Lecture 11:
Detection and Segmentation

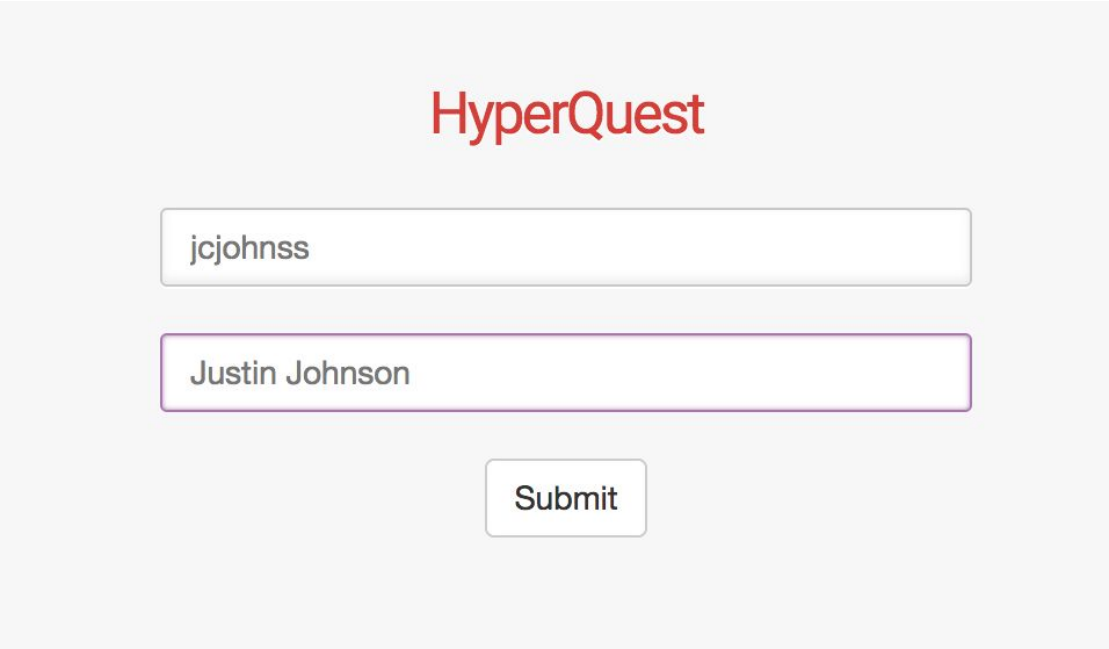
Administrative

Midterms being graded
Please don’t discuss midterms until next week - some students not yet taken

