

# Lecture 15:

# Detection and Segmentation

# Administrative

- Assignment 3 due 5/25.
- A2 grades are out.
- Milestone grades will be out later today.

# Image Classification: A core task in Computer Vision



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(assume given a set of possible labels)  
{dog, cat, truck, plane, ...}



cat

# Computer Vision Tasks

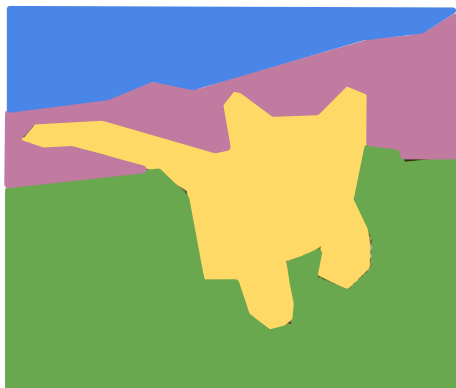
## Classification



**CAT**

No spatial extent

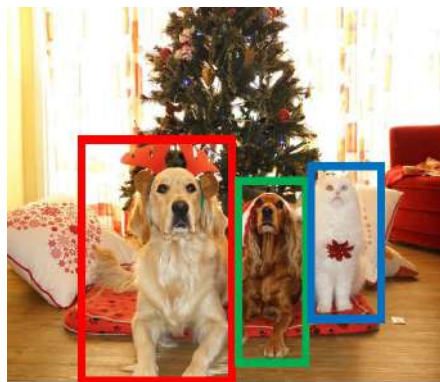
## Semantic Segmentation



**GRASS, CAT,  
TREE, SKY**

No objects, just pixels

## Object Detection



**DOG, DOG, CAT**

Multiple Object

## Instance Segmentation



**DOG, DOG, CAT**

[This image is CC0 public domain](#)

# Semantic Segmentation

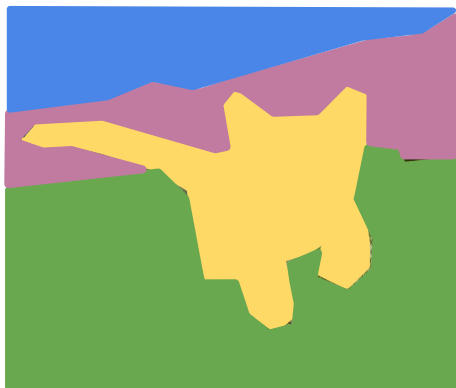
Classification



CAT

No spatial extent

Semantic Segmentation



GRASS, CAT,  
TREE, SKY

No objects, just pixels

Object Detection



DOG, DOG, CAT

Multiple Object

Instance Segmentation



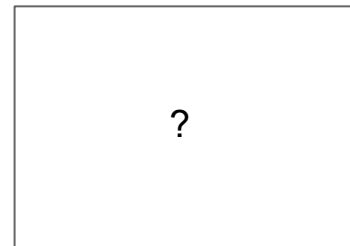
DOG, DOG, CAT

# Semantic Segmentation: The Problem



GRASS, CAT,  
TREE, SKY, ...

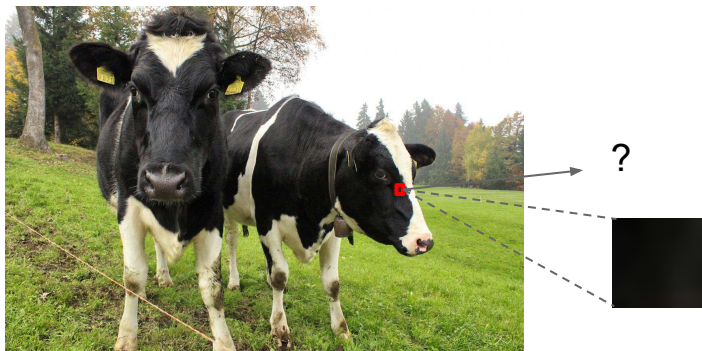
Paired training data: for each training image,  
each pixel is labeled with a semantic category.



At test time, classify each pixel of a new image.

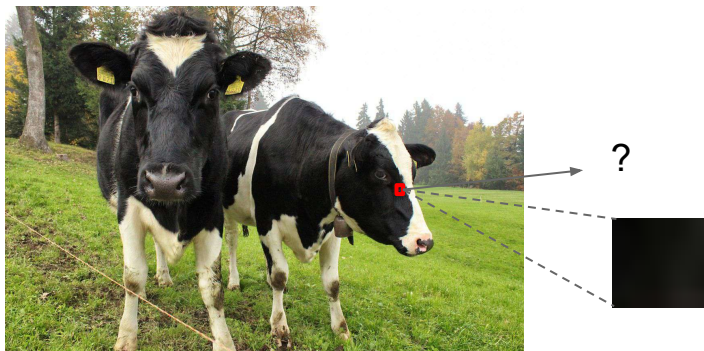
# Semantic Segmentation Idea: Sliding Window

Full image



# Semantic Segmentation Idea: Sliding Window

Full image

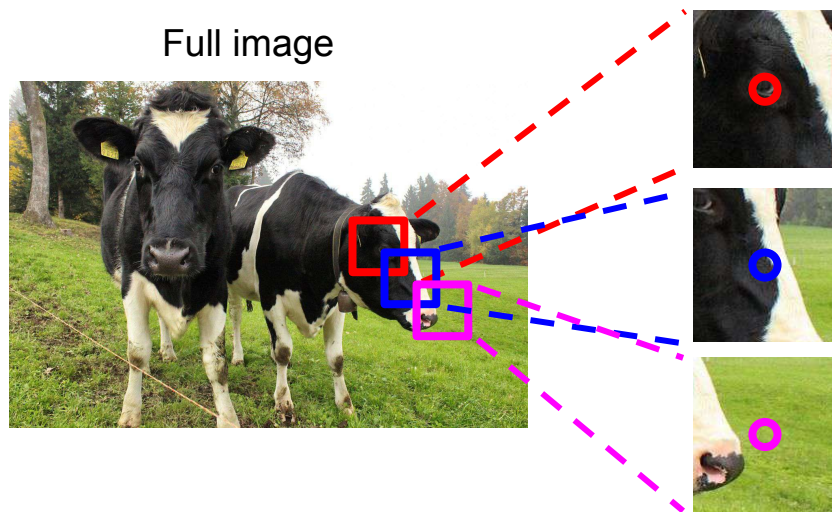


Impossible to classify without context

Q: how do we include context?

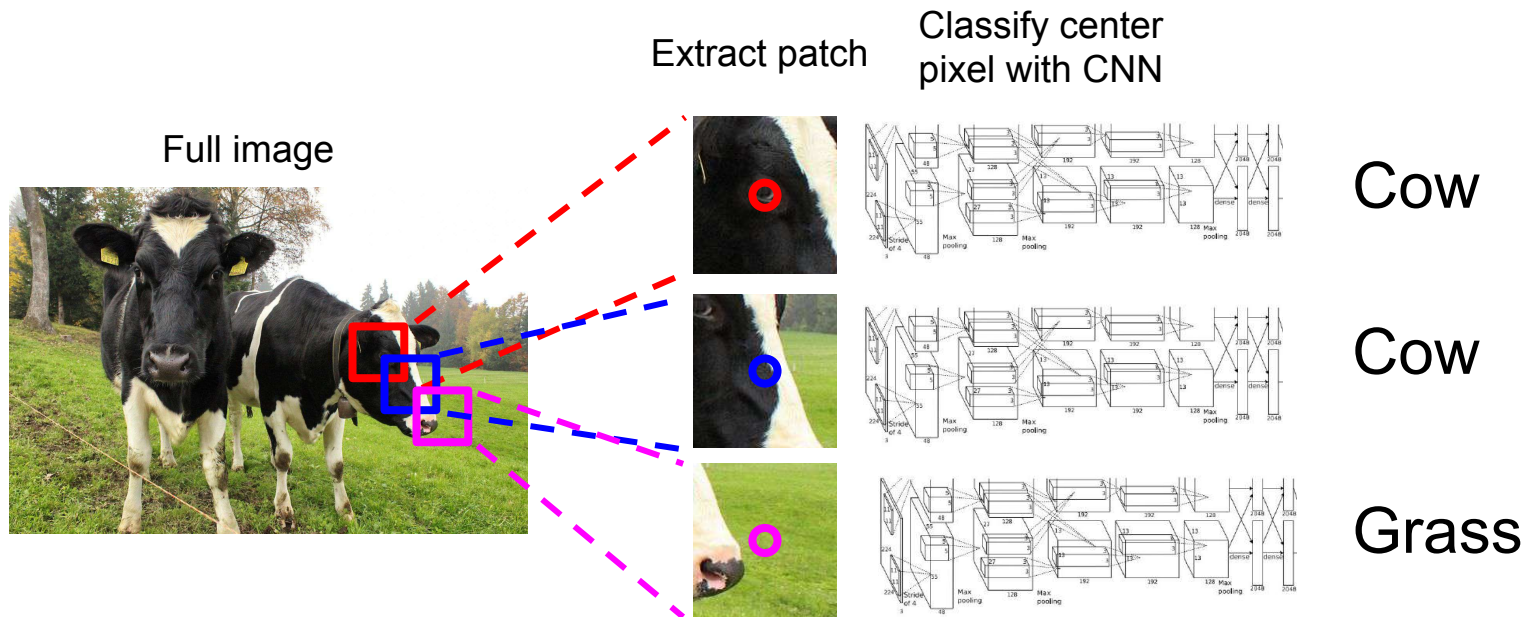


# Semantic Segmentation Idea: Sliding Window



Q: how do we model this?

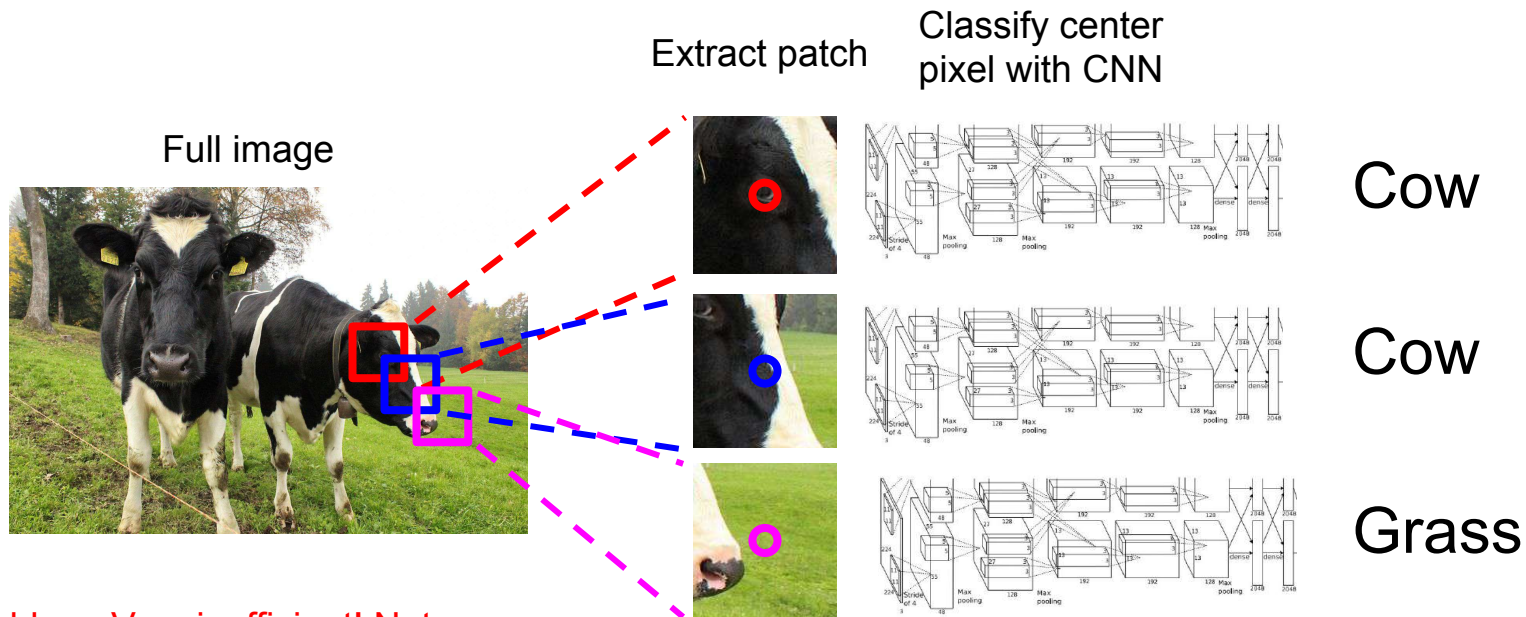
# Semantic Segmentation Idea: Sliding Window



Farabet et al, "Learning Hierarchical Features for Scene Labeling," TPAMI 2013

Pinheiro and Collobert, "Recurrent Convolutional Neural Networks for Scene Labeling", ICML 2014

# Semantic Segmentation Idea: Sliding Window

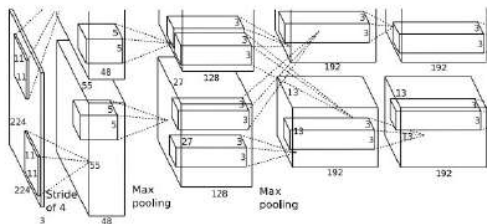


Problem: Very inefficient! Not reusing shared features between overlapping patches

Farabet et al, "Learning Hierarchical Features for Scene Labeling," TPAMI 2013  
Pinheiro and Collobert, "Recurrent Convolutional Neural Networks for Scene Labeling", ICML 2014

# Semantic Segmentation Idea: Convolution

Full image

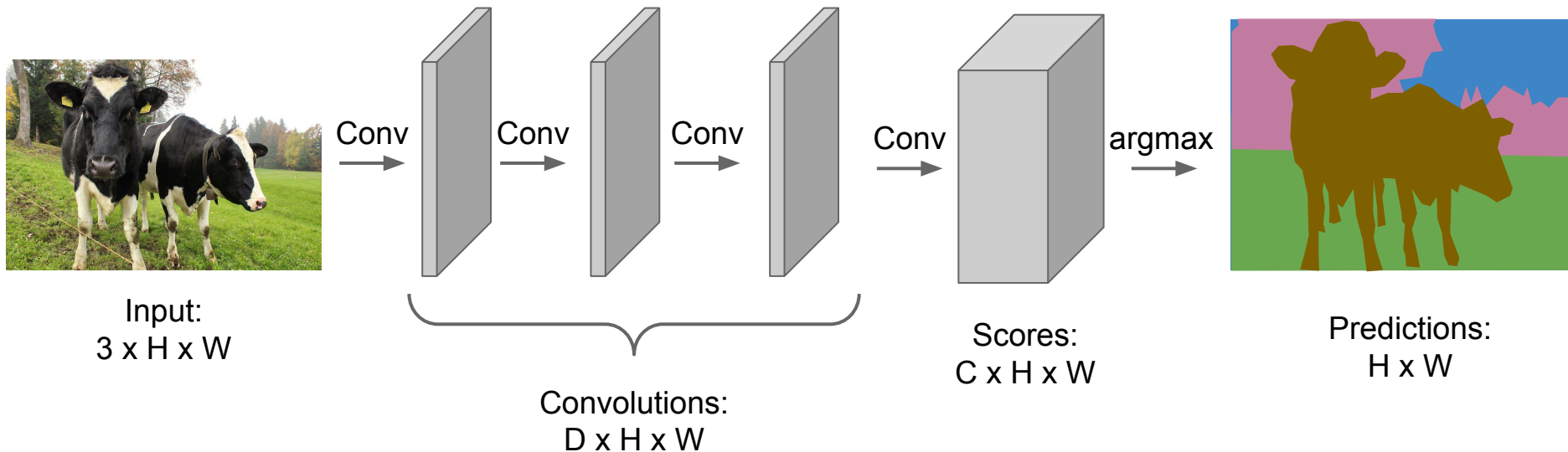


An intuitive idea: encode the entire image with conv net, and do semantic segmentation on top.

**Problem:** classification architectures often reduce feature spatial sizes to go deeper, but semantic segmentation requires the output size to be the same as input size.

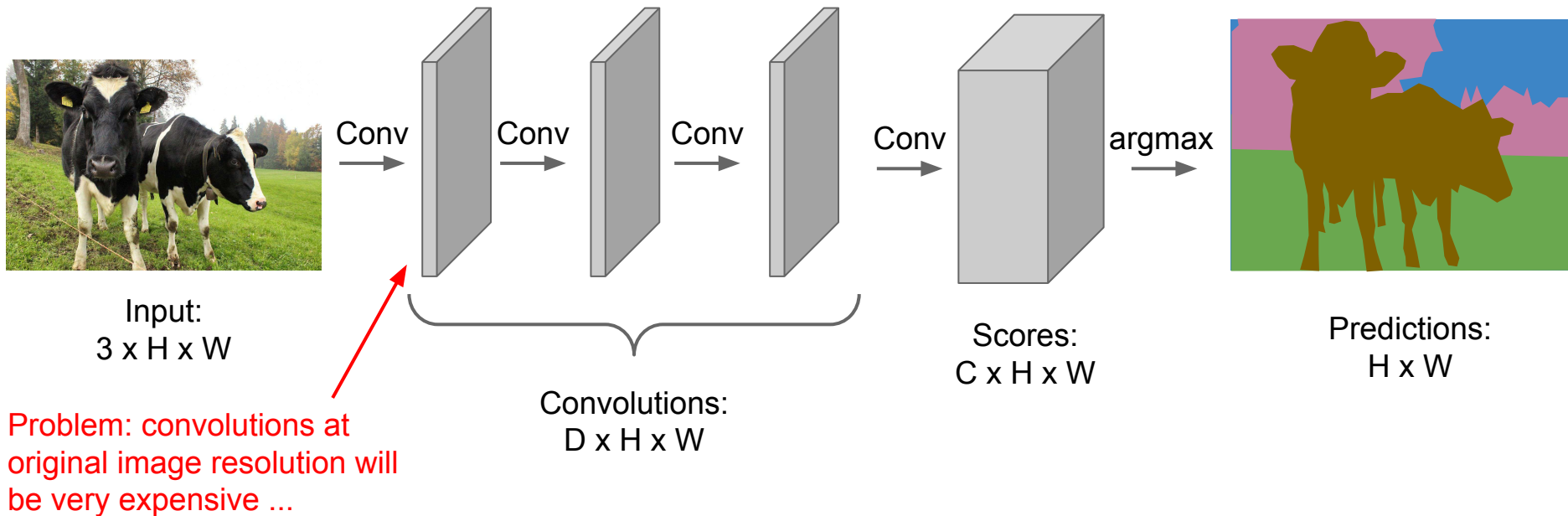
# Semantic Segmentation Idea: Fully Convolutional

Design a network with only convolutional layers without downsampling operators to make predictions for pixels all at once!



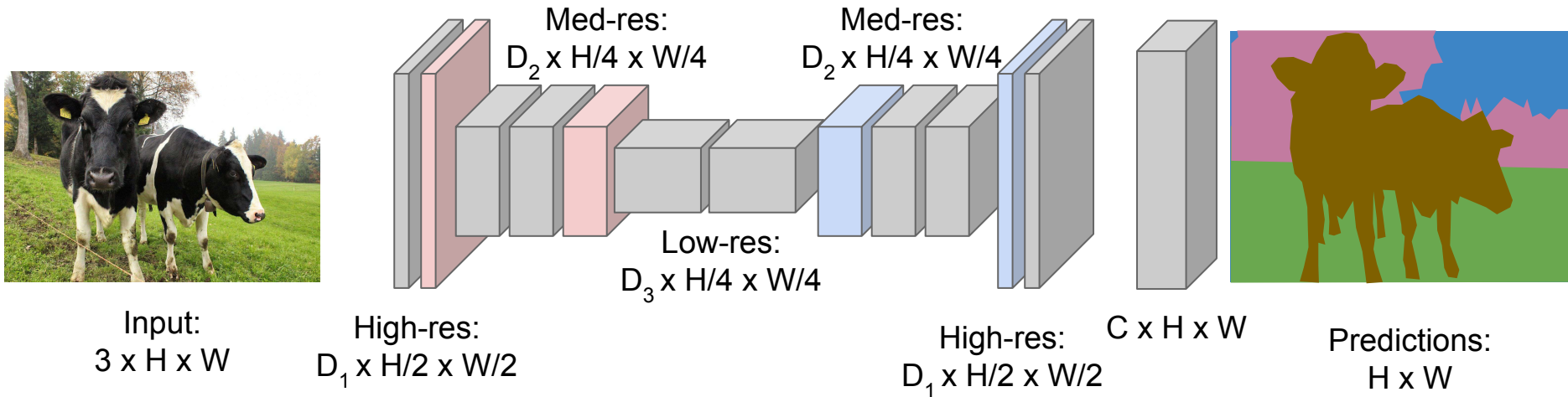
# Semantic Segmentation Idea: Fully Convolutional

Design a network with only convolutional layers without downsampling operators to make predictions for pixels all at once!



# Semantic Segmentation Idea: Fully Convolutional

Design network as a bunch of convolutional layers, with **downsampling** and **upsampling** inside the network!



Long, Shelhamer, and Darrell, "Fully Convolutional Networks for Semantic Segmentation", CVPR 2015  
Noh et al, "Learning Deconvolution Network for Semantic Segmentation", ICCV 2015



# Semantic Segmentation Idea: Fully Convolutional

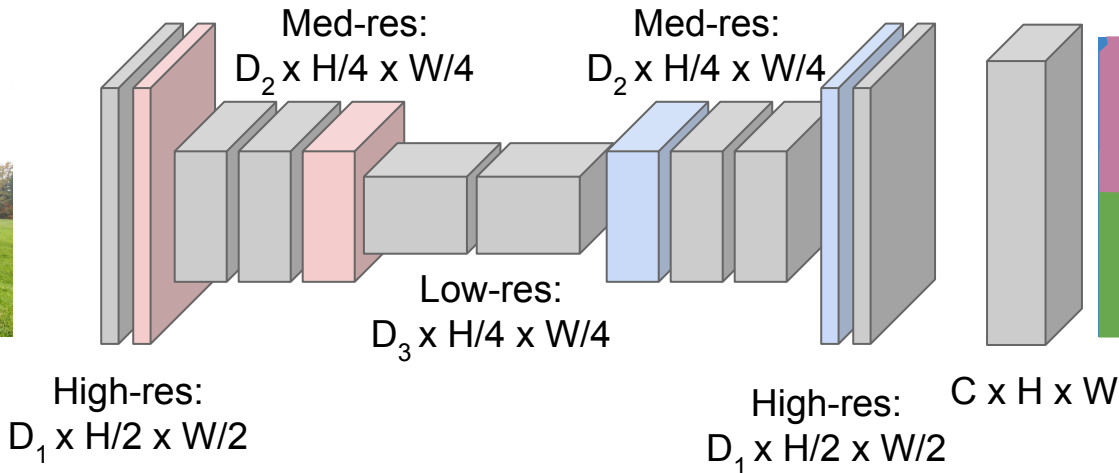
**Downsampling:**  
Pooling, strided  
convolution

Design network as a bunch of convolutional layers, with **downsampling** and **upsampling** inside the network!

**Upsampling:**  
???



Input:  
 $3 \times H \times W$



Predictions:  
 $H \times W$

Long, Shelhamer, and Darrell, "Fully Convolutional Networks for Semantic Segmentation", CVPR 2015  
Noh et al, "Learning Deconvolution Network for Semantic Segmentation", ICCV 2015



# In-Network upsampling: “Unpooling”

**Nearest Neighbor**

1	2
3	4

Input: 2 x 2



1	1	2	2
1	1	2	2
3	3	4	4
3	3	4	4

Output: 4 x 4

**“Bed of Nails”**

1	2
3	4

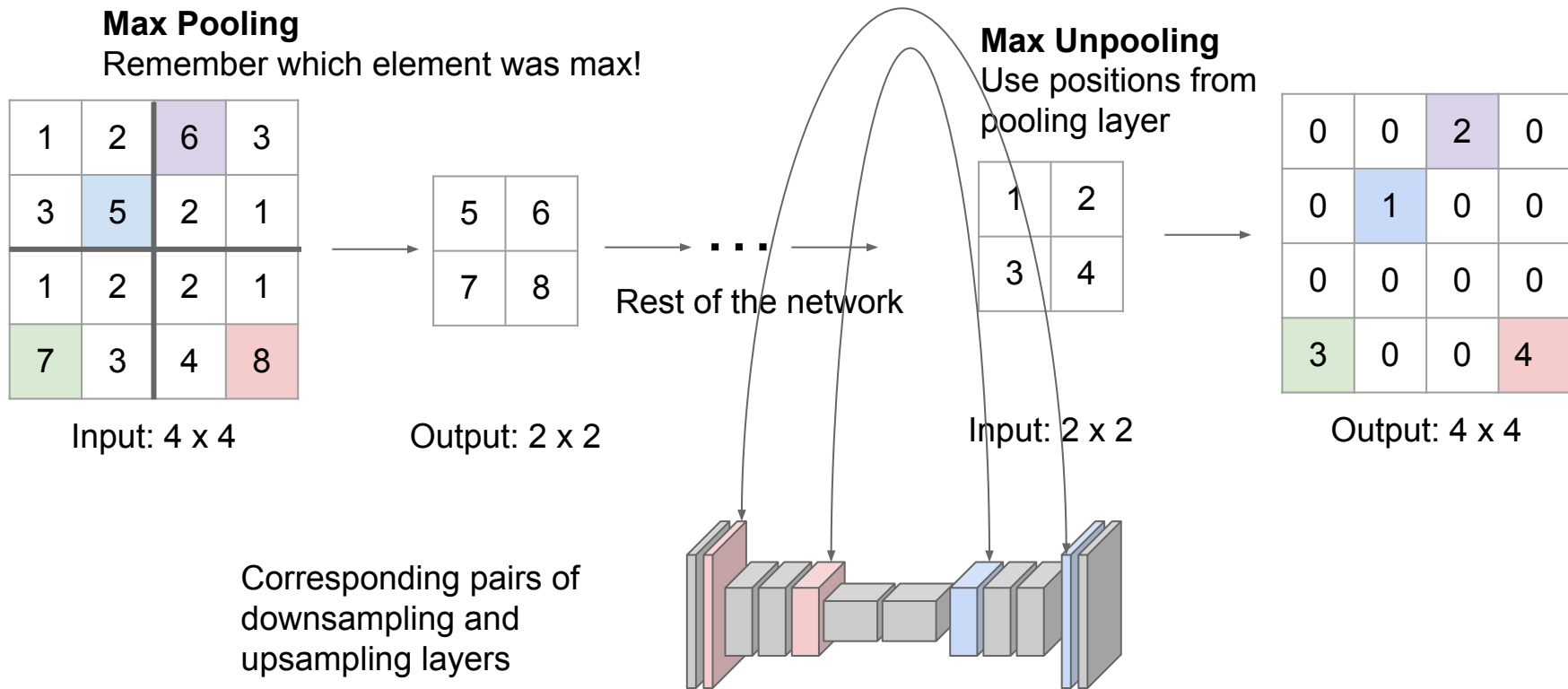
Input: 2 x 2



1	0	2	0
0	0	0	0
3	0	4	0
0	0	0	0

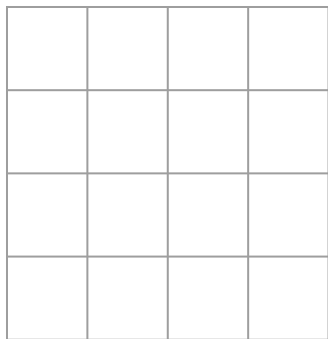
Output: 4 x 4

# In-Network upsampling: “Max Unpooling”

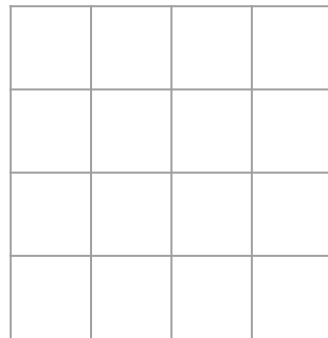


# Learnable Upsampling

**Recall:** Normal 3 x 3 convolution, stride 1 pad 1



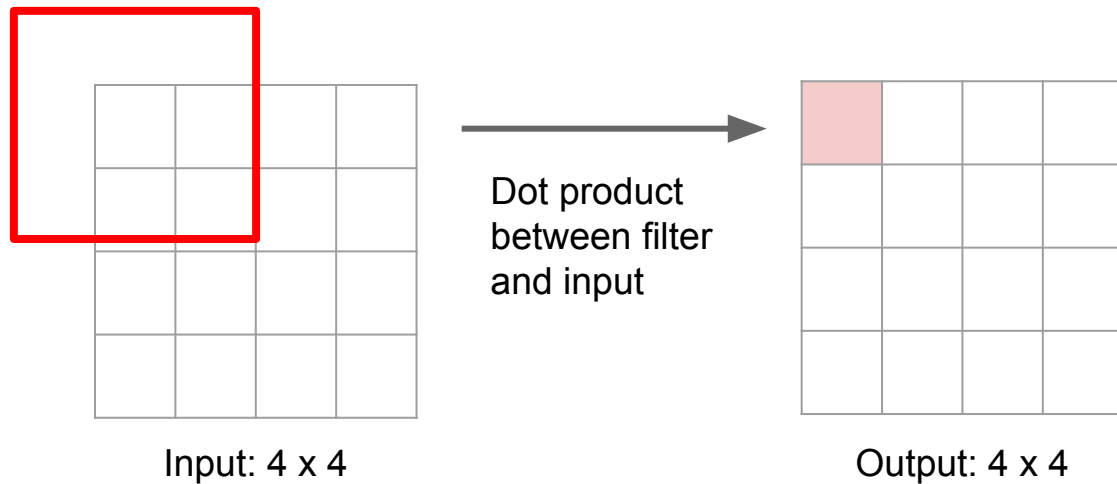
Input: 4 x 4



Output: 4 x 4

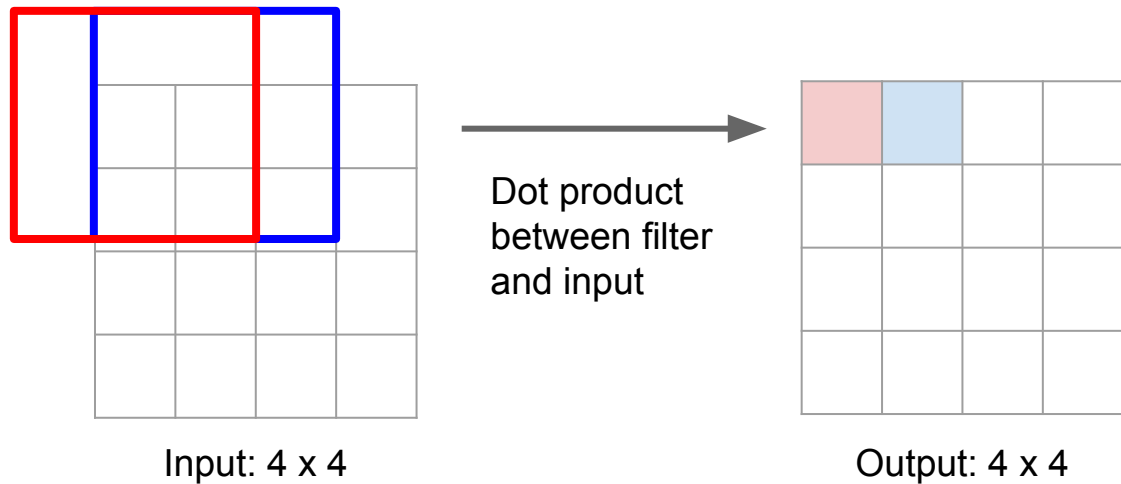
# Learnable Upsampling

**Recall:** Normal 3 x 3 convolution, stride 1 pad 1



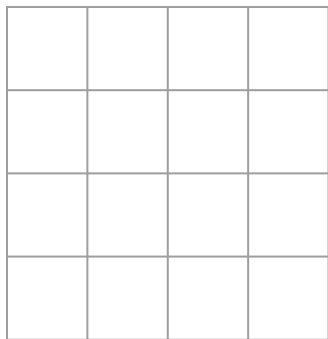
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**Recall:** Normal 3 x 3 convolution, stride 1 pad 1

