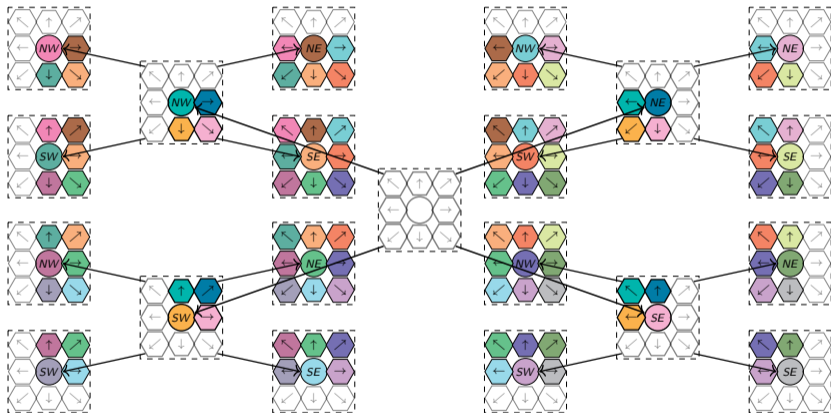
Propagation of spatial information: the same color indicates the same probability law

Designing the auxiliary process in STMTs



Propagation of spatial information: the same color indicates the same probability law

Designing the auxiliary process in STMTs



Propagation of spatial information: the same color indicates the same probability law

STMTs: numerical applications

- Ising-like transitions to propagate spatial homogeneity:

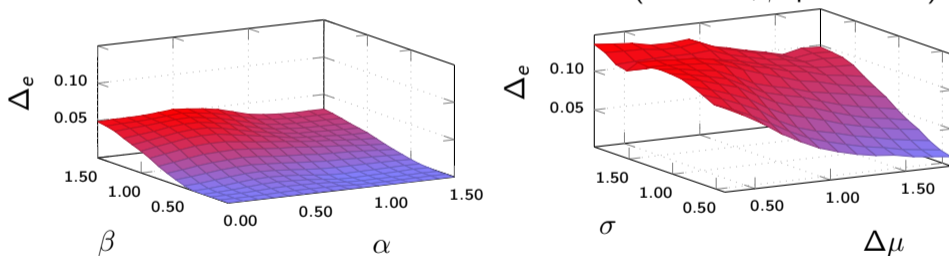
$$p(x_s | x_{s^-}, \mathbf{v}_{s^-}) = \frac{1}{Z} \exp \left(\alpha \delta_{x_s}^{x_{s^-}} + \sum_{\mathbf{v}_{s^-} \in \mathbf{V}_{s^-}} \beta \delta_{x_s}^{\mathbf{v}_{s^-}} \right), \text{ with } (\alpha, \beta) \in \mathbb{R}_+^2.$$

STMTs: numerical applications

- Ising-like transitions to propagate spatial homogeneity:

$$p(x_s | x_{s^-}, \mathbf{v}_{s^-}) = \frac{1}{Z} \exp \left(\alpha \delta_{x_s}^{x_{s^-}} + \sum_{\mathbf{v}_{s^-} \in \mathbf{V}_{s^-}} \beta \delta_{x_s}^{\mathbf{v}_{s^-}} \right), \text{ with } (\alpha, \beta) \in \mathbb{R}_+^2.$$

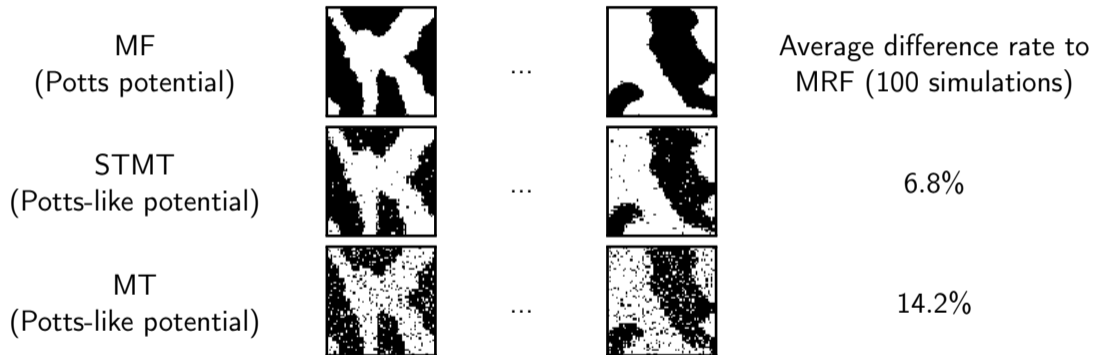
- Simulate STMTs and restore with STMTs and HMTs (known α, β parameters)



