A Deep Neural Network for Real-Time Driver Drowsiness Detection

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SUMMARY We develop a deep neural network (DNN) for detecting driver drowsiness in videos. The proposed DNN model that receives driver’s faces extracted from video frames as inputs consists of three components - a convolutional neural network (CNN), a convolutional control gate-based recurrent neural network (ConvCGRNN), and a voting layer. The CNN is to learn facial representations from global faces which are then fed to the ConvCGRNN to learn their temporal dependencies. The voting layer works like an ensemble of many sub-classifiers to predict drowsiness state. Experimental results on the NTHU-DDD dataset show that our model not only achieve a competitive accuracy of 84.81% without any post-processing but it can work in real-time with a high speed of about 100 fps.

key words: driver drowsiness detection, ConvCGRNN, CGRNN

1. Introduction

Driver drowsiness detection (DDD) is one of vital components in most driver monitoring systems since drowsy driving seriously involves to many traffic accidents. Drowsiness can occur silently without self-awareness from drivers, impairing driving performance, which leads to about 6% of all crashes annually from years 2009–2013 according to [1]. Generally, an active DDD system keeping track of driver’s behaviors in real-time provides timely reminders and warnings to prevent any possible accidents. Existing approaches for the DDD problem can be grouped into three major directions: systems that use driving operation information such as steering wheel angles and yaw angles [2]; systems that use physiological signals like electroencephalogram (EEG) [3]; and systems that use video signals [4], [5]. The first direction is convenient for drivers but hard to satisfy the requirement of accuracy and timeliness, while the second direction is accurate but not convenient because of wearable body sensors. In video-based DDD systems, an in-vehicle camera is adopted to capture driver’s behaviors, especially facial expression, to measure drowsiness levels, which is more practically applicable. Our goal is to develop a visual DDD system that is accurate and fast to be applied in practice.

Drowsiness state can be indicated visually by some specific facial expressions such as yawning, eye-blinking, eye-closing, and nodding which can be recognized by monitoring different facial parts and global faces through time. Therefore, a general DDD system consists of two parts: a preprocessing step to extract facial information, and a classification model. The preprocessing step is to extract sequence of faces from video frames, typically involves a set of face-related techniques including face detection, face tracking, and face alignment. The way of combining these techniques affects not only accuracy but overall speed of a DDD system. In particular, previous works [4], [5], [9] require face alignment to locate and learn relevant features from specific facial regions. However, performing face detection and alignment on every frames has many challenges such as different illumination conditions, hard human poses, and occlusions. Additionally, it increases overall processing time. In our work, we work directly with global faces. Face detection and face tracking are combined together to extract driver’s faces from video frames, which is simple, accurate, and very fast.

A classification model learns drowsiness-related facial features from video frames to estimate drowsiness levels. Conventionally, features are extracted spatially on each frame by a feature extraction method such as sparse coding [4], deep belief network (DBN) [5]; before being delivered to a temporal model like hidden Markov models (HMMs) to discover temporal dependencies between consecutive frames. Recently, deep learning (DL) models are widely implemented for the problem with different approaches such as long-term recurrent convolutional networks (LRCNs) [6], ensemble modeling [7], multi-task CNN [9], and 3D-CNN [8], [10]. The DL models are accurate, but computationally high in common because of window-based predictions. Furthermore, some post-processing methods [6], [9], [10] can be applied to smooth temporal predictions of model, which improves overall accuracy, but is hard to be applied in reality. In this paper, we develop a DL model that is not only accurate, but very fast at inference time. The proposed model firstly extracts facial representations from global faces by its CNN part, then its ConvCGRNN part is to learn their temporal relations while remaining spatial properties before feeding to a voting layer. Specifically, the model sequentially makes predictions by processing frame by frame instead of making window-based predictions. Thus, it is very fast, consuming much less computational cost, and capable to work in real-time.

To summarize, our contributions are listed as follows.
- We develop a deep neural network (DNN) model for the problem of real-time driver drowsiness detection in videos. The model is designed to work directly with global faces extracted from video frames by a combination of face detection and tracking techniques.

- We propose the use of ConvCGRNN to learn temporal dependencies while still preserving spatial relations from representations extracted from global faces by a CNN, and a voting layer to measure drowsiness state.

- We conduct experiments on the public NTHU-DDD dataset to evaluate performance of the proposed model. Our model achieves a competitive accuracy of 84.81% without any post-processing, and about 100 fps inference speed.

2. Our Approach

The proposed DDD system is illustrated in Fig. 1. Given a video stream, a preprocessing step including face detection and tracking extracts driver’s face from each frame. These faces are sequentially processed by a deep neural network (DNN) model to determine drowsiness state. In this section, the preprocessing step is presented before the DNN model is described in detail.