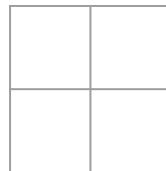


# Learnable Upsampling

**Recall:** Normal 3 x 3 convolution, stride 2 pad 1



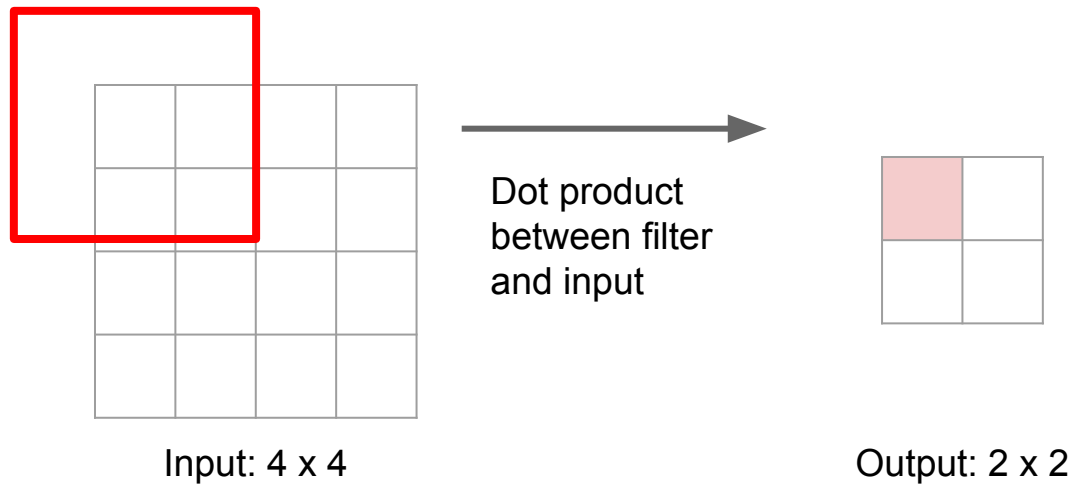
Input: 4 x 4



Output: 2 x 2

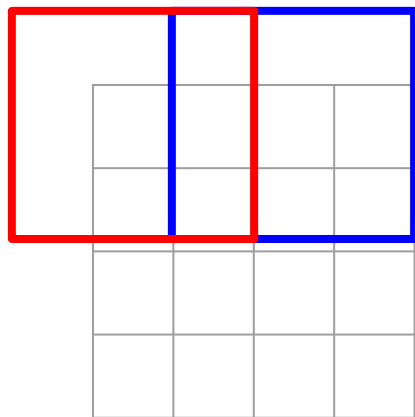
# Learnable Upsampling

**Recall:** Normal 3 x 3 convolution, stride 2 pad 1



# Learnable Upsampling

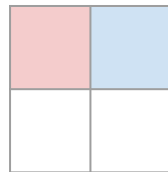
**Recall:** Normal 3 x 3 convolution, stride 2 pad 1



Input: 4 x 4



Dot product  
between filter  
and input



Output: 2 x 2

Filter moves 2 pixels in the input for every one pixel in the output

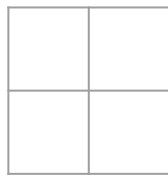
Stride gives ratio between movement in input and output

We can interpret strided convolution as “learnable downsampling”.

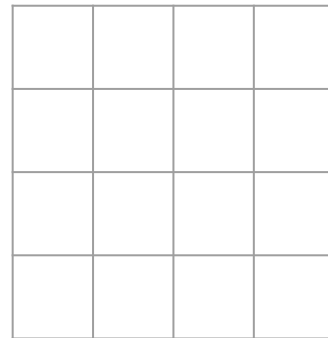


# Learnable Upsampling: Transposed Convolution

3 x 3 **transpose** convolution, stride 2 pad 1



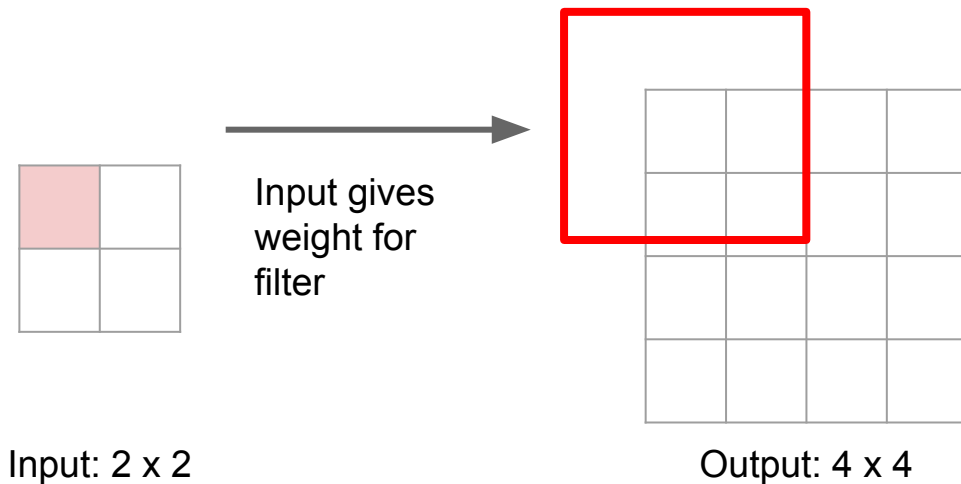
Input: 2 x 2



Output: 4 x 4

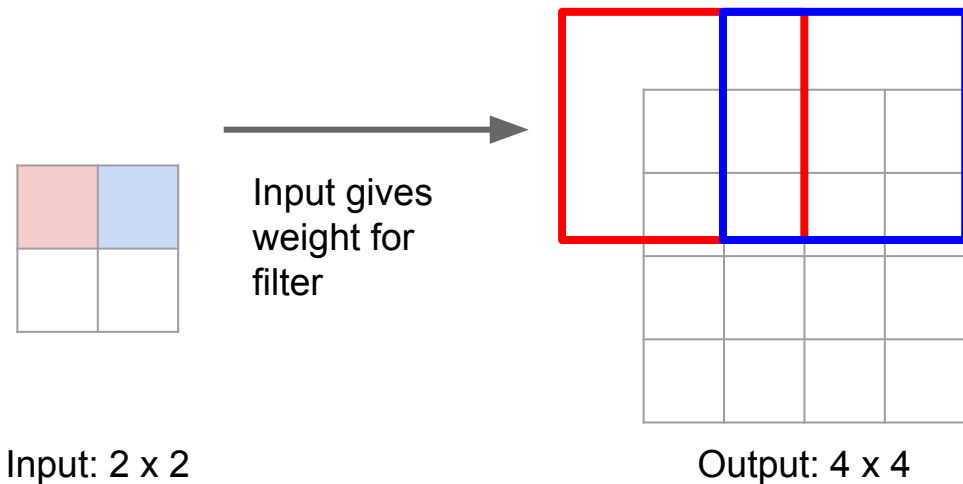
# Learnable Upsampling: Transposed Convolution

3 x 3 **transpose** convolution, stride 2 pad 1



# Learnable Upsampling: Transposed Convolution

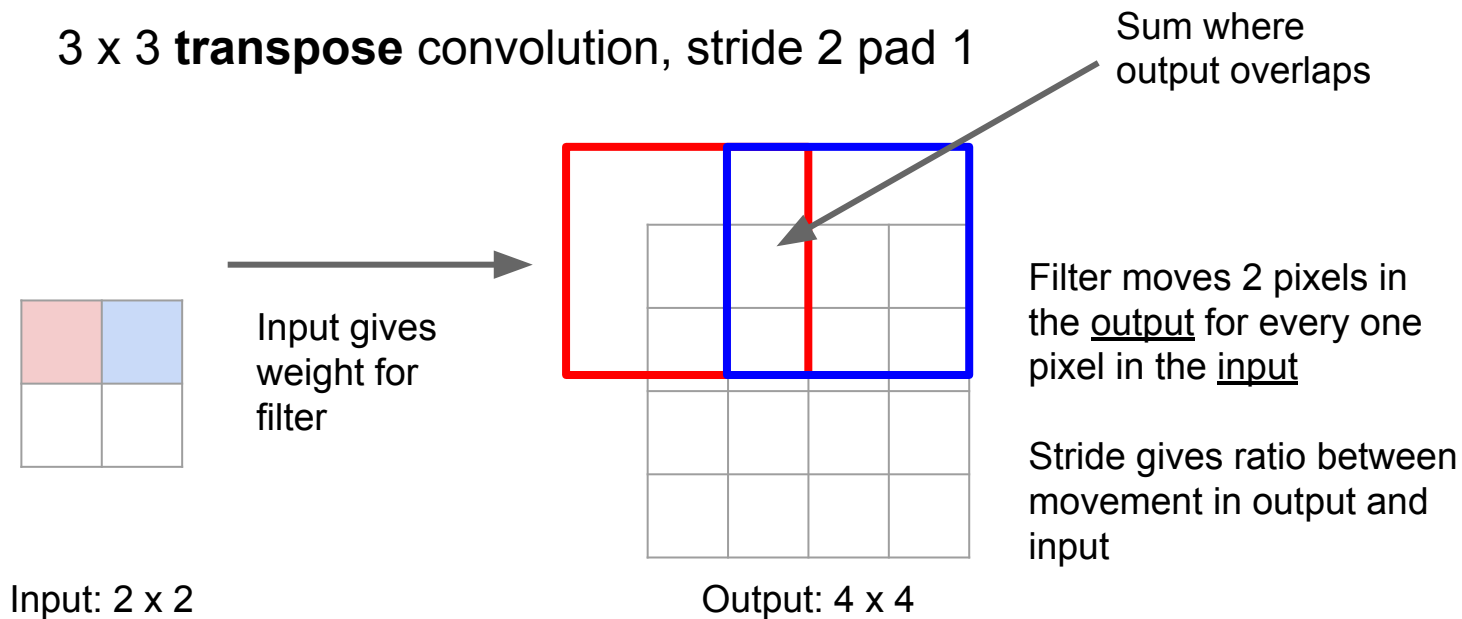
3 x 3 **transpose** convolution, stride 2 pad 1



Filter moves 2 pixels in the output for every one pixel in the input

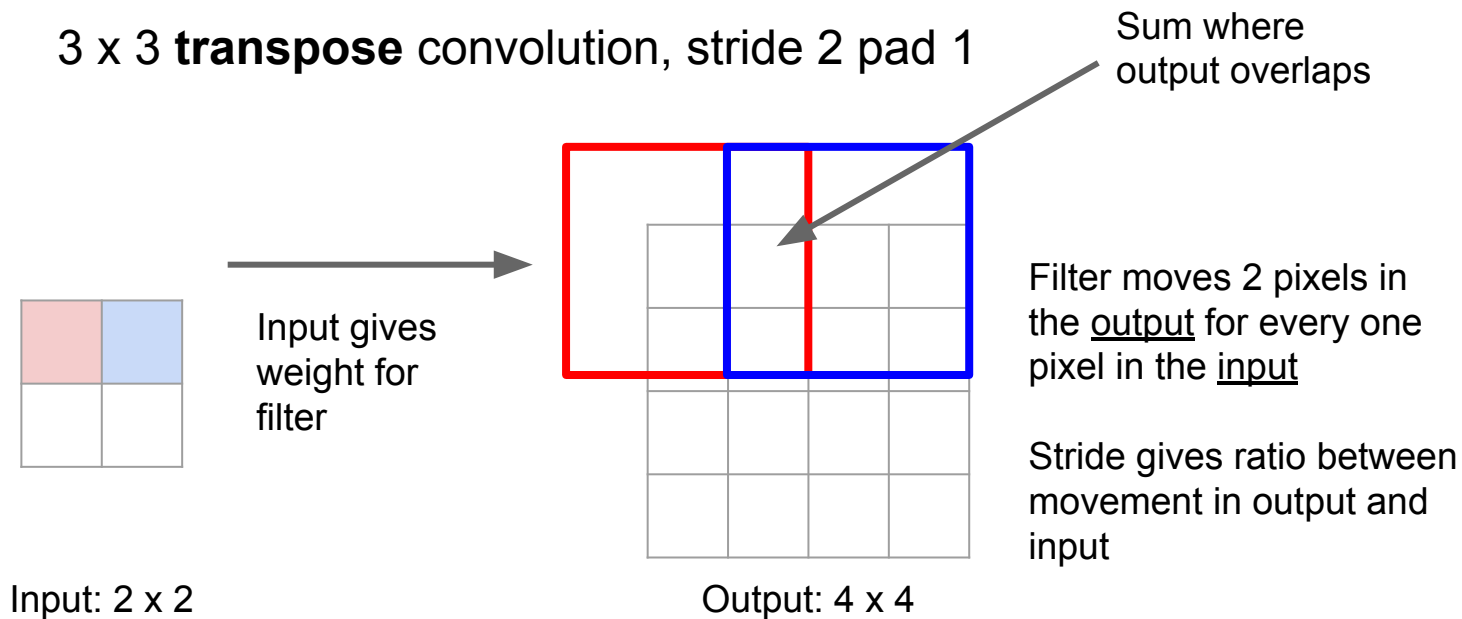
Stride gives ratio between movement in output and input

# Learnable Upsampling: Transposed Convolution

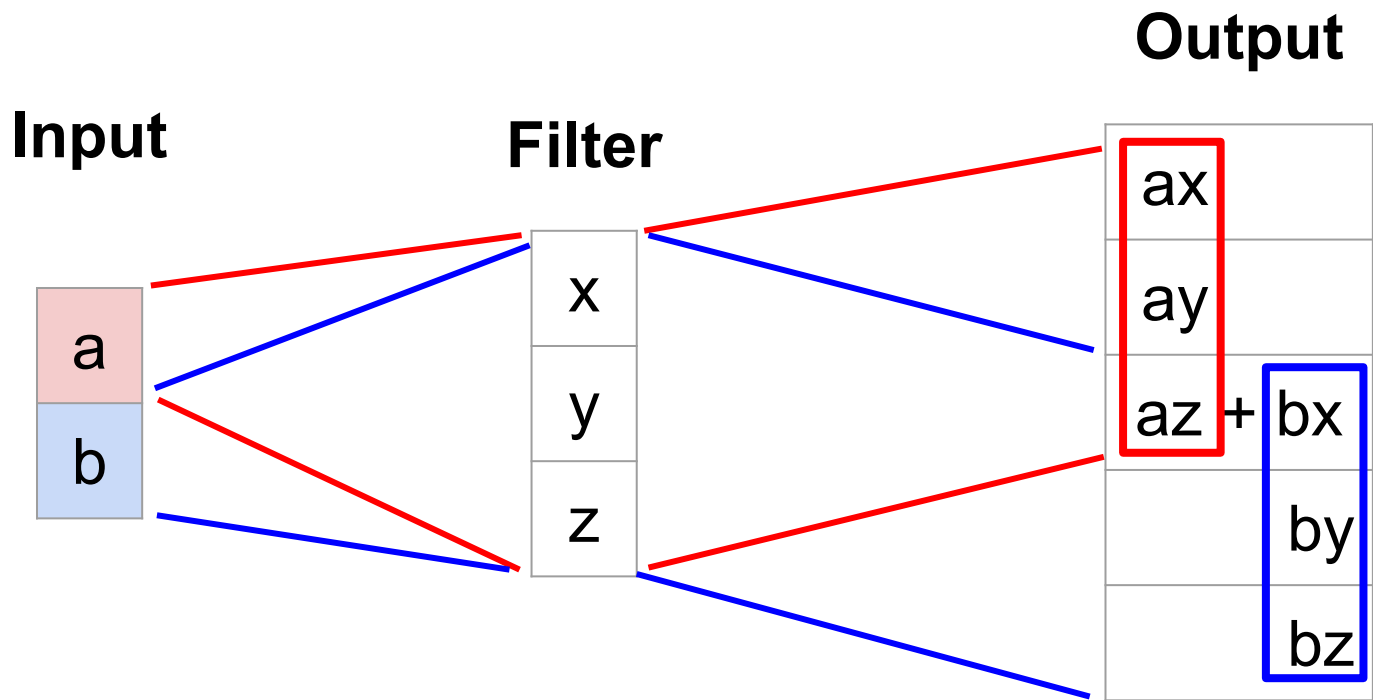


# Learnable Upsampling: Transposed Convolution

Q: Why is it called  
transpose  
convolution?



# Learnable Upsampling: 1D Example



Output contains copies of the filter weighted by the input, summing at where it overlaps in the output

# Convolution as Matrix Multiplication (1D Example)

We can express convolution in terms of a matrix multiplication

$$\vec{x} * \vec{a} = X\vec{a}$$

$$\begin{bmatrix} x & y & x & 0 & 0 & 0 \\ 0 & 0 & x & y & x & 0 \end{bmatrix} \begin{bmatrix} 0 \\ a \\ b \\ c \\ d \\ 0 \end{bmatrix} = \begin{bmatrix} ay + bz \\ bx + cy + dz \end{bmatrix}$$

Example: 1D conv, kernel  
size=3, stride=2, padding=1

# Convolution as Matrix Multiplication (1D Example)

We can express convolution in terms of a matrix multiplication

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$$\begin{bmatrix} x & y & x & 0 & 0 & 0 \\ 0 & 0 & x & y & x & 0 \end{bmatrix} \begin{bmatrix} 0 \\ a \\ b \\ c \\ d \\ 0 \end{bmatrix} = \begin{bmatrix} ay + bz \\ bx + cy + dz \end{bmatrix}$$

Example: 1D conv, kernel size=3, stride=2, padding=1

Convolution transpose multiplies by the transpose of the same matrix:

$$\vec{x} *^T \vec{a} = X^T \vec{a}$$

$$\begin{bmatrix} x & 0 \\ y & 0 \\ z & x \\ 0 & y \\ 0 & z \\ 0 & 0 \end{bmatrix} \begin{bmatrix} a \\ b \end{bmatrix} = \begin{bmatrix} ax \\ ay \\ az + bx \\ by \\ bz \\ 0 \end{bmatrix}$$

Example: 1D transpose conv, kernel size=3, stride=2, padding=0



# Semantic Segmentation Idea: Fully Convolutional

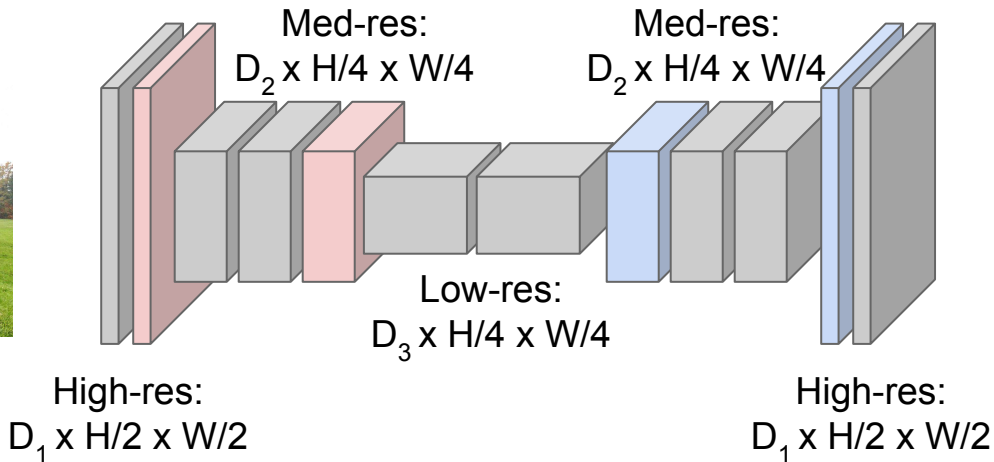
**Downsampling:**  
Pooling, strided  
convolution

Design network as a bunch of convolutional layers, with **downsampling** and **upsampling** inside the network!

**Upsampling:**  
Unpooling or strided  
transpose convolution



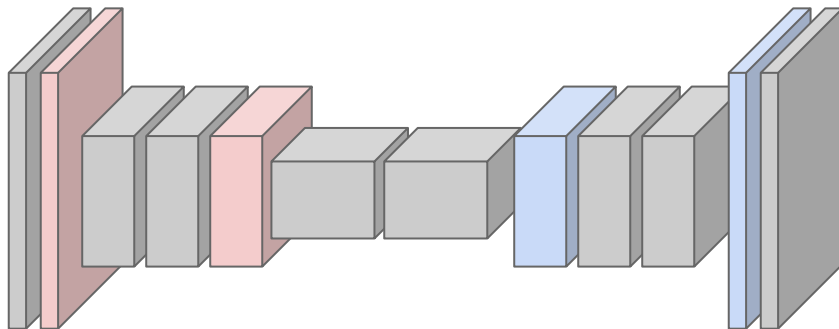
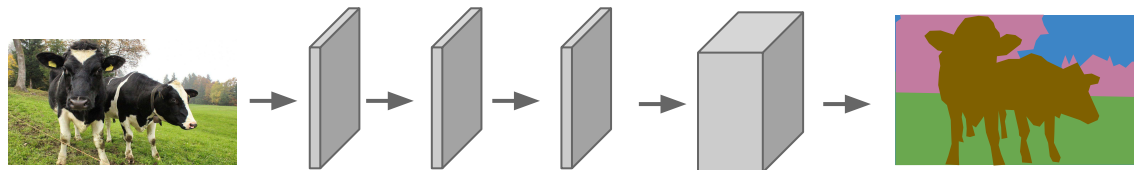
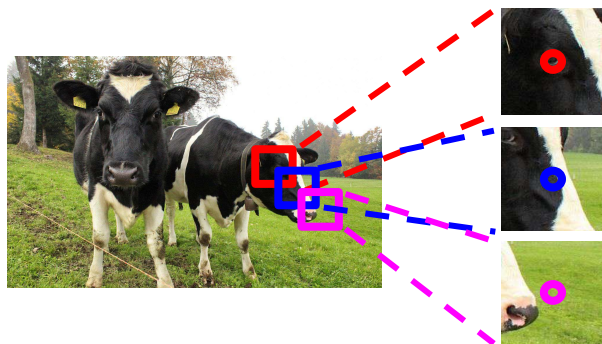
Input:  
 $3 \times H \times W$



Predictions:  
 $H \times W$

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Noh et al, "Learning Deconvolution Network for Semantic Segmentation", ICCV 2015

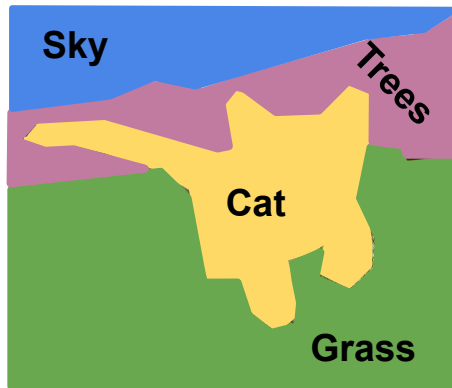
# Semantic Segmentation: Summary



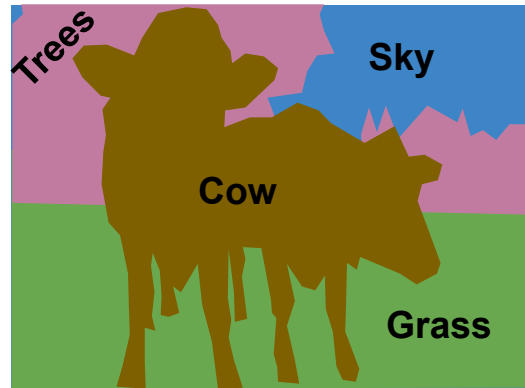
# Semantic Segmentation

Label each pixel in the image with a category label

Don't differentiate instances, only care about pixels



[This image](#) is [CC0 public domain](#)



# Object Detection

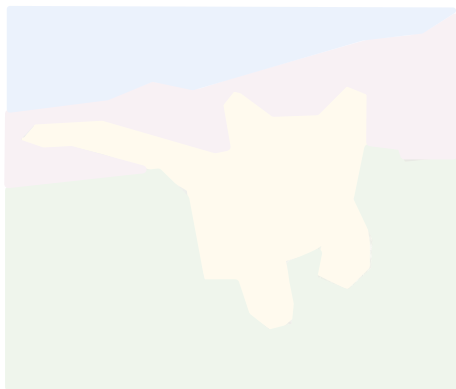
## Classification



CAT

No spatial extent

## Semantic Segmentation



GRASS, CAT,  
TREE, SKY

No objects, just pixels

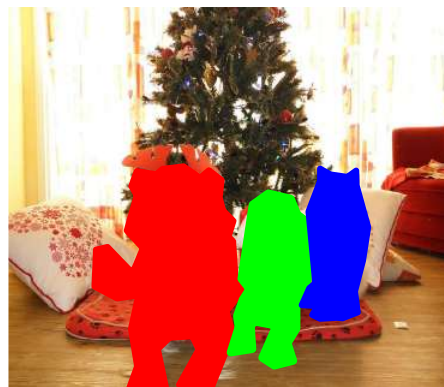
## Object Detection



DOG, DOG, CAT

Multiple Object

## Instance Segmentation



DOG, DOG, CAT

# Object Detection

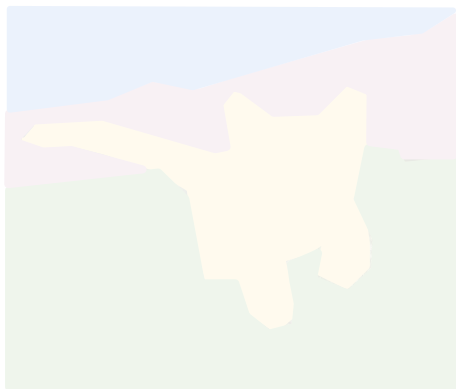
## Classification



CAT

No spatial extent

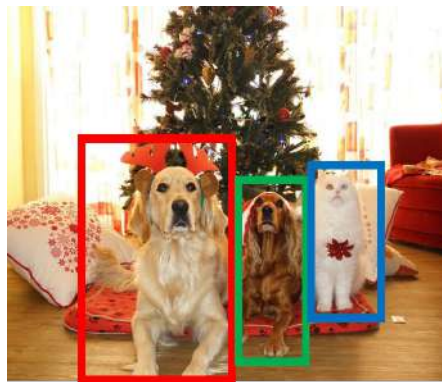
## Semantic Segmentation



GRASS, CAT,  
TREE, SKY

No objects, just pixels

## Object Detection



DOG, DOG, CAT

Multiple Object

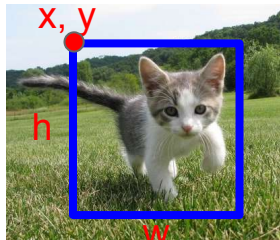
## Instance Segmentation



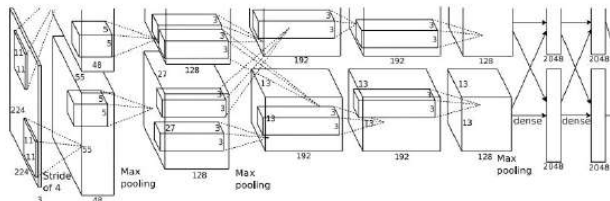
DOG, DOG, CAT

# Object Detection: Single Object

(Classification + Localization)



[This image](#) is [CC0 public domain](#)



**Fully  
Connected:**  
4096 to 1000

## Class Scores

Cat: 0.9  
Dog: 0.05  
Car: 0.01  
...