With $\Delta_e = err_{HMT} - err_{STMT}$: relative error rate

→ For all model parameters and noise levels STMT performs better than HMT

Clamped sampling experiment



Clamped samplings of the original X process (last layer only)

→ STMTs seem to capture the best the spatial context created by Markov Fields (MFs)

Outline

- ① Introduction
- ② Pairwise and Triplet Markov Models
- ③ Spatial Triplet Markov Trees
- ④ Unsupervised image segmentation**
- ⑤ Conclusion

Unsupervised parameter estimation

Case of independent Gaussian observations

We introduce Linear Least Square (LLS) estimator for α^t and β^t

$$[\alpha^t, \beta^t] = (B^T B)^{-1} B^T A$$

where the generic term of vector A is, $\forall s \in \mathcal{S}^L, \forall (x_s, x'_s) \in \Omega^2$,

$$A_s = \ln \frac{p(x_s, x_{s^-}, \mathbf{v}_{s^-} | \mathbf{y})}{p(x'_s, x_{s^-}, \mathbf{v}_{s^-} | \mathbf{y})} - \ln \frac{1}{\sqrt{2\pi\sigma_{x_s}^2}} + \frac{(y_s - \mu_{x_s})^2}{2\sigma_{x_s}^2} + \ln \frac{1}{\sqrt{2\pi\sigma_{x'_s}^2}} + \frac{(y_s - \mu_{x'_s})^2}{2\sigma_{x'_s}^2}$$

and the generic line of matrix B is

$$B_{s,:} = \left[\delta_{x_s}^{x_{s^-}} - \delta_{x'_s}^{x_{s^-}}, \sum_{\mathbf{v}_{s^-} \in \mathbf{V}_{s^-}} \left(\delta_{x_s}^{\mathbf{v}_{s^-}} - \delta_{x'_s}^{\mathbf{v}_{s^-}} \right) \right]$$

Unsupervised parameter estimation

Case of independent Gaussian observations

Maximum Likelihood (ML) estimator for μ^t and σ^t , $\forall \omega \in \Omega$:

$$\mu_{\omega}^t = \frac{1}{\sum_{s \in S^L} \mathbb{1}_{\{x_s^t = \omega\}}} \sum_{s \in S^L} y_s \mathbb{1}_{\{x_s^t = \omega\}}$$

and

$$\sigma_{\omega}^t = \left(\frac{1}{\sum_{s \in S^L} \mathbb{1}_{\{x_s^t = \omega\}}} \sum_{s \in S^L} (y_s - \mu_{\omega}^t)^2 \mathbb{1}_{\{x_s^t = \omega\}} \right)^{\frac{1}{2}}$$

Unsupervised parameter estimation

Algorithm 1: Iterative Parameter Estimation for Trees for STMTs.

Case $\Omega = \{\omega_1, \omega_2\}$

Data: $\theta^0 = \{\alpha^0, \beta^0, \mu_0^0, \mu_1^0, \sigma_0^0, \sigma_1^0\}$, an initial set of parameters,
 \mathbf{y} , the observations.

Result: $\theta^* = \{\alpha^*, \beta^*, \mu_0^*, \mu_1^*, \sigma_0^*, \sigma_1^*\}$, the estimated parameters.

1 $t \leftarrow 1$

2 **while** *convergence is not attained* **do**

3 1. MPM estimation:

4 $\hat{x}_s^{MPM,t} = \operatorname{argmax}_{x_s} p(x_s | \mathbf{y}, \theta^{t-1}), \forall s \in \mathcal{S}$

5 2. Estimation with the complete data $(\hat{\mathbf{x}}^{MPM,t}, \mathbf{y})$:

6 • LLS estimator for α^t and β^t

7 • ML estimator for μ_0^t and μ_1^t

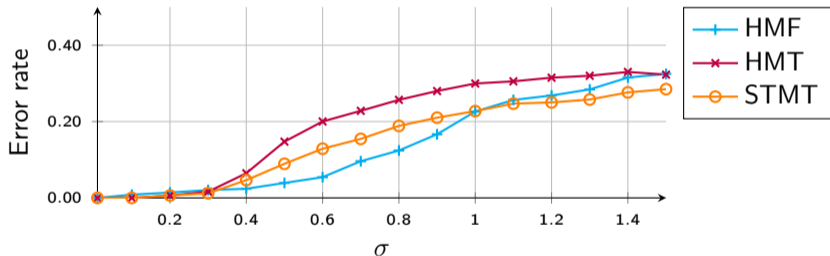
8 • ML estimator for σ_0^t and σ_1^t

9 $\theta^t \leftarrow \{\alpha^t, \beta^t, \mu_0^t, \mu_1^t, \sigma_0^t, \sigma_1^t\}$

