



Bangladesh Army International University Of Science And Technology

**Title : ArNet A Deep Learning Architecture For Pixel-
wise Semantic Segmentation Of Images**

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Introduction

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Segmentation - Process that classify object in image



segmented →

- 1: Person
- 2: Purse
- 3: Plants/Grass
- 4: Sidewalk
- 5: Building/Structures

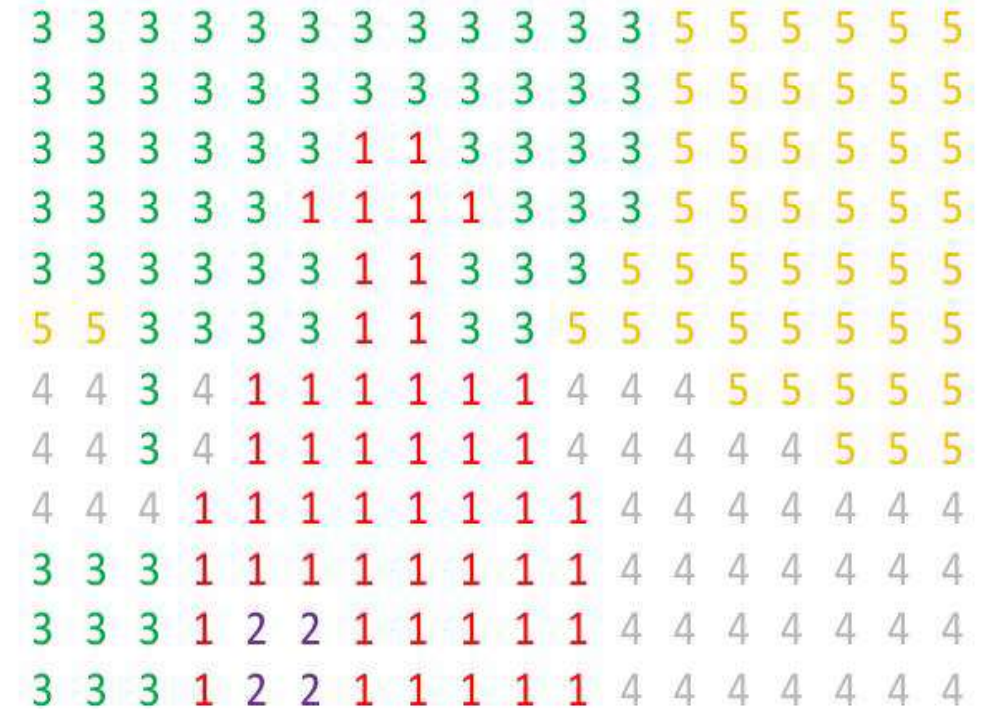


Figure 1: Visualization of how semantic segmentation works [1].

Challenges



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- **Building the DCNN**
- **Layer reduction**
- **Time reduction**
- **Add more classes**
- **Calculate the class weights**

Motivation for Research



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SegNet: A Deep Convolutional Encoder-Decoder Architecture for Image Segmentation [2]

- **Build to understand road scenes**
- **Model appearances and shapes**
- **Understand the spatial resolution between classes**
- **Used mostly for autonomous driving**

Literature Review



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- In *“Feedforward semantic segmentation with zoom-out features”* Mohammadreza Mostajabi, Payman Yadollahpour, and Gregory Shakhnarovich represented the statistical structure of an image by a purely feed forward network by mapping Superpixels using zoom-out features [3]
- In *“Convolutional Feature Masking for Joint Object and Stuff Segmentation ”* Jifeng Dai, Kaiming He, and Jian Sun image shape information was exploited by Convolutional Neural Network for objects that are connected [4]