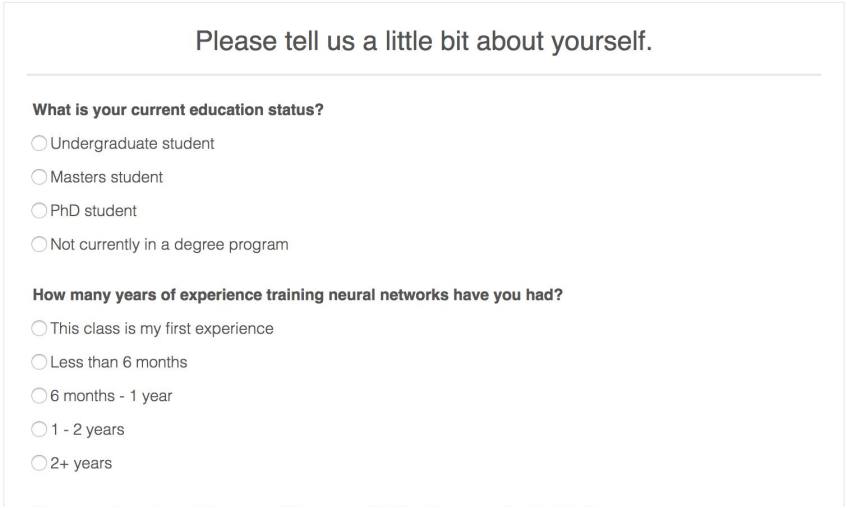
A2 being graded

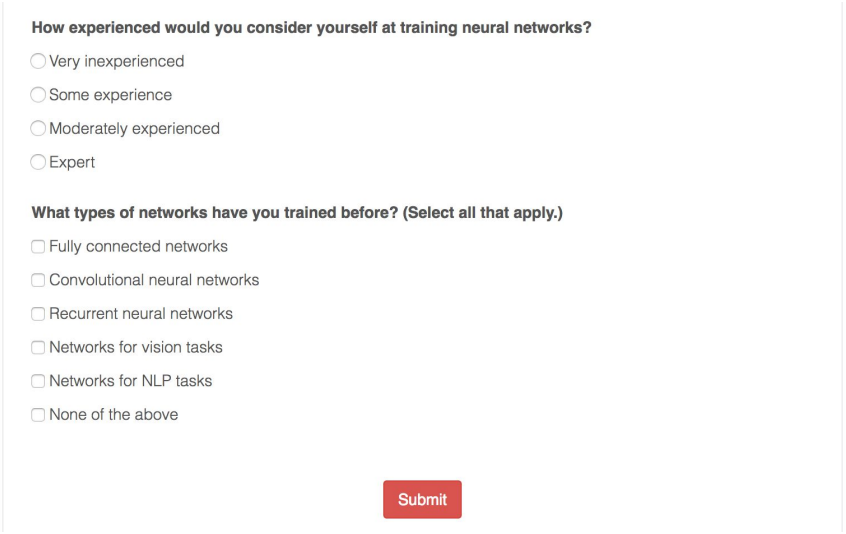
Project milestones due Tuesday 5/16

HyperQuest

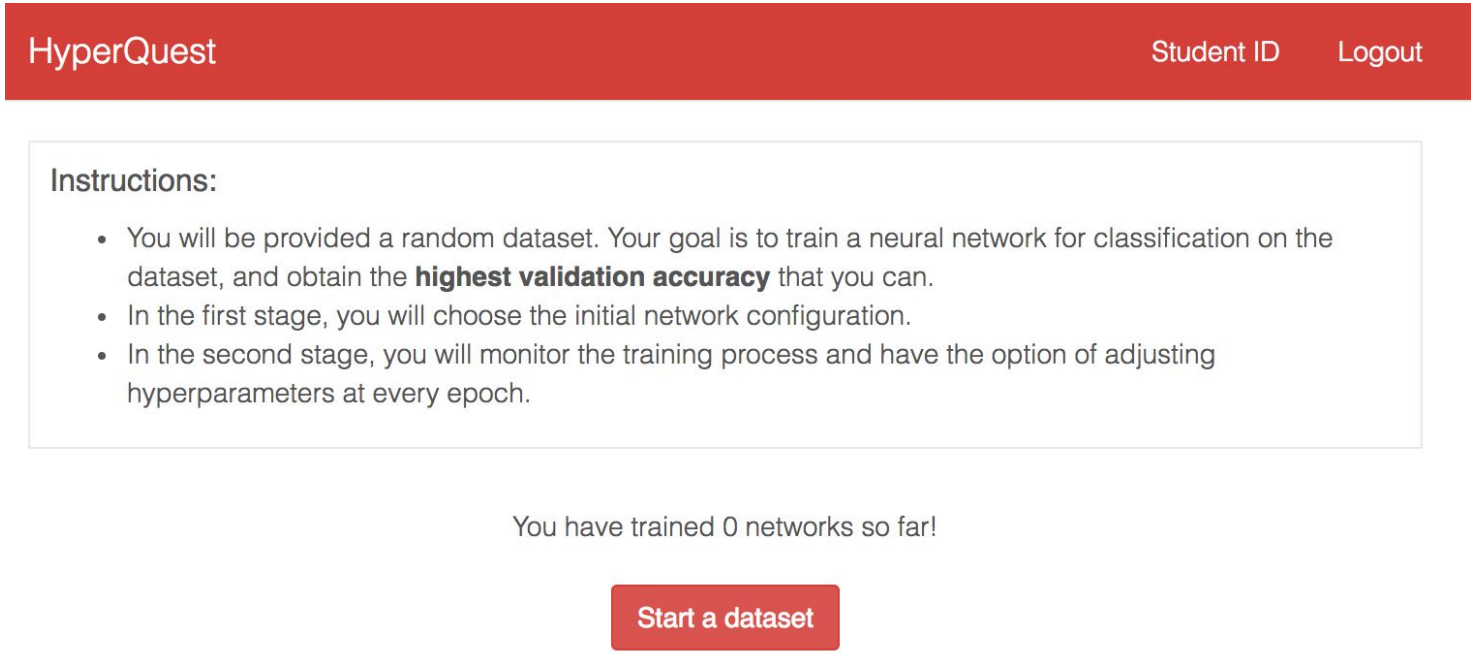


HyperQuest

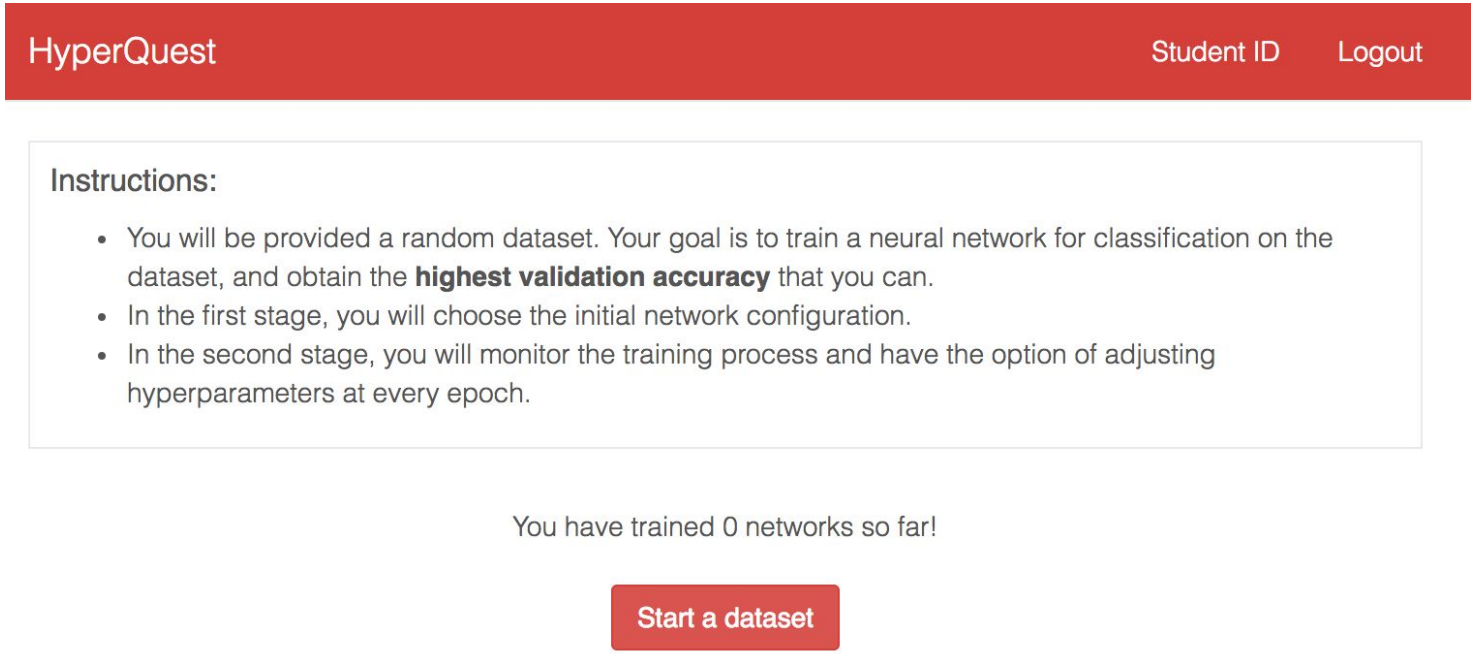

Please tell us a little bit about yourself.
What is your current education status?
Undergraduate student
Masters student
PhD student
Not currently in a degree program
How many years of experience training neural networks have you had?
This class is my first experience
Less than 6 months
6 months - 1 year
1 - 2 years
2+ years


How experienced would you consider yourself at training neural networks?
Very inexperienced
Some experience
Moderately experienced
Expert
What types of networks have you trained before? (Select all that apply.)
Fully connected networks
Convolutional neural networks
Recurrent neural networks
Networks for vision tasks
Networks for NLP tasks
None of the above
Submit

HyperQuest


HyperQuest
Student ID
Logout
Instructions:
You will be provided a random dataset. Your goal is to train a neural network for classification on the dataset, and obtain the highest validation accuracy that you can.
In the first stage, you will choose the initial network configuration.
In the second stage, you will monitor the training process and have the option of adjusting hyperparameters at every epoch.
You have trained 0 networks so far!
Start a dataset

HyperQuest


HyperQuest
Student ID
Logout
Instructions:
You will be provided a random dataset. Your goal is to train a neural network for classification on the dataset, and obtain the highest validation accuracy that you can.
In the first stage, you will choose the initial network configuration.
In the second stage, you will monitor the training process and have the option of adjusting hyperparameters at every epoch.
You have trained 0 networks so far!
Start a dataset

HyperQuest jcjohns2 Logout

Instructions:

- In this stage, choose your initial network configuration. You may refer to the provided dataset statistics for reference. Click on info icons for definitions.

Initial Network Configuration

CNN network width	Learning rate	CNN network depth	Dropout rate
○ 32	○ 0.1	○ 2	○ 0
○ 64	○ 0.01	○ 4	○ 0.5
○ 128	○ 0.001	○ 8	

Submit

Dataset Statistics

Classes: 10
Input data size: [3, 32, 32]
Examples per split: Train (8500), Val (1500)

HyperQuest jcjohns2 Logout

Goal: maximize **best** validation accuracy

Leaderboard: updated periodically here

Action 1 of max 60

(After training 1 of max 30 epochs)

- Continue
- Done training
- Revert (max 5 consecutive)

Submit

Hyperparameter Adjustment

Weight decay (0)	CNN Network depth (2)	Dropout (0.0)	Learning rate (1.00e-2)	CNN Network width (32)
Same	Same	Same	Same	Same
Next value: 0	Next value: 2	Next value: 0	Next value: 1.00e-2	Next value: 32

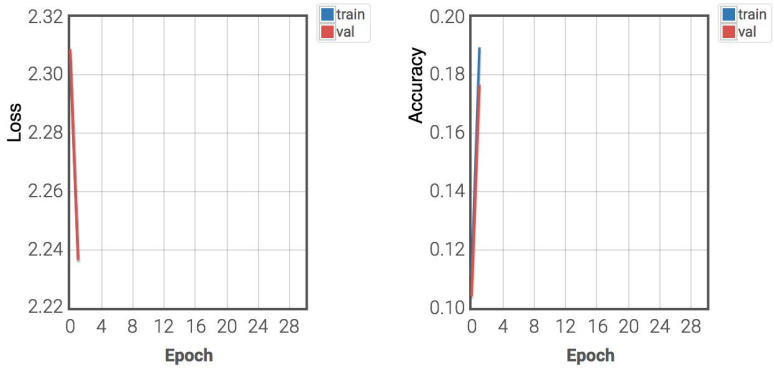
Dataset Statistics

Classes: 10
Input data size: [3, 32, 32]
Examples per split: Train (8500), Val (1500)

Configuration History

1. Width = 32, Depth = 2, Learning rate = 0.01, Dropout = 0, Weight decay = 0

Current best training accuracy: 0.190
Current best validation accuracy: 0.177 (Baseline: 0.283)



HyperQuest jcjohns2 Logout

Goal: maximize **best** validation accuracy

Leaderboard: updated periodically here

Action 3 of max 60

(After training 3 of max 30 epochs)

- (•) Continue
- ( ) Done training
- ( ) Revert (max 5 consecutive)

Submit

Hyperparameter Adjustment

Weight decay (0)	CNN Network depth (2)	Dropout (0.0)	Learning rate (1.00e-2)	CNN Network width (32)
(•) Same ( ) ↑ ( ) ↓	(•) Same ( ) ↑	(•) Same ( ) ↑ ( ) ↓	(•) Same ( ) ↑ ( ) ↓	(•) Same ( ) ↑
Next value: 0	Next value: 2	Next value: 0	Next value: 1.00e-2	Next value: 32

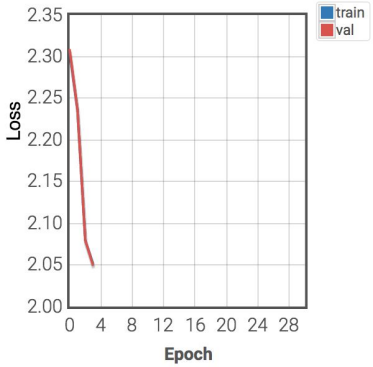
Dataset Statistics

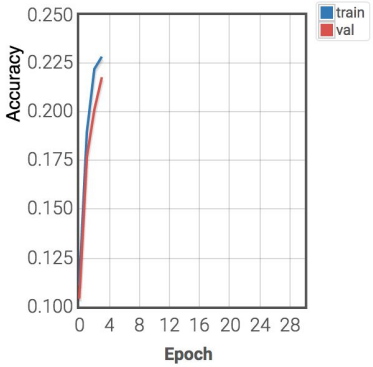
Classes: 10
Input data size: [3, 32, 32]
Examples per split: Train (8500), Val (1500)

Configuration History

3. Width = 32, Depth = 2, Learning rate = 0.01, Dropout = 0, Weight decay = 0
2. Width = 32, Depth = 2, Learning rate = 0.01, Dropout = 0, Weight decay = 0
1. Width = 32, Depth = 2, Learning rate = 0.01, Dropout = 0, Weight decay = 0