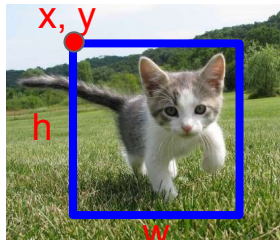
**Vector:**  
4096

**Fully  
Connected:**  
4096 to 4

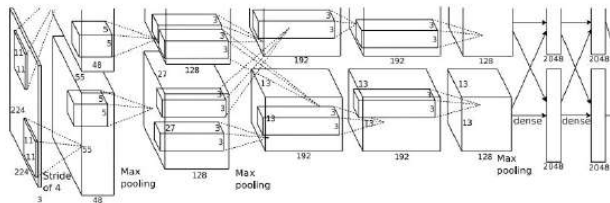
**Box  
Coordinates**  
(x, y, w, h)

# Object Detection: Single Object

(Classification + Localization)



[This image](#) is [CC0 public domain](#)



**Fully Connected:**  
4096 to 1000

## Class Scores

Cat: 0.9  
Dog: 0.05  
Car: 0.01  
...

**Correct label:**  
Cat

**Softmax Loss**

**Vector:**  
4096

**Fully Connected:**  
4096 to 4

**Box Coordinates**  
(x, y, w, h)

**L2 Loss**

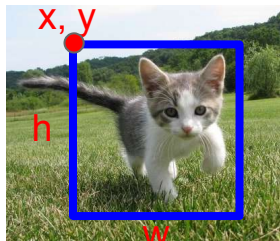
**Correct box:**  
(x', y', w', h')

Treat localization as a regression problem!

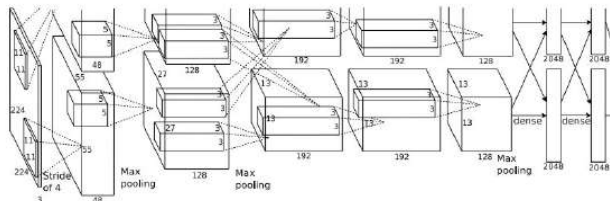


# Object Detection: Single Object

(Classification + Localization)



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**Vector:**  
4096

**Fully Connected:**  
4096 to 4

## Class Scores

Cat: 0.9  
Dog: 0.05  
Car: 0.01  
...

**Correct label:**  
Cat

**Softmax Loss**

**Multitask Loss**

**+** → **Loss**

**Box Coordinates**  
(x, y, w, h)

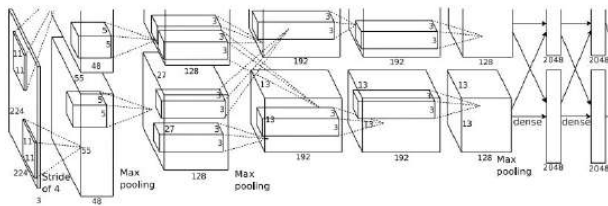
**L2 Loss**

**Correct box:**  
(x', y', w', h')

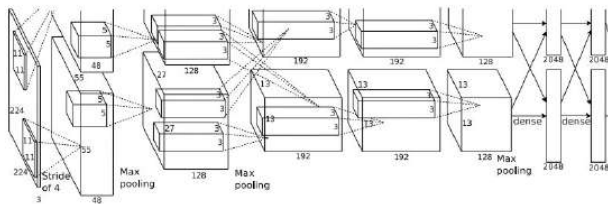
Treat localization as a regression problem!



# Object Detection: Multiple Objects



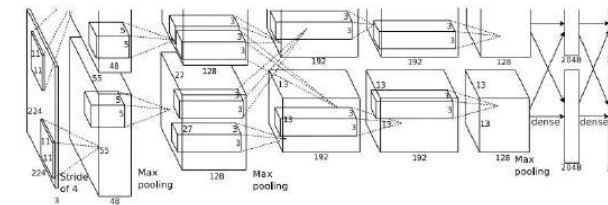
CAT: (x, y, w, h)



DOG: (x, y, w, h)

DOG: (x, y, w, h)

CAT: (x, y, w, h)



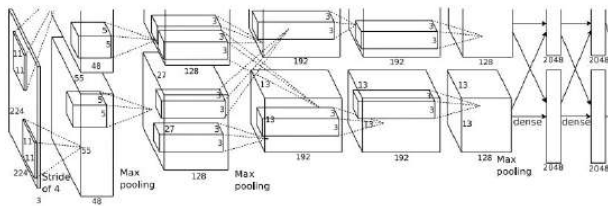
DUCK: (x, y, w, h)

DUCK: (x, y, w, h)

....

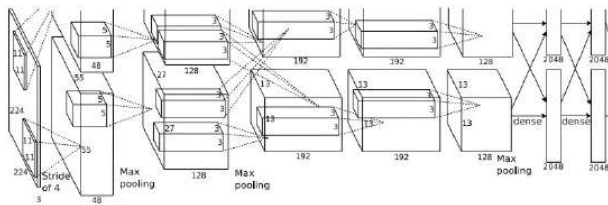
# Object Detection: Multiple Objects

Each image needs a  
different number of outputs!



CAT:  $(x, y, w, h)$

4 numbers

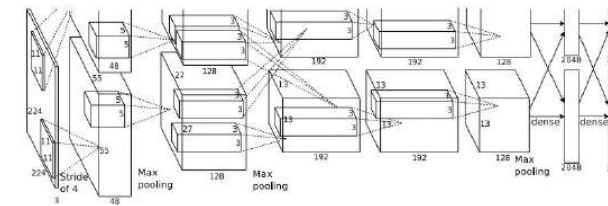


DOG:  $(x, y, w, h)$

DOG:  $(x, y, w, h)$

CAT:  $(x, y, w, h)$

12 numbers



DUCK:  $(x, y, w, h)$

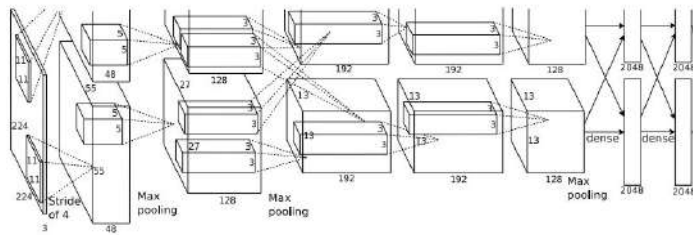
DUCK:  $(x, y, w, h)$

....

Many  
numbers!

# Object Detection: Multiple Objects

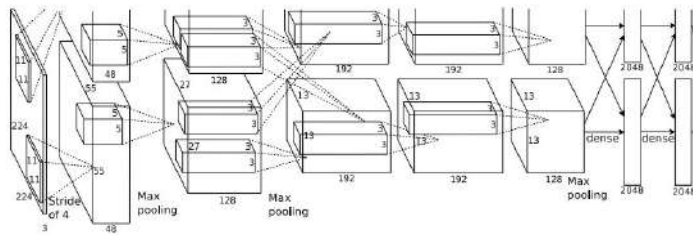
Apply a CNN to many different crops of the image, CNN classifies each crop as object or background



Dog? NO  
Cat? NO  
Background? YES

# Object Detection: Multiple Objects

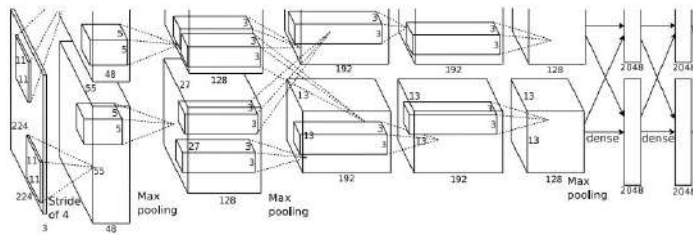
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Dog? YES  
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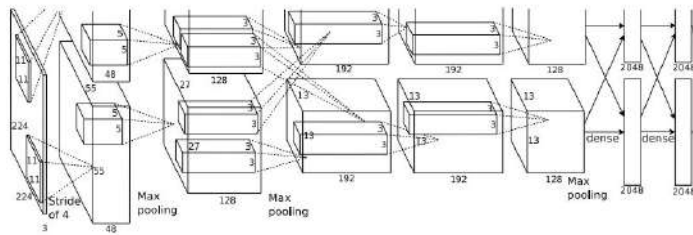


Dog? YES  
Cat? NO  
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# Object Detection: Multiple Objects

Apply a CNN to many different crops of the image, CNN classifies each crop as object or background

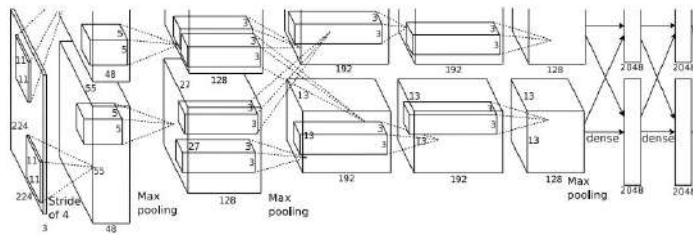
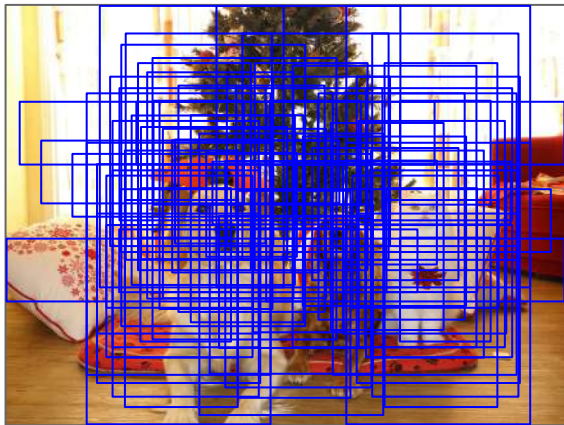


Dog? NO  
Cat? YES  
Background? NO

Q: What's the problem with this approach?

# Object Detection: Multiple Objects

Apply a CNN to many different crops of the image, CNN classifies each crop as object or background

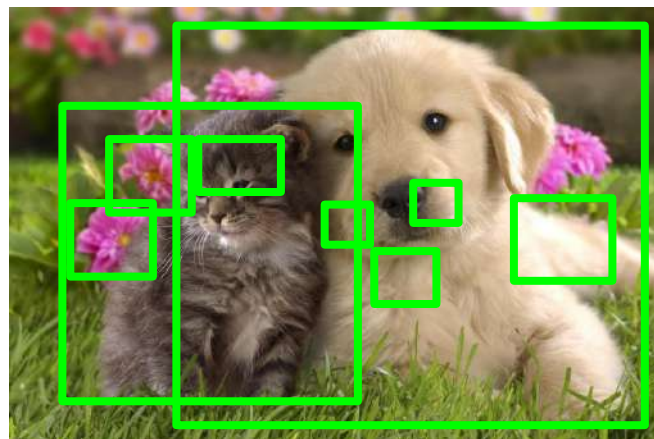


Dog? NO  
Cat? YES  
Background? NO

Problem: Need to apply CNN to huge number of locations, scales, and aspect ratios, very computationally expensive!

# Region Proposals: Selective Search

- Find “blobby” image regions that are likely to contain objects
- Relatively fast to run; e.g. Selective Search gives 2000 region proposals in a few seconds on CPU



Alexe et al, “Measuring the objectness of image windows”, TPAMI 2012  
Uijlings et al, “Selective Search for Object Recognition”, IJCV 2013  
Cheng et al, “BING: Binarized normed gradients for objectness estimation at 300fps”, CVPR 2014  
Zitnick and Dollar, “Edge boxes: Locating object proposals from edges”, ECCV 2014



# R-CNN



Input image

Girshick et al, "Rich feature hierarchies for accurate object detection and semantic segmentation", CVPR 2014.  
Figure copyright Ross Girshick, 2015; [source](#). Reproduced with permission.

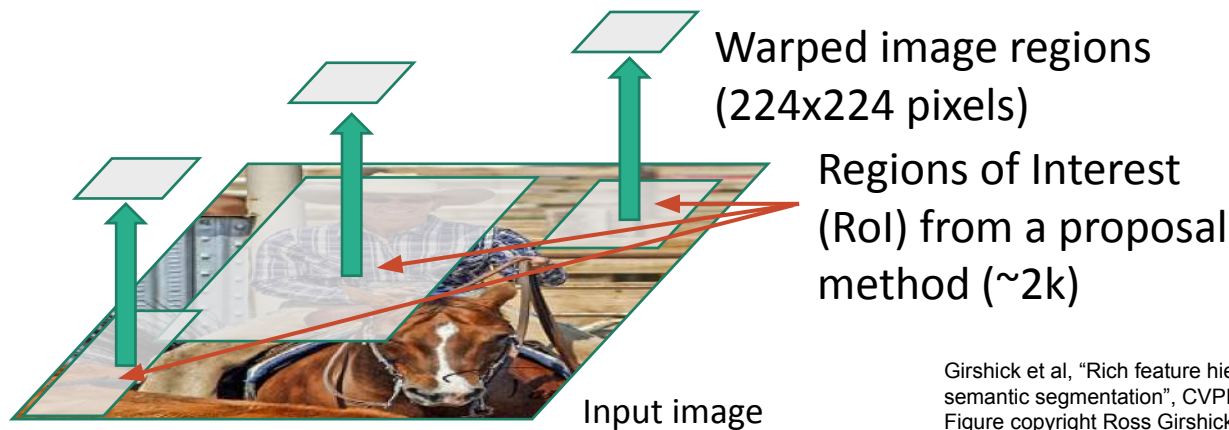
# R-CNN



Regions of Interest  
(RoI) from a proposal  
method (~2k)

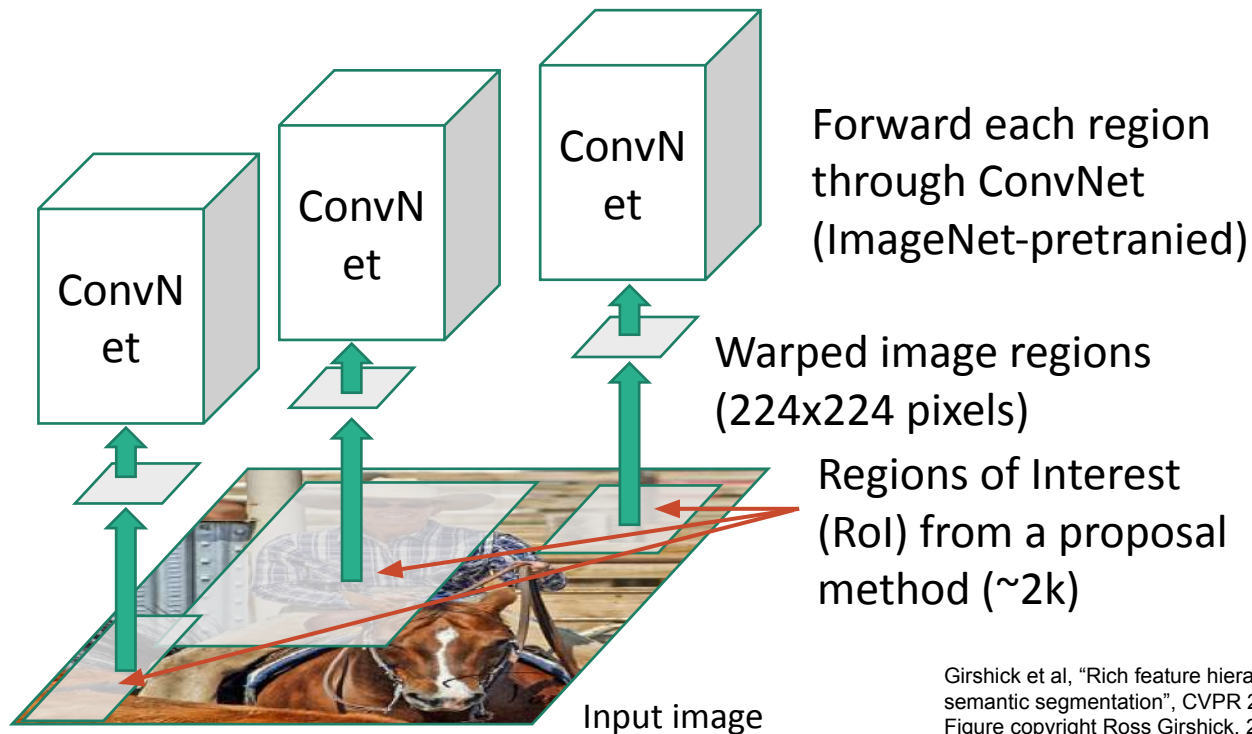
Girshick et al, "Rich feature hierarchies for accurate object detection and semantic segmentation", CVPR 2014.  
Figure copyright Ross Girshick, 2015; [source](#). Reproduced with permission.

# R-CNN



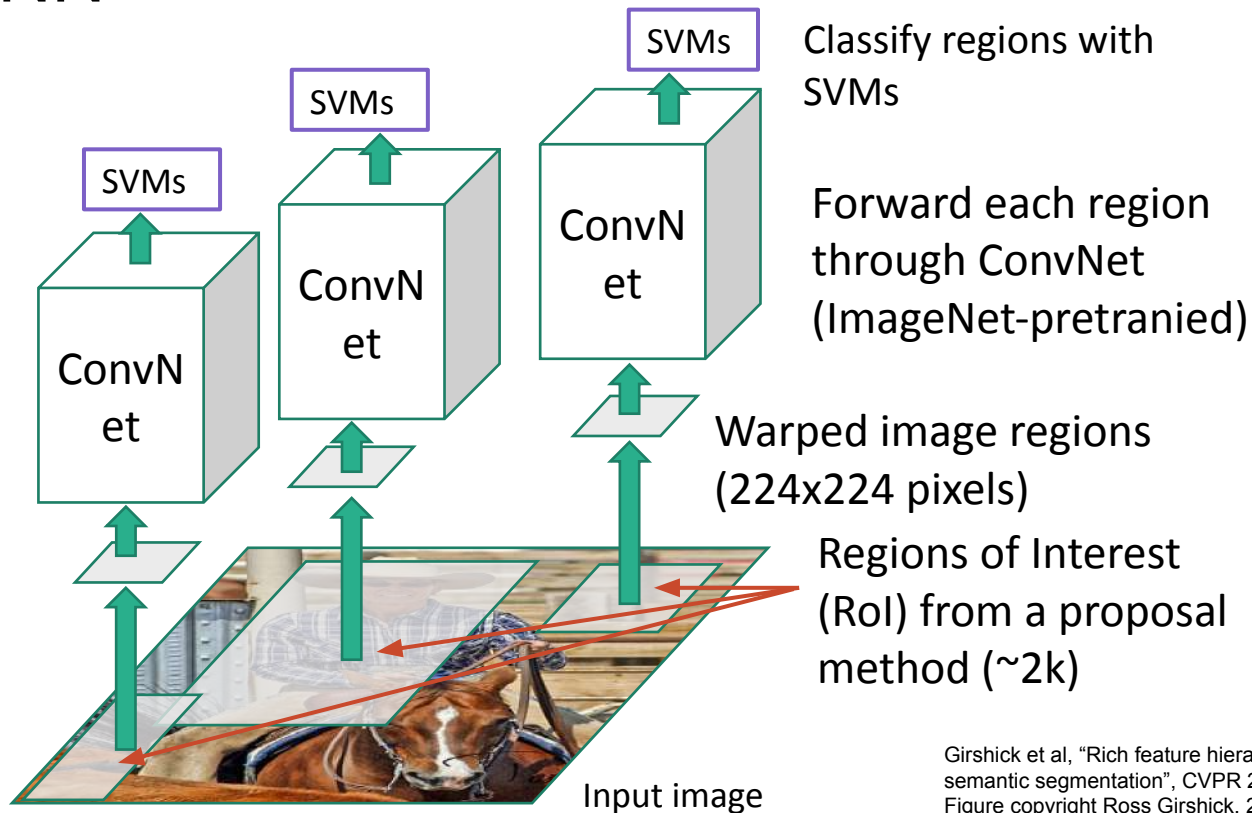
Girshick et al, "Rich feature hierarchies for accurate object detection and semantic segmentation", CVPR 2014.  
Figure copyright Ross Girshick, 2015; [source](#). Reproduced with permission.

# R-CNN



Girshick et al, "Rich feature hierarchies for accurate object detection and semantic segmentation", CVPR 2014.  
Figure copyright Ross Girshick, 2015; [source](#). Reproduced with permission.

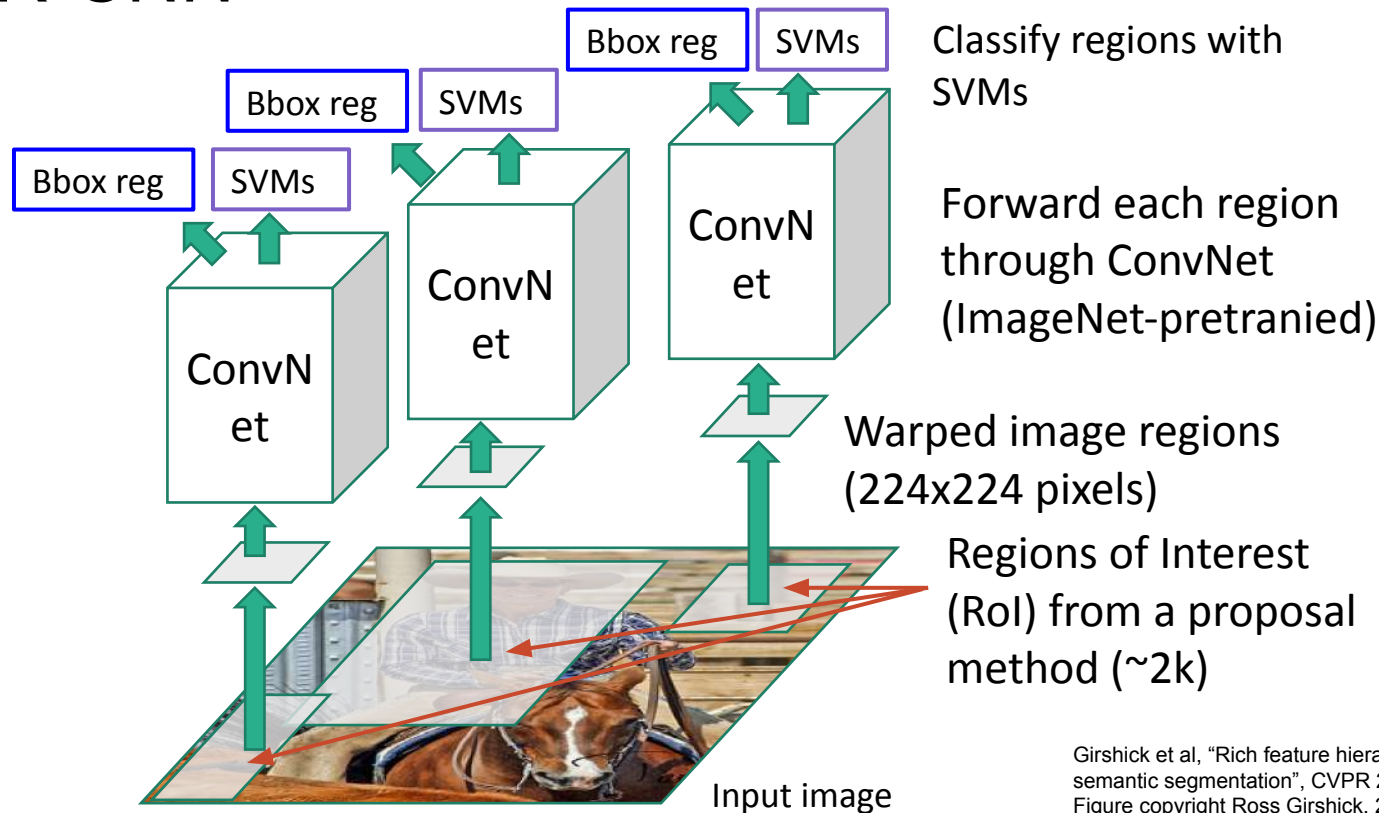
# R-CNN



Girshick et al, "Rich feature hierarchies for accurate object detection and semantic segmentation", CVPR 2014.  
Figure copyright Ross Girshick, 2015; [source](#). Reproduced with permission.

# R-CNN

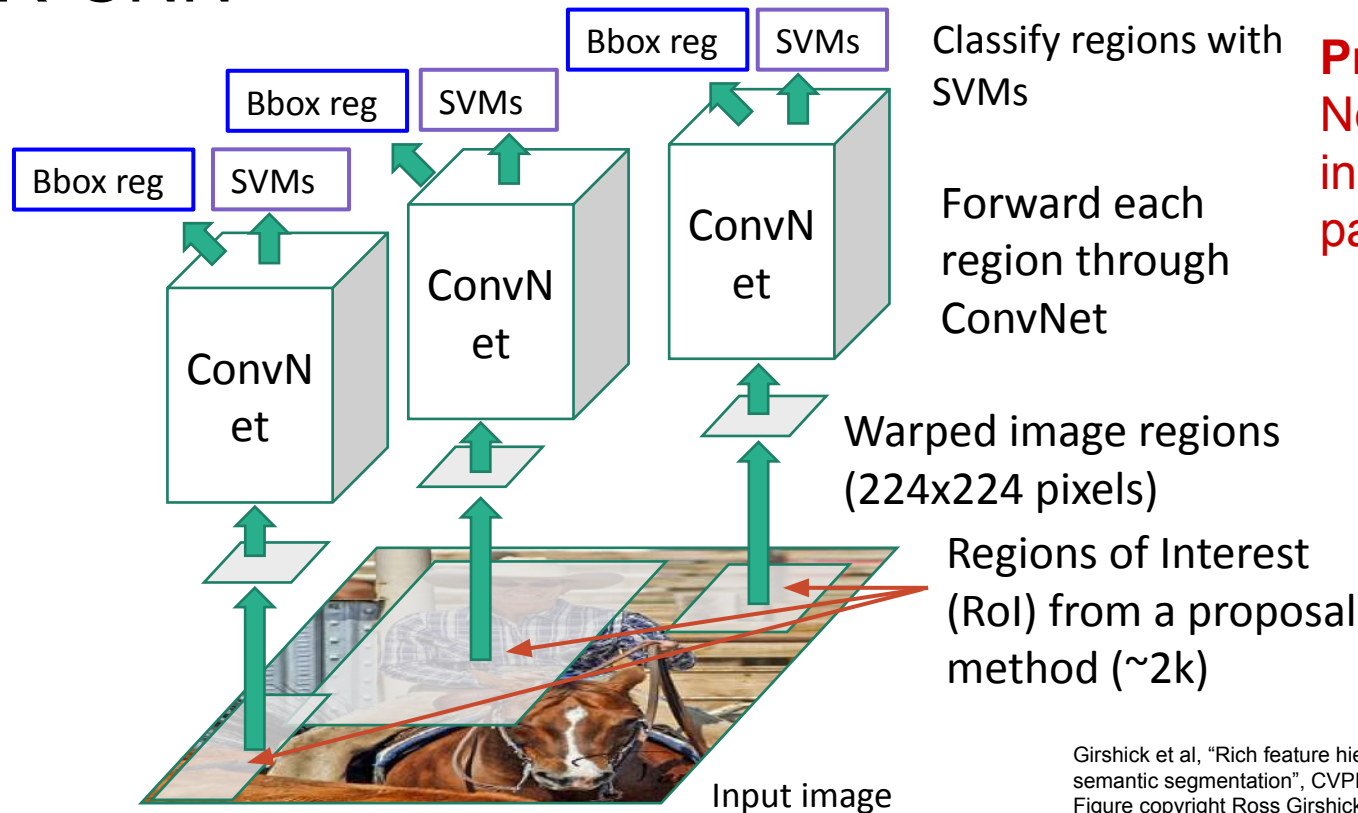
Predict “corrections” to the RoI: 4 numbers: (dx, dy, dw, dh)



Girshick et al, “Rich feature hierarchies for accurate object detection and semantic segmentation”, CVPR 2014.  
Figure copyright Ross Girshick, 2015; [source](#). Reproduced with permission.