Methodology

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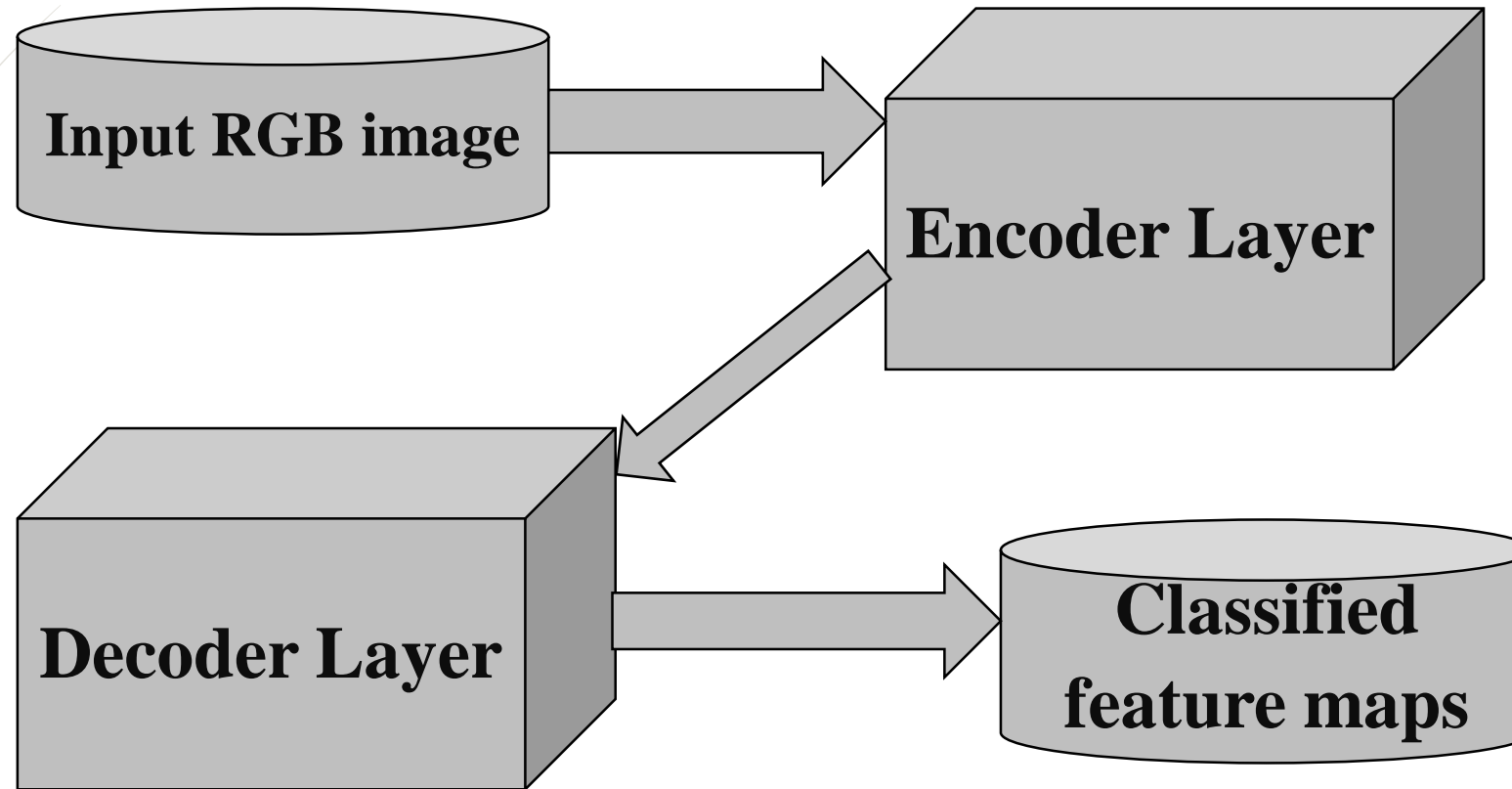


Figure 2: Overview of ArNet architecture.

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Encoder Layer

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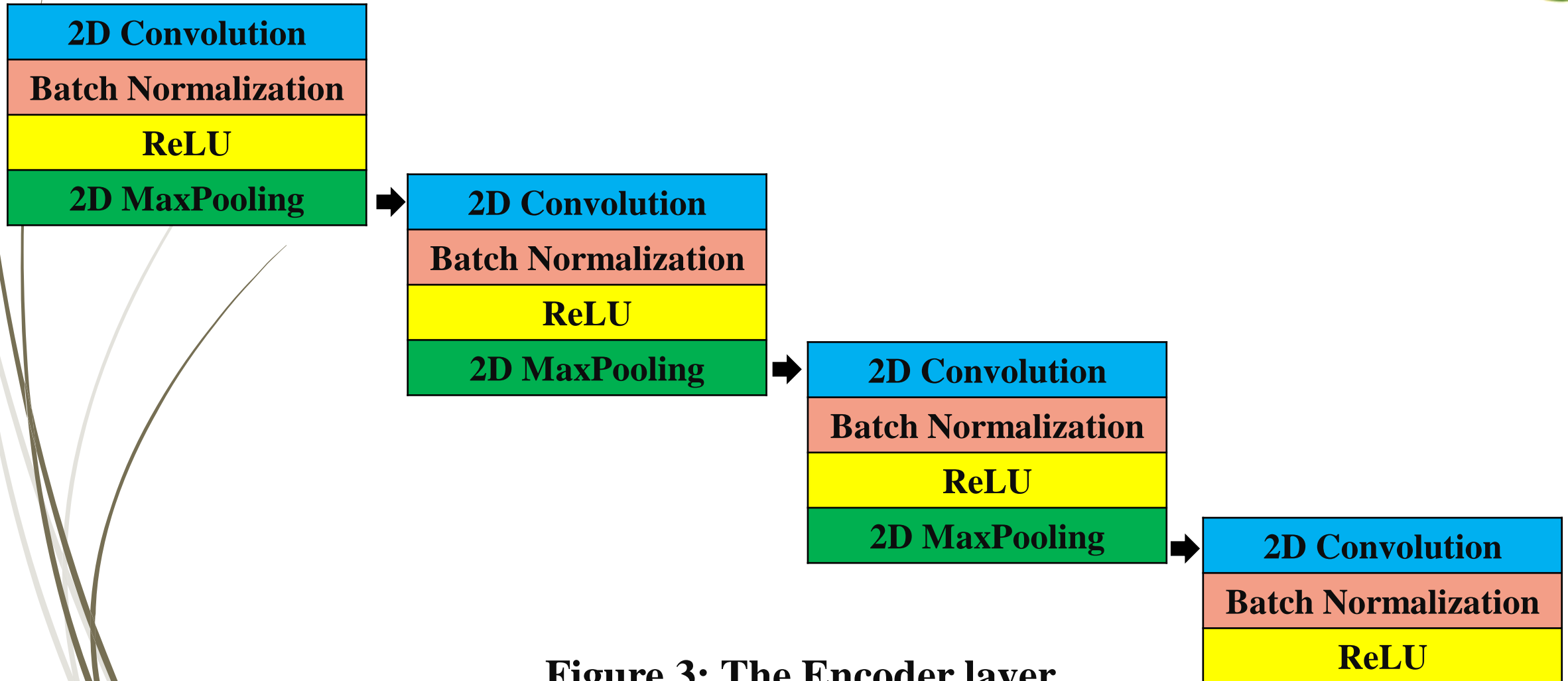