Current best training accuracy: 0.229
Current best validation accuracy: 0.218 (Baseline: 0.283)





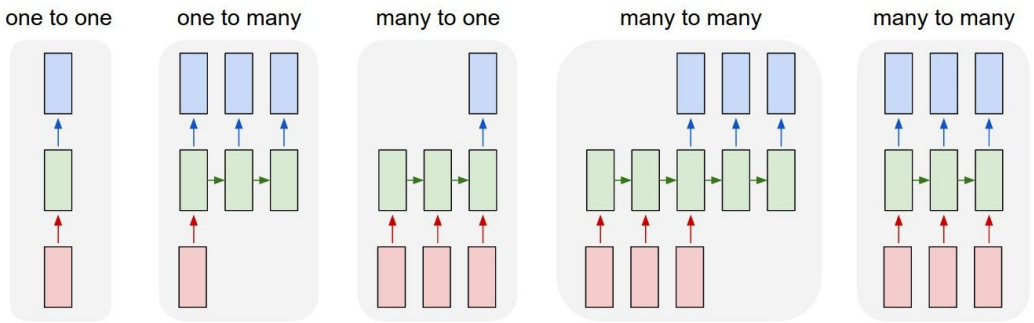
HyperQuest

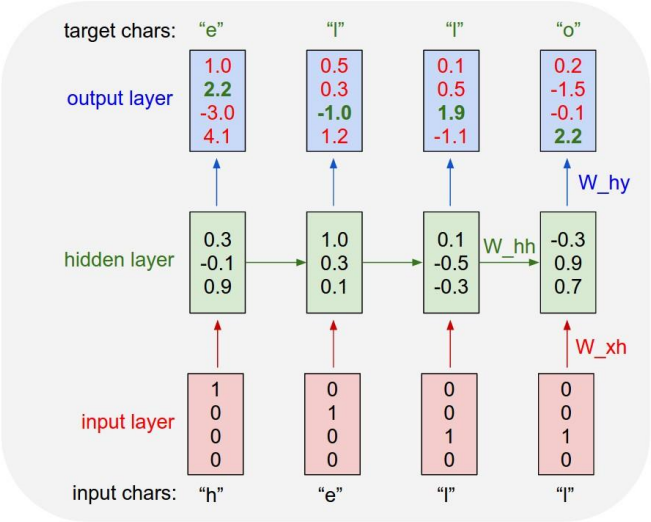
Will post more details on Piazza this afternoon

하이퍼 퀘스트 공부과정

net2net, network morphism 논문

Last Time: Recurrent Networks





Last Time: Recurrent Networks

For $\bigoplus_{n=1,\ldots,m}$ where $\mathcal{L}_{m_\bullet} = 0$, hence we can find a closed subset $\mathcal{H}$ in $\mathcal{H}$ and any sets $\mathcal{F}$ on X, U is a closed immersion of S, then $U \to T$ is a separated algebraic space.

Proof. Proof of (1). It also start we get

$$S = \mathrm{Spec}(R) = U \times_X U \times_X U$$

and the compariconly in the fibre product covering we have to prove the lemma generated by $\coprod Z \times_U U \to V$. Consider the maps M along the set of points Sch_{fppf} and $U \to U$ is the fibre category of S in U in Section, ?? and the fact that any U affine, see Morphisms, Lemma ??. Hence we obtain a scheme S and any open subset $W \subset U$ in $Sh(G)$ such that $\mathrm{Spec}(R') \to S$ is smooth or an

$$U = \bigcup U_i \times_{S_i} U_i$$

which has a nonzero morphism we may assume that f_i is of finite presentation over S. We claim that $\mathcal{O}_{X,x}$ is a scheme where $x, x', s'' \in S'$ such that $\mathcal{O}_{X,x'} \to \mathcal{O}'_{X',x'}$ is separated. By Algebra, Lemma ?? we can define a map of complexes $\mathrm{GL}_{S'}(x'/S'')$ and we win. □

To prove study we see that $\mathcal{F}|_U$ is a covering of $\mathcal{X}'$, and $\mathcal{T}_i$ is an object of $\mathcal{F}_{X/S}$ for $i > 0$ and $\mathcal{F}_p$ exists and let $\mathcal{F}_i$ be a presheaf of $\mathcal{O}_X$-modules on $\mathcal{C}$ as a $\mathcal{F}$-module. In particular $\mathcal{F} = U/\mathcal{F}$ we have to show that

$$\widetilde{M}^\bullet = \mathcal{I}^\bullet \otimes_{\mathrm{Spec}(k)} \mathcal{O}_{S,s} - i_X^{-1}\mathcal{F})$$

is a unique morphism of algebraic stacks. Note that

$$\mathrm{Arrows} = (Sch/S)^{opp}_{fppf}, (Sch/S)_{fppf}$$

and

$$V = \Gamma(S, \mathcal{O}) \longmapsto (U, \mathrm{Spec}(A))$$

is an open subset of X. Thus U is affine. This is a continuous map of X is the inverse, the groupoid scheme S.

Proof. See discussion of sheaves of sets. □

The result for prove any open covering follows from the less of Example ??. It may replace S by $X_{spaces,étale}$ which gives an open subspace of X and T equal to S_{Zar}, see Descent, Lemma ??. Namely, by Lemma ?? we see that R is geometrically regular over S.

```
PANDARUS:
Alas, I think he shall be come approached and the day
When little srain would be attain'd into being never fed,
And who is but a chain and subjects of his death,
I should not sleep.

Second Senator:
They are away this miseries, produced upon my soul,
Breaking and strongly should be buried, when I perish
The earth and thoughts of many states.

DUKE VINCENTIO:
Well, your wit is in the care of side and that.

Second Lord:
They would be ruled after this chamber, and
my fair nues begun out of the fact, to be conveyed,
Whose noble souls I'll have the heart of the wars.

Clown:
Come, sir, I will make did behold your worship.

VIOLA:
I'll drink it.
```

```
static void do_command(struct seq_file *m, void *v)
{
  int column = 32 << (cmd[2] & 0x80);
  if (state)
    cmd = (int)(int_state ^ (in_8(&ch->ch_flags) & Cmd) ? 2 : 1);
  else
    seq = 1;
  for (i = 0; i < 16; i++) {
    if (k & (1 << 1))
      pipe = (in_use & UMXTHREAD_UNCCA) +
        ((count & 0x00000000ffffff8) & 0x000000f) << 8;
    if (count == 0)
      sub(pid, ppc_md.kexec_handle, 0x20000000);
    pipe_set_bytes(i, 0);
  }
  /* Free our user pages pointer to place camera if all dash */
  subsystem_info = &of_changes[PAGE_SIZE];
  rek_controls(offset, idx, &soffset);
  /* Now we want to deliberately put it to device */
  control_check_polarity(&context, val, 0);
  for (i = 0; i < COUNTER; i++)
    seq_puts(s, "policy ");
}
```

Last Time: Recurrent Networks

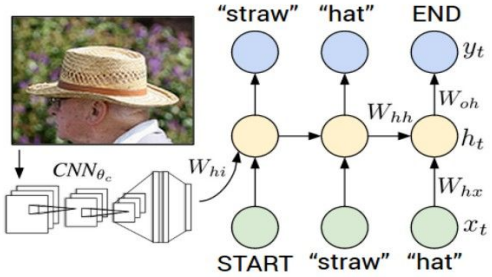


Figure from Karpathy et a, "Deep Visual-Semantic Alignments for Generating Image Descriptions", CVPR 2015; figure copyright IEEE, 2015.
Reproduced for educational purposes.

