Transferable Interactiveness Prior for Human-Object Interaction Detection

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Abstract

Human-Object Interaction (HOI) Detection is an important problem to understand how humans interact with objects. In this paper, we explore Interactiveness Prior which indicates whether human and object interact with each other or not. We found that interactiveness prior can be learned across HOI datasets, regardless of HOI category settings. Our core idea is to exploit an Interactiveness Network to learn the general interactiveness prior from multiple HOI datasets and perform Non-Interaction Suppression before HOI classification in inference. On account of the generalization of interactiveness prior, interactiveness network is a transferable knowledge learner and can be cooperated with any HOI detection models to achieve desirable results. We extensively evaluate the proposed method on HICO-DET and V-COCO datasets. Our framework outperforms state-of-the-art HOI detection results by a great margin, verifying its efficacy and flexibility. Source codes and models will be made publicly available.

1. Introduction

Human-Object Interaction (HOI) detection task retrieves human and object locations and infers their interaction classes from still image. As a sub-task of visual relationship detection [18, 22], HOI is crucial for human behavior understanding and can facilitate human activity understanding [2], robotic manipulation [7] and imitation learning [1], etc. In recent years, impressive progress has been made by utilizing Deep Neural Networks (DNNs) in this area [3, 13, 24, 10].

Generally, humans and objects need to be detected first. Given an image and detections, human and objects are often paired exhaustively [13, 10, 24]. HOI detection task aims to classify these pairs as different HOI categories. Previous one-stage methods [3, 13, 10, 14, 24] directly classify a pair as specific HOIs. These methods actually predict interactiveness implicitly at the same time, where interactiveness indicates whether a human-object pair is interactive. For example, when a pair is classified as HOI “eat apple”, we can implicitly predict that it is interactive.

Though interactiveness is an essential element for HOI detection, we neglected to study how to utilize it and improve its learning. In comparison to HOI categories, interactiveness conveys more basic information. Such attribute makes it easier for interactiveness to transfer across datasets regardless of different HOI category settings. Based on this inspiration, we propose a general and transferable Interactiveness Prior learning method as seen in Figure 1. With our framework, interactiveness prior can be learned across many datasets and applied to any specific dataset. By utilizing interactiveness prior, we take two stages to identify HOIs: we first discriminate a human-object pair as interactive or not and then classify it as specific HOIs. Compared to previous one-stage method [3, 13, 10, 14, 24], we take advantage of powerful interactiveness prior that incorporates more information from other datasets. Thus our method can decrease the false positives significantly. Additionally, after the interactiveness filtering in the first stage, we do not need to handle a large number of non-interactive pairs which are...
overwhelmingly more than interactive ones.

In this paper, we propose a novel two-stage method to classify pairs hierarchically as shown in Figure 2. We introduce an interactiveness network which can be combined with any HOI detection model. We set a hierarchical logical strategy: by utilizing binary interactiveness labels, interactiveness network will import a strong supervised constraint which refines the framework in training and learns the interactiveness prior from multiple datasets. In testing, interactiveness network performs Non-Interaction Suppression (NIS) first. Then the HOI detection model will classify the remaining pairs as specific HOIs, where non-interactive pairs have been decreased significantly. Moreover, if the model classifies a pair as specific HOIs, it should figure out that the pair is interactive simultaneously. Such two-stage prediction will alleviate the learning difficulty and bring in interpretability. For special attention, interactiveness prior offers extra information to help HOI classification and is independent of HOI category settings. That means it can be transferred across datasets and utilized to enhance HOI models designed for different HOI settings.

We perform extensive experiments on HICO-DET [3], V-COCO [14] datasets. Our method cooperated with transferred interactiveness prior outperforms the state-of-the-art methods by 2.38, 3.06, and 2.17 mAP on three Default category sets on HICO-DET, and 4.0 mAP on V-COCO.