Figure 3: The Encoder layer.

Encoder Layer

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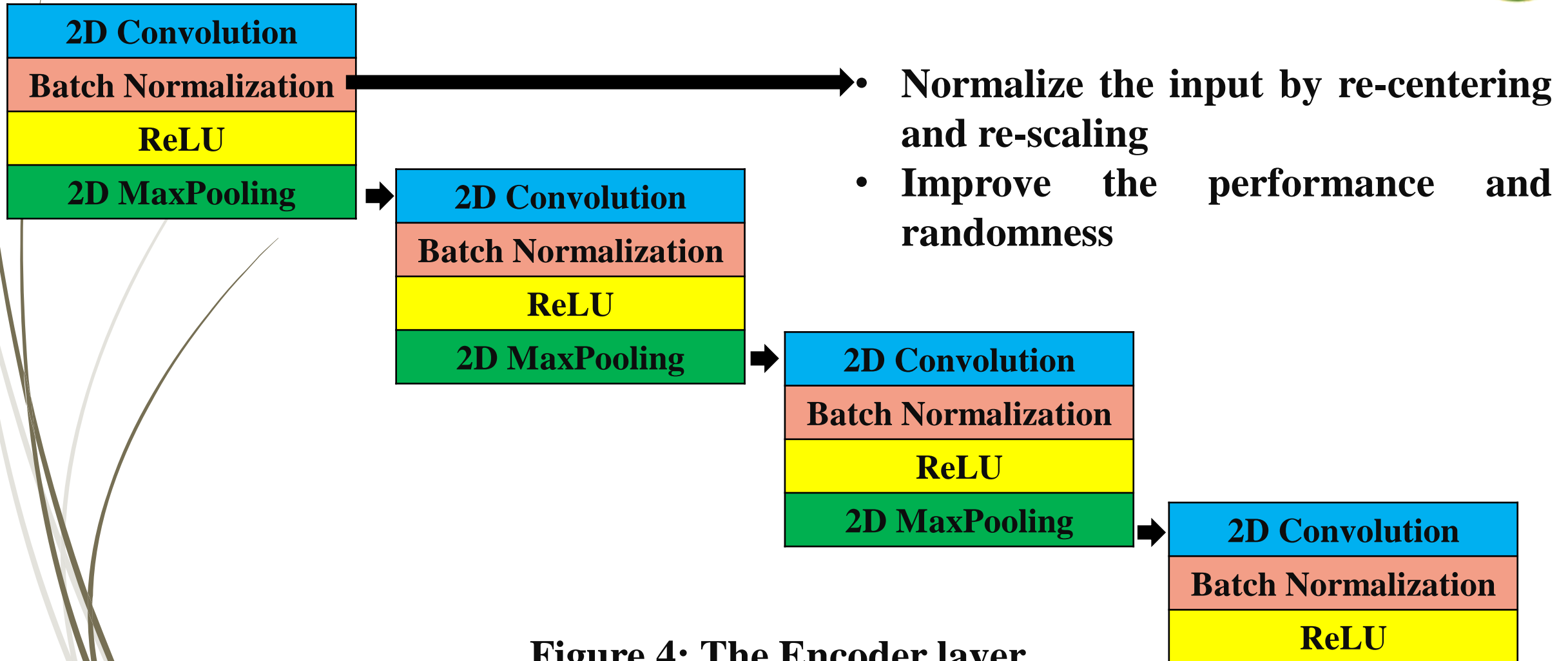


Figure 4: The Encoder layer.