# R-CNN

Predict “corrections” to the RoI: 4 numbers: (dx, dy, dw, dh)



Classify regions with SVMs

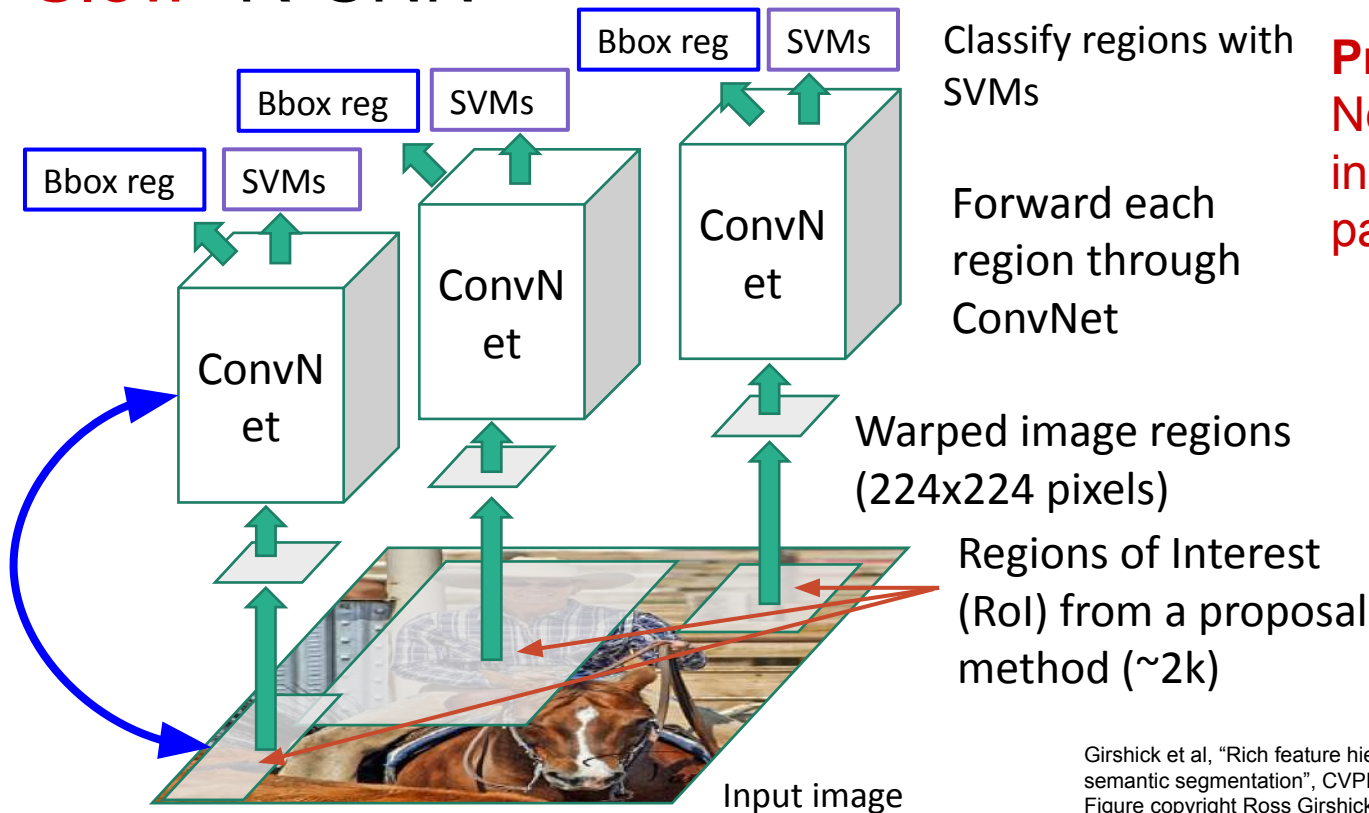
Forward each region through ConvNet

**Problem: Very slow!**  
Need to do ~2k independent forward passes for each image!

Girshick et al, “Rich feature hierarchies for accurate object detection and semantic segmentation”, CVPR 2014.  
Figure copyright Ross Girshick, 2015; [source](#). Reproduced with permission.

# “Slow” R-CNN

Predict “corrections” to the RoI: 4 numbers: (dx, dy, dw, dh)



**Problem:** Very slow!  
Need to do ~2k  
independent forward  
passes for each image!

**Idea:** Pass the  
image through  
convnet before  
cropping! Crop the  
conv feature instead!

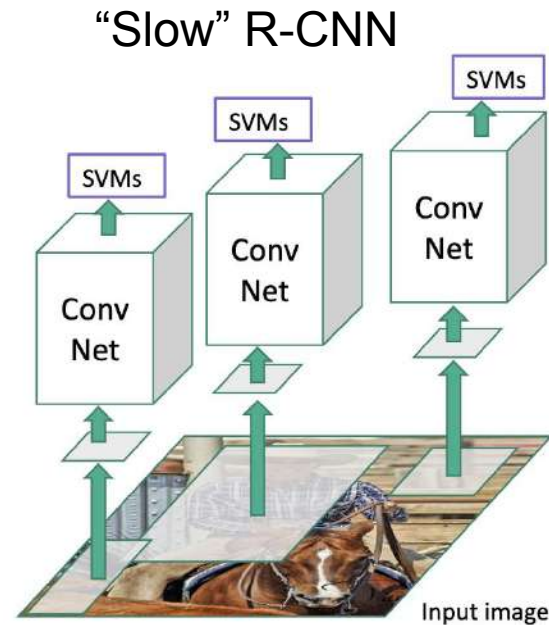
Girshick et al, “Rich feature hierarchies for accurate object detection and semantic segmentation”, CVPR 2014.  
Figure copyright Ross Girshick, 2015; [source](#). Reproduced with permission.



# Fast R-CNN

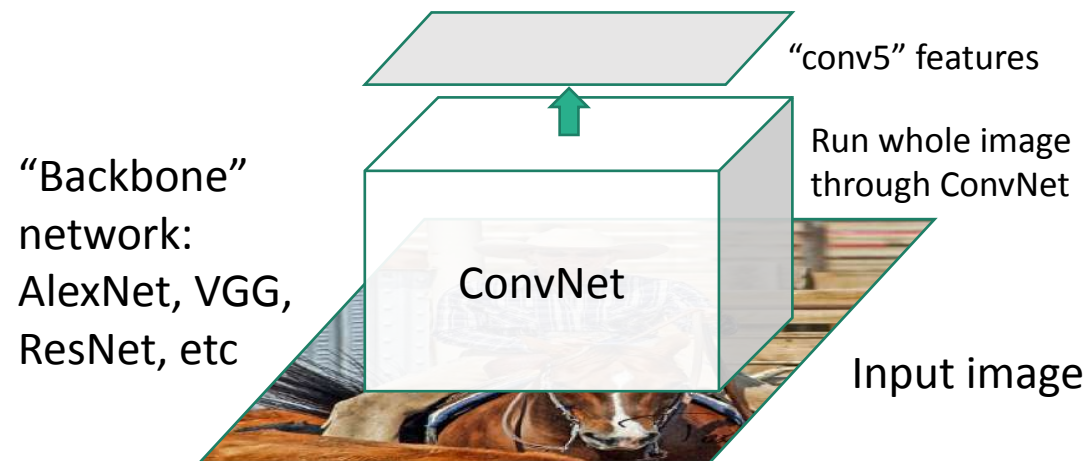


Input image

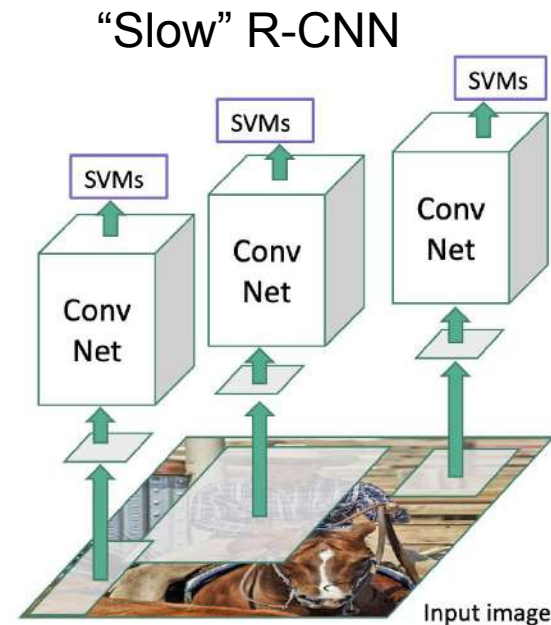


Girshick, “Fast R-CNN”, ICCV 2015. Figure copyright Ross Girshick, 2015; [source](#). Reproduced with permission.

# Fast R-CNN



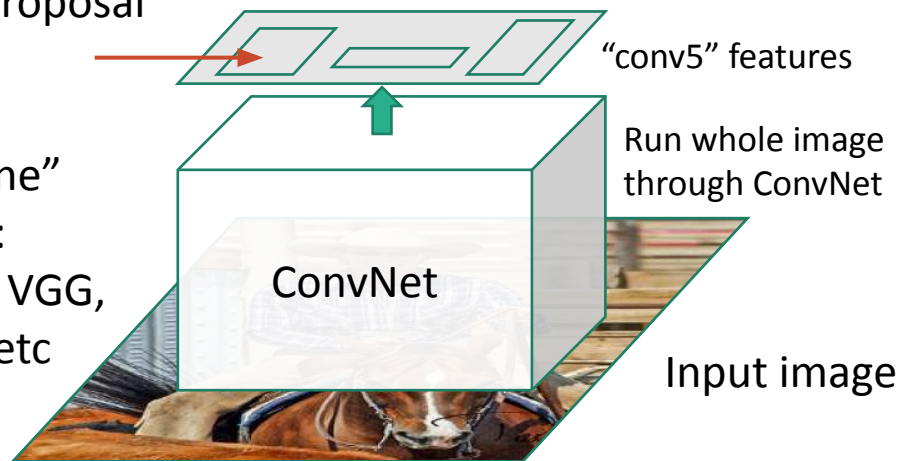
Girshick, “Fast R-CNN”, ICCV 2015. Figure copyright Ross Girshick, 2015; [source](#). Reproduced with permission.



# Fast R-CNN

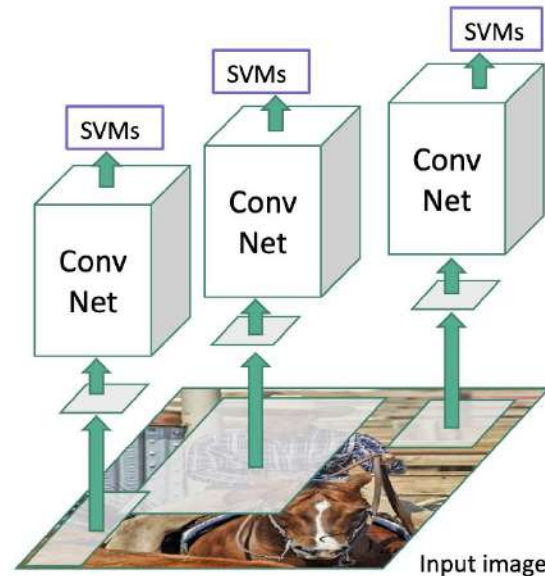
Regions of Interest (RoIs) from a proposal method

“Backbone” network:  
AlexNet, VGG, ResNet, etc



Girshick, “Fast R-CNN”, ICCV 2015. Figure copyright Ross Girshick, 2015; [source](#). Reproduced with permission.

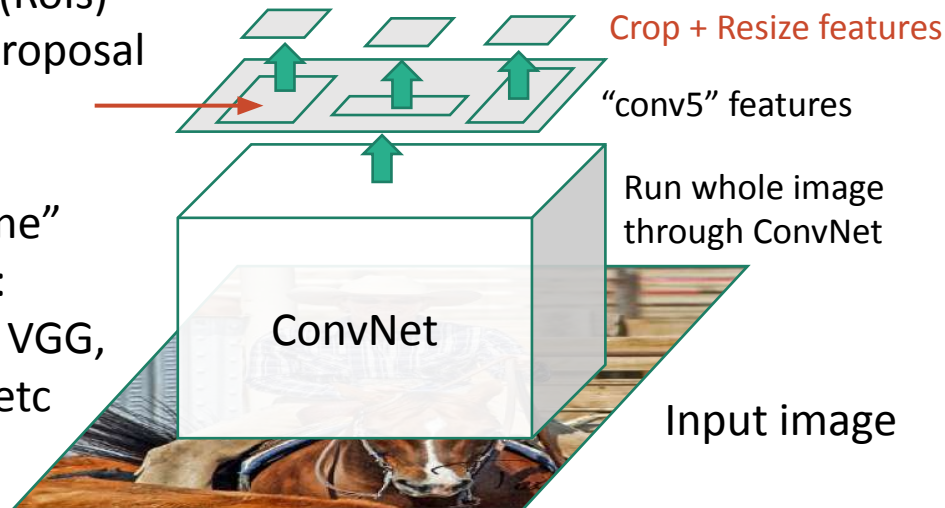
“Slow” R-CNN



# Fast R-CNN

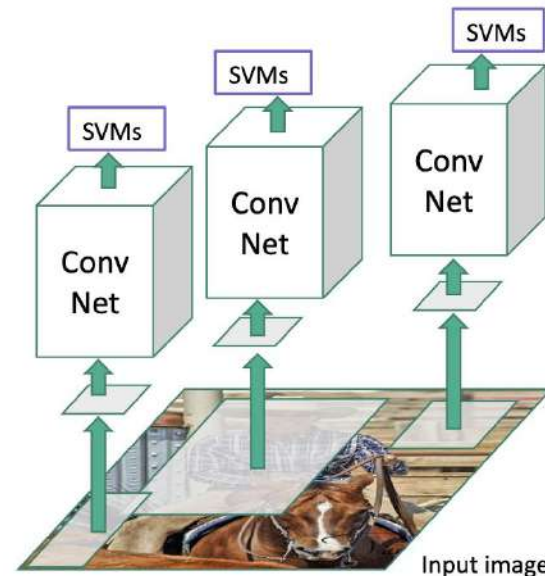
Regions of Interest (RoIs) from a proposal method

“Backbone” network:  
AlexNet, VGG, ResNet, etc

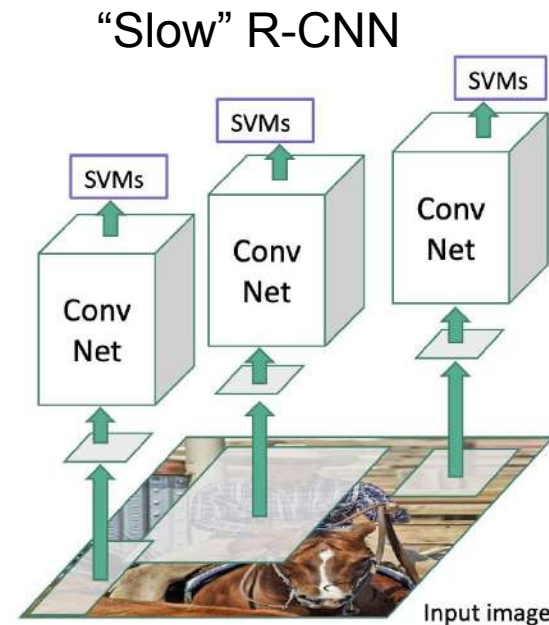
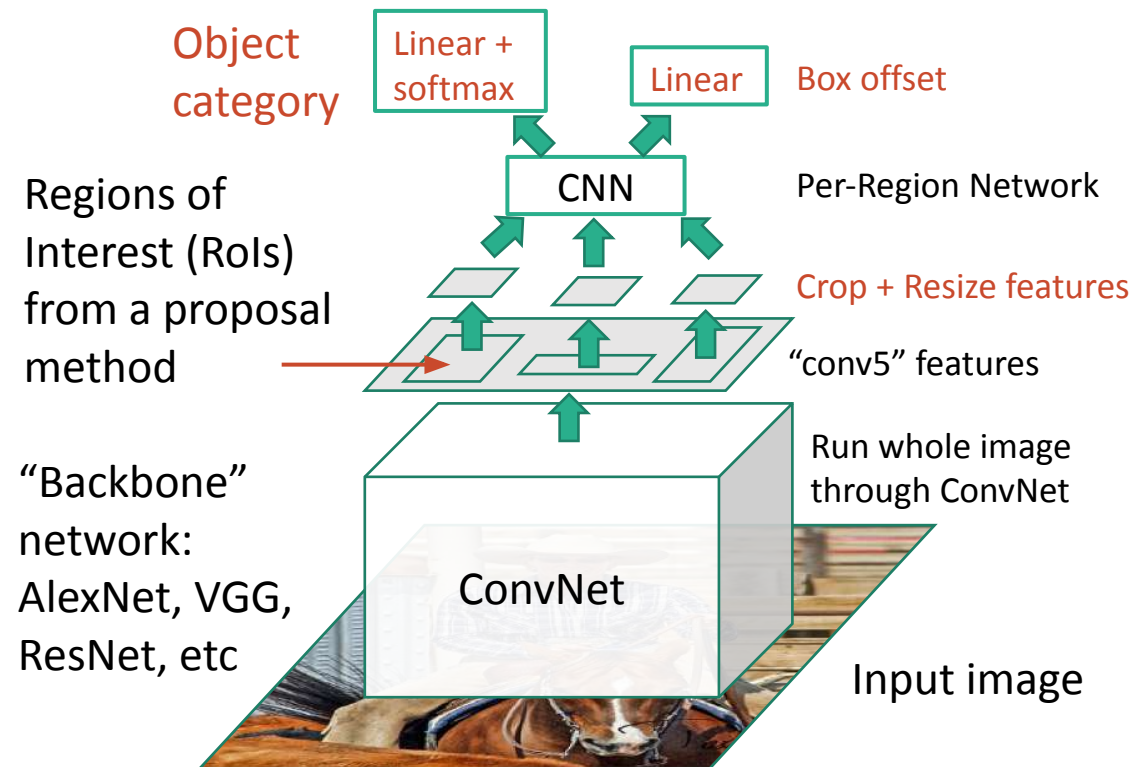


Girshick, "Fast R-CNN", ICCV 2015. Figure copyright Ross Girshick, 2015; [source](#). Reproduced with permission.

## “Slow” R-CNN

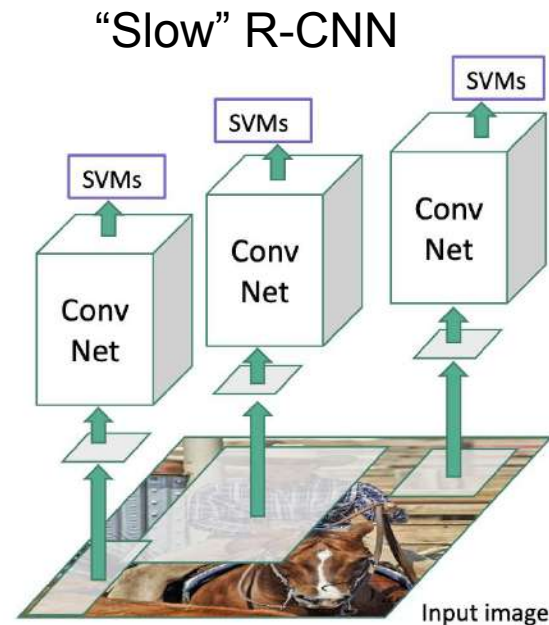
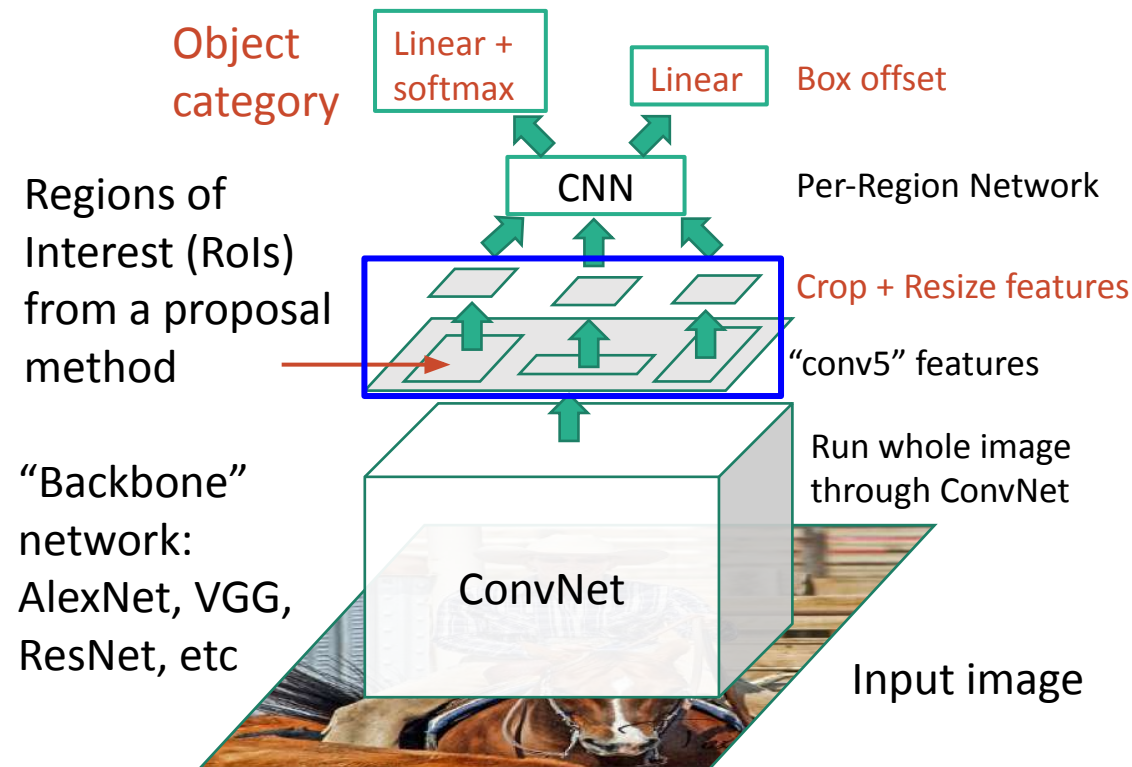


# Fast R-CNN



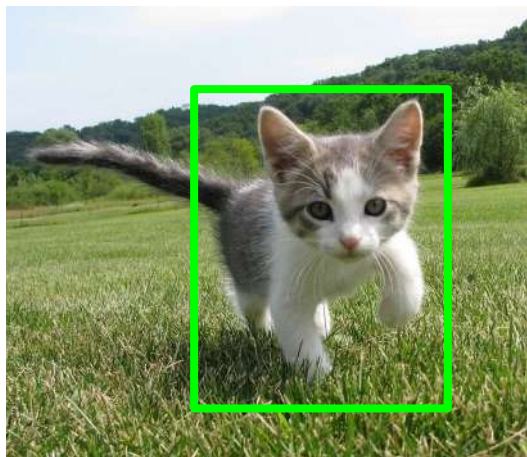
Girshick, "Fast R-CNN", ICCV 2015. Figure copyright Ross Girshick, 2015; [source](#). Reproduced with permission.

# Fast R-CNN



Girshick, "Fast R-CNN", ICCV 2015. Figure copyright Ross Girshick, 2015; [source](#). Reproduced with permission.

# Cropping Features: RoI Pool



Input Image  
(e.g. 3 x 640 x 480)

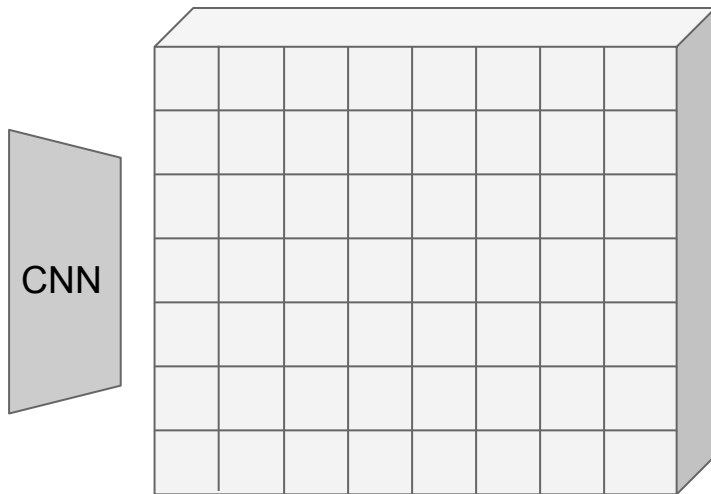


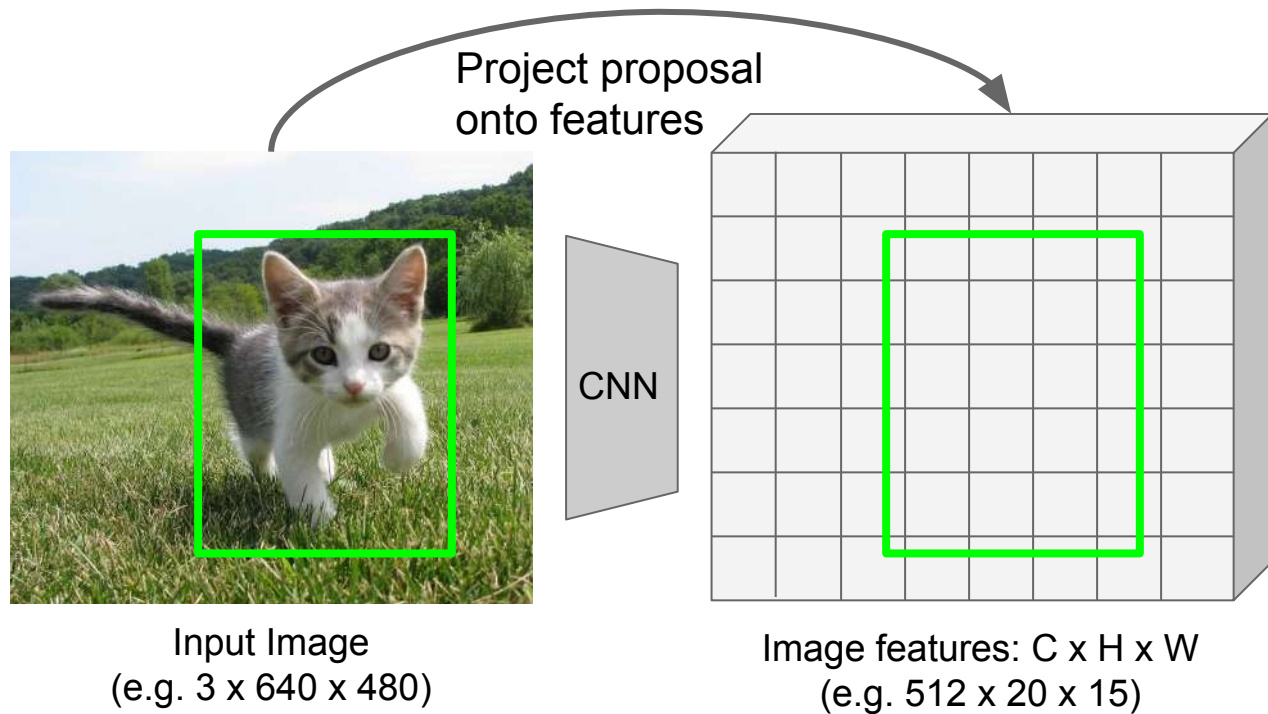
Image features: C x H x W  
(e.g. 512 x 20 x 15)

Girshick, "Fast R-CNN", ICCV 2015.

Girshick, "Fast R-CNN", ICCV 2015.



# Cropping Features: RoI Pool

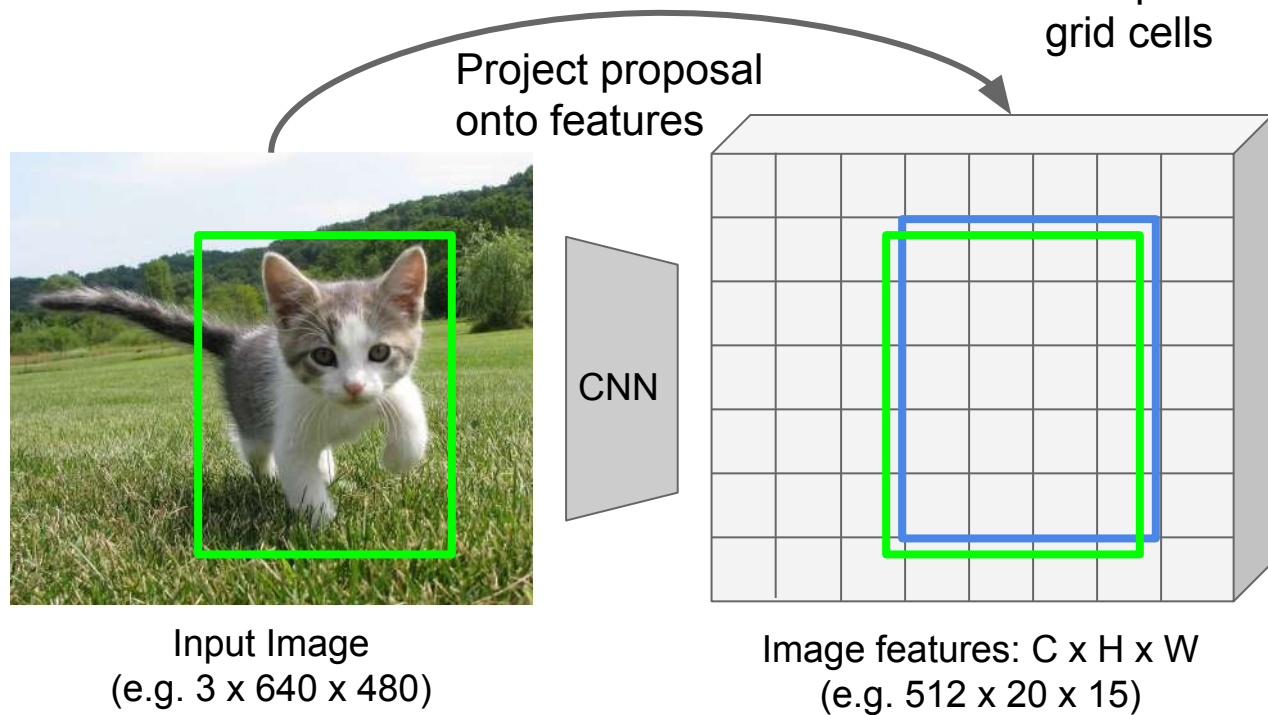


Girshick, "Fast R-CNN", ICCV 2015.

Girshick, "Fast R-CNN", ICCV 2015.