A cat sitting on a suitcase on the floor

A cat is sitting on a tree branch

A woman is holding a cat in her hand

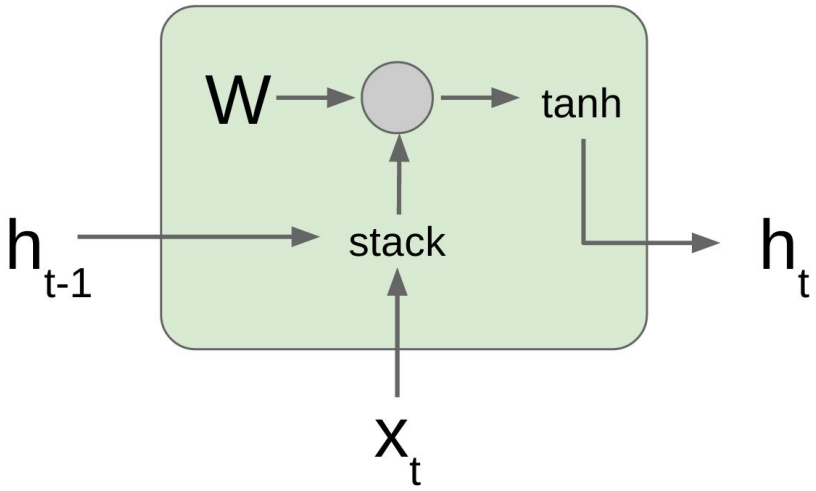
Two people walking on the beach with surfboards

A tennis player in action on the court

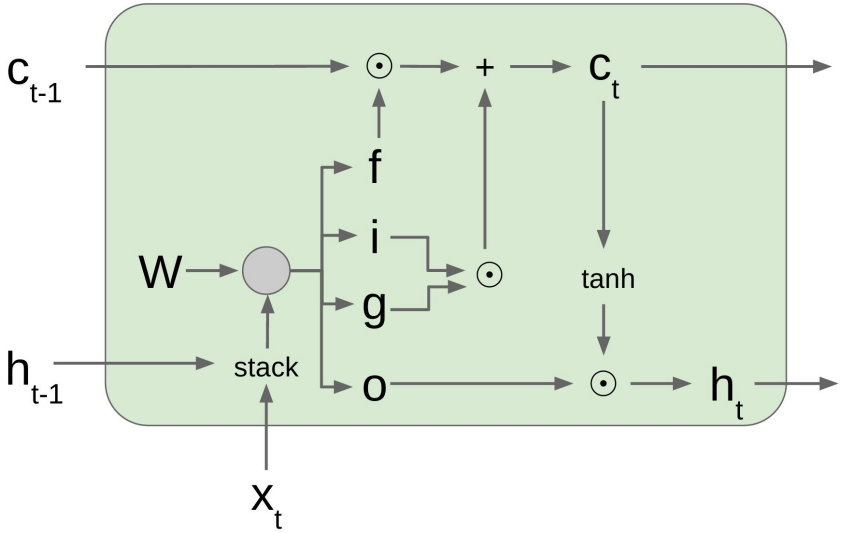
A person holding a computer mouse on a desk

Last Time: Recurrent Networks

Vanilla RNN
Simple RNN
Elman RNN



Long Short Term Memory (LSTM)



Elman, "Finding Structure in Time", Cognitive Science, 1990.
Hochreiter and Schmidhuber, "Long Short-Term Memory", Neural computation, 1997

지금까진 image classification.

Today: Segmentation, Localization, Detection

다양한 CV tasks

So far: Image Classification

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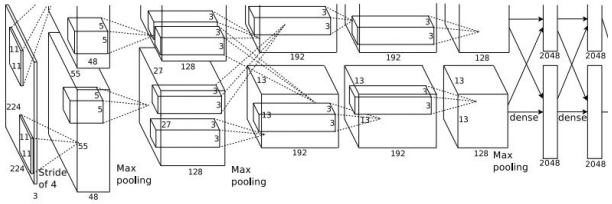


Figure copyright Alex Krizhevsky, Ilya Sutskever, and Geoffrey Hinton, 2012. Reproduced with permission.

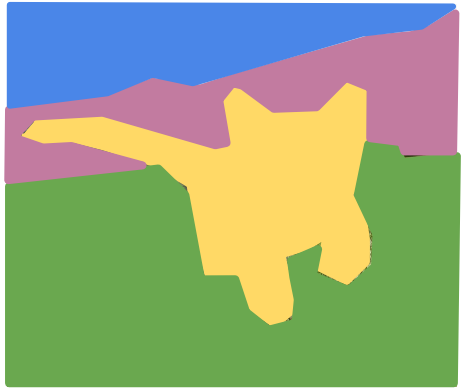
Vector:
4096

Fully-Connected:
4096 to 1000

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

Other Computer Vision Tasks

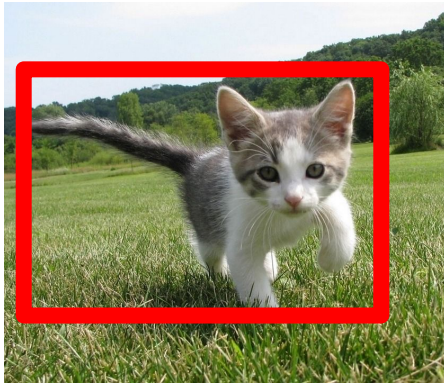
Semantic Segmentation



GRASS, CAT, TREE, SKY

No objects, just pixels

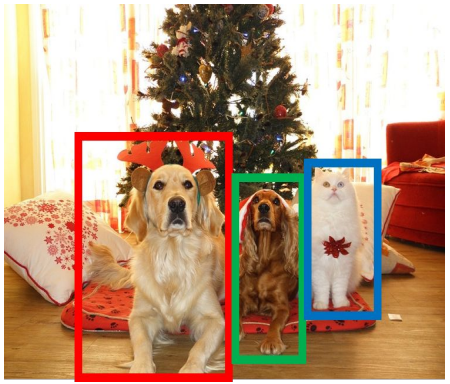
Classification + Localization



CAT

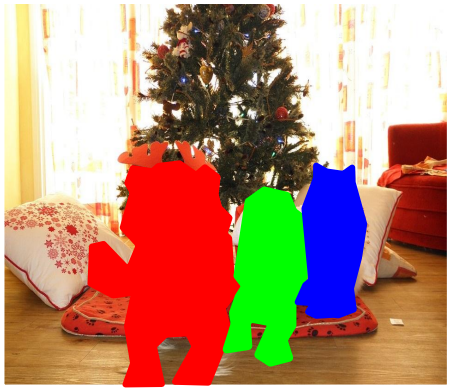
Single Object

Object Detection



DOG, DOG, CAT

Instance Segmentation



DOG, DOG, CAT

Multiple Object

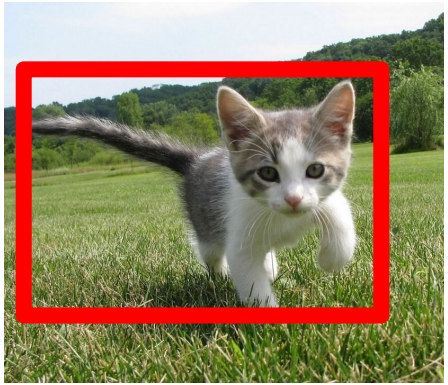
Semantic Segmentation

→ 모든 픽셀에 카테고리가 매겨짐, 개별 객체를 구분하지 X

입력: 이미지, 출력: 이미지의 모든 픽셀에 카테고리를 할당.

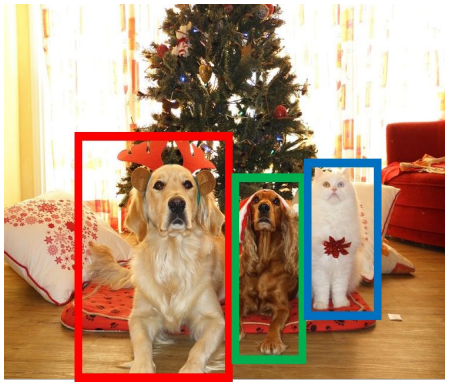
out: GRASS, CAT, TREE, SKY

No objects, just pixels

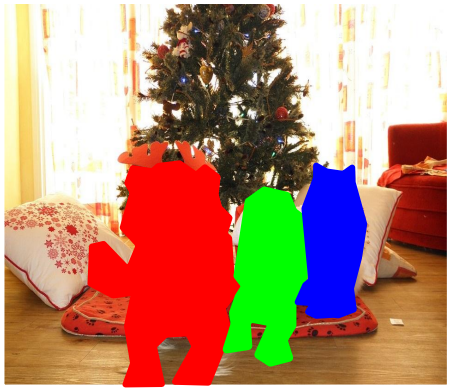


CAT

Single Object



DOG, DOG, CAT



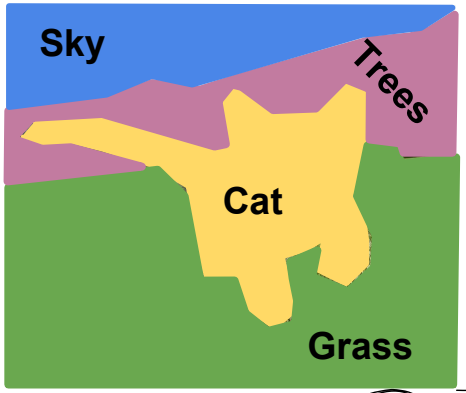
DOG, DOG, CAT

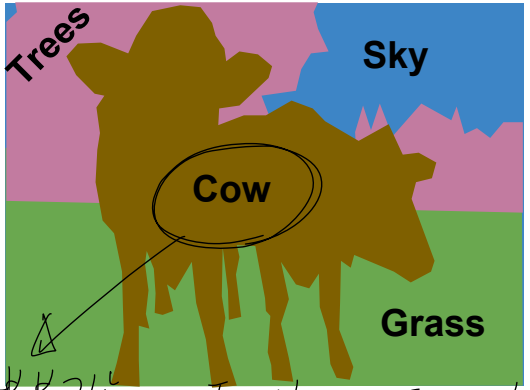
Multiple Object

Semantic Segmentation

Label each pixel in the image with a category label

Don’t differentiate instances, only care about pixels

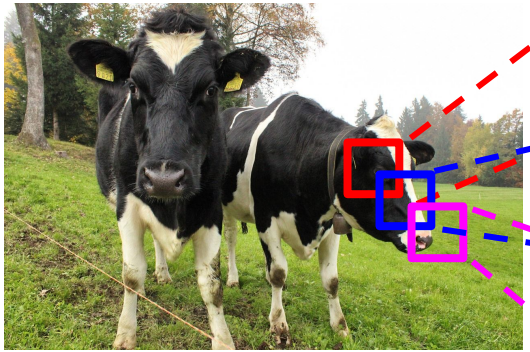




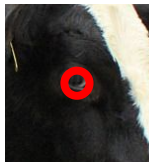
(through classification).