Encoder Layer

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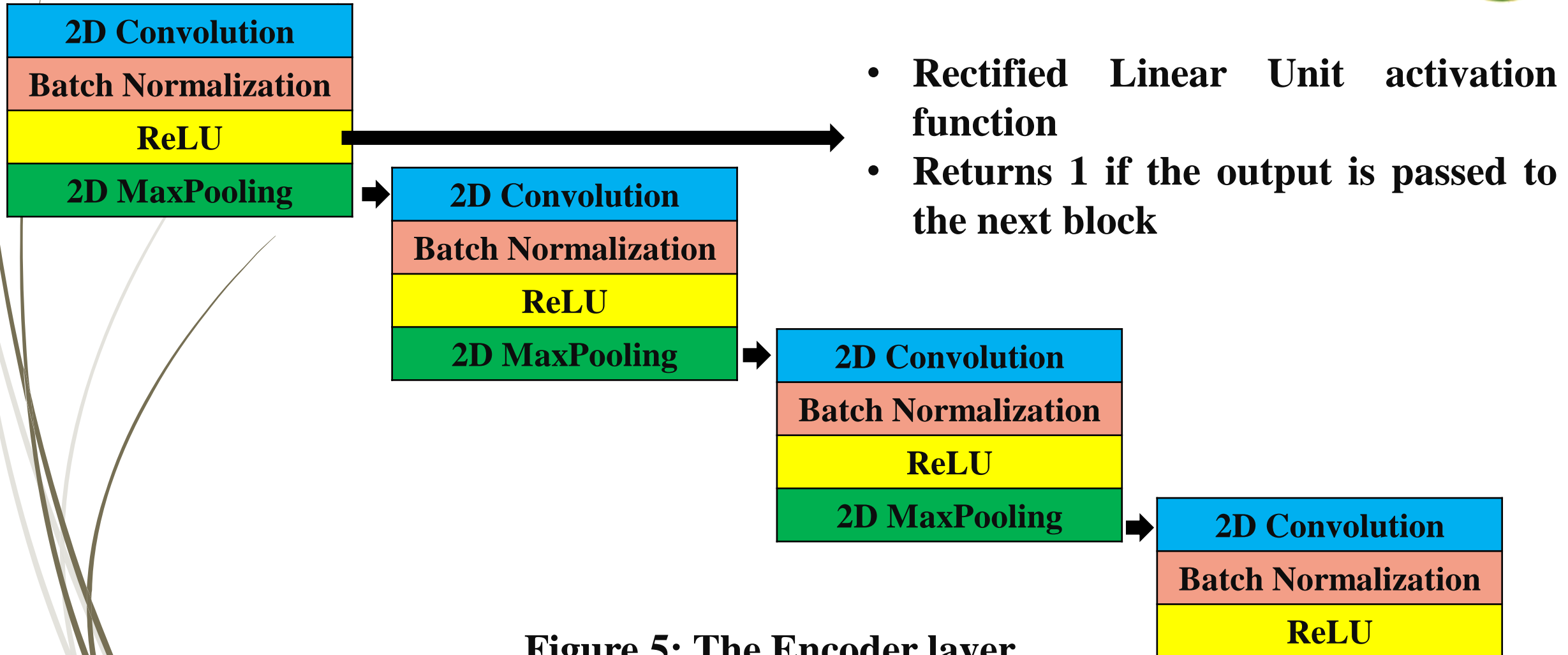


Figure 5: The Encoder layer.