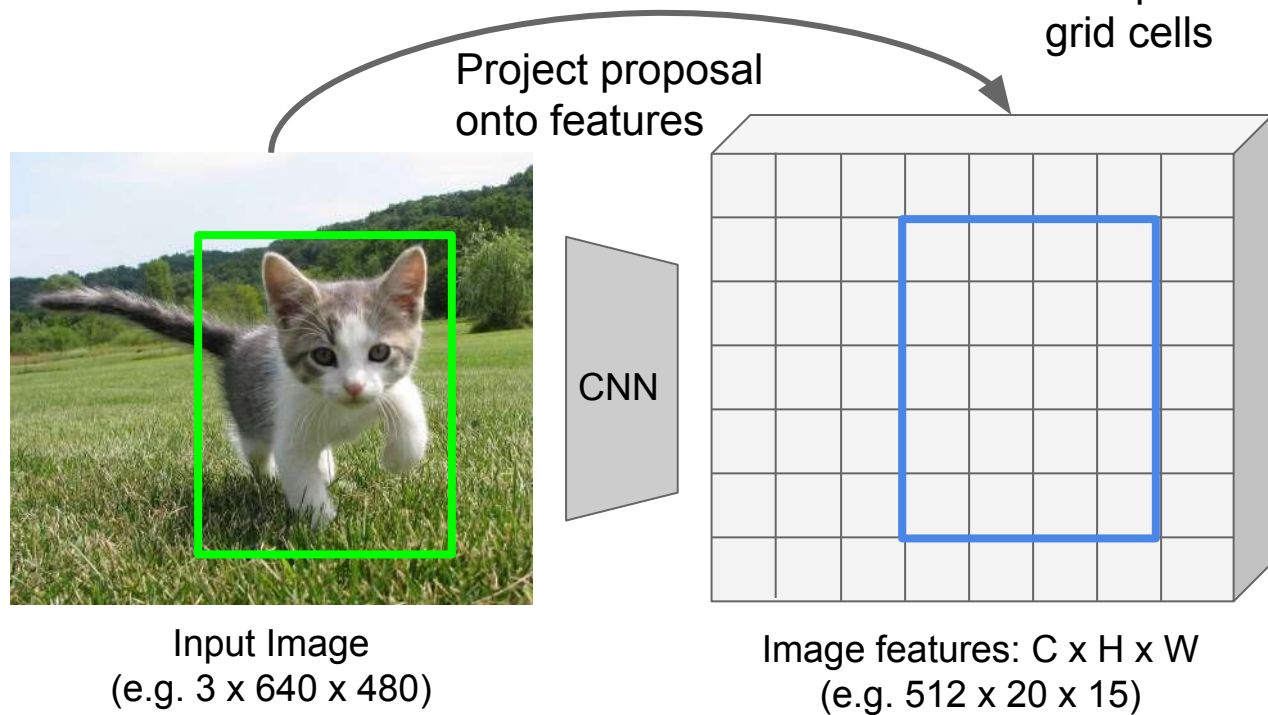


# Cropping Features: RoI Pool



Girshick, "Fast R-CNN", ICCV 2015.

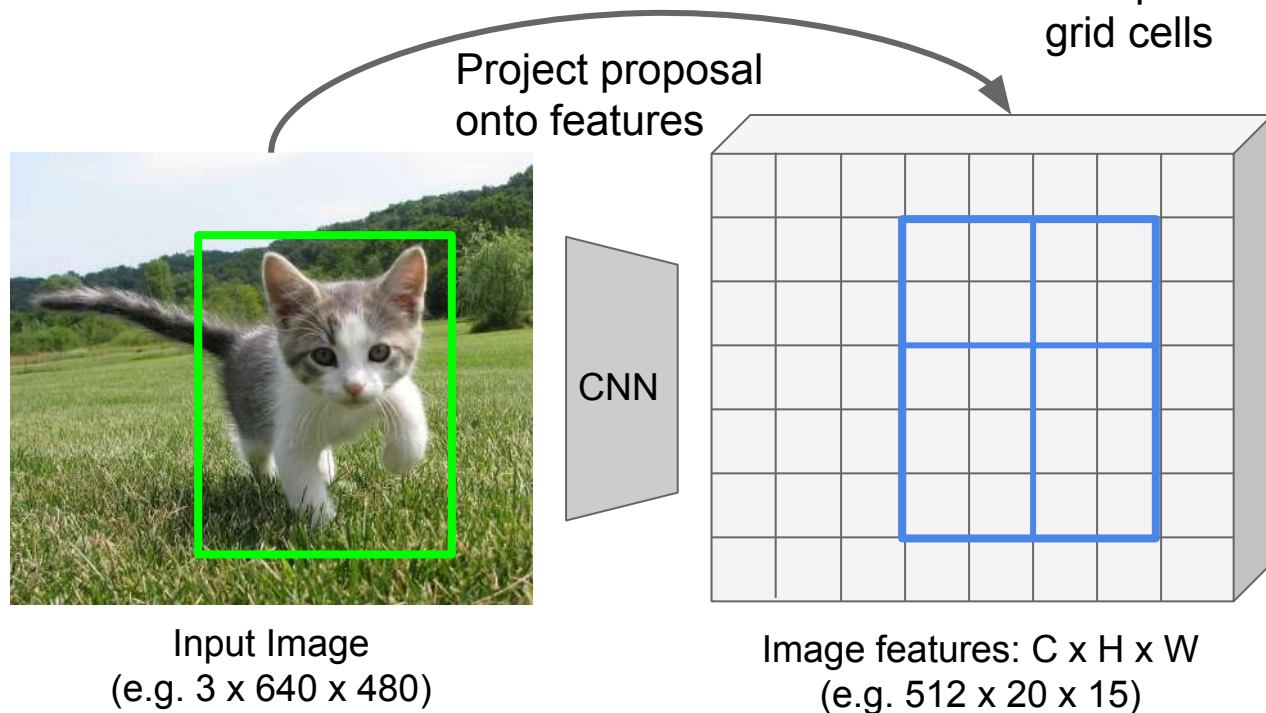
# Cropping Features: RoI Pool



Q: how do we resize the 512 x 20 x 15 region to, e.g., a 512 x 2 x 2 tensor?.

Girshick, "Fast R-CNN", ICCV 2015.

# Cropping Features: RoI Pool

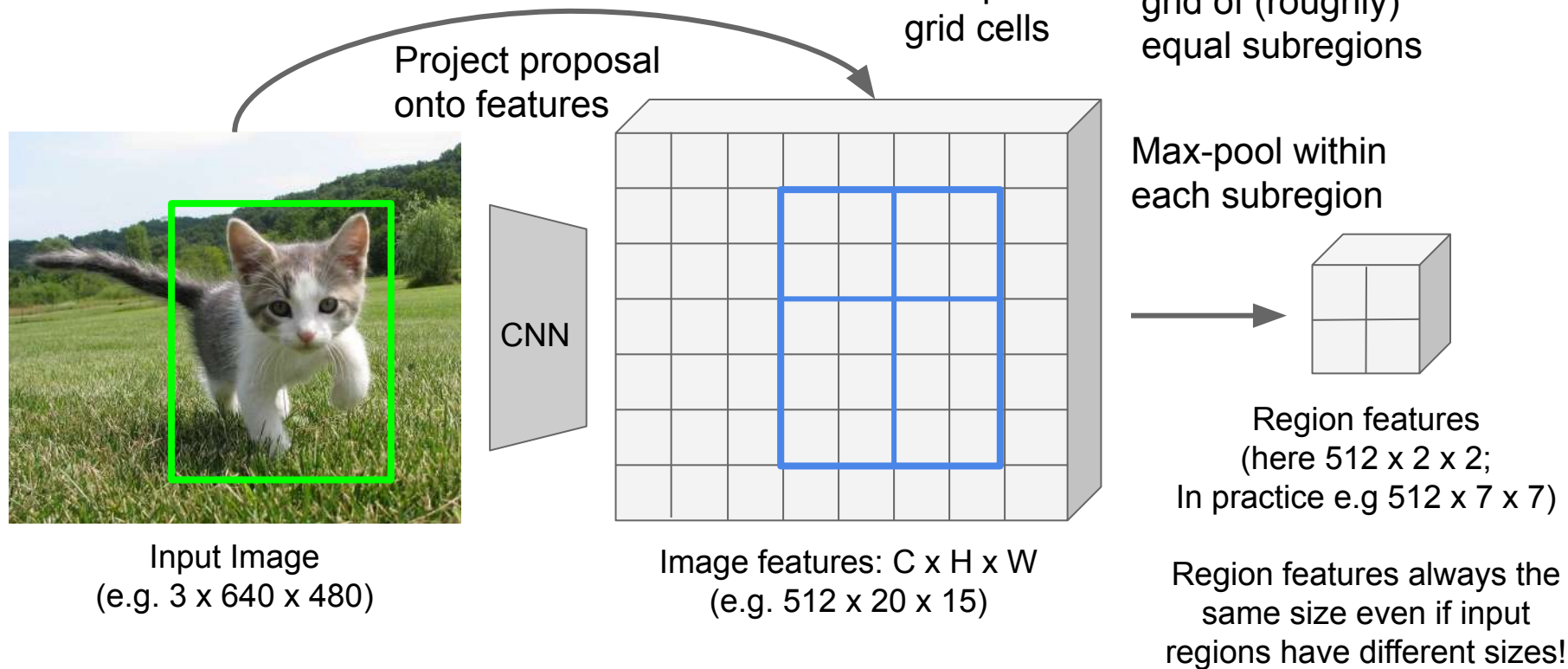


Divide into 2x2  
grid of (roughly)  
equal subregions

Q: how do we resize the 512  
x 20 x 15 region to, e.g., a  
512 x 2 x 2 tensor?.

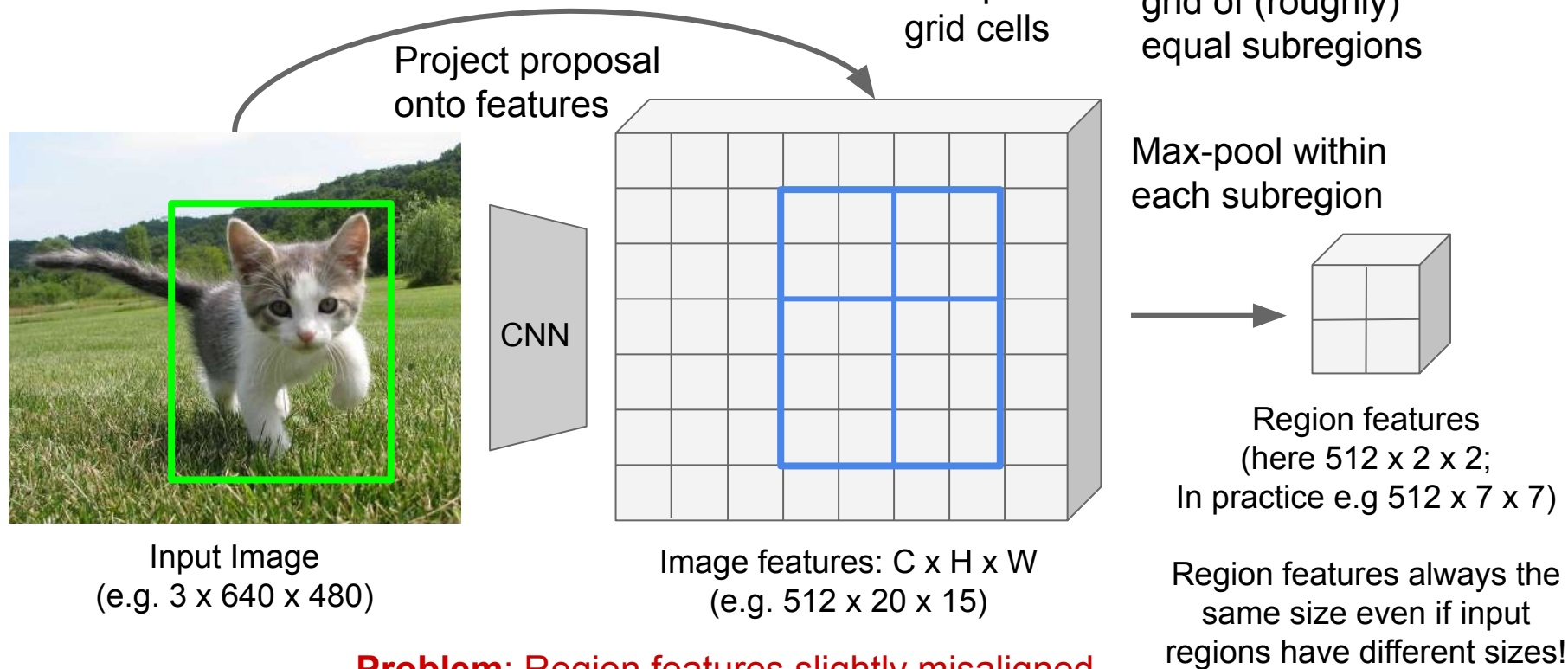
Girshick, “Fast R-CNN”, ICCV 2015.

# Cropping Features: RoI Pool



Girshick, “Fast R-CNN”, ICCV 2015.

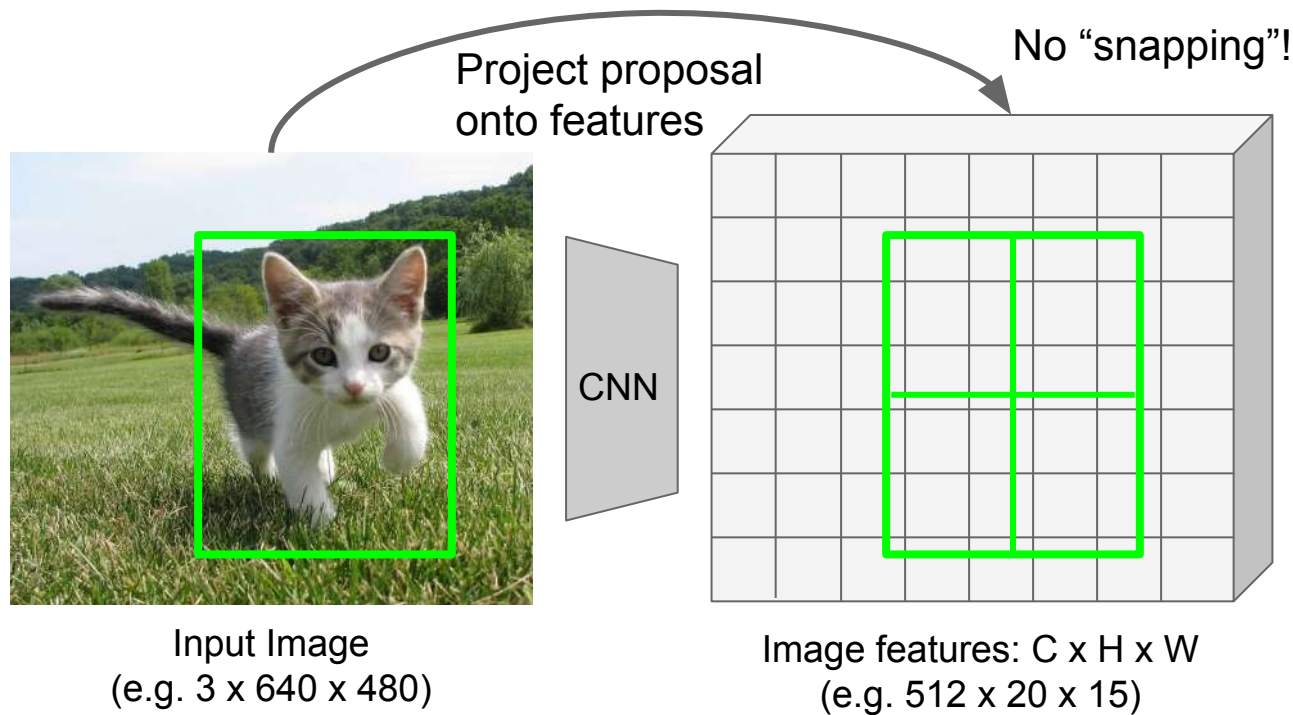
# Cropping Features: RoI Pool



**Problem: Region features slightly misaligned**

Girshick, “Fast R-CNN”, ICCV 2015.

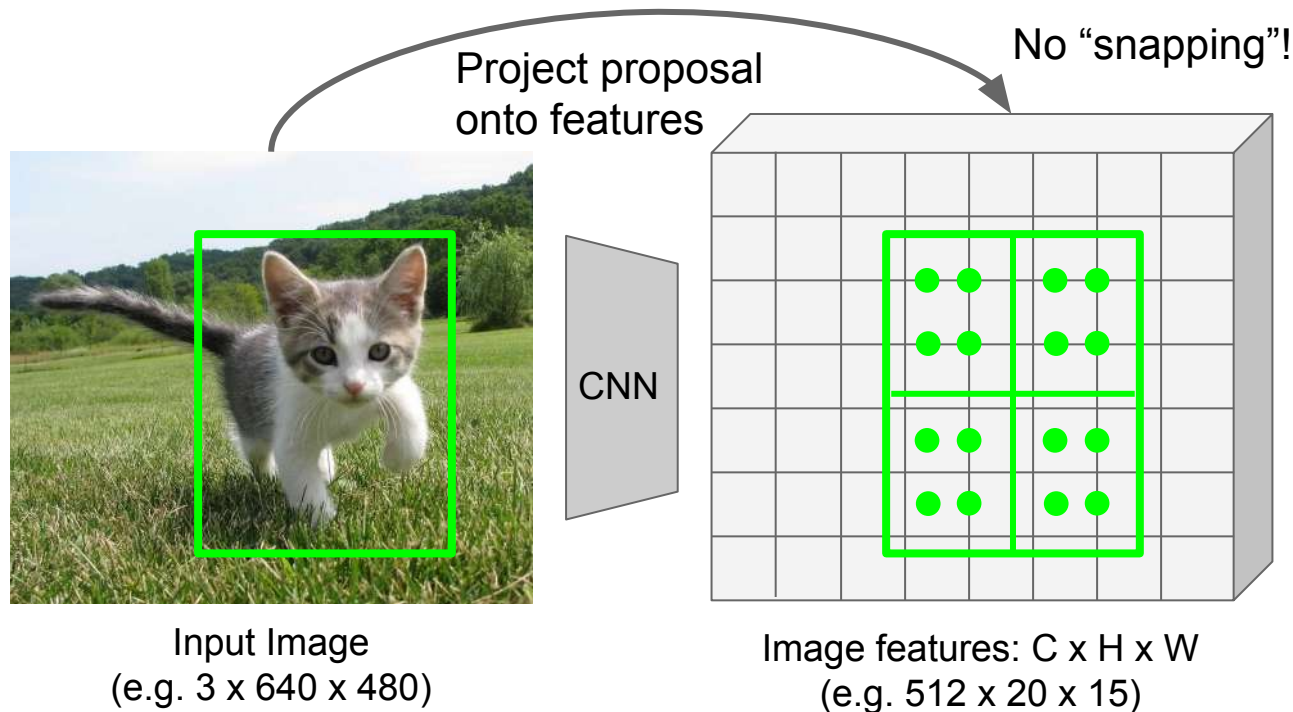
# Cropping Features: RoI Align



He et al, “Mask R-CNN”, ICCV 2017

# Cropping Features: RoI Align

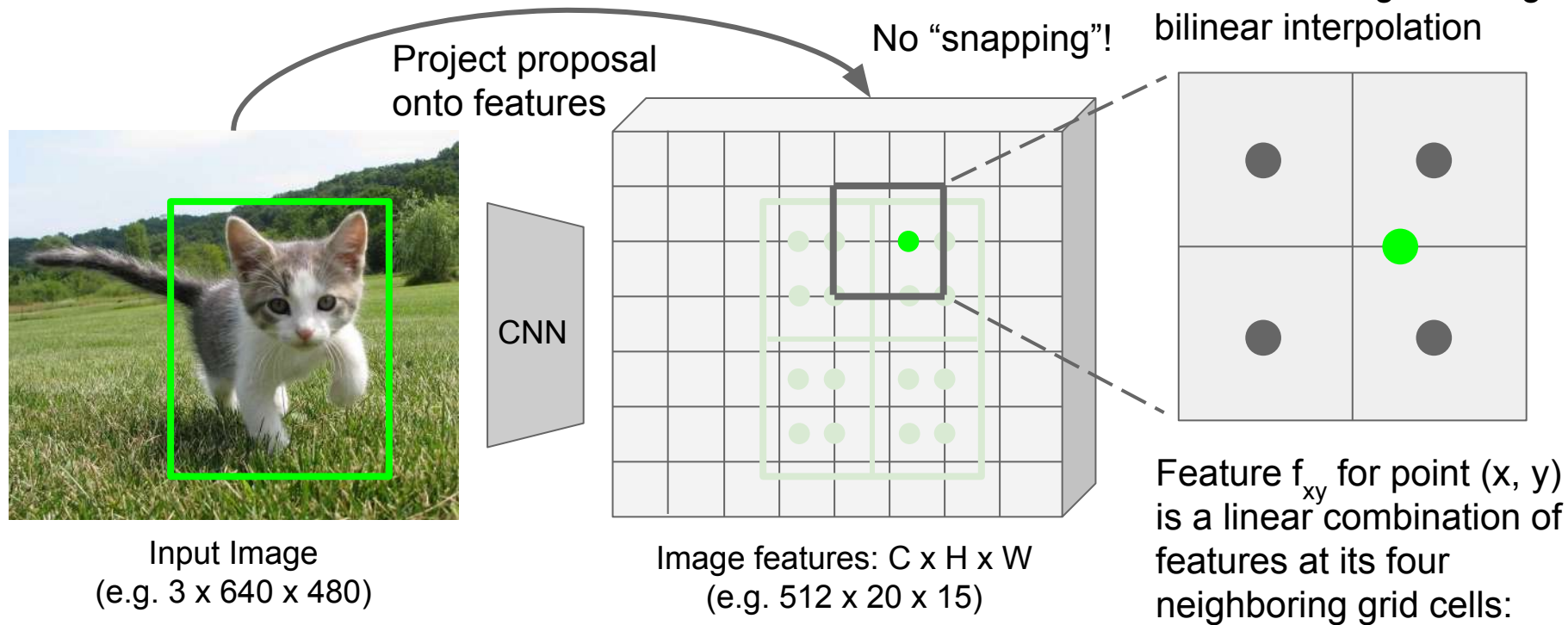
Sample at regular points  
in each subregion using  
bilinear interpolation



He et al, “Mask R-CNN”, ICCV 2017



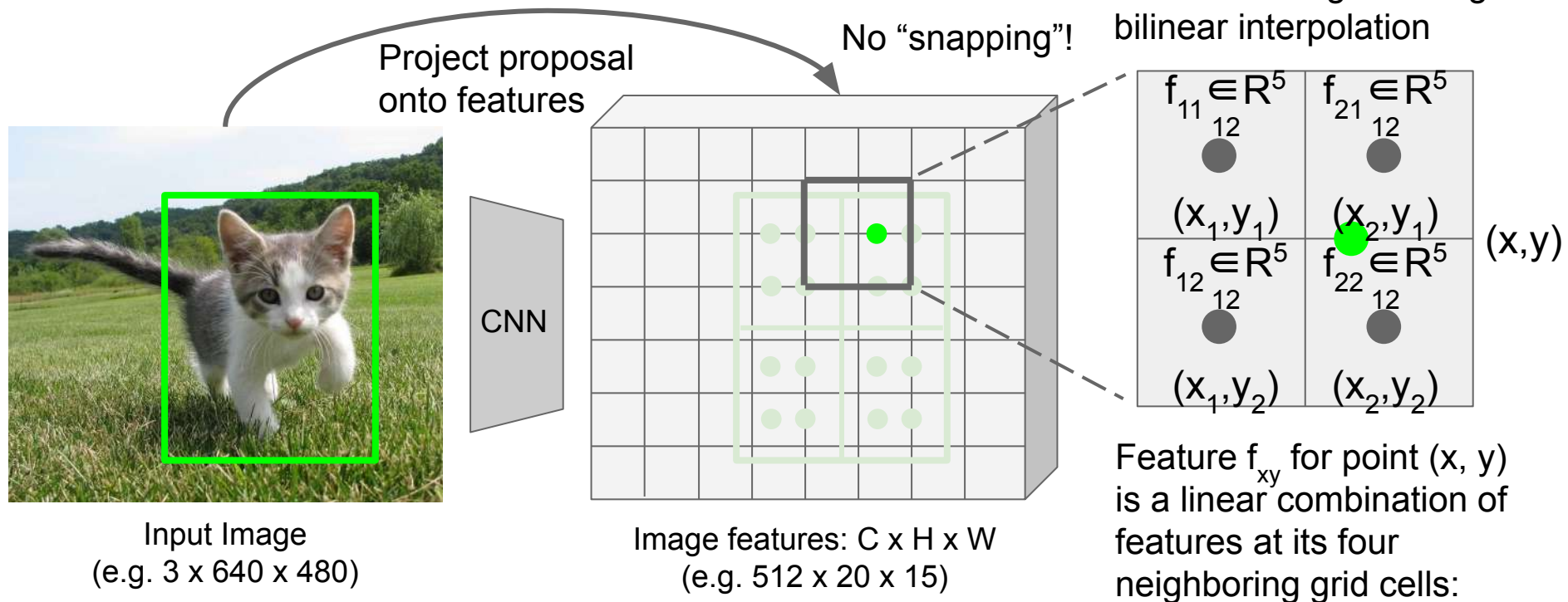
# Cropping Features: RoI Align



He et al, "Mask R-CNN", ICCV 2017



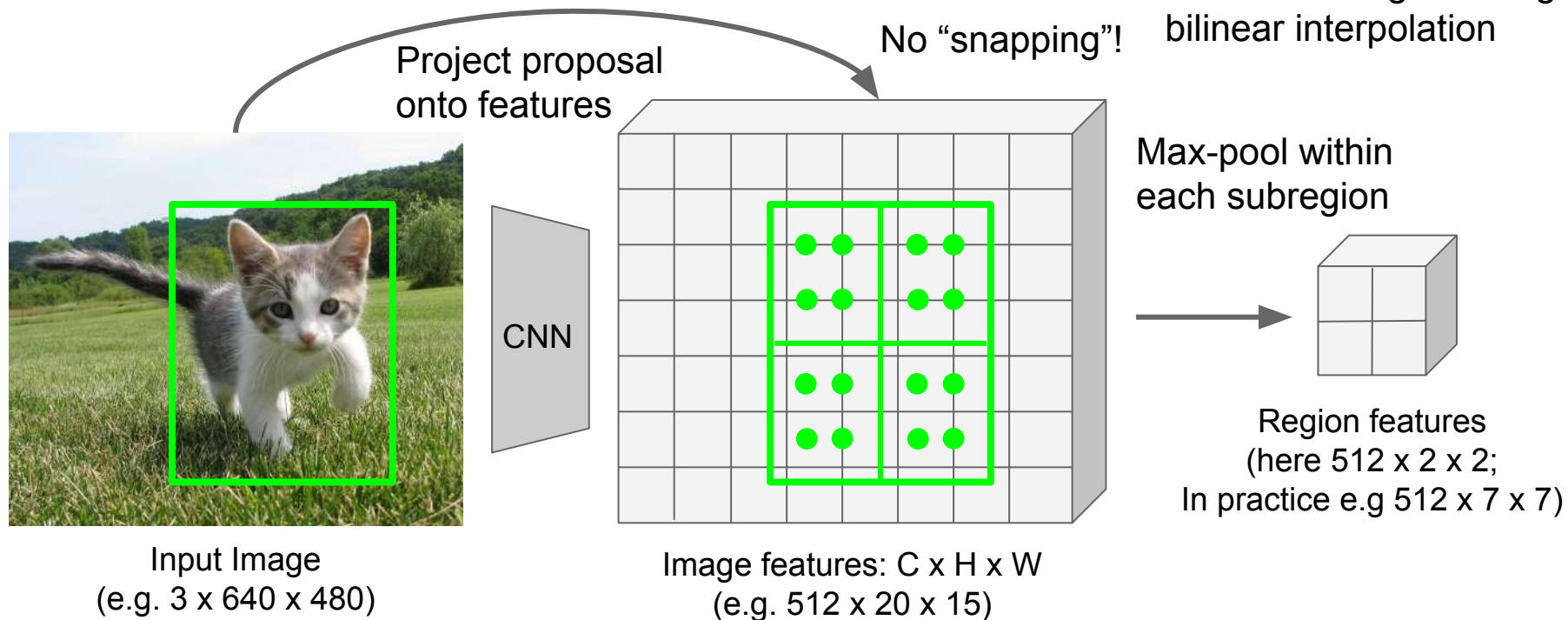
# Cropping Features: RoI Align



$$f_{xy} = \sum_{i,j=1}^2 f_{i,j} \max(0, 1 - |x - x_i|) \max(0, 1 - |y - y_j|)$$

He et al, “Mask R-CNN”, ICCV 2017

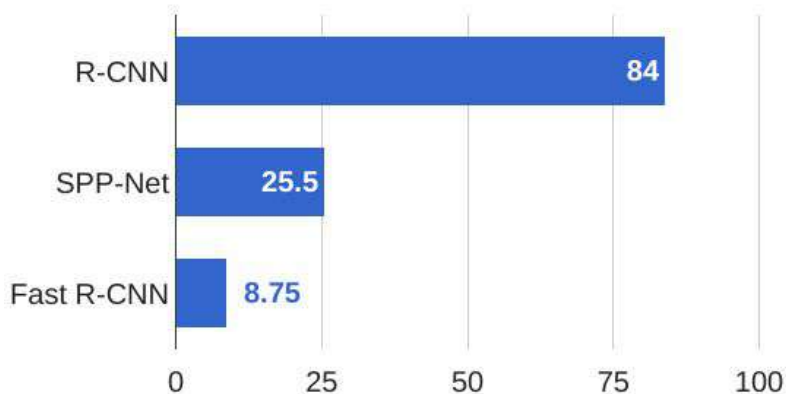
# Cropping Features: RoI Align



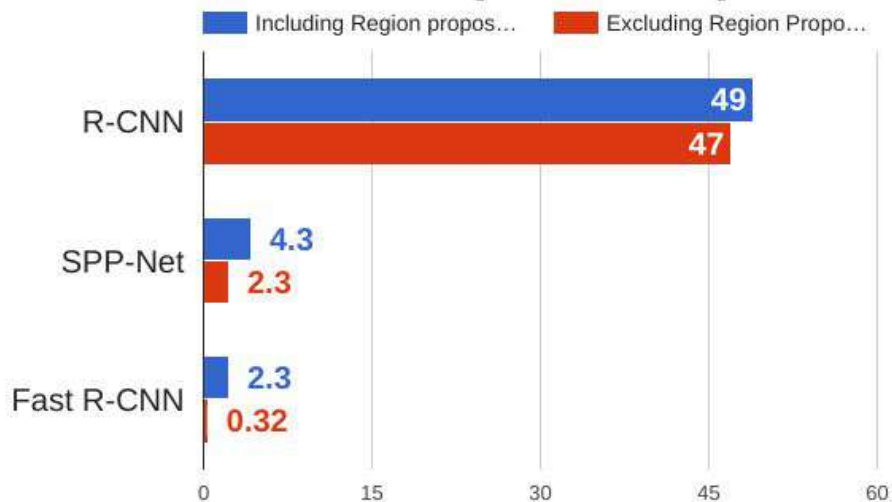
He et al, "Mask R-CNN", ICCV 2017

# R-CNN vs Fast R-CNN

## Training time (Hours)



## Test time (seconds)



Girshick et al, "Rich feature hierarchies for accurate object detection and semantic segmentation", CVPR 2014.