2.1 Preprocessing

The preprocessing step is to extract driver’s faces from video frames. Typically, face detection is employed to extract faces from images, but it can have various difficulties such as different illumination conditions, hard poses, and occlusions. Performing face detection on every frames also increases processing time. In our work, we make a combination of face detection and tracking which is accurate and much faster. Driver’s face is firstly detected by a face detector, then face locations are determined and tracked by a tracker at subsequent frames. To prevent drifting problem in tracking, we perform face detection after a cycle. If it detects successfully, we reinitialize the tracking state; otherwise, we keep tracking the current state.

In our implementation, we employ MTCNN [12] for face detection, and a correlation function in dlib [11] for tracking. The cycle time is fixed to 45 timesteps which corresponds to three seconds in our experiments. After extraction, faces are converted to grayscale, and resized to 128 × 128.

2.2 Deep Neural Network Model

The proposed DNN model consists of three components: a convolutional neural network (CNN), a convolutional control gate-based recurrent neural network (ConvCGRNN), and a voting layer. It sequentially processes input faces to estimate drowsiness states (yes or no) at every timesteps.

- **CNN.** The CNN is to extract facial representations from each input face, and is constructed in a VGG-style [13] with batchnorm [15] after every convolutional layers. The details of the CNN part is shown in Table 1. Its output is a feature map with size of (128 × 8 × 8). Each 128D vector in the feature map corresponds to a receptive field which covers almost the input face.

- **ConvCGRNN.** ConvCGRNN is a convolutional version of control gate-based recurrent neural network (CGRNN) [14] which is designed for effective sequence modeling with a low resource-consumption by employing an additional control gate. Figure 2 illustrates the computational structure of this.

### Table 1 The DNN architecture. (convX – Y and convcgX – Y denote convolutional layer and ConvCGRNN layer respectively, where X is kernel size, Y is number of output channels. Stride size is one for all convolutional layers in both CNN and ConvCGRNN. Batchnorm and ReLU are applied after every convX – Y; batchnorm is applied after every convolution operators of input in ConvCGRNN, which are not shown for brevity. mpX presents a max-pooling layer where X is kernel size and stride size. fc – X denotes a fully-connected layer with output size X.)

| Name     | Configuration                  | Output size  |
|----------|--------------------------------|--------------|
| Input    | input                          | (1 × 128 × 128) |
| CNN      | conv3 – 16 + mp2              | (128 × 8 × 8) |
|          | conv3 – 32 + conv3 – 32 + mp2 |              |
|          | conv3 – 64 + conv3 – 64 + mp2 |              |
|          | conv3 – 128 + conv3 – 128 + mp2 | (128 × 8 × 8) |
|          | conv3 – 128 + conv3 – 128     |              |
| ConvCGRNN| convcg1 – 128                  | (128 × 8 × 8) |
|          | convcg1 – 128                  |              |
| Voting   | 64 × (fc – 128) + ReLU         | (64)         |
| Output   | global max pooling             | (1)          |

![Fig. 1](image1.png) The proposed driver drowsiness detection system.

![Fig. 2](image2.png) Computational structure of a ConvCGRNN cell. (Blue arrows present convolution operators.)
a ConvCGRNN cell. \(i_t, h_t, \hat{h}_t\), and \(c_t\) are input, hidden state, temporal state, and control gate at a time step \(t\), respectively. They are all referred as feature maps.

At a time step \(t\), a temporal state is given by

\[
\hat{h}_t = f(W_{ih} * i_t + W_{hh} * h_{t-1})
\]  
(1)

and a control gate is computed as

\[
c_t = \sigma(W_{ic} * i_t + W_{hc} * h_{t-1})
\]  
(2)

The new hidden state is derived as

\[
h_t = c_t \odot \hat{h}_t + (1 - c_t) \odot \hat{h}_t
\]  
(3)

where \(f\) is an activation function, and is commonly a hyperbolic tangent function; \(\sigma\) is a logistic sigmoid function. \(W_{ih}, W_{hh}, W_{ic}\), and \(W_{hc}\) are weight matrices. The symbol \(\odot\) denotes element-wise multiplication, * denotes convolution operator. Furthermore, batch normalization can be applied after a convolution operator of the hidden state \(h_t\); we do not apply it after a convolution operator of the hidden state \(h_{t-1}\) to preserve gating property of ConvCGRNN.

In Eqs. (1) and (2), convolution operator is applied on both input and hidden state, which maintains spatial information of these feature maps. From Eq. (3), the temporal state \(\hat{h}_t\) works like a source of new information; the previous hidden state \(h_{t-1}\) brings information from the past; and the control gate \(c_t\) scales the amount of information each source contributes to the new hidden state \(h_t\). Thus, ConvCGRNN is able to not only learn temporal long-term dependencies, but also preserve spatial properties of the input feature maps.