2D Convolution

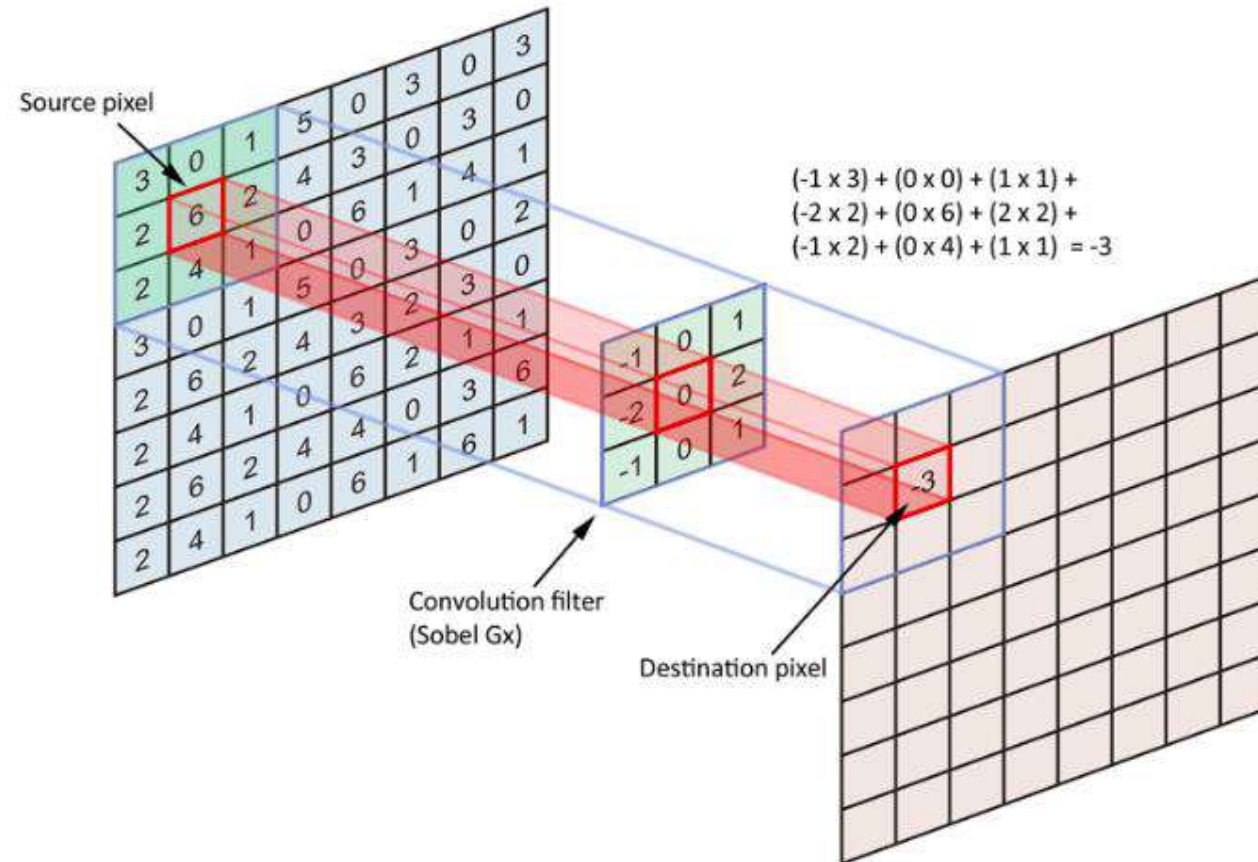


Figure 6: A 2D convolution operation [5].

2D MaxPooling

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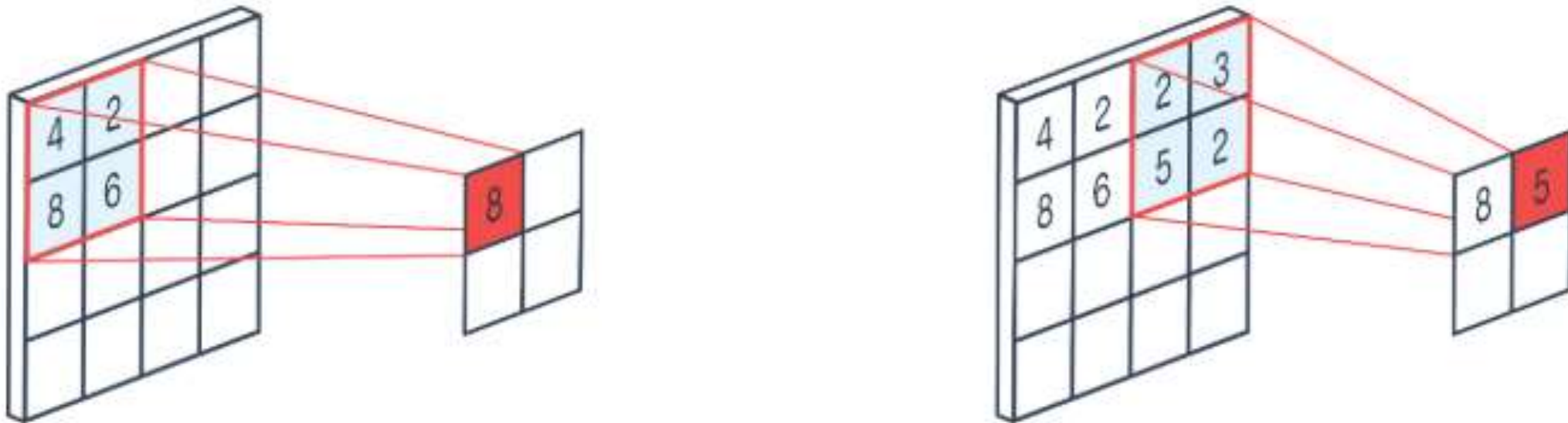


Figure 7: 2D MaxPooling [6].



Decoder Layer

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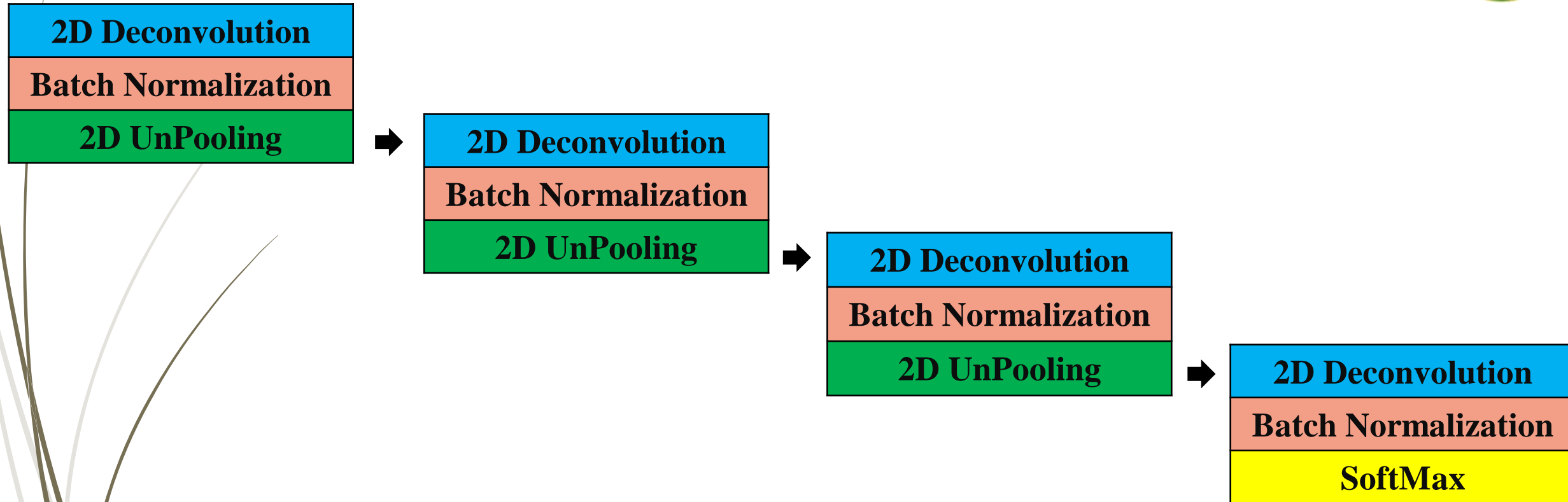