2. Related Works

Visual Relationship Detection. Visual relationship detection [26, 22, 18, 31] aims to detect the objects and classify their relationships simultaneously. In [22], Lu et al. proposed a relationship dataset VRD and an approach combined with language priors. Predicates within relationship triplet \( \langle \text{subject}, \text{predicate}, \text{object} \rangle \) include actions, verbs, spatial and preposition vocabularies. Such vocabulary setting and severe long-tail issue within the dataset make this task quite difficult. Large-scale dataset Visual Genome [18] is then proposed to promote studies in this problem. Recent works [29, 33, 34, 15, 32] put attention on more effective visual feature extraction and try to exploit semantic information to refine the relationship detection.

Human-Object Interaction Detection. Human-Object Interaction [28, 30, 17] is essential to understand human-centric interaction with objects. Recently several large-scale datasets, such as V-COCO [14], HICO-DET [3], HCVRD [35], were proposed for the exploration of HOI detection. Some competitions like Open Images Challenge [19] also drew attention to HOI detection studies. Different from HOI recognition [6, 4, 5, 8, 23] which is an image level classification problem, HOI detection needs to detect interactive human-object pairs and classify their interactions in instance level. With the assistance of DNNs and large-scale datasets, recently methods have made significant progress. Chao et al. [3] proposed a multi-stream model combining visual features, spatial locations to help tackle this problem. To address the long tail issue, Shen et al. [27] studied zero-shot learning problem and predicted the verb and object separately. In [13], an action specific density map estimation method is introduced to locate objects interacted with human. In [24], Qi et al. proposed GPNN incorporating DNN and graphical model, which uses message parsing to iteratively update states and classifies all possible pairs/edges. Gao et al. [10] exploited an instance centric attention module to enhance the information from the interest region and facilitate the HOI classification. Generally, these methods follow one-stage inference and may suffer from severe non-interactive pair domination problem. To address this issue, we utilize interactiveness prior to explicitly discriminate non-interactive pairs and suppress them before HOI classification.

3. Preliminary

HOI representation can be described as a graph model [24, 29] as seen in Figure 2. Instances and relations are expressed as nodes and edges respectively. With exhaustive pairing [13, 10], HOI graph \( G = (V, E) \) is dense connected, where \( V \) includes human node \( V_h \) and object node \( V_o \). Let \( v_h \in V_h \) and \( v_o \in V_o \) denote the human and object nodes. Thus edges \( e \in E \) are expressed as \( e = (v_h, v_o) \in V_h \times V_o \). With \( n \) nodes, exhaustive pairing will generate tremendous edges. We aim to assign HOI (including no HOI) labels on those edges. Considering that a vast majority of non-interactive edges existing in \( E \) should be discarded, our goal is to seek a sparse \( G^* \) with corrected HOI labeling on its edges.
4. Our Method

4.1. Overview

As aforementioned, we introduce **Interactiveness Prior** to advance HOI detection performance. That is, explicitly discriminate the non-interactive pairs and suppress them before HOI classification. From the semantic point of view, interactiveness prior provides more general information than conventional HOI categories. Since any human-object pair can be assigned binary interactiveness labels according to the HOI annotations, *i.e.* “interactive” or “non-interactive”, interactiveness prior can be learned from multiple datasets with different HOI category settings and transferred to any specific HOI detection task.

To exploit this cue, we proposed interactiveness network (interactiveness predictor, referred as \( P \)) which utilizes interactiveness prior to reduce false positives caused by overmuch non-interactive pair candidates. Some conventional modules are also included, namely, **Representation Network** \( R \) (feature extractor) and **Classification Network** \( C \) (HOI classifier). \( R \) is responsible for feature extraction from detected instances. \( C \) utilizes node and edge features to perform HOI classification. Figure 3 is an overview of our framework which follows the hierarchical classification paradigm. Specifically, we first train \( P \) and \( C \) jointly to learn the interactiveness prior and HOIs knowledge. Under usual circumstances, the ratio of non-interactive edges is dominant within inputs. Hence \( P \) will bring a strong supervised signal to refine the framework. In testing, \( P \) is utilized in two stages. First, \( P \) evaluates the interactiveness of edges by exploiting the learned interactiveness prior, so we can convert the dense HOI graph to a sparse one. Second, combined with interactiveness score from \( P \), \( C \) will process the sparse graph and classify the remaining edges.