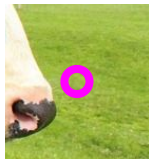
Semantic Segmentation Idea: Sliding Window

Full image

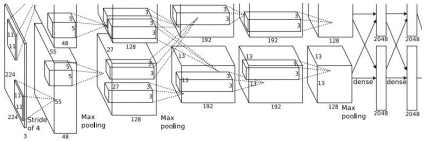


Extract patch

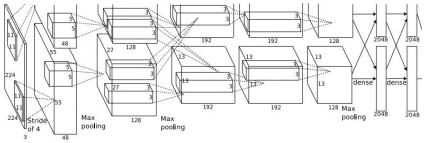




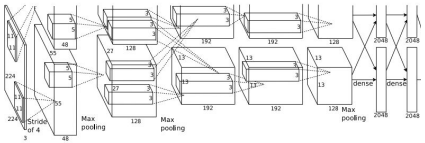
Classify center pixel with CNN



Cow



Cow

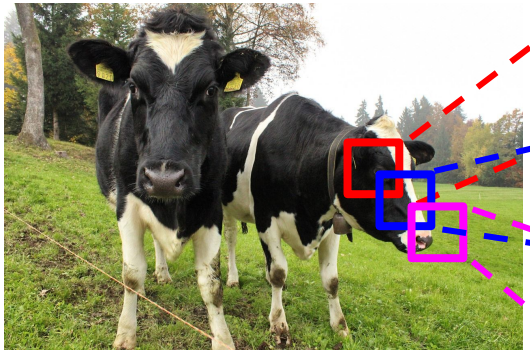


Grass

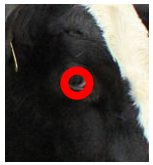
Farabet et al, “Learning Hierarchical Features for Scene Labeling,” TPAMI 2013
Pinheiro and Collobert, “Recurrent Convolutional Neural Networks for Scene Labeling”, ICML 2014

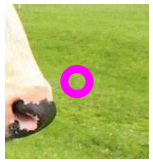
Semantic Segmentation Idea: Sliding Window

Full image

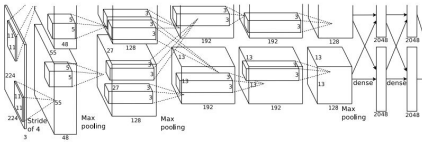


Extract patch

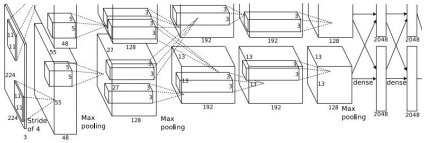




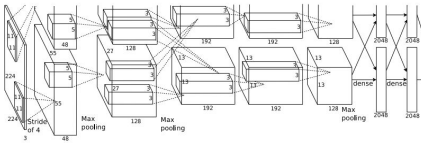
Classify center pixel with CNN



Cow



Cow



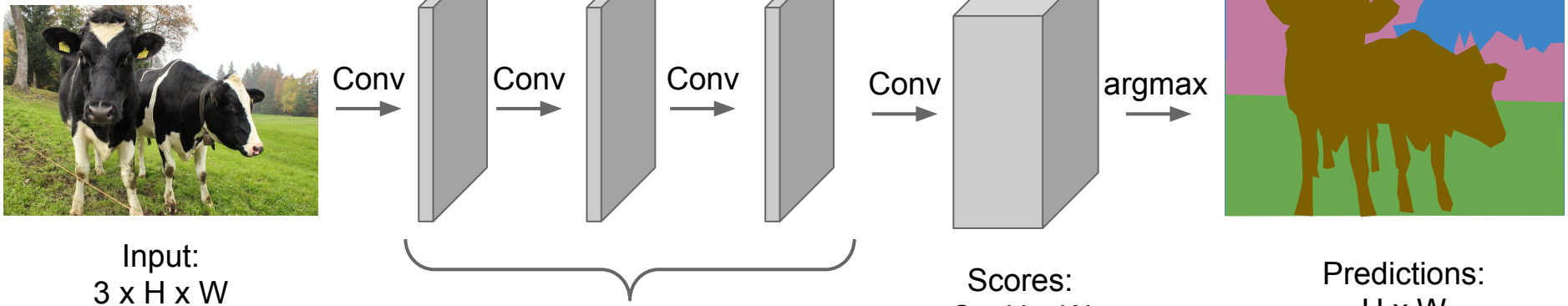
Grass

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: Fully Convolutional

Design a network as a bunch of convolutional layers
to make predictions for pixels all at once!



Semantic Segmentation Idea: Fully Convolutional

Design a network as a bunch of convolutional layers to make predictions for pixels all at once!

Input:
3 x H x W

Conv → Conv → Conv → Conv → argmax

Convolutions:
D x H x W

Scores:
C x H x W

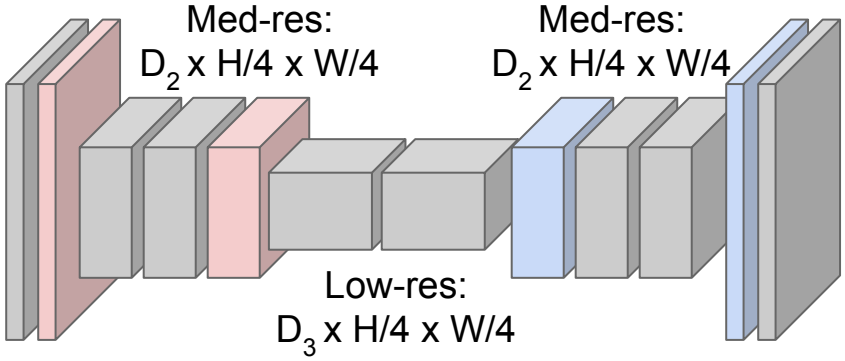
Predictions:
H x W

Problem: convolutions at original image resolution will be very expensive ...

Semantic Segmentation Idea: Fully Convolutional

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

Input:
3 x H x W



High-res:
D_1 x H/2 x W/2

High-res:
D_1 x H/2 x W/2

Predictions:
H x W

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

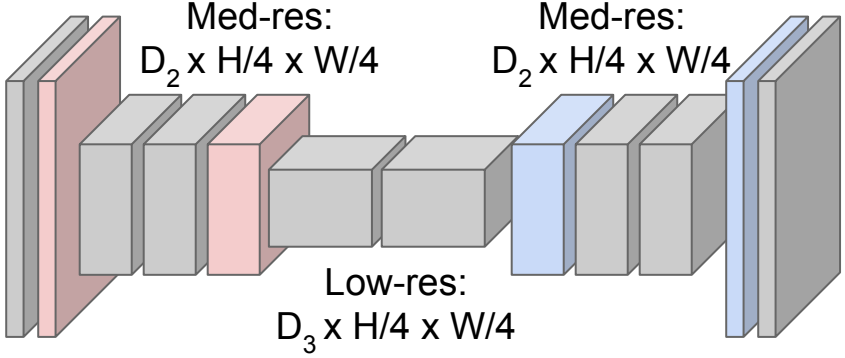
Semantic Segmentation Idea: Fully Convolutional

Downsampling: Pooling, strided convolution

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

Upsampling: ???

Input:
3 x H x W



High-res:
D1 x H/2 x W/2

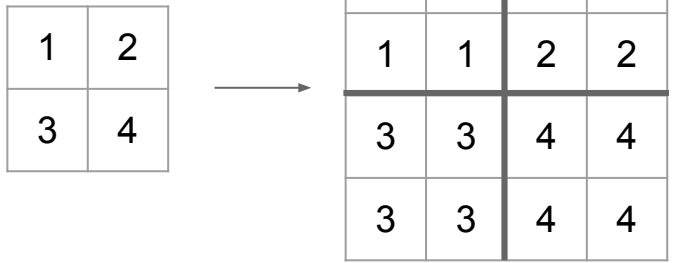
High-res:
D1 x H/2 x W/2

Predictions:
H x 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”

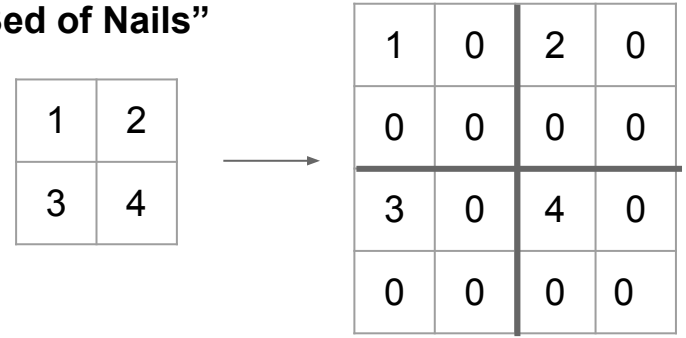
Nearest Neighbor



Input: 2 x 2

Output: 4 x 4

“Bed of Nails”



Input: 2 x 2

Output: 4 x 4

In-Network upsampling: “Max Unpooling”

Max Pooling
Remember which element was max!