Figure 8: The Decoder layer.

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Decoder Layer

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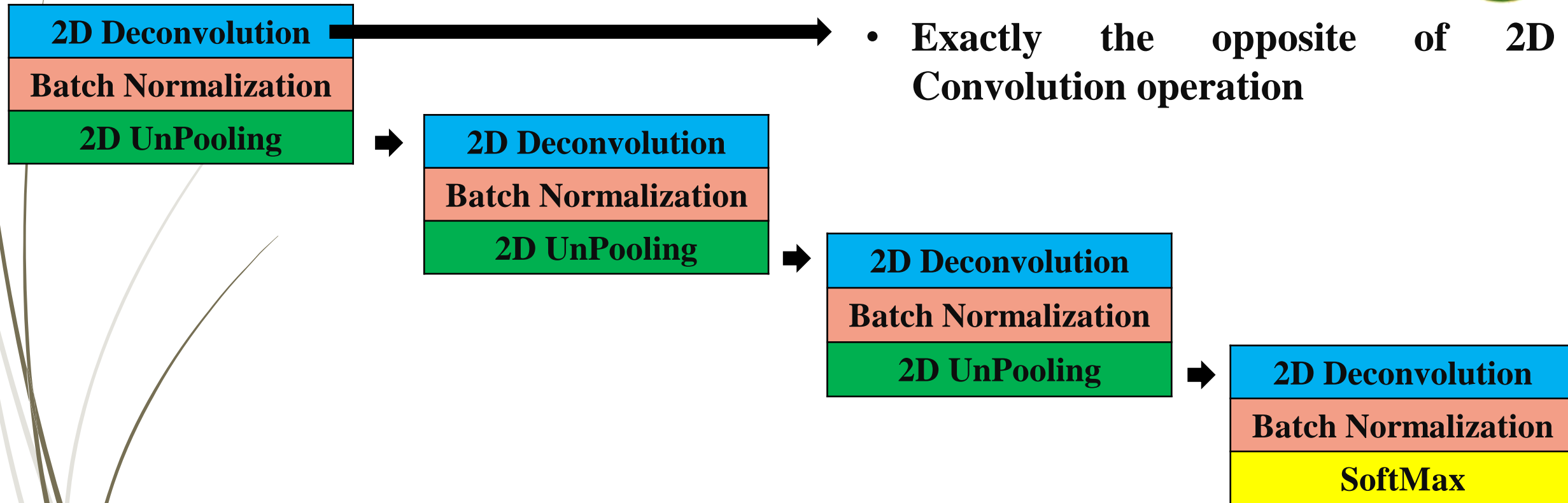


Figure 9: The Decoder layer.

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Decoder Layer

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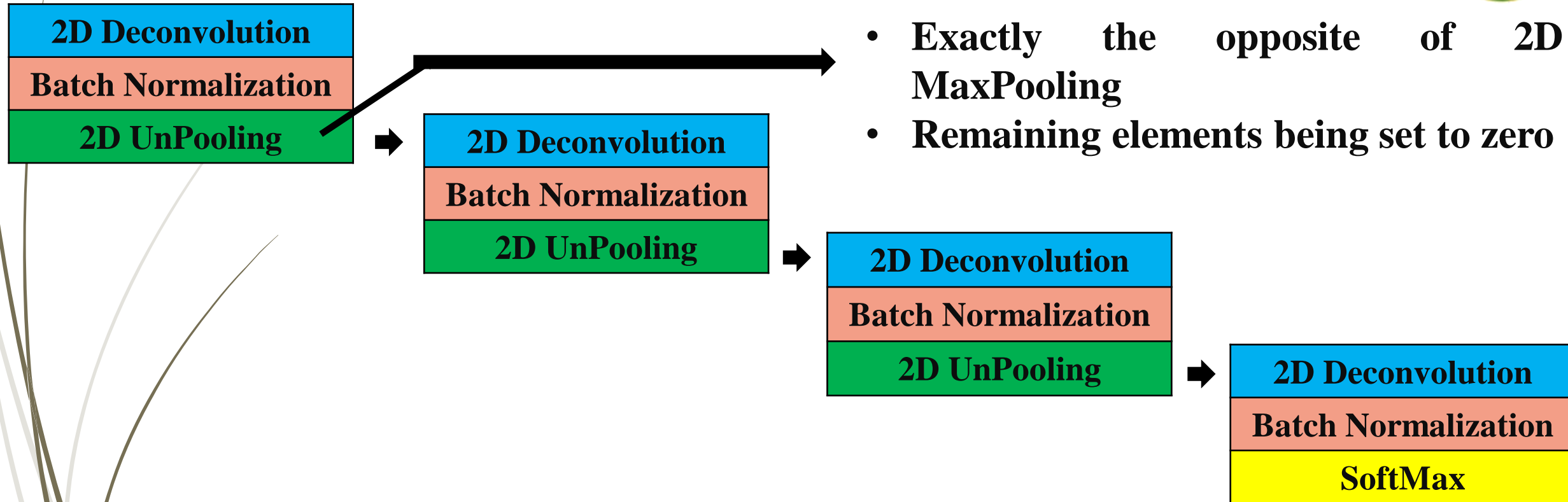