In addition, on account of the generalization ability of interactiveness prior, it can be transferred with \( P \) across datasets (Section 4.4). Details of the framework architecture are illustrated in Section 4.2 and 4.3. The process of training and testing will be detailed in Section 4.4.

4.2. Representation and Classification Networks

**Human and Object Detection.** In HOI detection, human and object need to be detected first. In this work, we follow the setting of [10] and employ the Detectron [12] with ResNet-50-FPN [20] to prepare bounding boxes and detection scores. Before post-processing, detection results will be filtered by the detection score thresholds first.

**Representation Network.** In previous methods [3, 13, 10], \( R \) is often modified from object detector such as Fast R-CNN [11] or Faster R-CNN [25]. We also exploited a Faster R-CNN [25] with ResNet-50 [16] based \( R \) here. During training and testing, \( R \) is frozen and acts as a feature extractor. Given the detected bounding boxes, we produce human and object features by cropping ROI pooling feature maps according to box coordinates.

**HOI Classification Network.** As for \( C \), multi-stream architecture and late fusion strategy are frequently used and approved effective [3, 10]. Follow [3, 10], for our classification network \( C \), we utilize a human stream and an object stream to extract human, object and context features. Within each stream, a residual block [16] (denoted as \( H^C \), \( O^C \), seen in Figure 3) with pooling layer and fully connected layers (FCs) are adopted. Moreover, an extra spatial stream [3] is adopted to encode the spatial locations of human and object appearance.
instances. Its input is a two-channel tensor consisting of a human map and an object map, shown in Figure 4. Human and object maps are all 64x64 and obtained from the human-object union box. In the human channel, the value is 1 in the human bounding box and 0 in other areas. The object channel is similar which has value 1 in the object bounding box and 0 elsewhere. Following the late fusion strategy, each stream will first perform HOI classification, then three prediction scores will be fused by element-wise sum in the same proportion to produce the final result of C.

4.3. Interactiveness Network

Interactiveness prior need to be learned by extracting and combining essential information. The visual appearance of human and object are obviously required. Besides, interactive and non-interactive pairs also have other distinguishing features, e.g. spatial location and human pose information. For example, in the upper image of Figure 4, Person 1 and the giraffe far from him are not interactive. Their spatial maps [3] can provide pieces of evidence to help with classification. Furthermore, human pose information is also helpful. In the lower image, although two people are both close to the giraffe, only Person 2 and the giraffe are interactive. The arm of Person 2 is uplift and touching the giraffe. Whilst Person 1 is back on to the giraffe, and his pose is quite different from the typical pose of “feed”.

Based on these reasons, the combination of visual appearance, spatial location and human pose information is key to interactiveness discrimination. Hence P needs to encode these key elements together to learn the interactiveness prior. A natural choice is the multi-stream architecture as presented: human, object and spatial-pose streams.

Human and Object stream. For human and object appearance, we extract ROI pooling features from representation network R, then input them into residual blocks \( H^P \) and \( O^P \), respectively. The architecture of \( H^P \) and \( O^P \) are same as \( H^C \) and \( O^C \) (Figure 3). Through subsequent global average pooling and FCs, the output features of two streams are denoted as \( f_h \) and \( f_o \), respectively.

Spatial-Pose Stream. Different from [3], our spatial-pose stream input includes a special 64x64 pose map. Given the union box of each human and his/her paired object, we employ pose estimation [9] to estimate his/her 17 keypoints (in COCO format [21]). Then, we link the keypoints with lines of different gray value ranging from 0.15 to 0.95 to represent different body parts, which implicitly encodes the human pose features. Whilst the other area is set as 0. Finally, we reshape the union box to 64x64 to construct the pose map. We concatenate the pose map with human and object maps which are the same as those in the spatial stream of C. This forms the input for our spatial-pose stream. Next, we exploit two convolutional layers with max pooling and two 1024 sized FCs to extract the feature \( f_{sp} \) of three maps. Last, the output will be concatenated with the outputs of human and object streams for interactiveness discrimination.