He et al, "Spatial pyramid pooling in deep convolutional networks for visual recognition", ECCV 2014

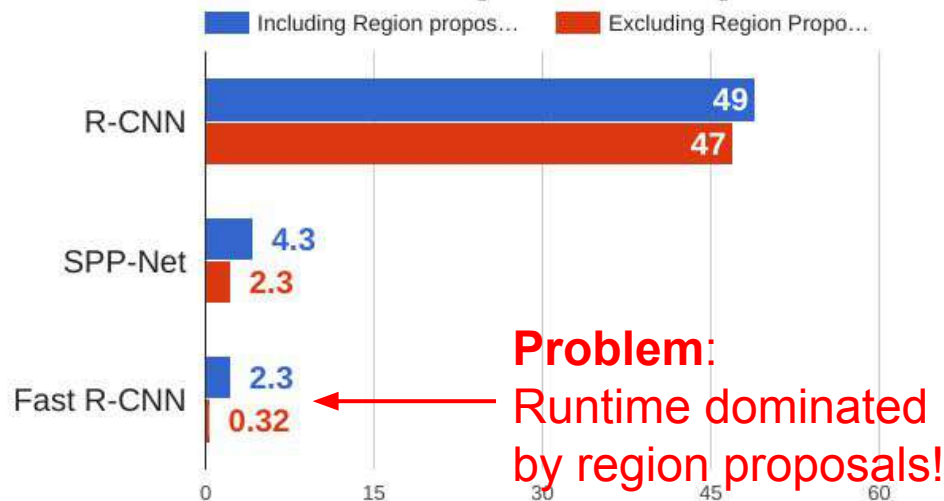
Girshick, "Fast R-CNN", ICCV 2015

# R-CNN vs Fast R-CNN

## Training time (Hours)



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Girshick et al, "Rich feature hierarchies for accurate object detection and semantic segmentation", CVPR 2014.

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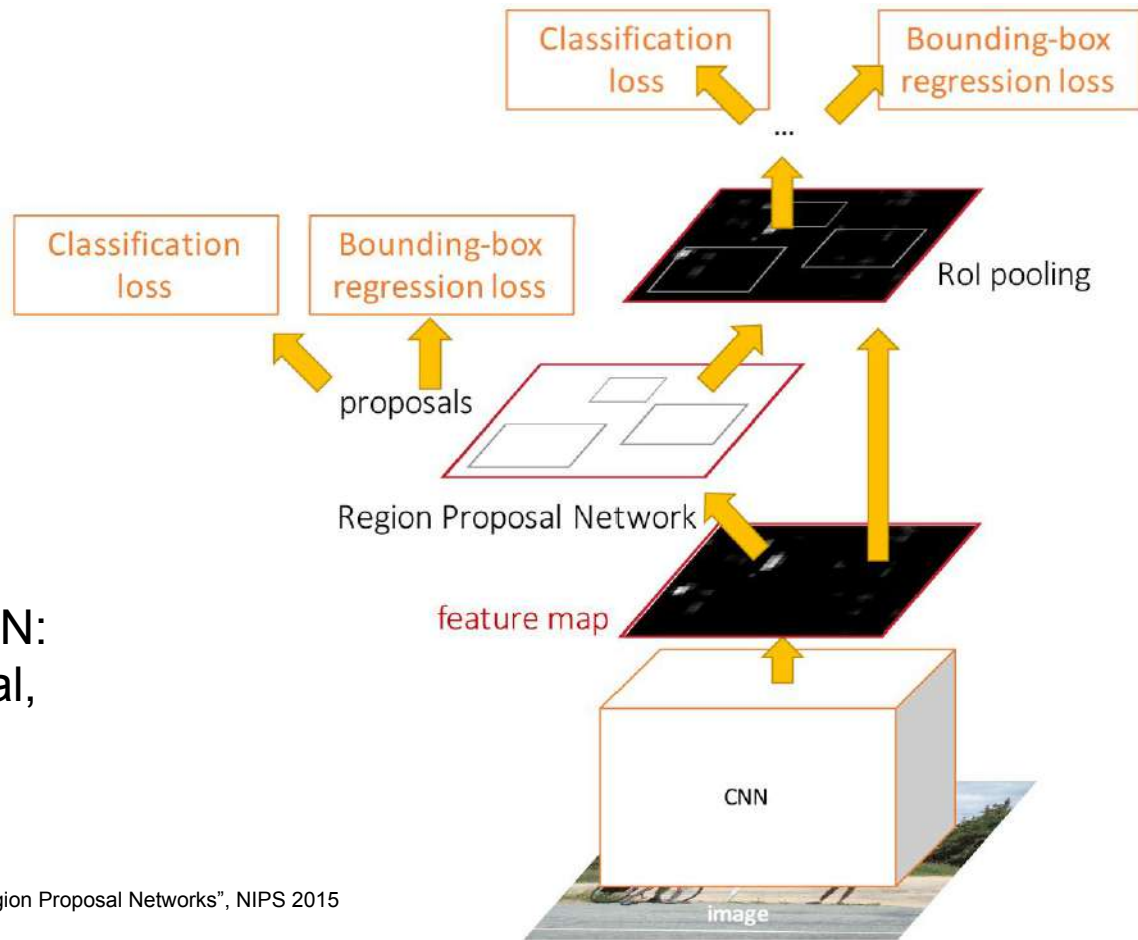
Girshick, "Fast R-CNN", ICCV 2015

# Faster R-CNN:

Make CNN do proposals!

Insert **Region Proposal Network (RPN)** to predict proposals from features

Otherwise same as Fast R-CNN:  
Crop features for each proposal,  
classify each one



Ren et al, "Faster R-CNN: Towards Real-Time Object Detection with Region Proposal Networks", NIPS 2015  
Figure copyright 2015, Ross Girshick; reproduced with permission

# Region Proposal Network



Input Image  
(e.g. 3 x 640 x 480)

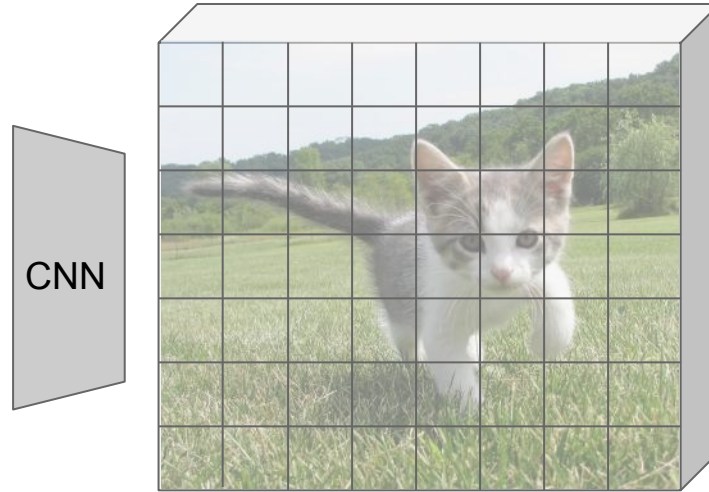


Image features  
(e.g. 512 x 20 x 15)

# Region Proposal Network

Imagine an **anchor box**  
of fixed size at each  
point in the feature map



Input Image  
(e.g. 3 x 640 x 480)

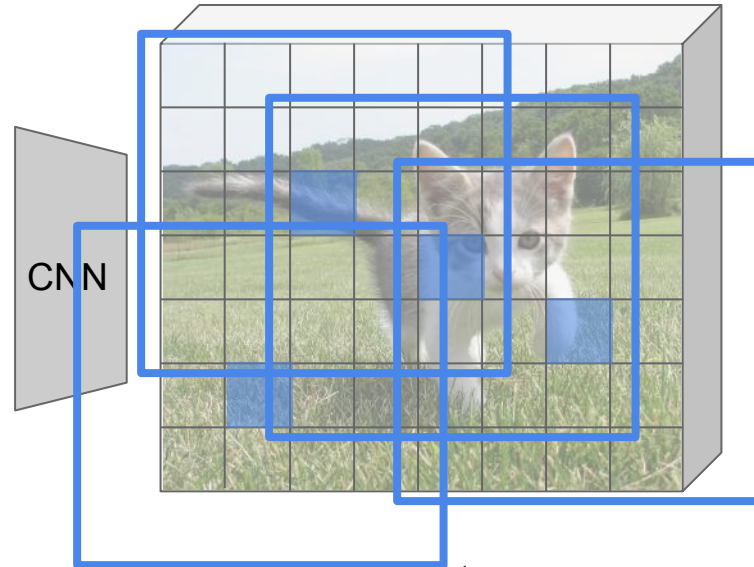


Image features  
(e.g. 512 x 20 x 15)



# Region Proposal Network



Input Image  
(e.g. 3 x 640 x 480)

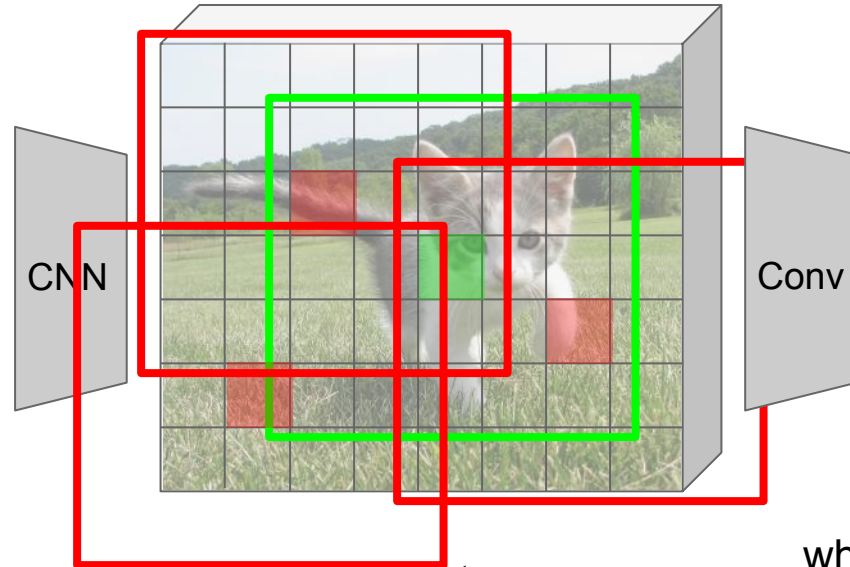


Image features  
(e.g. 512 x 20 x 15)

Imagine an **anchor box**  
of fixed size at each  
point in the feature map

Anchor is an object?  
1 x 20 x 15

At each point, predict  
whether the corresponding  
anchor contains an object  
(binary classification)



# Region Proposal Network



Input Image  
(e.g.  $3 \times 640 \times 480$ )

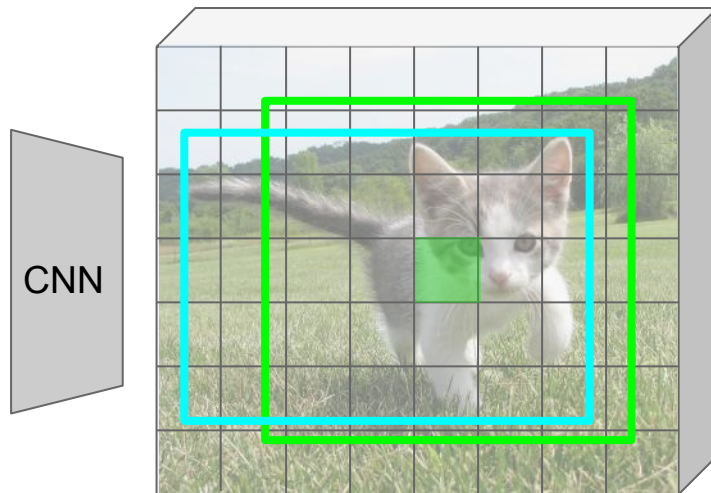
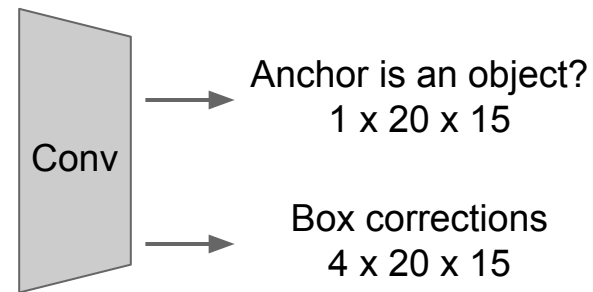


Image features  
(e.g.  $512 \times 20 \times 15$ )

Imagine an **anchor box**  
of fixed size at each  
point in the feature map



For positive boxes, also predict  
a corrections from the anchor to  
the ground-truth box (regress 4  
numbers per pixel)

# Region Proposal Network

In practice use  $K$  different anchor boxes of different size / scale at each point



Input Image  
(e.g.  $3 \times 640 \times 480$ )

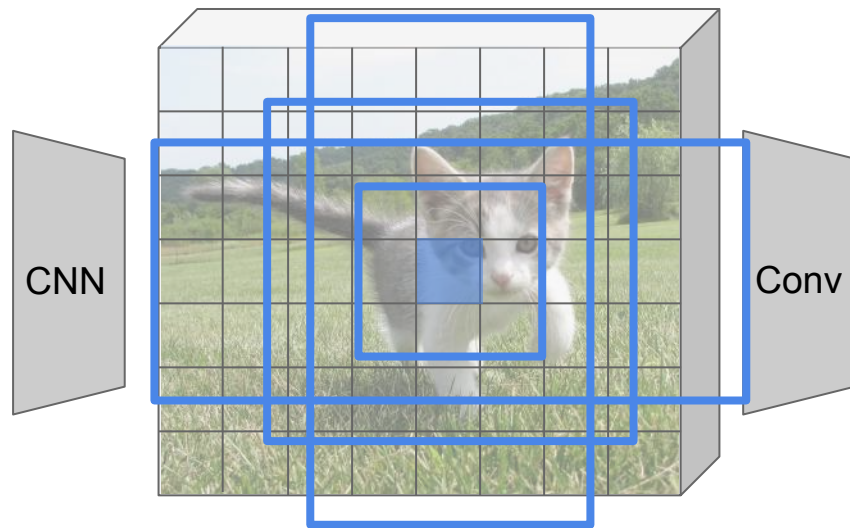


Image features  
(e.g.  $512 \times 20 \times 15$ )

Anchor is an object?  
 $K \times 20 \times 15$

Box transforms  
 $4K \times 20 \times 15$

# Region Proposal Network

In practice use  $K$  different anchor boxes of different size / scale at each point



Input Image  
(e.g.  $3 \times 640 \times 480$ )

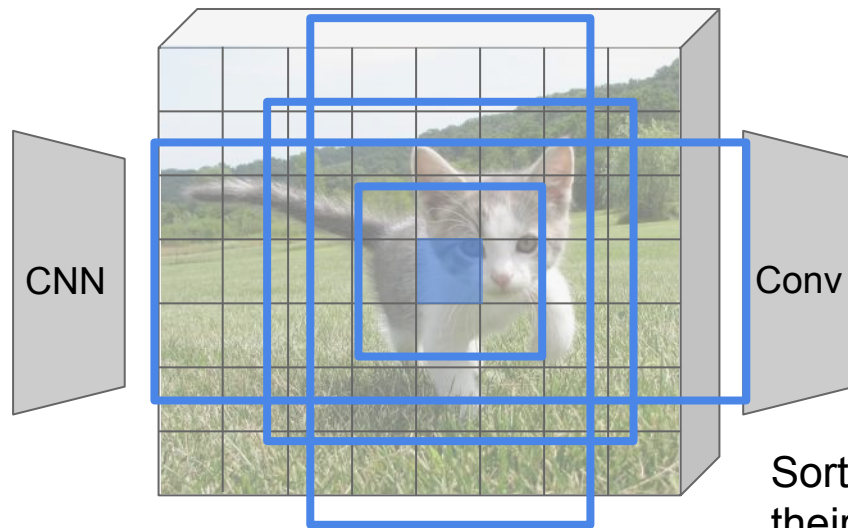


Image features  
(e.g.  $512 \times 20 \times 15$ )

Anchor is an object?  
 $K \times 20 \times 15$

Box transforms  
 $4K \times 20 \times 15$

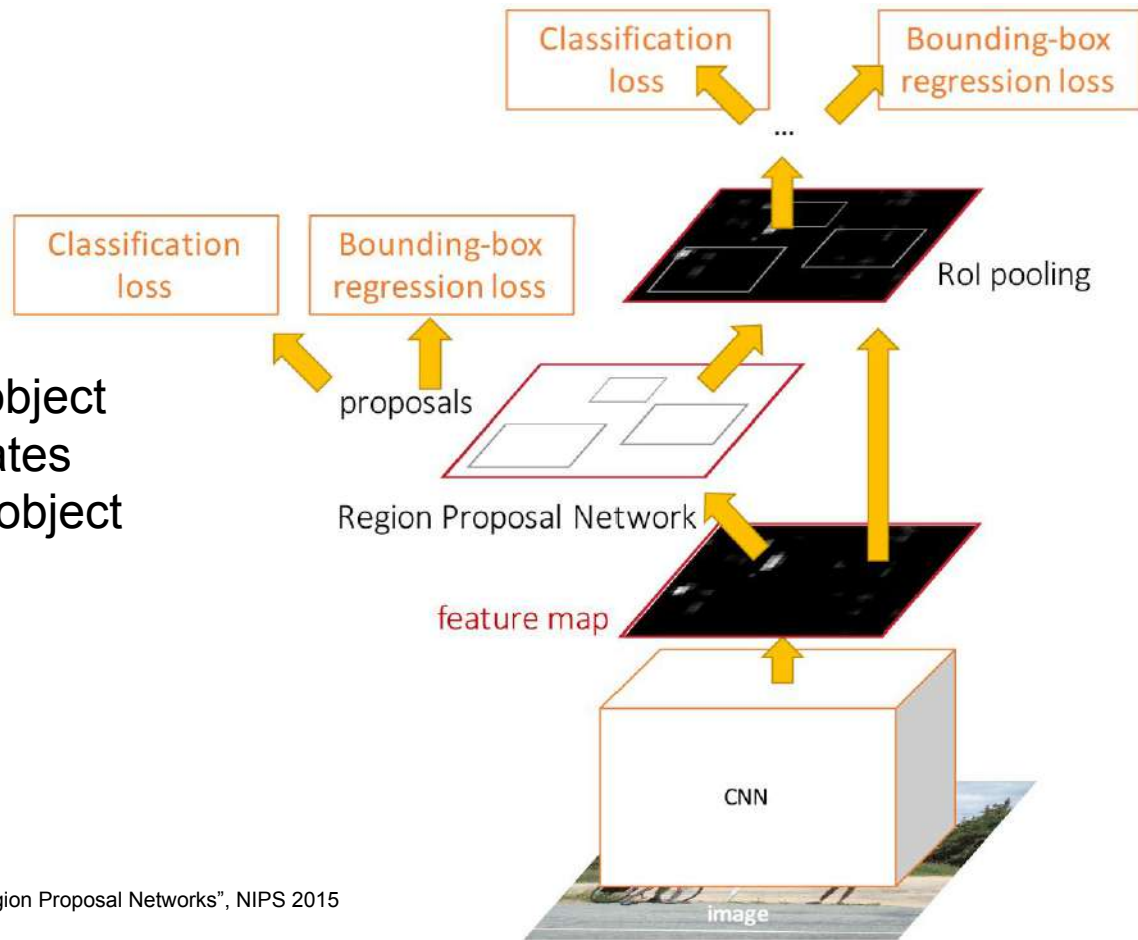
Sort the  $K \times 20 \times 15$  boxes by their “objectness” score, take top  $\sim 300$  as our proposals

# Faster R-CNN:

Make CNN do proposals!

Jointly train with 4 losses:

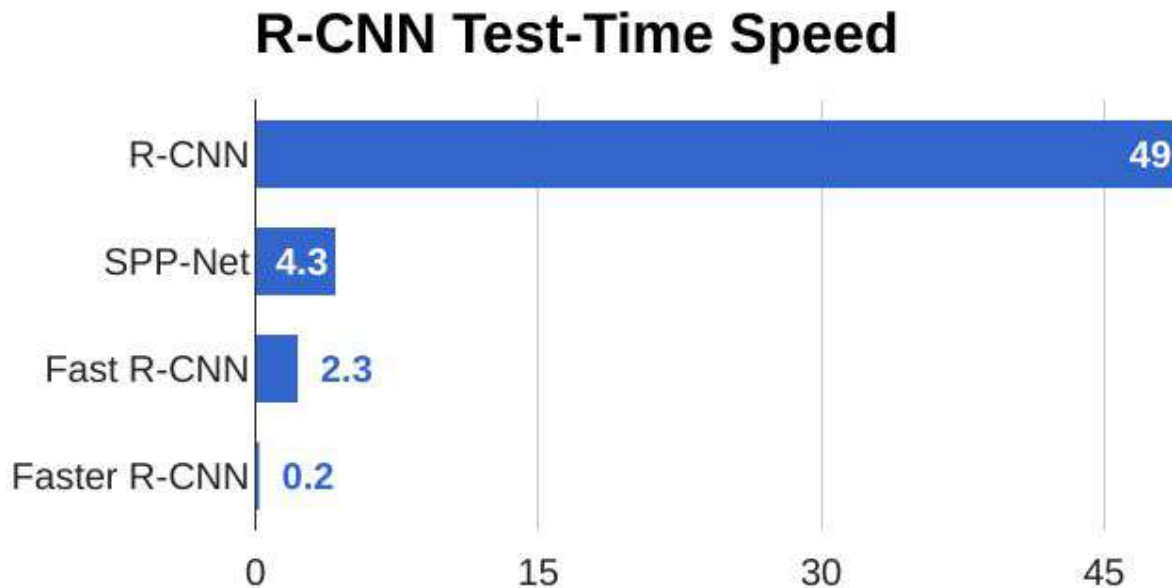
1. RPN classify object / not object
2. RPN regress box coordinates
3. Final classification score (object classes)
4. Final box coordinates



Ren et al, "Faster R-CNN: Towards Real-Time Object Detection with Region Proposal Networks", NIPS 2015  
Figure copyright 2015, Ross Girshick; reproduced with permission

# Faster R-CNN:

Make CNN do proposals!

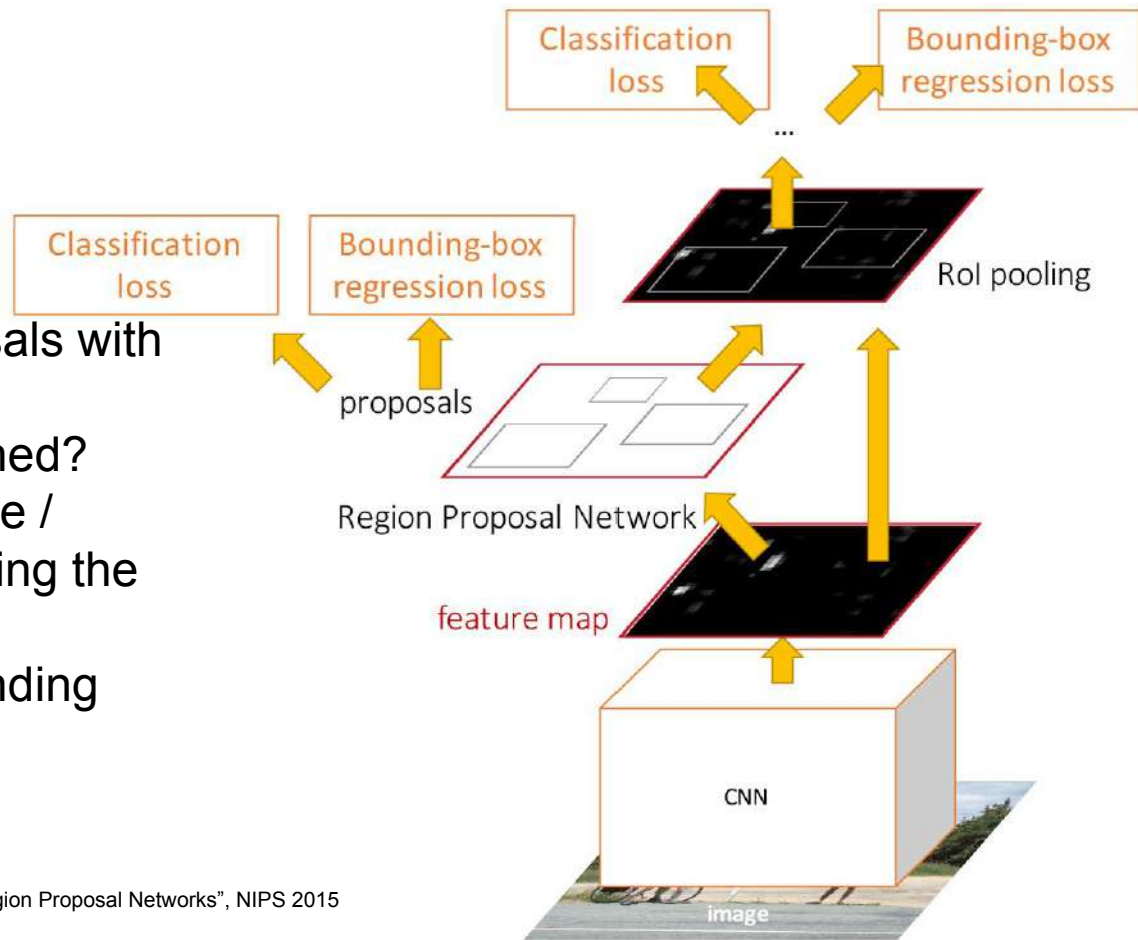


# Faster R-CNN:

Make CNN do proposals!

Glossing over many details:

- Ignore overlapping proposals with **non-max suppression**
- How are anchors determined?
- How do we sample positive / negative samples for training the RPN?
- How to parameterize bounding box regression?



Ren et al, "Faster R-CNN: Towards Real-Time Object Detection with Region Proposal Networks", NIPS 2015  
Figure copyright 2015, Ross Girshick; reproduced with permission



# Faster R-CNN:

Make CNN do proposals!