10 $t \leftarrow t + 1$

Unsupervised image segmentation experiment

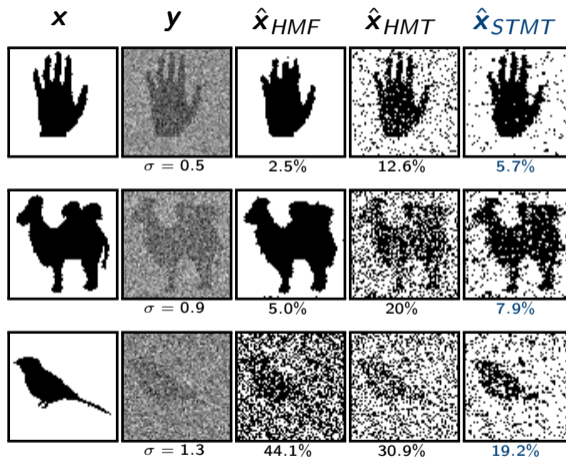
Comparing Hidden Markov Fields (HMFs), HMTs and STMTs in unsupervised segmentation:



Error rate in unsupervised segmentation function of the noise level

- STMTs greatly improve HMT results
- STMTs closer to HMF results

Unsupervised image segmentation experiment



Unsupervised segmentation HMF, HMT and STMT models

Outline

- ① Introduction
- ② Pairwise and Triplet Markov Models
- ③ Spatial Triplet Markov Trees
- ④ Unsupervised image segmentation
- ⑤ Conclusion**

Conclusion

Summary

- STMTs are generalizations of HMTs
 - increased modeling possibilities
 - strengthened spatial correlations
- Inference remains exact and deterministic

Conclusion

Summary

- STMTs are generalizations of HMTs
 - increased modeling possibilities
 - strengthened spatial correlations
- Inference remains exact and deterministic

Perspectives

- *Spatial* correlations induced → theoretical links between STMTs and HMFs ?
- STMTs as the variational distribution for variational inference in trees with semi-cycles as in (Gangloff et al. 2020) for 2D segmentation

References I

- [1] L. E. Baum and T. Petrie. "Statistical inference for probabilistic functions of finite state Markov chains". In: *The annals of mathematical statistics* 37.6 (1966), pp. 1554–1563.
- [2] L. E. Baum, T. Petrie, G. Soules, and N. Weiss. "A maximization technique occurring in the statistical analysis of probabilistic functions of Markov chains". In: *The annals of mathematical statistics* 41.1 (1970), pp. 164–171.
- [3] C. M. Bishop. *Pattern recognition and machine learning*. Springer, 2006.
- [4] J.-B. Courbot, E. Monfrini, V. Mazet, and C. Collet. "Triplet markov trees for image segmentation". In: *SSP 2018: IEEE Workshop on Statistical Signal Processing*. IEEE Computer Society, 2018, pp. 233–237.
- [5] H. Gangloff, J.-B. Courbot, E. Monfrini, and C. Collet. "Spatial Triplet Markov Trees for auxiliary variational inference in Spatial Bayes Networks". In: *Stochastic Modeling Techniques and Data Analysis international conference (SMTDA'20)*. 2020. In press.
- [6] S. Geman and D. Geman. "Stochastic relaxation, Gibbs distributions, and the Bayesian restoration of images". In: *IEEE Transactions on pattern analysis and machine intelligence* 6 (1984), pp. 721–741.
- [7] I. Goodfellow, Y. Bengio, and A. Courville. *Deep learning*. MIT Press, 2016.
- [8] I. Gorynin, H. Gangloff, E. Monfrini, and W. Pieczynski. "Assessing the segmentation performance of pairwise and triplet Markov models". In: *Signal Processing* 145 (2018), pp. 183–192.
- [9] D. Koller and N. Friedman. *Probabilistic graphical models: principles and techniques*. MIT Press, 2009.
- [10] J.-M. Laferté, P. Pérez, and F. Heitz. "Discrete Markov image modeling and inference on the quadtree". In: *IEEE Transactions on image processing* 9.3 (2000), pp. 390–404.
- [11] K. P. Murphy. *Machine learning: a probabilistic perspective*. MIT Press, 2012.
- [12] W. Pieczynski. "Arbres de Markov couple". In: *Comptes Rendus Mathématique* 335.1 (2002), pp. 79–82.