1	2	6	3
3	5	2	1
1	2	2	1
7	3	4	8

Input: 4 x 4

5	6
7	8

Output: 2 x 2

Rest of the network

Max Unpooling
Use positions from pooling layer

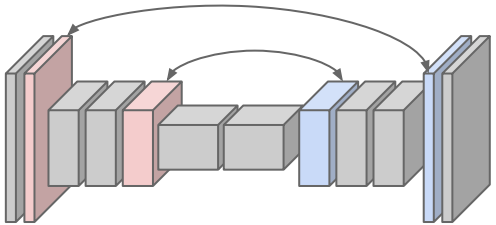
1	2
3	4

Input: 2 x 2

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

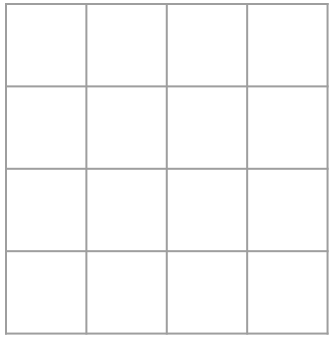
Output: 4 x 4

Corresponding pairs of downsampling and upsampling layers

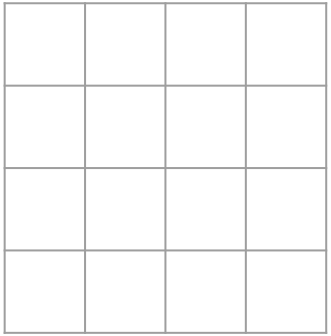


Learnable Upsampling: Transpose Convolution

Recall: Typical 3 x 3 convolution, stride 1 pad 1



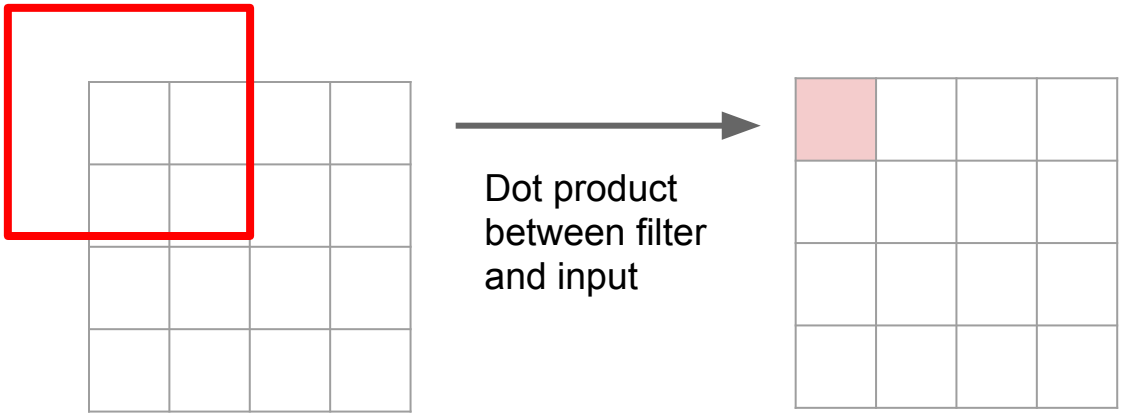
Input: 4 x 4



Output: 4 x 4

Learnable Upsampling: Transpose Convolution

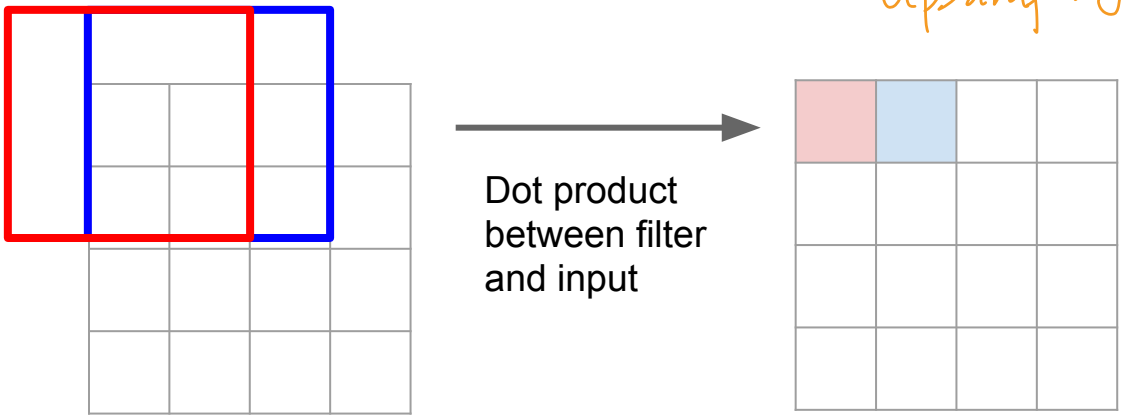
Recall: Normal 3 x 3 convolution, stride 1 pad 1



Learnable Upsampling: Transpose Convolution

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

upsampling transpose conv

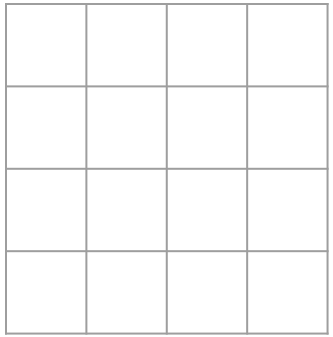


Input: 4 x 4

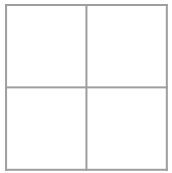
Output: 4 x 4

Learnable Upsampling: Transpose Convolution

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



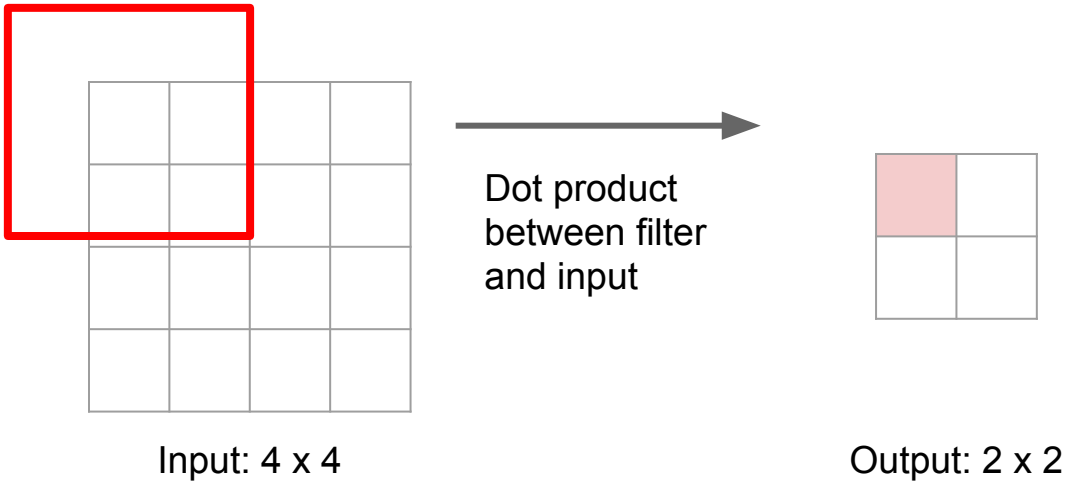
Input: 4 x 4



Output: 2 x 2

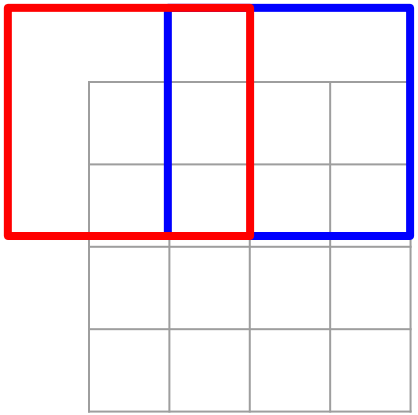
Learnable Upsampling: Transpose Convolution