Given a HOI graph \( G \) with all possible edges, \( P \) will evaluate the interactiveness of pair \((v_h, v_o)\) based on learned prior, and gives a confidence:

\[
s^P_{(h,o)} = f_P(f_h, f_o, f_{sp}) \ast L(s_h, s_o),
\]

where \( L(s_h, s_o) \) is a novel weight function named Low-grade Instance Suppressive Function (LIS). It takes the human and object detection scores \( s_h, s_o \) as inputs:

\[
L(s_h, s_o) = \mathcal{P}(s_h) \ast \mathcal{P}(s_o),
\]

![Figure 4. Inputs of the spatial-pose stream. Three kinds of maps are included: pose map, human map and object map. Person 2 in two images both have interaction “feed” with giraffes. But two pairs of Person 1 and giraffe are all non-interactive. Their poses and locations are helpful for the interactiveness discrimination.](image)

![Figure 5. The illustration of \( \mathcal{P}(\cdot) \) within Low-grade Suppressive Function. Its input is object detection score. High-grade detected objects will be emphasized and distinguished with low-grade ones.](image)
\[ P(x) = \frac{T}{1 + e^{(k - w)x}}, \quad (3) \]

\( P(\cdot) \) is a part of the logistic function, the value of \( T \), \( k \) and \( w \) will be determined by data-driven manner. Figure 5 depicts the curve of \( P(\cdot) \) whose domain definition is \((0, 1)\). Bounding boxes will have low weight till their score is higher than a threshold. Previous works [10, 13] often directly multiply detection scores by the final classification score. But they cannot notably emphasize the differentiation between high quality and inaccurate detection results. LIS has the ability to enhance the differentiation between high and low grade object detections as shown in Figure 5.

**Weights Sharing Strategy.** An additional benefit of our interactiveness network is that, if cooperated with multi-stream HOI detection model \( C \), \( P \) can share the weights of convolutional blocks with the ones in \( C \). As shown in Figure 3, blocks \( H^P \) and \( O^P \) can share weights with \( H^C \) and \( O^C \) in the joint training. This weights sharing strategy can guarantee information sharing and better optimization of \( P \) and \( C \) in the multi-task training.

**4.4. Interactiveness Prior Transfer Training**

With \( R \), \( P \) and \( C \), our framework has two modes of utilization: hierarchical joint training in **Default Mode**, and interactiveness prior transfer training in **Transfer Learning Mode**.

**Hierarchical Joint Training.** In **Default Mode**, we introduce our hierarchical joint training scheme, as illustrated in Figure 6 (a). By adding a supervisor \( P \), our framework works in an unconventional training mode. To be specific, the framework is trained with hierarchical classification tasks, i.e. explicit interactiveness discrimination and HOI classification. The objective function of the framework can be expressed as:

\[ \mathcal{L} = \mathcal{L}^C + \mathcal{L}^P, \quad (4) \]

where \( \mathcal{L}^C \) denotes the HOI classification cross entropy loss, while \( \mathcal{L}^P \) is the binary classification cross entropy loss.

Different from one-stage methods, additional interactiveness discrimination enforces the model to learn interactiveness prior, which can bring more powerful supervised constraints and interpretability. Namely, when a pair is predicted as specific HOIs such as “cut cake”, \( P \) must give the prediction “interactive” simultaneously. Experiment results (Section 5.4) prove that interactiveness prior learning can effectively refine the training and improve the performance. The framework in Default Mode is called “\( R P_{Tn} C_D \)” in the following, where “\( T \)” indicates “Transfer”, and “\( n \)” means \( P \) learns interactiveness prior from \( n \) datasets. \( 1) \) \( R P_{T1} C_D \): train \( P \) on 1 dataset and apply \( P \) to another dataset. \( 2) \) \( R P_{T2} C_D \): train \( P \) on 2 datasets and apply \( P \) to them respectively.