Figure 10: The Decoder layer.

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Decoder Layer

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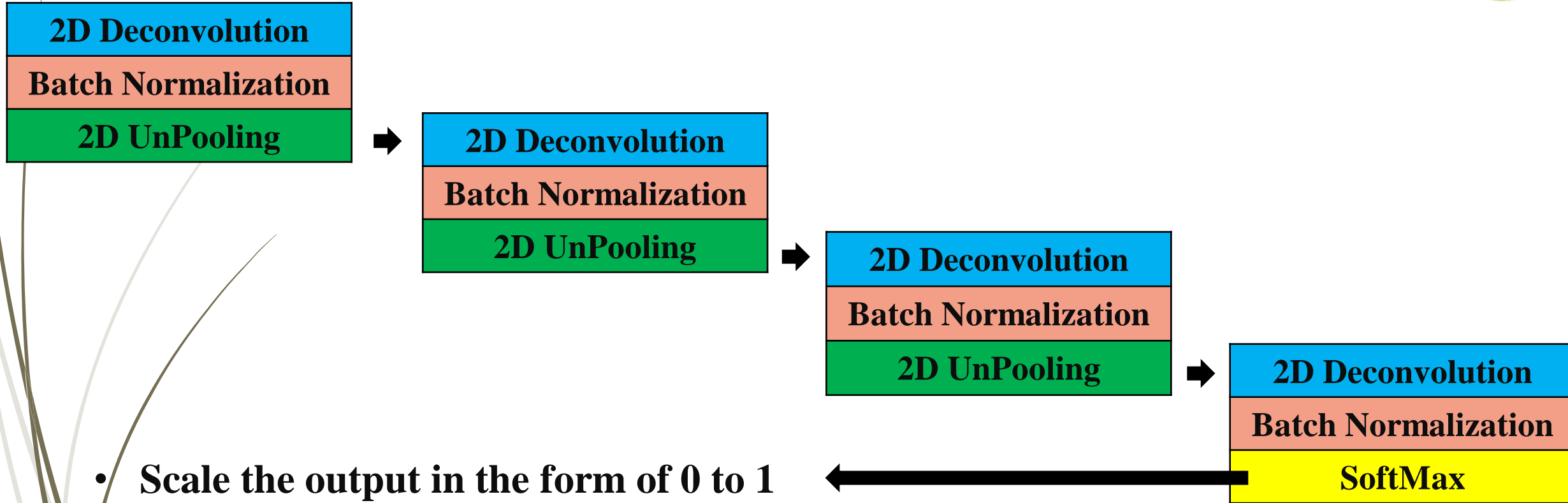


Figure 11: The Decoder layer.

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Dataset

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Figure 12: Some random image from the CamVid Dataset [2].