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



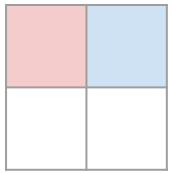
Learnable Upsampling: Transpose Convolution

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



Input: 4 x 4

Dot product between filter and input



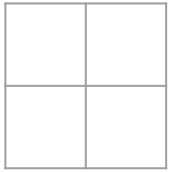
Output: 2 x 2

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

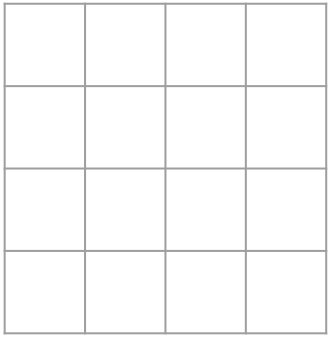
Stride gives ratio between movement in input and output

Learnable Upsampling: Transpose Convolution

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



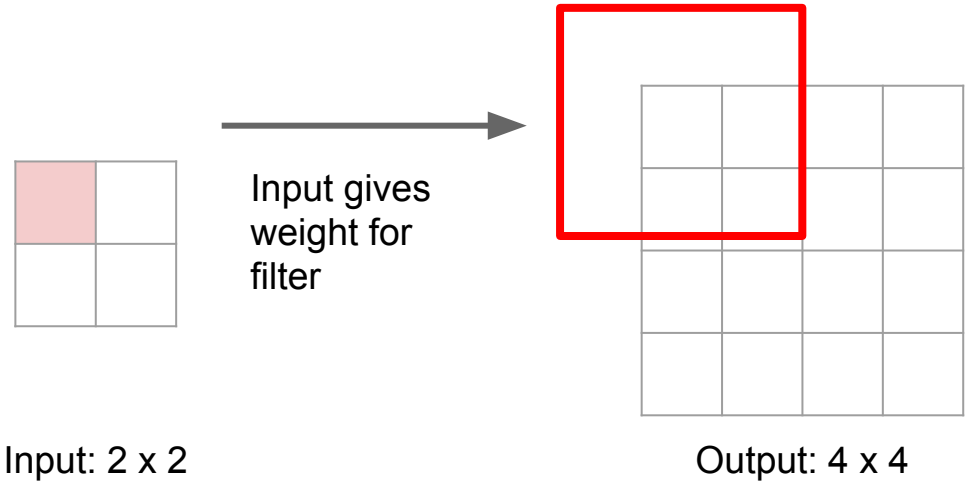
Input: 2 x 2



Output: 4 x 4

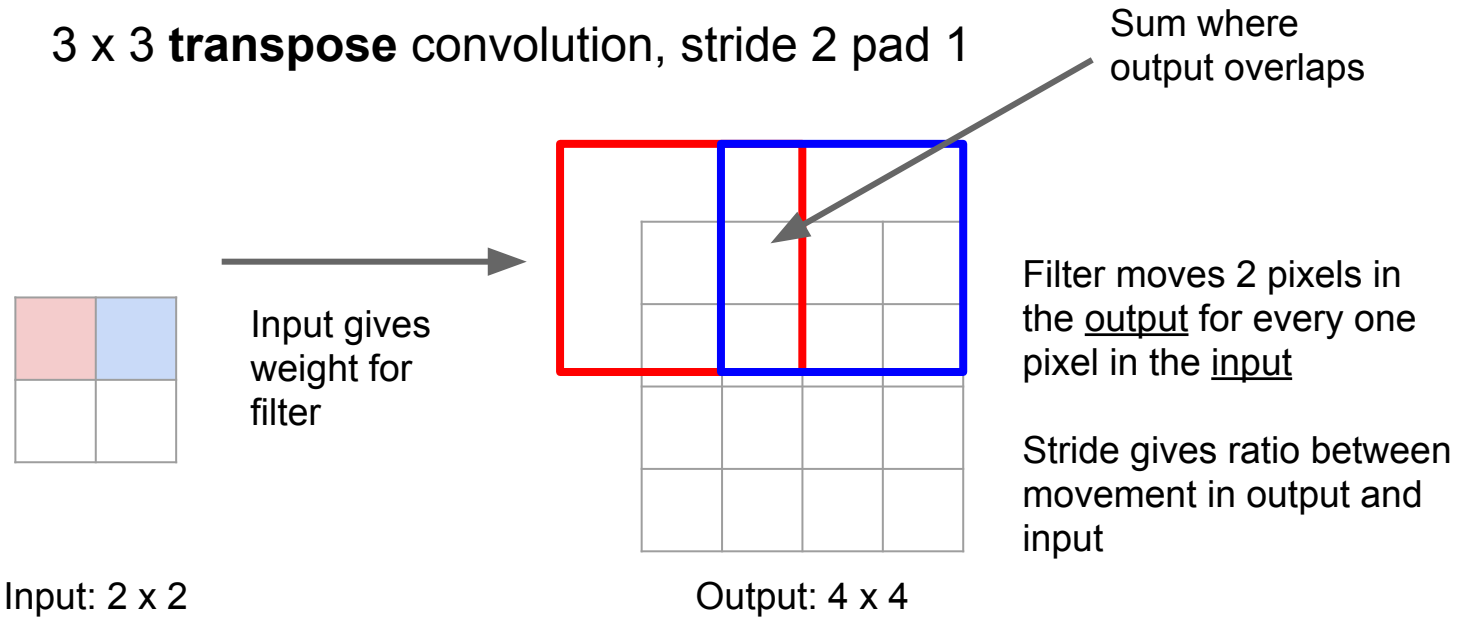
Learnable Upsampling: Transpose Convolution

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

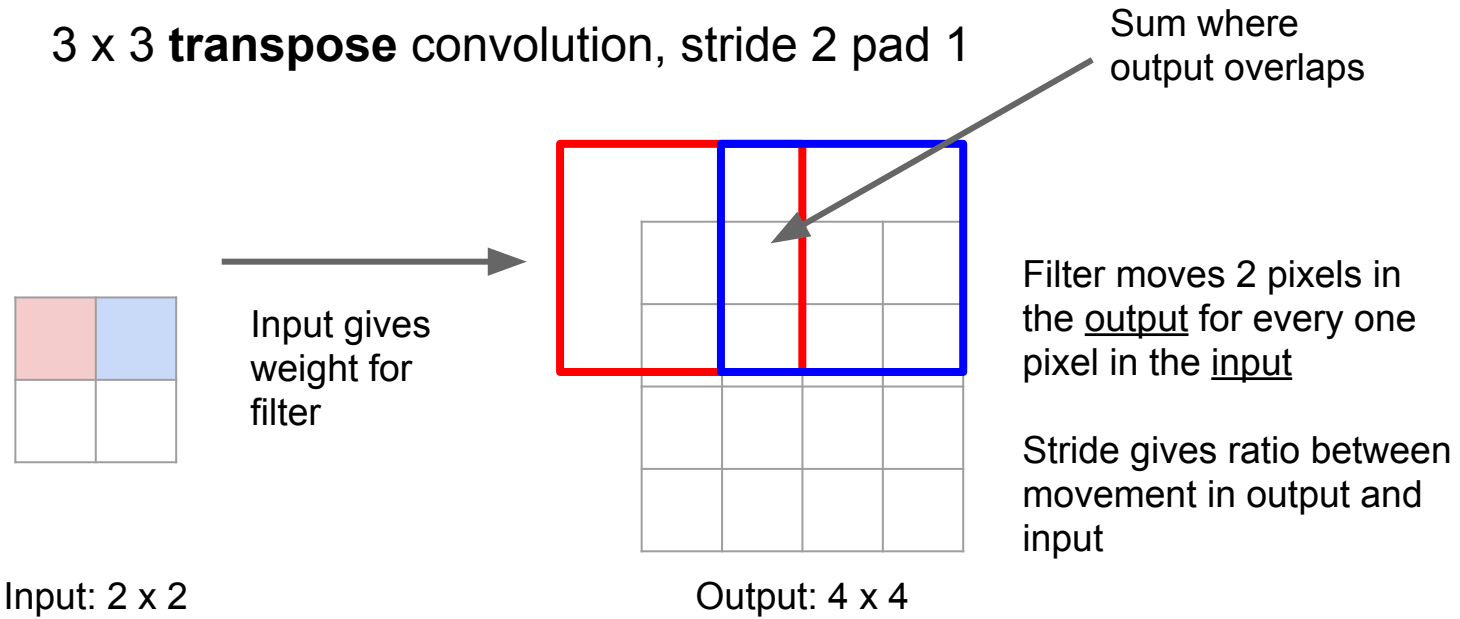


Learnable Upsampling: Transpose Convolution

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



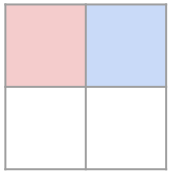
Learnable Upsampling: Transpose Convolution