To compare the transferability of interactiveness prior and HOIs knowledge, we set a transfer learning mode “\( R C_T \)” for \( C \). \( 3) \) \( R C_T \): train \( C \) (without \( P \)) on one dataset and apply it to another dataset. For example, we first train and test \( C \) on HICO-DET (referred as “\( R C_D \)”). Second, we replace the last FC layer of \( C \) with a FC layer that fits the number of V-COCO HOIs, then finetune \( C \) for 1 epoch on V-COCO train set. Last, we test this new \( C \) on V-COCO test set. Details of the above modes can be found in Table 1.

**4.5. Testing with Non-Interaction Suppression**

After the interactiveness prior learning, we further utilize \( P \) to suppress the non-interactive pair candidates in testing, i.e. Non-Interaction Suppression (NIS). The inference process is based on tree structure as shown in Figure 2. Detected instances in test set will be paired exhaustively, so a dense graph \( G \) of human and objects is generated. First, we employ \( P \) to compute the interactiveness score of all edges. Next, we suppress the edges that meet NIS conditions, i.e.
interaction score \( s^P_{(h,o)} \) small than a certain threshold \( \alpha \).

Through NIS, we can convert \( G \) to \( G' \) where \( G' \) denotes the approximate sparse HOI graph. The HOI classification score vector \( S^C_{(h,o)} \) of \((v_h,v_o)\) from \( C \) is:

\[
S^C_{(h,o)} = F_C[\Gamma'; G'(v_h,v_o)], \quad (5)
\]

where \( \Gamma' \) are input features. The final HOI score vector of a pair \((v_h,v_o)\) can be obtained by:

\[
S_{(h,o)} = S^C_{(h,o)} * s^P_{(h,o)}. \quad (6)
\]

Here we multiply interactiveness score \( s^P_{(h,o)} \) from \( P \) by the output of \( C \).

5. Experiments

In this section, we first introduce datasets and metrics adopted and then give implementation details of our framework. Next, we report our HOI detection results quantitatively and qualitatively compared with state-of-the-art approaches. Finally, we conduct ablation studies to validate the validity of the components in our framework.

5.1. Datasets and Metrics

Datasets. We adopt two HOI datasets HICO-DET [3] and V-COCO [14]. **HICO-DET** [3] includes 47,776 images (38,118 in train set and 9658 in test set), 600 HOI categories on 80 object categories (same with [21]) and 117 verbs, and provides more than 150k annotated human-object pairs. **V-COCO** [14] provides 10,346 images (2,533 for training, 2,867 for validating and 4,946 for testing) and 16,199 person instances. Each person has annotations for 29 action categories (five of them have no paired object). The objects are divided into two types: “object” and “instrument”.

Metrics. We follow the settings adopted in [3], i.e. a prediction is a true positive only when the human and object bounding boxes both have IOUs larger than 0.5 with reference to ground truth, and the HOI classification result is accurate. The role mean average precision [14] is used to measure the performance.

5.2. Implementation Details

We employ a Faster R-CNN [25] with ResNet-50 [16] as \( R \) and keep it frozen. \( C \) consists of three streams similar to [3, 10], extracting features \( \Gamma' \) from instance appearance, spatial location as well as context. Within human and object streams, a residual block [16] with global average pooling, and four 1024 sized FCs are used. Relatively, the spatial stream is composed of two convolutional layers with max pooling, and two 1024 sized FCs. Following [3, 10], we use the late fusion strategy in \( C \). \( P \) also consists of three streams (seen in Figure 3). A residual block [16] with global average pooling, and two 1024 sized FCs are adopted in human and object streams. Residual blocks within these two streams will share weights with those in \( C \). Spatial-Pose stream consists of two convolutional layers with max pooling and two 1024 sized FCs. The outputs of three streams are concatenated and passed through two 1024 sized FCs to perform interactiveness discrimination.