Result

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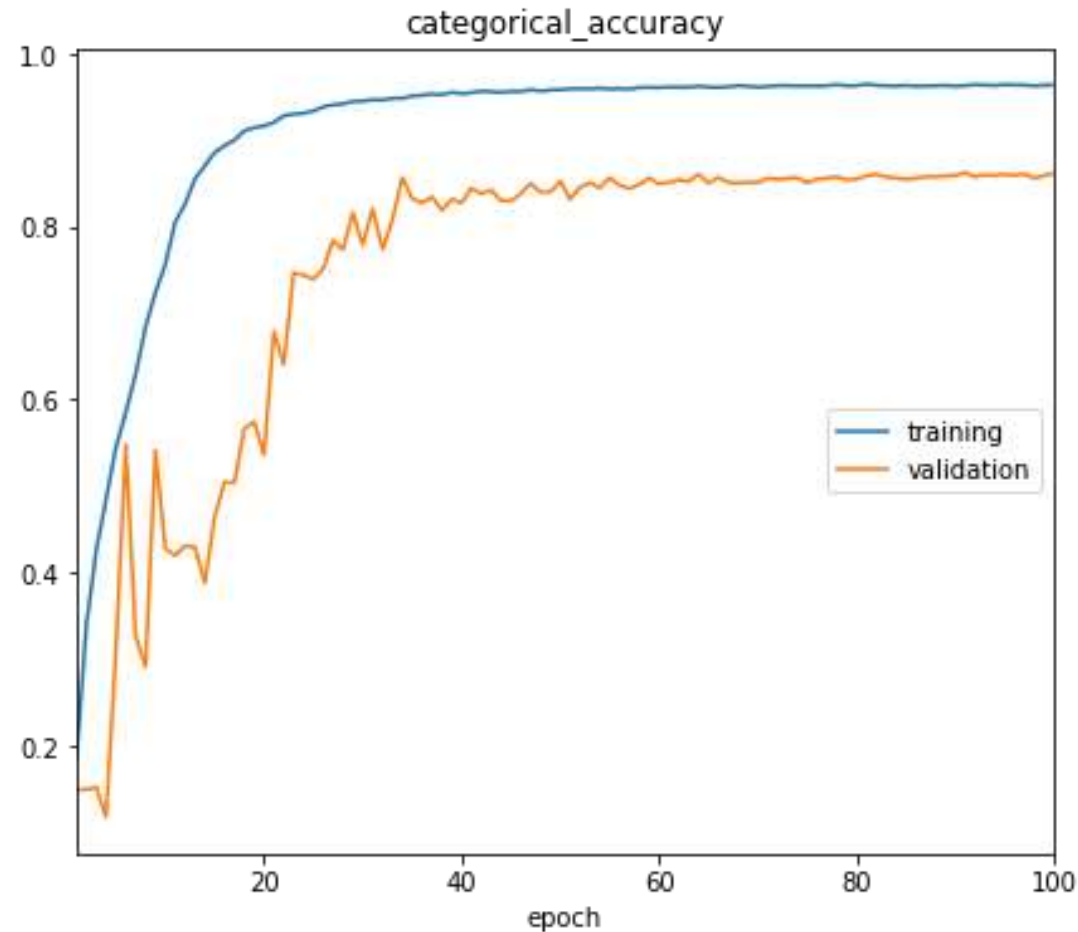


Figure 13: Categorical accuracy per epoch of the training and validation data.

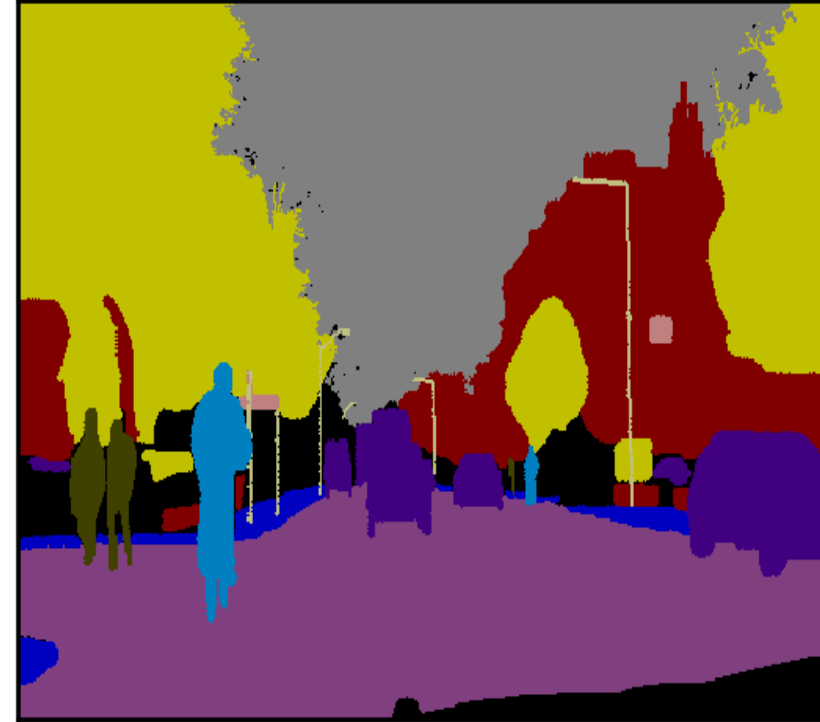
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Result

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(a) Input Image



(b) Visualization of feature map

Figure 14: Visualizing the results of ArNet architecture.

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Comparison

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Table 1: Validation accuracy comparison between some the state-of-the-art architecture and ArNet.

Architecture	Validation Accuracy	Time Per Epoch (avg)
FCN8 [13]	62.5%	12 minutes
SegNet [18]	88.0%	1.6 hours
FC-DenseNet100 [19]	91.2%	13 hours (only one epoch was done completely)
ArNet	88.7%	32 minutes

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Limitations

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- **Machine oriented architecture**
- **Very time consuming**
 - **32 minutes per epoch on average**
- **Low number of dataset**

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Conclusion

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- **Improve machine visions**
- **Improve robotics**
- **Improve autonomous driving technology**



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Future Work

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- **Lower number of blocks**
- **Lower processing time**
- **More dataset**
- **Interface canny edge detector**

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References



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Thank you.....