In this paper, we implement 2D convolution operator for ConvCGRNN structure. As shown in Table 1, the ConvCGRNN part is constructed by two ConvCGRNN layers with kernel size of 1 for all their convolution operators, and output channel size of 128. This configuration enables the ConvCGRNN to process each 128D vector on the CNN feature maps independently. Output of the ConvCGRNN at a timestep is a feature map with size of \((128 \times 8 \times 8)\). Each 128D vector on this feature map corresponds to a vector at the same location on the CNN feature map, and represents its temporal long-term dependencies.

- **Voting layer.** The voting layer is a set of two fully-connected layers without weight-sharing (Table 1). The purpose is to make independent decision for each 128D vector of the ConvCGRNN feature maps. We can consider each location vector on the feature maps has its own classifier. The voting layer works like an ensemble of many classifiers; the final output is a maximum value of the voting outputs.

Outputs of the model indicate the driver’s state (drowsiness or non-drowsiness). Binary cross-entropy (BCE) loss is used as a loss function for the problem. Overall, the cost function is given by

\[
C = -\frac{1}{N} \sum_{i=1}^{N} [y_i \log \hat{y}_i + (1 - y_i) \log(1 - \hat{y}_i)] + \frac{\lambda}{2} \|\Theta\|^2
\]  
(4)

Where the first term is BCE loss; the second term is weight-decay regularization term. \(y\) is the output label; \(\hat{y}\) is the predicted probability. \(N\) is a batch size.

At inference time, the DNN model sequentially makes predictions by processing frame by frame without the need of resetting ConvCGRNN states. By this way, computational cost at a timestep is approximate to that of a similar structure DNN processing an input image, which is low at resource consumption.

3. **Experiments**

3.1 **Dataset**

We conduct experiments on the public NTHU-DDD dataset [5] to validate performance of the proposed model. The video dataset consists of both male and female participants with diversity in appearances, ethnicities. Videos are recorded in a simulated environment under many scenarios including BareFace, Glasses, Sunglasses, Night-BareFace and Night-Glasses. They capture different driver’s behaviors such as Yawning, Nodding, Looking aside, Talking and laughing, Sleepy-eyes, Drowsy, and Stillness. Some example frames of the database are illustrated in Fig. 3. The dataset provides four frame-level annotations: drowsiness, head, mouth, and eye.

The dataset includes a training set that has 356 videos of 18 subjects, and a test set that has 20 videos of 4 subjects. In our experiments, we divide the training set into two parts: 14 subjects for training, 4 subjects for validation. Videos are resampled to 15 fps.

3.2 **Training Details**

We firstly initialize the CNN part by pretraining it on FER+ dataset [16] to learn rich facial representations from many subjects. Specifically, images in FER+ are resized to 64×64; two FC layers \( (fc - 128 + ReLU + fc - 10) \) are added right after the CNN part with an average pooling applied in the middle. This pretraining step enables the DNN model to
Table 2  Detection performances of the proposed model on the test set of the NTHU-DDD dataset.

| Scenario       | Non-drowsiness F1-score (%) | Drowsiness F1-score (%) | Accuracy (%) |
|----------------|----------------------------|-------------------------|--------------|
| Bareface       | 84.65                      | 88.34                   | 86.75        |
| Glasses        | 70.00                      | 82.59                   | 77.97        |
| Sunglasses     | 65.18                      | 79.36                   | 74.08        |
| Night-Bareface | 82.88                      | 90.77                   | 88.00        |
| Night-Glasses  | 90.95                      | 85.37                   | 88.82        |
| Overall        | 82.99                      | 86.28                   | 84.81        |

Table 3  Comparison of different methods on the test set of the NTHU-DDD dataset.

| Method                  | Accuracy % |
|-------------------------|------------|
| 3D-DCNN [8]             | 71.20      |
| Ensemble modeling [7]   | 73.06      |
| Scale-Pruned 3D-CNN [10]| 78.48      |
| MSTN [6]                | 82.61      |
| seqMT-DMF [9]           | 83.44      |
| Human [7]               | 80.83      |
| Ours                    | 84.81      |

For comprehensive evaluation, processing time of each module in the proposed DDD system is measured. By applying face detection and tracking together, the preprocessing speed can reach 60 fps, is much faster about 12 times than that of using only face detection. The DNN model achieves a high inference speed of 100 fps. The number can be still improved in the future since our implementation in the voting layer has not been optimal because of sequential computing. Thus, the proposed system satisfies the real-time requirement of a DDD system.

4. Conclusions

We present a DDD system which is very accurate, and very fast to work in real-time. The main component of the system is a DNN model that works directly with global faces extracted from video frames by a combination of face detection and tracking techniques. The DNN consists of three component: a CNN, a ConvCGRNN, and a voting layer; works effectively to extract spatiotemporal representations from input faces, and predict drowsiness state. At inference time, the DNN sequentially processes frames from video stream without resetting ConvCGRNN states, so inference time is very fast. Experimental results on the NTHU-DDD dataset illustrate the effectiveness and efficiency of the proposed model.

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