For fair comparison, we adopt the object detection results and COCO [21] pre-trained weights from [10] which are provided by authors. Since NIS and LIS can suppress non-interactive pairs, we set detection confidence thresholds lower than [10], i.e. 0.6 for human and 0.4 for object. The image-centric training strategy [25] is also applied. In other words, pair candidates from one image make up the mini-batch. We adopt SGD and set initial learning rate as 1e-4, weight decay as 1e-4, momentum as 0.9. In training, the ratio of positive and negative samples is 1:3. We jointly train the framework for 25 epochs. In LIS mentioned in Equation 3, we set \( T = 8.4, k = 12.0, w = 10.0 \). In testing, the interactiveness threshold \( \alpha \) in NIS is set as 0.1. All experiments are conducted on a single Nvidia Titan X GPU.

5.3. Results and Comparisons

We compare our method with five state-of-the-art HOI detection methods [3, 27, 13, 24, 10] on HICO-DET, and four methods [14, 13, 24, 10] on V-COCO. The HOI detection result is evaluated with mean average precision. For HICO-DET, we follow the settings in [3]: Full (600 HOIs), Rare (138 HOIs), Non-Rare (462 HOIs) in Default and Known Object mode. For V-COCO, we evaluate \( A P_{role} \) (24 actions with roles). More details can be found in [3, 14].

**Default Mode.** From Table 2, we can find that the default \( RP_D C_D \) has already outperformed compared methods. We respectively achieve **17.03** and **19.17** mAP on Default and Know Object Full sets on HICO-DET. In particular, we boost the performance of **2.97** and **4.18** mAP on Rare sets. To illustrate, as the generalization ability of interactiveness prior is beyond HOI category settings, information scarcity and learning difficulty of rare categories is alleviated. So the performance difference between rare and non-rare categories is accordingly reduced. Results on V-COCO are shown in Table 3. \( RP_D C_D \) also achieves superior per-
formance and outperforms state-of-the-art method [10] (late and early fusion model), yielding 47.8 mAP, which quantitatively validates the efficacy of the interactiveness prior. Notably, \( \text{RC}_D \) shows limited performance when compared with other models containing \( P \). This reveals the performance enhancement ability of interactiveness network \( P \).

**Transfer Learning Mode.** By leveraging transferred interactiveness prior, \( \text{RP}_T \text{C}_D \) presents great performance improvement and achieves the most state-of-the-art performance. On HICO-DET, \( \text{RP}_T \text{C}_D \) surpasses [10] by 2.38, 3.06, and 2.17 mAP on three Default category sets. Meanwhile, it also outperforms [10] by 4.0 and 3.4 mAP on V-COCO. This indicates the good transferability and effectiveness of interactiveness prior. Since HICO-DET train set (38K) is much bigger than V-COCO train set (2.5K), improvement is also larger when transferring is performed from HICO-DET to V-COCO. As we can see, mode \( \text{RP}_{T_1} \text{C}_D \) achieves obvious improvement on V-COCO, but it shows a relatively smaller improvement on HICO-DET when compared with mode \( \text{RP}_D \text{C}_D \).

We also evaluate the transferability of HOIs knowledge. In comparison with \( \text{RC}_D \), \( \text{RC}_T \) shows a significant performance decrease of 3.14 and 4.7 mAP on two datasets, as shown in Table 2 and 3. It proves that interactiveness prior is more suitable and easier to transfer than HOIs knowledge.

**Non-Interaction Reduction.** The non-interactive pairs reduction effect after employing NIS are shown in Table 4. As we cannot annotate all non-interactive pairs in test set, so we compute the ratio according to the assigned binary labels. Specially, HICO-DET has 80 “no-interaction” HOIs correspond to 80 objects. When NIS condition is satisfied, we keep the scores of these 80 HOIs and discard the scores of all the other 520 HOIs.