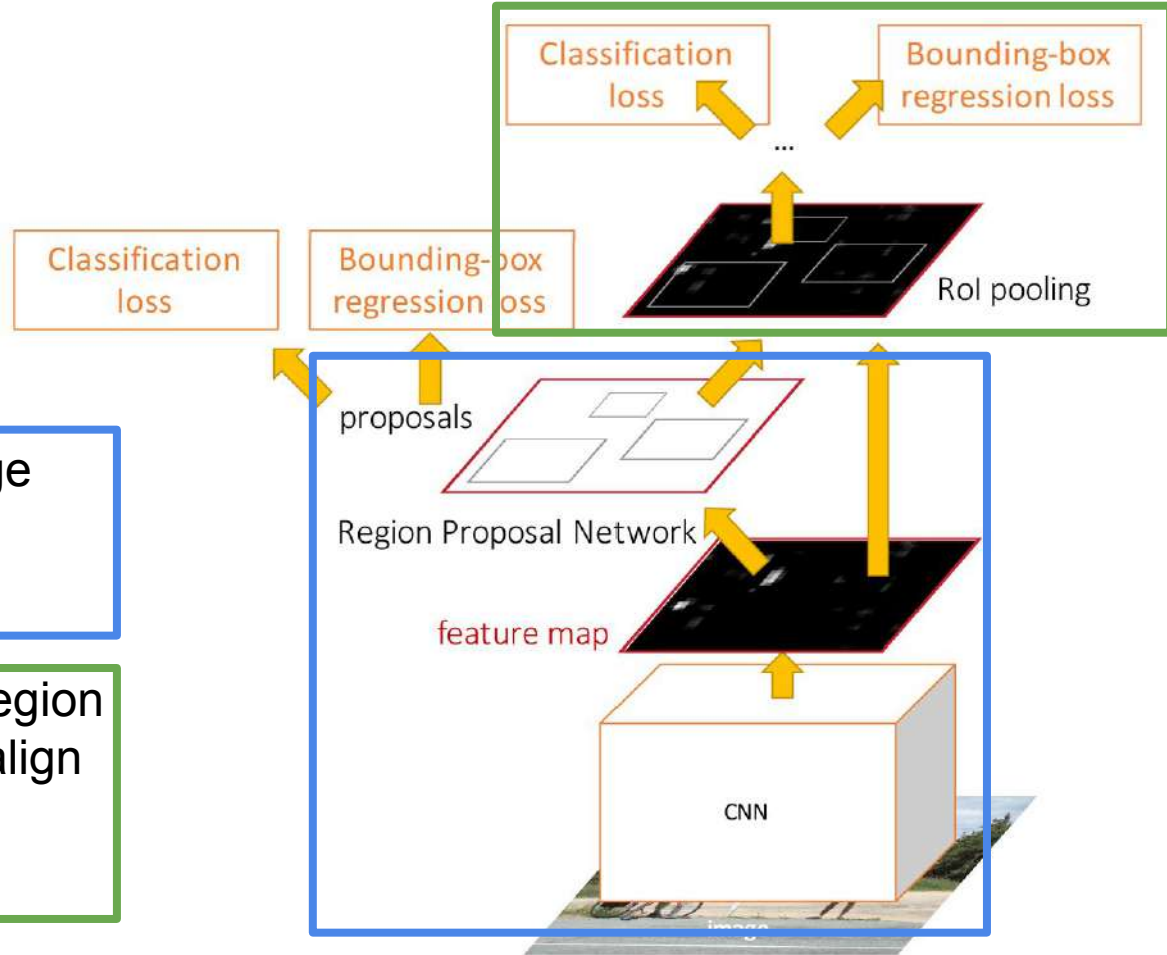
Faster R-CNN is a  
**Two-stage object detector**

First stage: Run once per image

- Backbone network
- Region proposal network

Second stage: Run once per region

- Crop features: RoI pool / align
- Predict object class
- Prediction bbox offset



# Faster R-CNN:

Make CNN do proposals!

Faster R-CNN is a  
**Two-stage object detector**

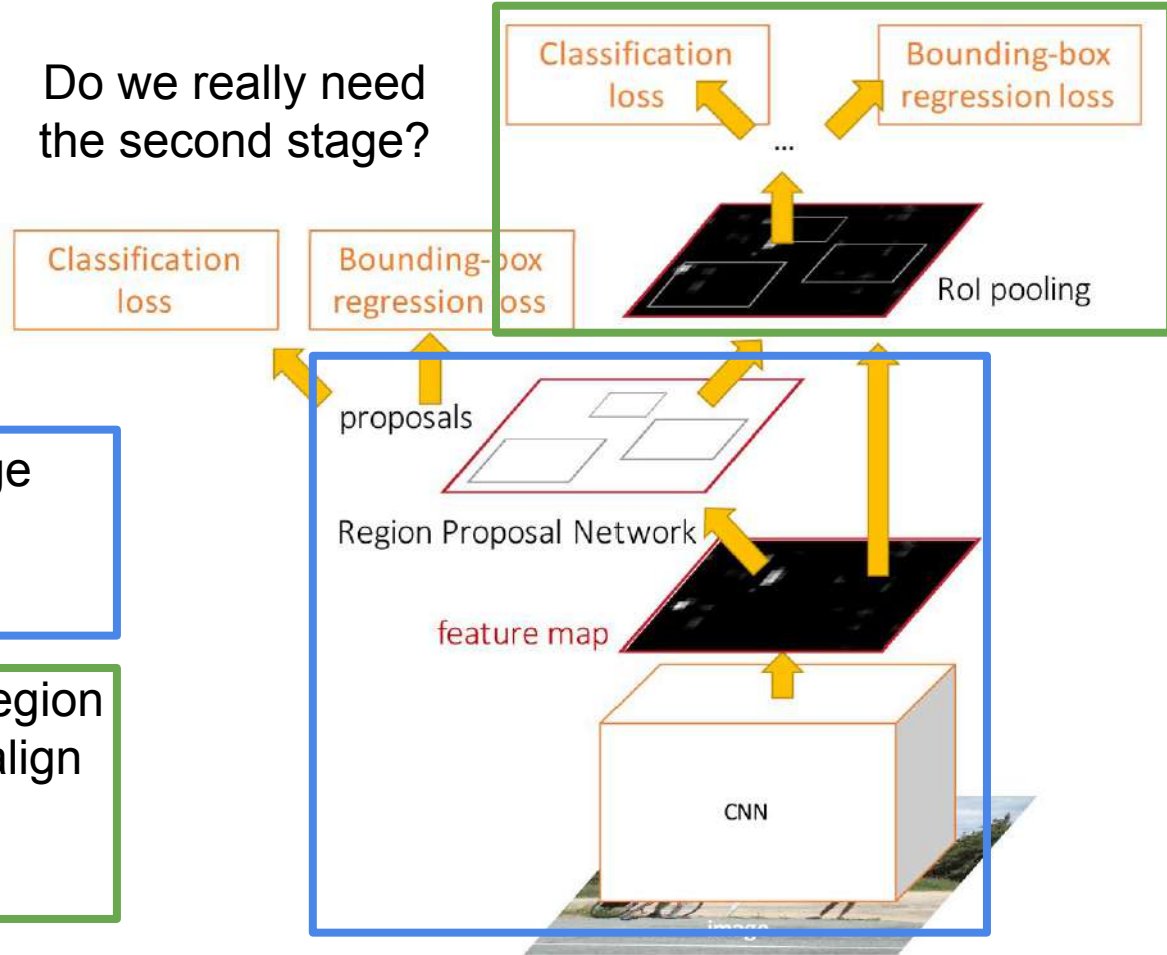
First stage: Run once per image

- Backbone network
- Region proposal network

Second stage: Run once per region

- Crop features: RoI pool / align
- Predict object class
- Prediction bbox offset

Do we really need  
the second stage?

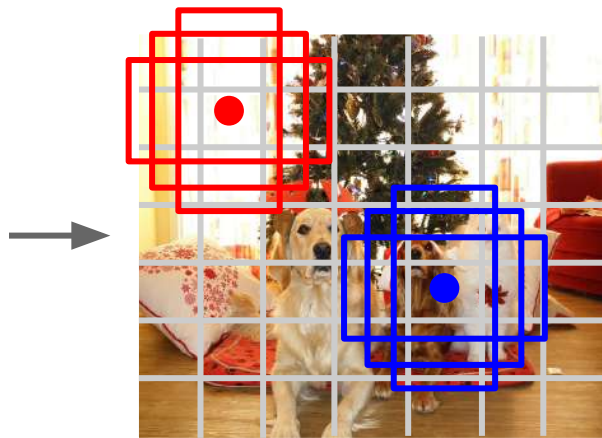




# Single-Stage Object Detectors: YOLO / SSD / RetinaNet



Input image  
 $3 \times H \times W$



Divide image into grid  
 $7 \times 7$

Image a set of **base boxes**  
centered at each grid cell  
Here  $B = 3$

Within each grid cell:

- Regress from each of the  $B$  base boxes to a final box with 5 numbers:  
( $dx, dy, dh, dw, confidence$ )
- Predict scores for each of  $C$  classes (including background as a class)
- Looks a lot like RPN, but category-specific!

Output:  
 $7 \times 7 \times (5 * B + C)$

Redmon et al, "You Only Look Once:  
Unified, Real-Time Object Detection", CVPR 2016  
Liu et al, "SSD: Single-Shot MultiBox Detector", ECCV 2016  
Lin et al, "Focal Loss for Dense Object Detection", ICCV 2017

# Object Detection: Lots of variables ...

## Backbone Network

VGG16

ResNet-101

Inception V2

Inception V3

Inception

ResNet

MobileNet

## “Meta-Architecture”

Two-stage: Faster R-CNN

Single-stage: YOLO / SSD

Hybrid: R-FCN

## Image Size

## # Region Proposals

...

## Takeaways

Faster R-CNN is slower  
but more accurate

SSD is much faster but  
not as accurate

Bigger / Deeper  
backbones work better

Huang et al, “Speed/accuracy trade-offs for modern convolutional object detectors”, CVPR 2017

R-FCN: Dai et al, “R-FCN: Object Detection via Region-based Fully Convolutional Networks”, NIPS 2016

Inception-V2: Ioffe and Szegedy, “Batch Normalization: Accelerating Deep Network Training by Reducing Internal Covariate Shift”, ICML 2015

Inception V3: Szegedy et al, “Rethinking the Inception Architecture for Computer Vision”, arXiv 2016

Inception ResNet: Szegedy et al, “Inception-V4, Inception-ResNet and the Impact of Residual Connections on Learning”, arXiv 2016

MobileNet: Howard et al, “Efficient Convolutional Neural Networks for Mobile Vision Applications”, arXiv 2017

# Object Detection: Lots of variables ...

## Backbone Network

VGG16

ResNet-101

Inception V2

Inception V3

Inception

ResNet

MobileNet

## “Meta-Architecture”

Two-stage: Faster R-CNN

Single-stage: YOLO / SSD

Hybrid: R-FCN

## Image Size

## # Region Proposals

...

## Takeaways

Faster R-CNN is slower  
but more accurate

SSD is much faster but  
not as accurate

Bigger / Deeper  
backbones work better

Huang et al, “Speed/accuracy trade-offs for modern convolutional object detectors”, CVPR 2017

Zou et al, “Object Detection in 20 Years: A Survey”, [arXiv 2019](#)

R-FCN: Dai et al, “R-FCN: Object Detection via Region-based Fully Convolutional Networks”, NIPS 2016

Inception-V2: Ioffe and Szegedy, “Batch Normalization: Accelerating Deep Network Training by Reducing Internal Covariate Shift”, ICML 2015

Inception V3: Szegedy et al, “Rethinking the Inception Architecture for Computer Vision”, arXiv 2016

Inception ResNet: Szegedy et al, “Inception-V4, Inception-ResNet and the Impact of Residual Connections on Learning”, arXiv 2016

MobileNet: Howard et al, “Efficient Convolutional Neural Networks for Mobile Vision Applications”, arXiv 2017

# Instance Segmentation

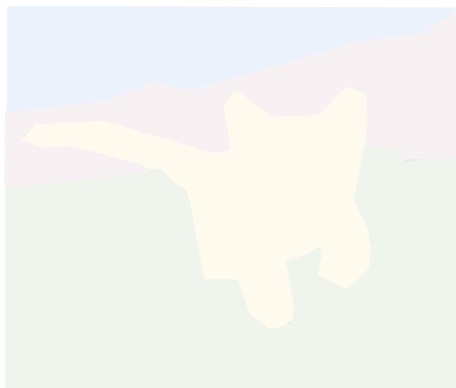
Classification



CAT

No spatial extent

Semantic Segmentation



GRASS, CAT,  
TREE, SKY

No objects, just pixels

Object Detection



DOG, DOG, CAT

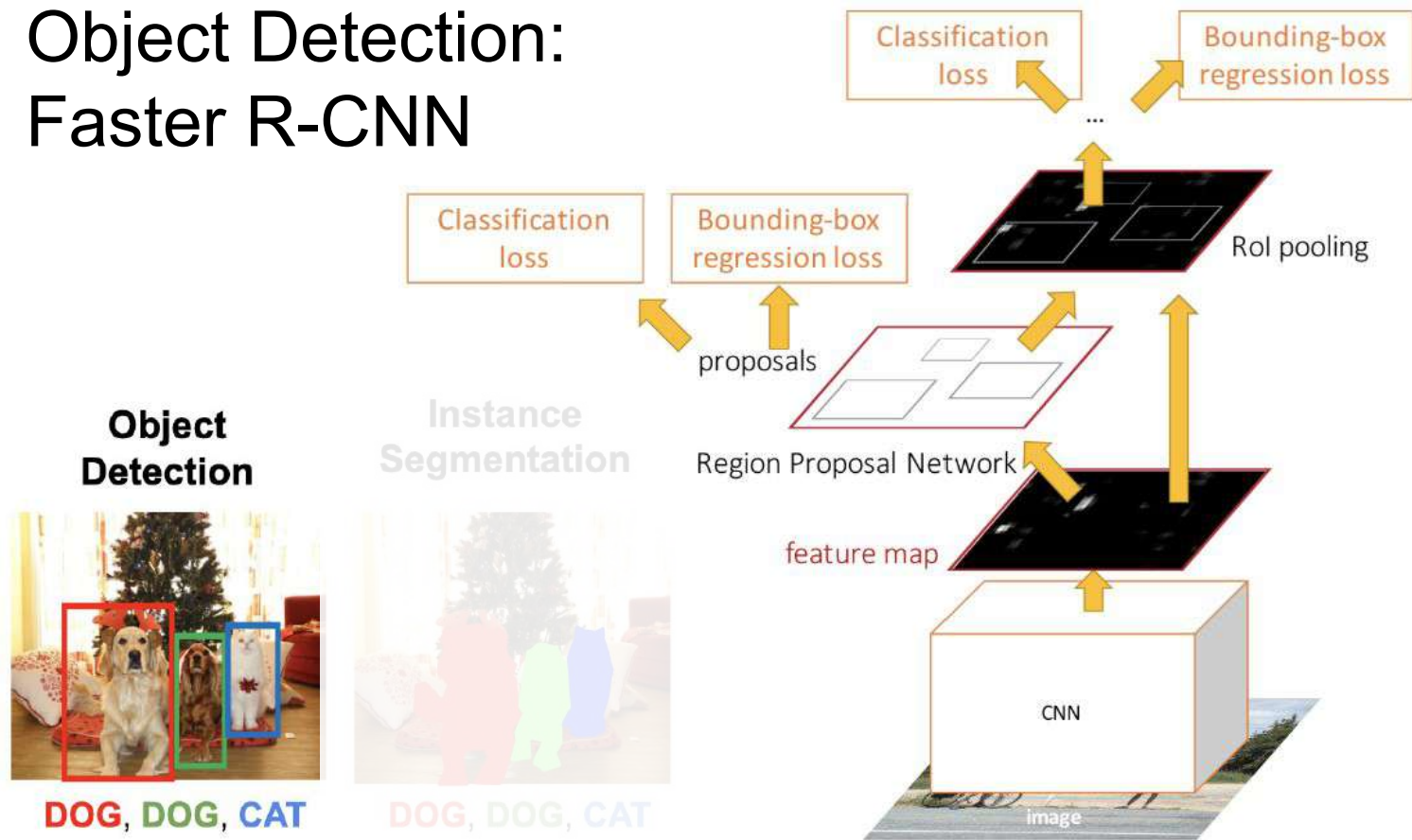
Multiple Object

Instance Segmentation

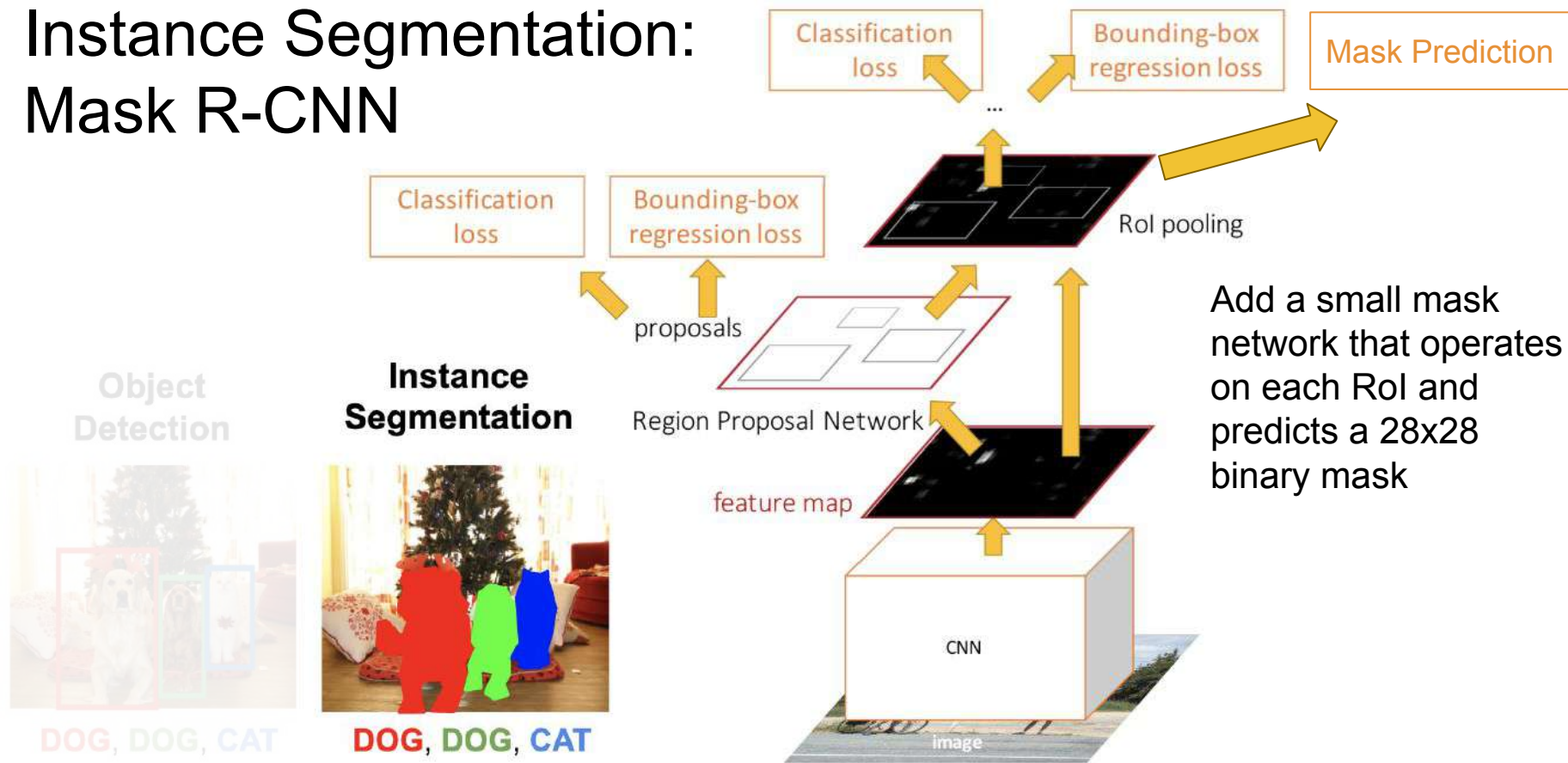


DOG, DOG, CAT

# Object Detection: Faster R-CNN

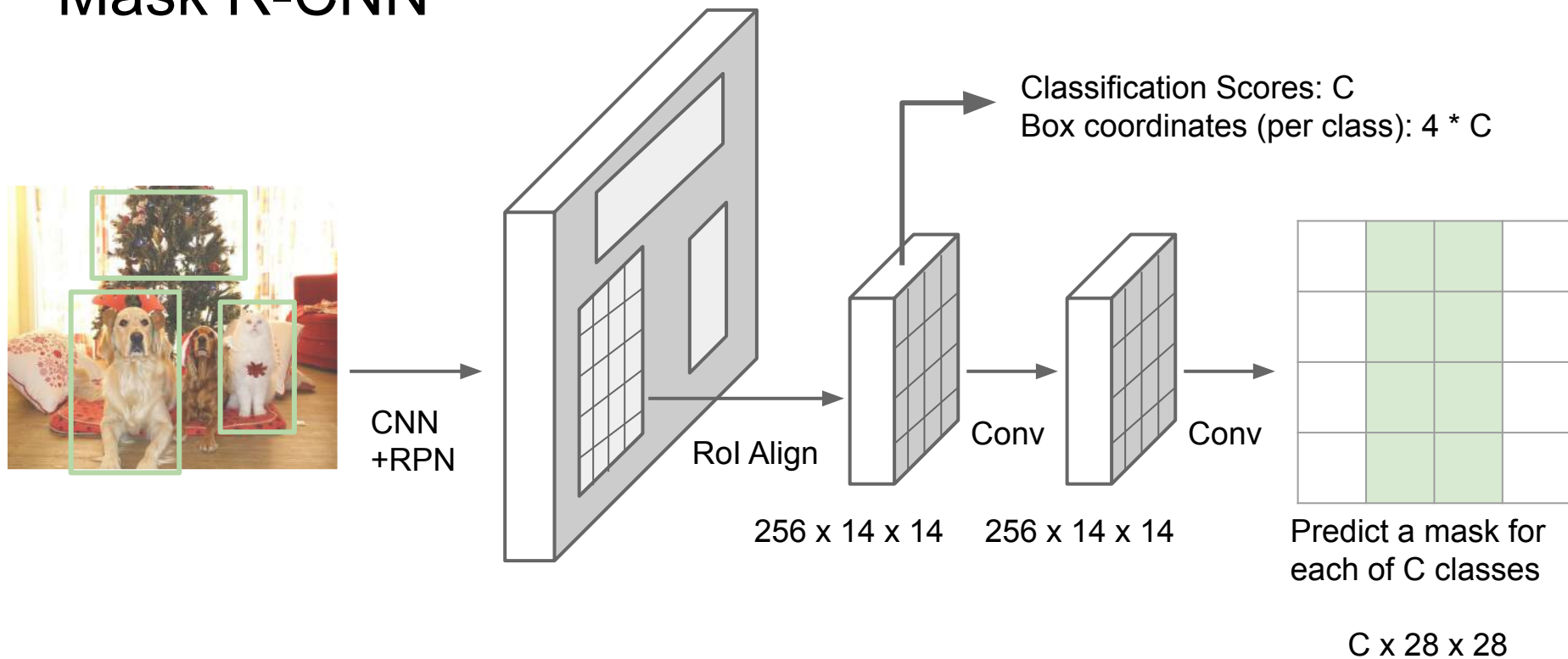


# Instance Segmentation: Mask R-CNN



He et al, "Mask R-CNN", ICCV 2017

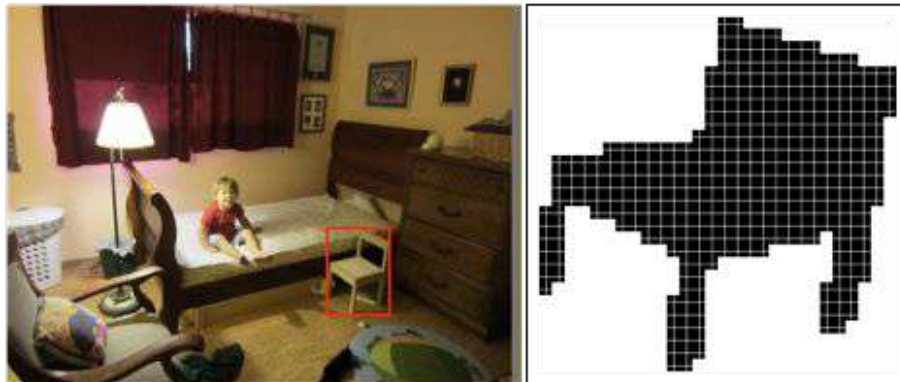
# Mask R-CNN



He et al, "Mask R-CNN", arXiv 2017

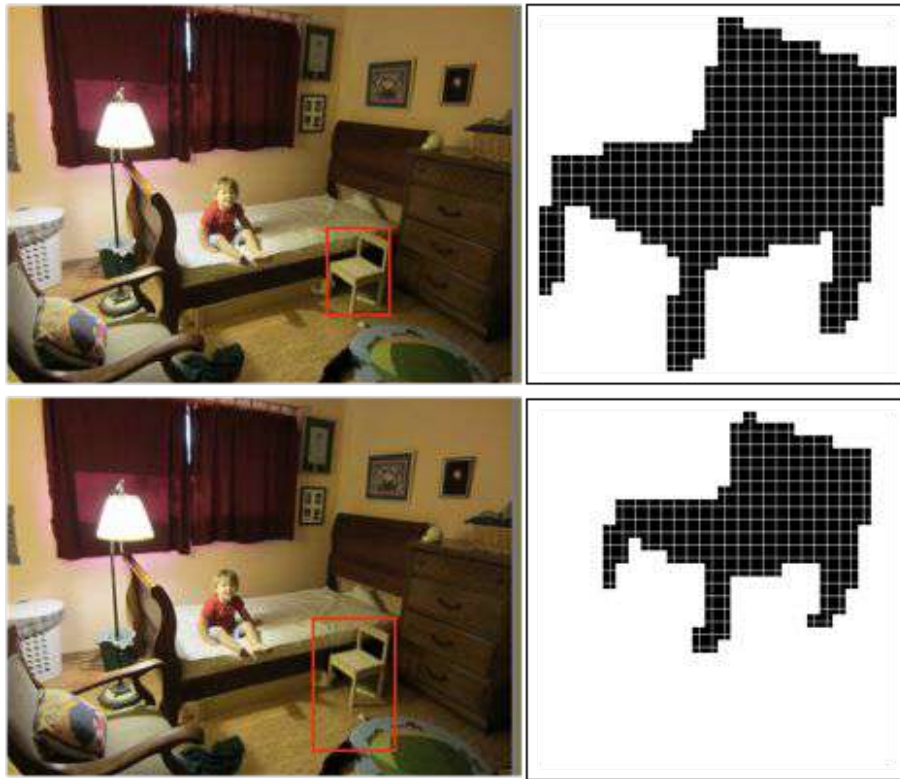


# Mask R-CNN: Example Mask Training Targets

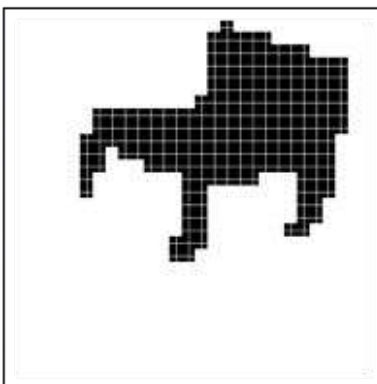
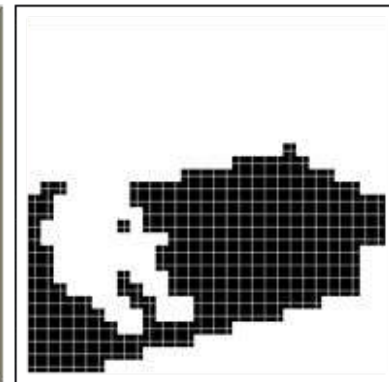
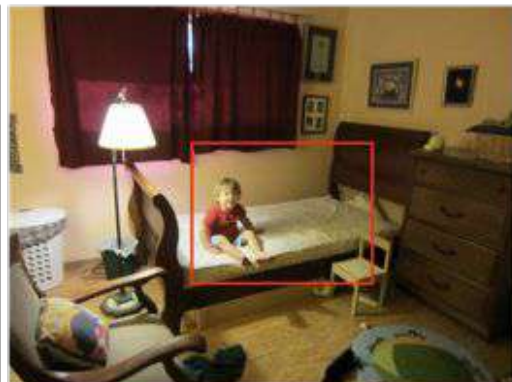
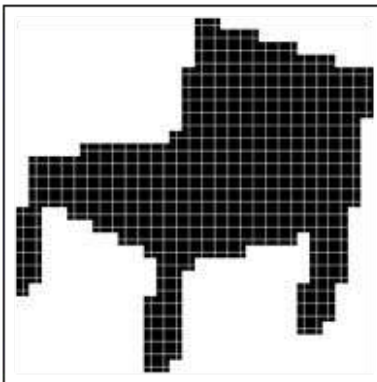




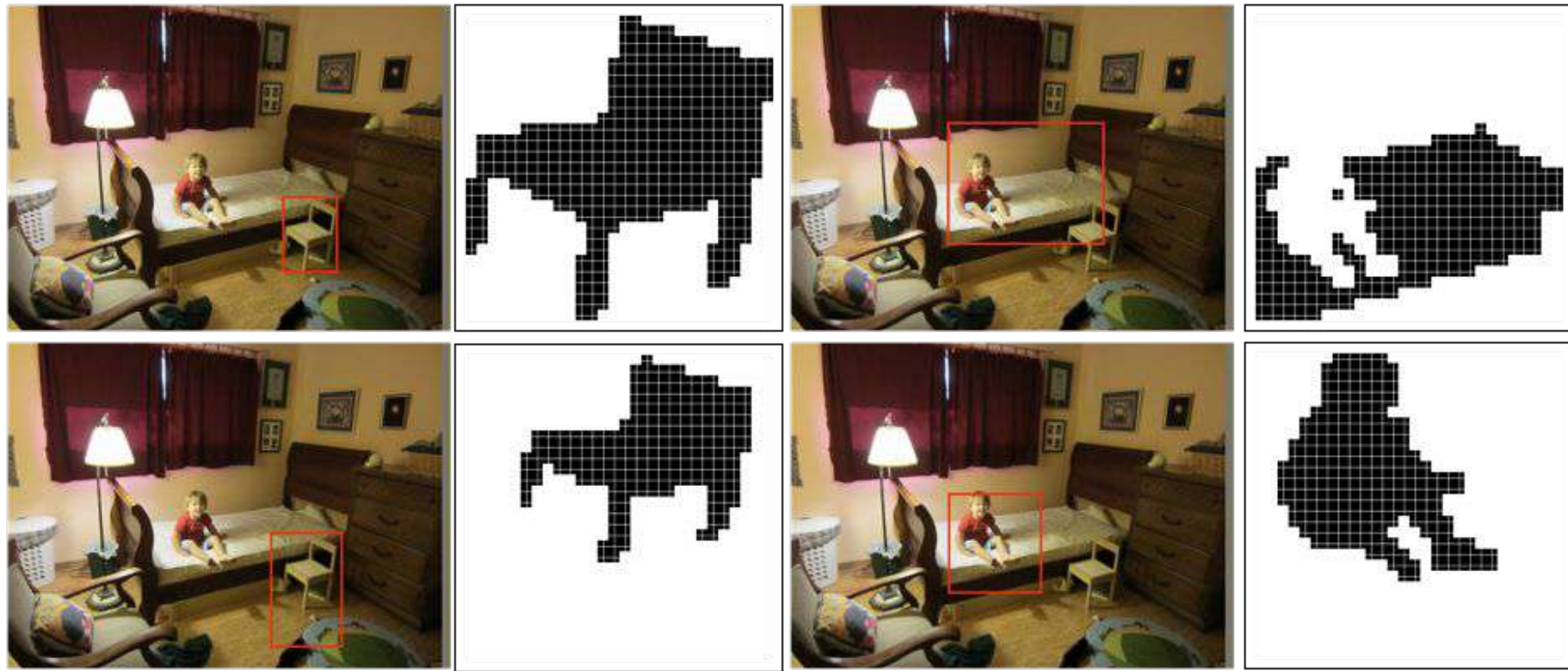
# Mask R-CNN: Example Mask Training Targets



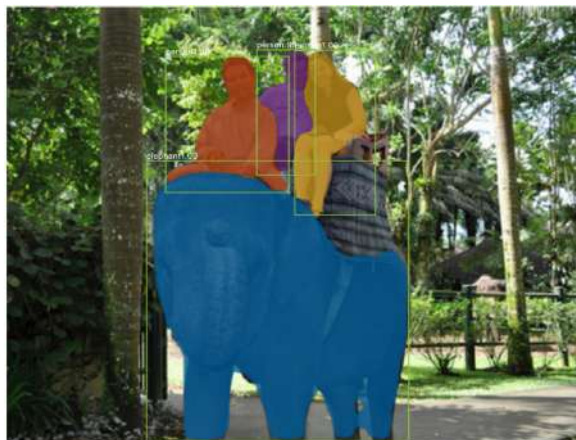
# Mask R-CNN: Example Mask Training Targets



# Mask R-CNN: Example Mask Training Targets



# Mask R-CNN: Very Good Results!

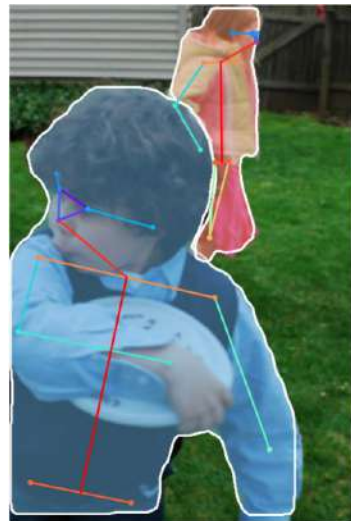
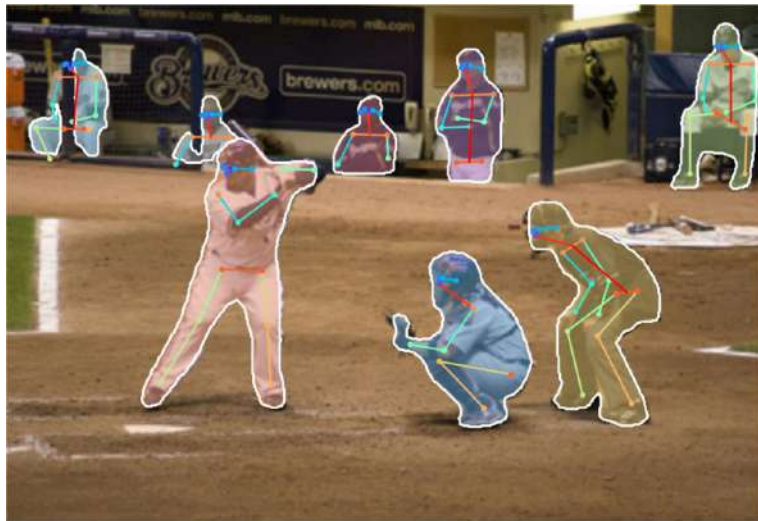


He et al, "Mask R-CNN", ICCV 2017



# Mask R-CNN

## Also does pose



He et al, "Mask R-CNN", ICCV 2017

# Open Source Frameworks

Lots of good implementations on GitHub!