In default mode \( \text{RP}_D \text{C}_D \), NIS shows obvious effectiveness. With interactiveness prior transferred from multiple datasets, \( \text{RP}_{T_2} \text{C}_D \) achieves better suppressive effect and discards 70.94% and 73.62% non-interactive pairs respectively on two datasets, thus bringing more performance gain. Meanwhile, \( \text{RP}_{T_1} \text{C}_D \) also performs well and suppresses a certain amount of non-interactive pair candidates. This suggests the good transferability of interactiveness prior.

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**Figure 7.** Visualization of sample HOI detections. Subjects and objects are represented with blue and red bounding boxes. While interactions are marked by green lines linking the box centers.

**Figure 8.** Shows the visualized effects of NIS. We can see that NIS effectively distinguish the non-interactive pairs and suppress them even in extremely difficult scenarios, such as a person and the handbag close to him, a person performing a confusing action and the tennis ball, a crowd of people with ties. In the bottom-left corner we show a even harder sample. When the subject and object are the left hand and right hand, \( C \) predicts wrong HOI “type_on keyboard”. \( C \) may mistake the left hand for the keyboard because they are too close. However, \( P \) accurately figures out that two hands are non-interactive. These results prove that the one-stage method would yield many false positives without interactiveness prior and NIS.

**5.4. Ablation Studies**

In mode \( \text{RP}_D \text{C}_D \), we analyze the significance of Low-grade Instance Suppressive, Non-Interaction Suppression and the three streams within \( P \) (seen in Table 5).
Figure 8. Visualized effects of NIS. Green lines mean accurate HOIs, while purple lines mean non-interactive pairs which are suppressed. Without NIS, C would generate false positive predictions for these non-interactive pairs in one-stage inference, which are shown by the purple texts below the images. Even some extremely hard scenarios can be discovered and suppressed, such as mis-groupings between person and object close to each other, person and object in clutter scene.

| Test Set | Method     | Reduction |
|----------|------------|-----------|
| HICO-DET | $R_{D}C_{D}$ | -65.96%   |
|          | $R_{T_1}C_{D}$ | -62.24%   |
|          | $R_{T_2}C_{D}$ | -70.94%   |
| V-COCO   | $R_{D}C_{D}$  | -65.98%   |
|          | $R_{T_1}C_{D}$ | -59.51%   |
|          | $R_{T_2}C_{D}$ | -73.62%   |

Table 4. Non-interactive pairs reduction after performing NIS.

**Non-Interaction Suppression** NIS plays a key role to reduce the non-interactive pairs. We evaluate its impact by removing NIS during testing. In other words, we directly use the $S_{(h,o)}$ from Equation 6 as the final predictions without NIS. Consequently, the model shows an obvious performance degradation, which proves the importance of NIS.

**Low-grade Instance Suppressive** LIS suppress the low-grade object detections and reward the high-grade ones. By removing $L(s_h, s_o)$ in Equation 1, we observe a degradation in Table 5. This suggests that LIS is capable of distinguishing the low-grade detections and improves the performance without using more costly superior object detector.

**NIS & LIS** Without NIS and LIS both, our method only takes effect in the joint training of $P$ and $C$. As we can see in Table 5, performance degrades greatly but still outperforms other methods, which indicates the enhancement brought by $P$ in the hierarchical joint training.

**Three Streams.** By keeping one stream in $P$ each time, we evaluate their contributions as shown in Table 5. We can find that spatial-pose stream is the largest contributor, but we still need appearance features from the other two streams to achieve better performance.

### 6. Conclusion

In this paper, we propose a novel method to learn and utilize the implicit Interactiveness Prior, which is general and beyond HOI categories. Thus, it can be transferred across...
datasets. With interactivity prior, we exploit an interactivity network to perform Non-interaction Suppression before HOI classification in inference. Extensive experimental results show the efficacy of interactivity prior. By combining our method with existing detection models, we achieve state-of-the-art results on HOI detection.

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