TensorFlow Detection API:

[https://github.com/tensorflow/models/tree/master/research/object\\_detection](https://github.com/tensorflow/models/tree/master/research/object_detection)

Faster RCNN, SSD, RFCN, Mask R-CNN, ...

Detectron2 (PyTorch)

<https://github.com/facebookresearch/detectron2>

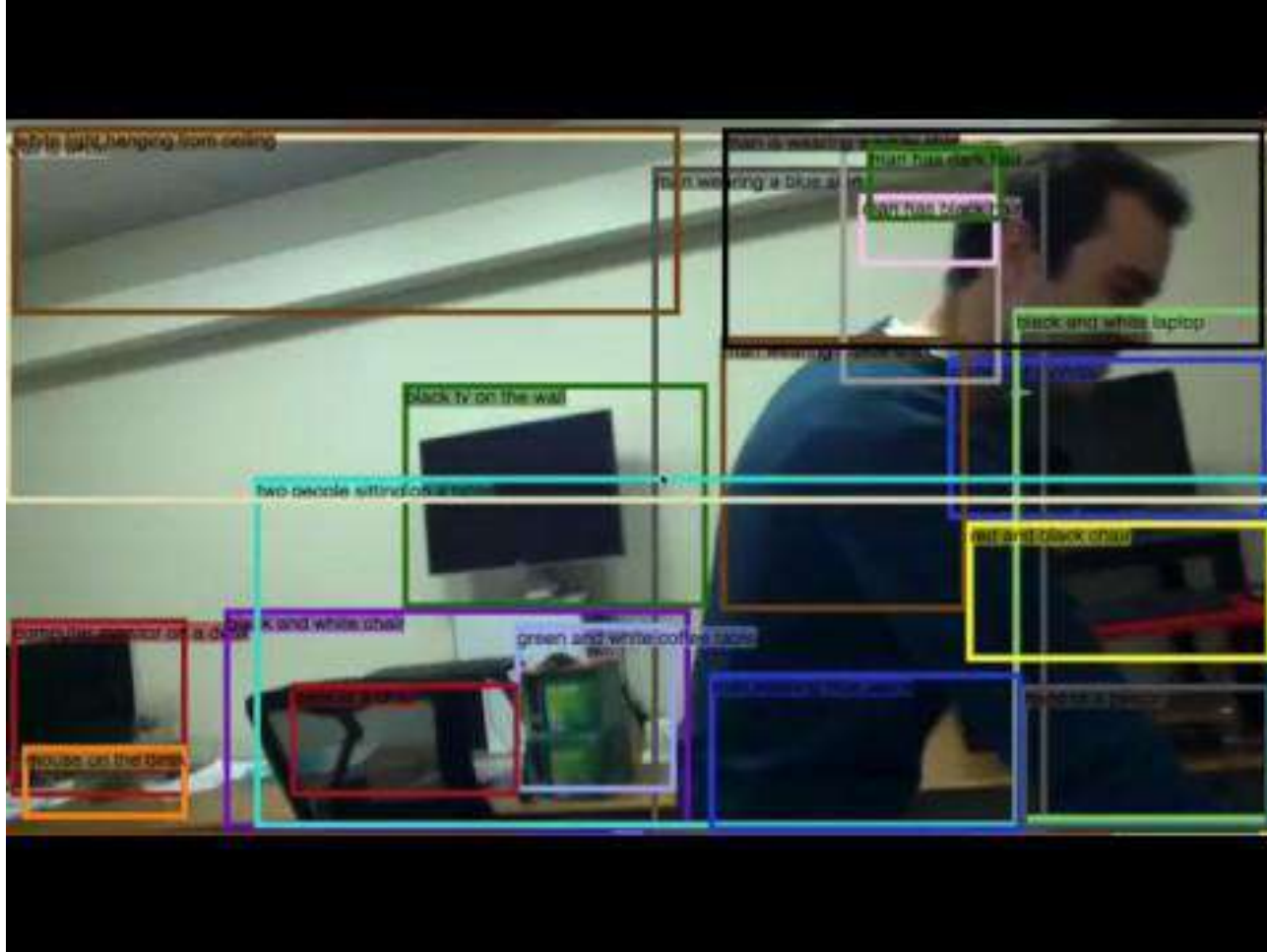
Mask R-CNN, RetinaNet, Faster R-CNN, RPN, Fast R-CNN, R-FCN, ...

Finetune on your own dataset with pre-trained models

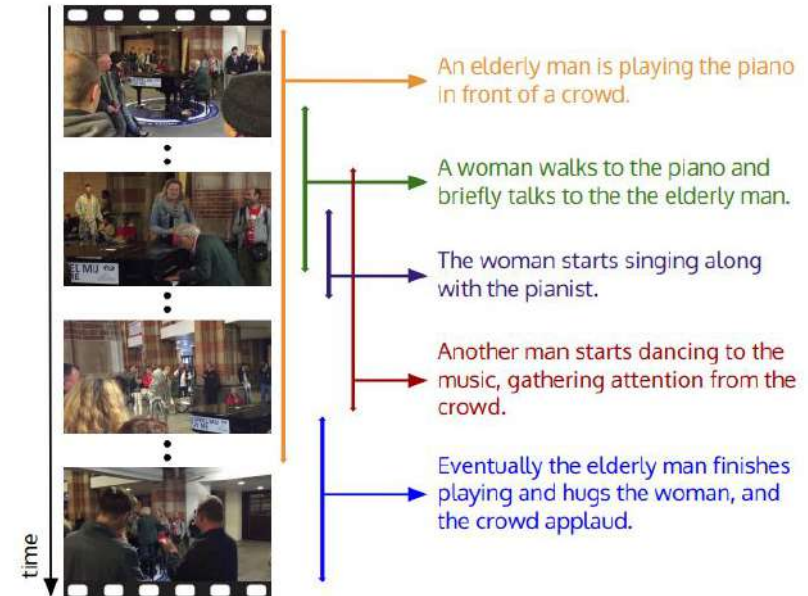
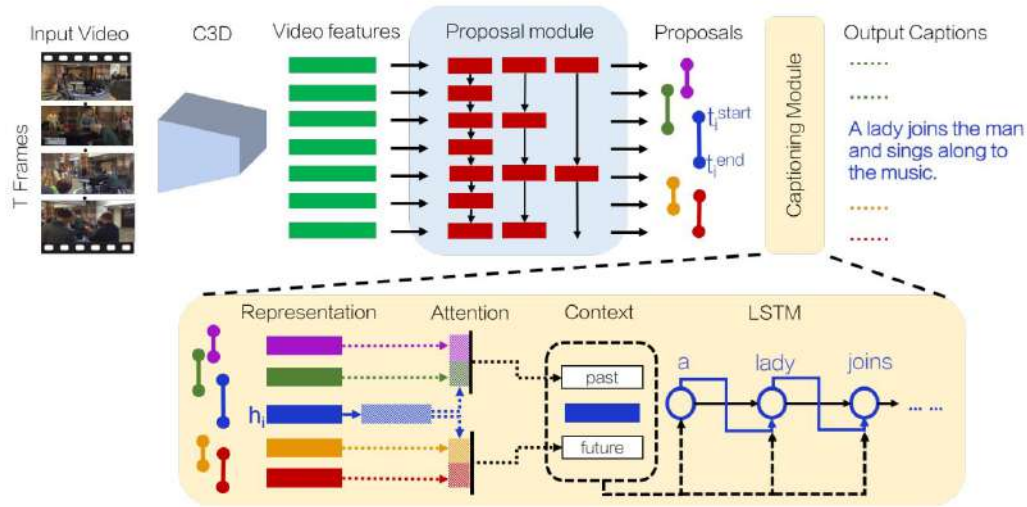
# Beyond 2D Object Detection...





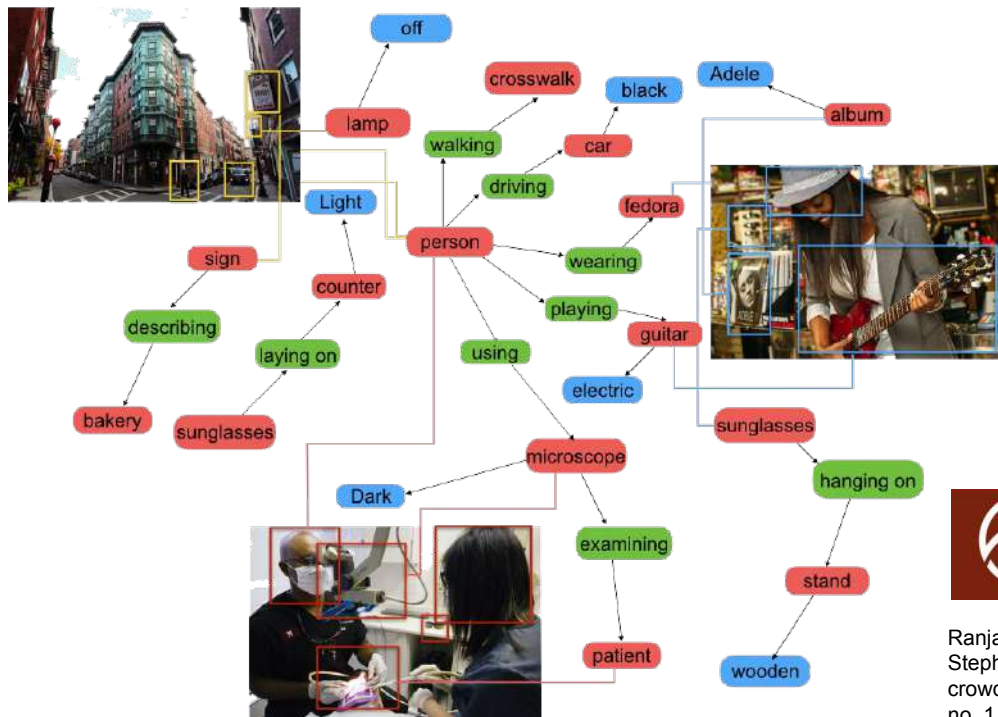


# Dense Video Captioning



Ranjay Krishna et al., "Dense-Captioning Events in Videos", ICCV 2017  
Figure copyright IEEE, 2017. Reproduced with permission.

# Objects + Relationships = Scene Graphs



108,077 Images

5.4 Million Region Descriptions

1.7 Million Visual Question Answers

3.8 Million Object Instances

2.8 Million Attributes

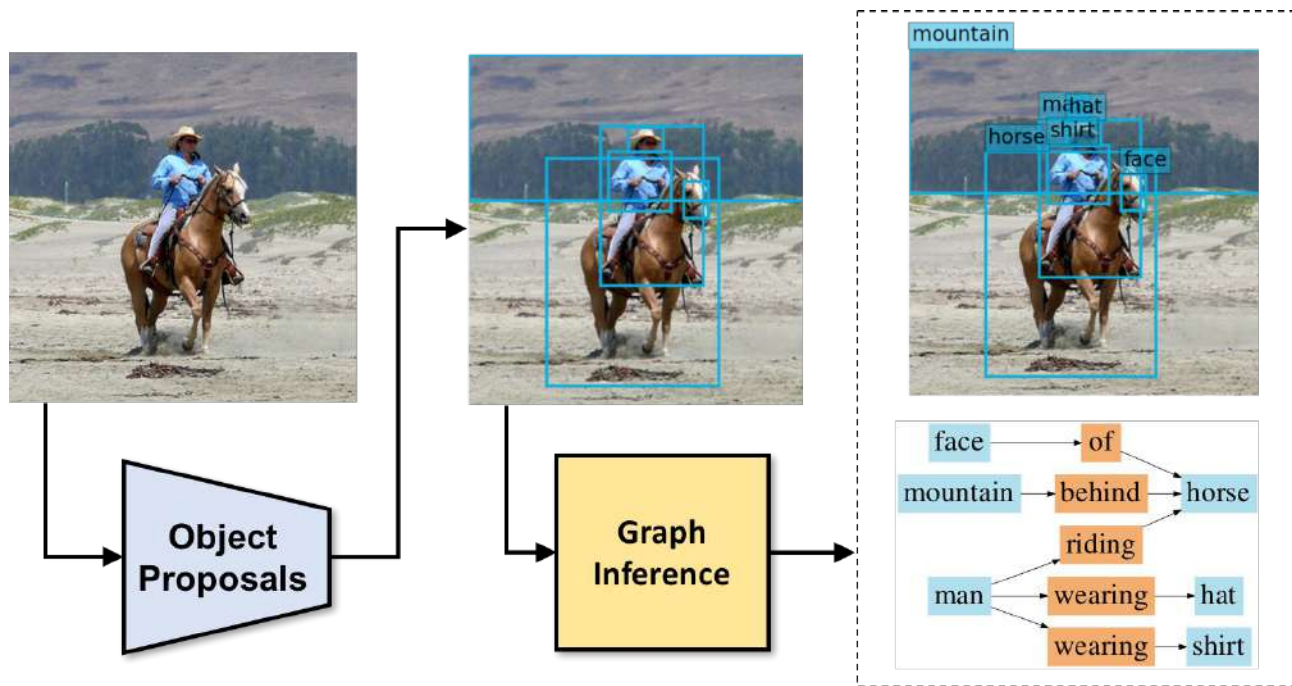
2.3 Million Relationships

Everything Mapped to Wordnet Synsets



Ranjay Krishna, Yuke Zhu, Oliver Groth, Justin Johnson, Kenji Hata, Joshua Kravitz, Stephanie Chen et al. "Visual genome: Connecting language and vision using crowdsourced dense image annotations." International Journal of Computer Vision 123, no. 1 (2017): 32-73.

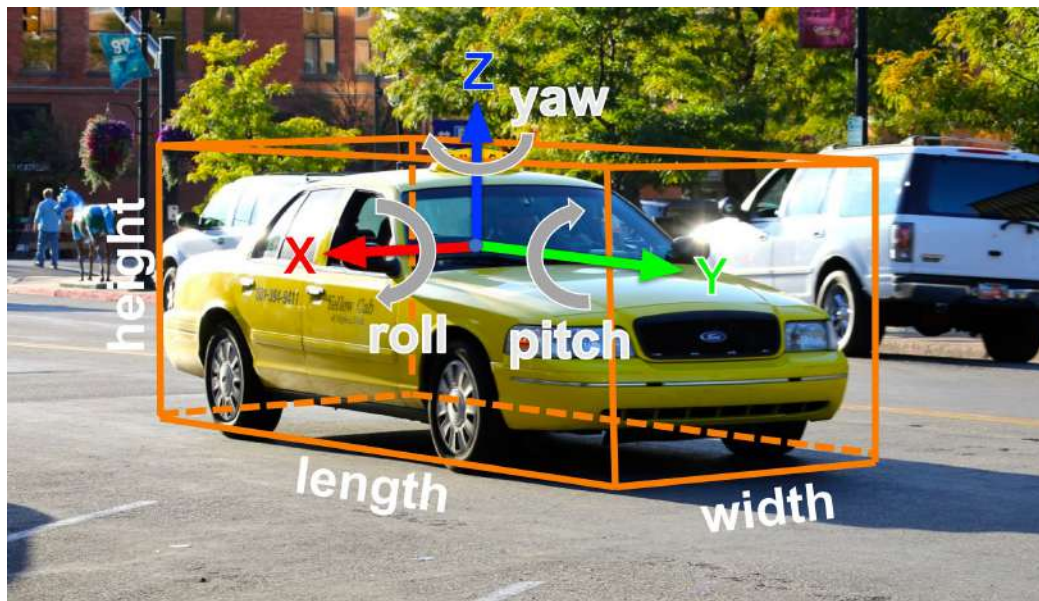
# Scene Graph Prediction



Xu, Zhu, Choy, and Fei-Fei, "Scene Graph Generation by Iterative Message Passing", CVPR 2017  
Figure copyright IEEE, 2018. Reproduced for educational purposes.



# 3D Object Detection



2D Object Detection:

2D bounding box

$(x, y, w, h)$

3D Object Detection:

3D oriented bounding box

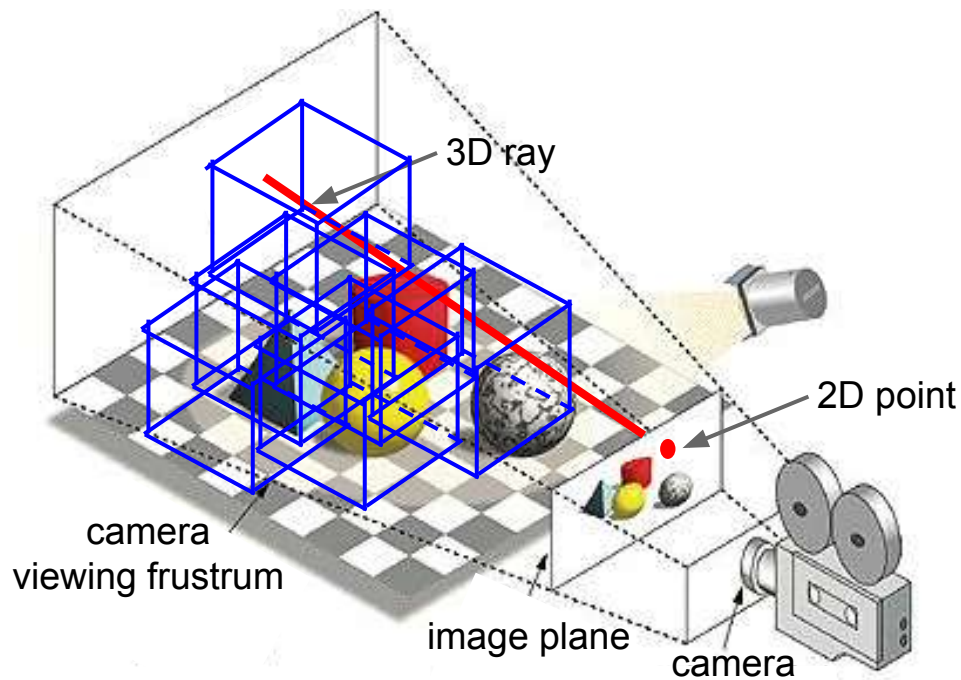
$(x, y, z, w, h, l, r, p, \gamma)$

Simplified bbox: no roll & pitch

Much harder problem than 2D  
object detection!

[This image](#) is [CC0 public domain](#)

# 3D Object Detection: Simple Camera Model



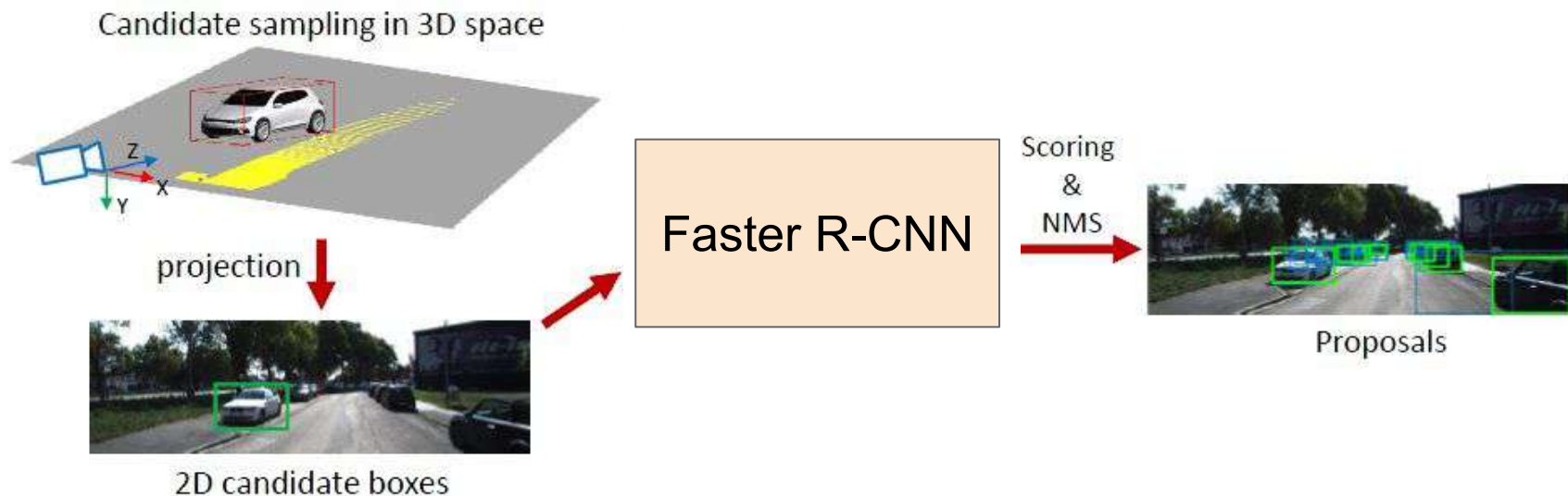
A point on the image plane corresponds to a **ray** in the 3D space

A 2D bounding box on an image is a **frustrum** in the 3D space

Localize an object in 3D:  
The object can be anywhere in the **camera viewing frustum**!

Image source: [https://www.pcmag.com/encyclopedia\\_images/\\_FRUSTUM.GIF](https://www.pcmag.com/encyclopedia_images/_FRUSTUM.GIF)

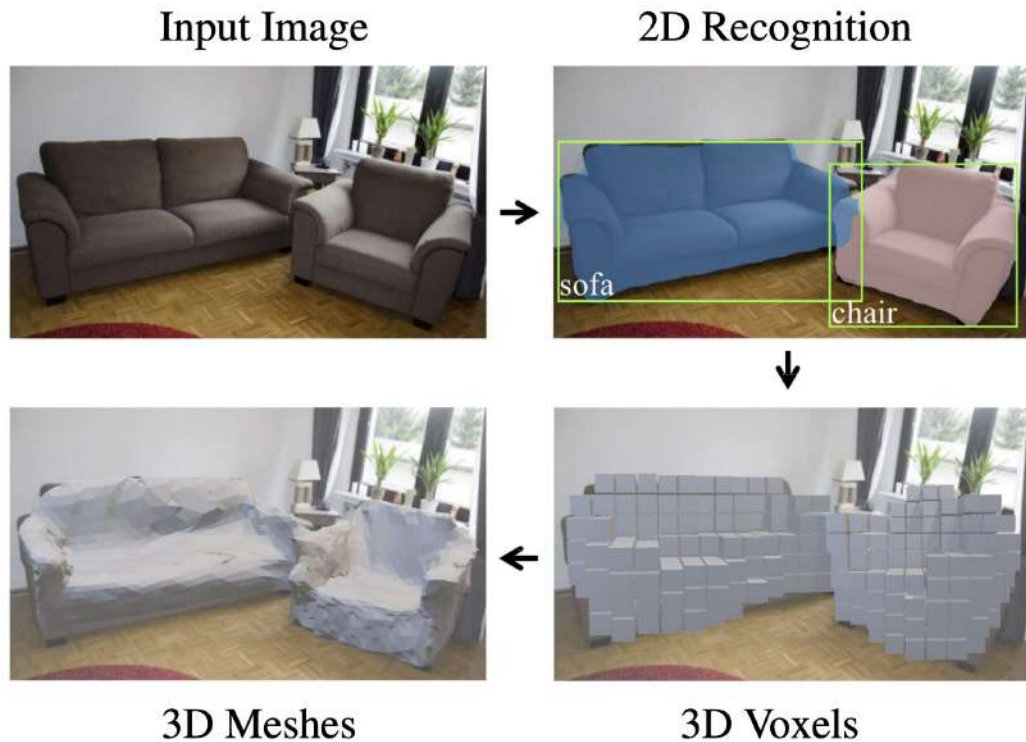
# 3D Object Detection: Monocular Camera



- Same idea as Faster RCNN, but proposals are in 3D
- 3D bounding box proposal, regress 3D box parameters + class score

Chen, Xiaozi, Kaustav Kundu, Ziyu Zhang, Huimin Ma, Sanja Fidler, and Raquel Urtasun. "Monocular 3d object detection for autonomous driving." CVPR 2016.

# 3D Shape Prediction: Mesh R-CNN



Gkioxari et al., Mesh RCNN, ICCV 2019



# Recap: Lots of computer vision tasks!

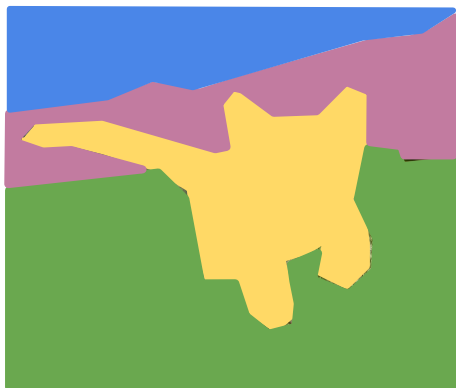
## Classification



**CAT**

No spatial extent

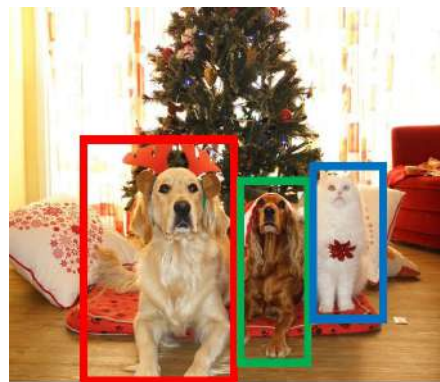
## Semantic Segmentation



**GRASS, CAT,  
TREE, SKY**

No objects, just pixels

## Object Detection



**DOG, DOG, CAT**

Multiple Object

## Instance Segmentation



**DOG, DOG, CAT**

[This image is CC0 public domain](#)

Next time:

Guest lecture on **Neural Radiance Field**  
Jon Barron (Google Research)