Learnable Upsampling: Transpose Convolution

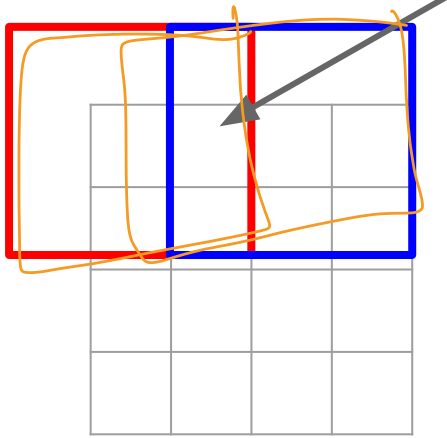
Other names:
-Deconvolution (bad)
-Upconvolution
-Fractionally strided convolution
-Backward strided convolution

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



Input: 2 x 2

Input gives weight for filter



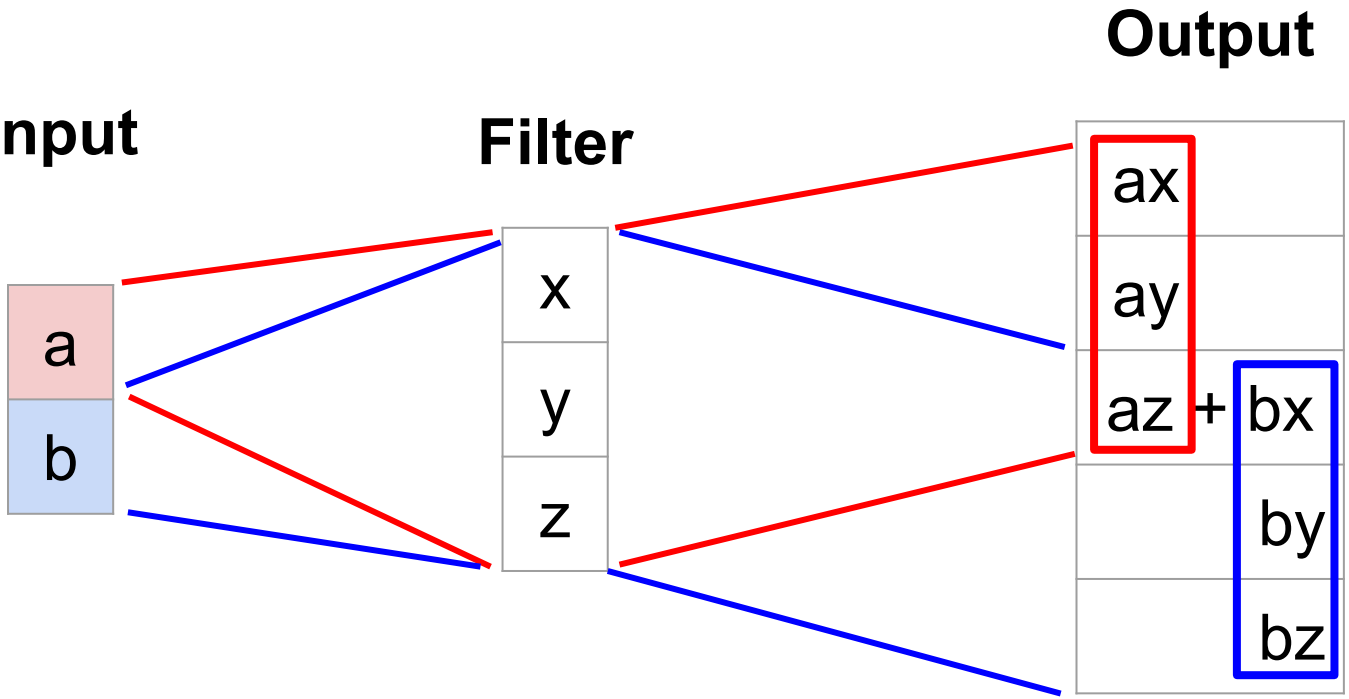
Output: 4 x 4

Sum where output overlaps

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

Stride gives ratio between movement in output and input

Transpose Convolution: 1D Example



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

Need to crop one pixel from output to make output exactly 2x input

Convolution as Matrix Multiplication (1D Example)

We can express convolution in terms of a matrix multiplication

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

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

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

Convolution as Matrix Multiplication (1D Example)

We can express convolution in terms of a matrix multiplication

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

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

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

Convolution transpose multiplies by the transpose of the same matrix:

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

$$\begin{bmatrix} x & 0 & 0 & 0 \\ y & x & 0 & 0 \\ z & y & x & 0 \\ 0 & z & y & x \\ 0 & 0 & z & y \\ 0 & 0 & 0 & z \end{bmatrix} \begin{bmatrix} a \\ b \\ c \\ d \end{bmatrix} = \begin{bmatrix} ax \\ ay + bx \\ az + by + cx \\ bz + cy + dx \\ cz + dy \\ dz \end{bmatrix}$$

When stride=1, convolution transpose is just a regular convolution (with different padding rules)

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

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

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

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

Convolution transpose multiplies by the transpose of the same matrix:

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

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

When stride>1, convolution transpose is no longer a normal convolution!

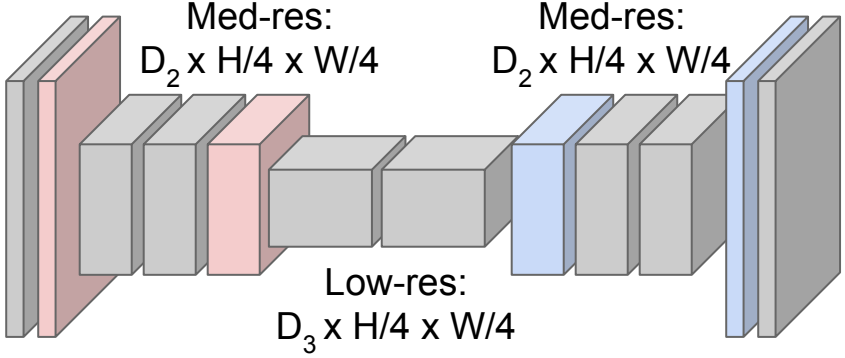
Semantic Segmentation Idea: Fully Convolutional

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 x H x W



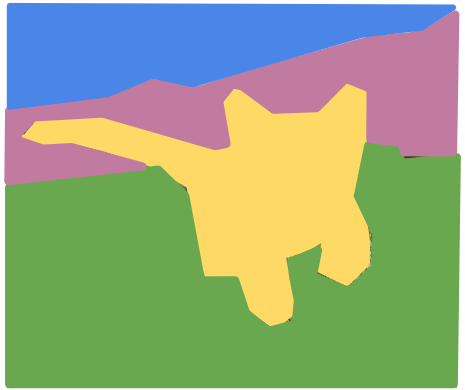
High-res:
D_1 x H/2 x W/2

High-res:
D_1 x H/2 x W/2

Predictions:
H x W

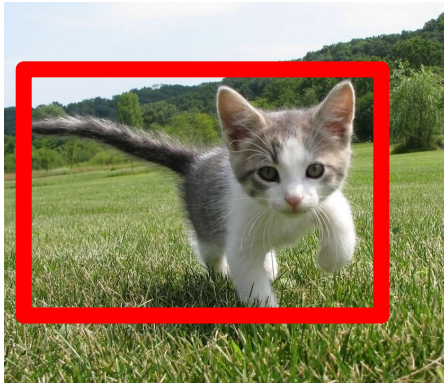
Long, Shelhamer, and Darrell, “Fully Convolutional Networks for Semantic Segmentation”, CVPR 2015
Noh et al, “Learning Deconvolution Network for Semantic Segmentation”, ICCV 2015

Classification + Localization



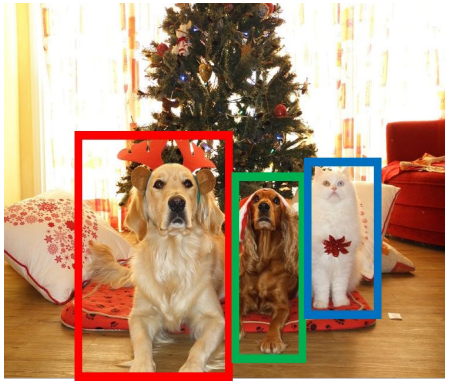
GRASS, CAT, TREE, SKY

No objects, just pixels

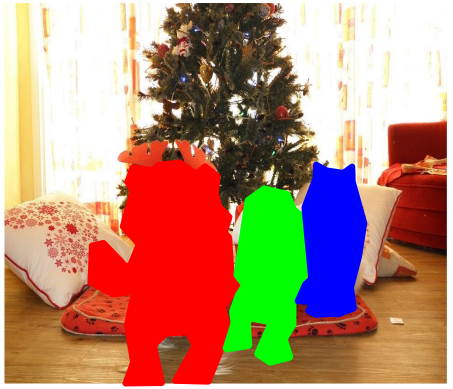


CAT

Single Object



DOG, DOG, CAT



DOG, DOG, CAT

Multiple Object

Classification + Localization

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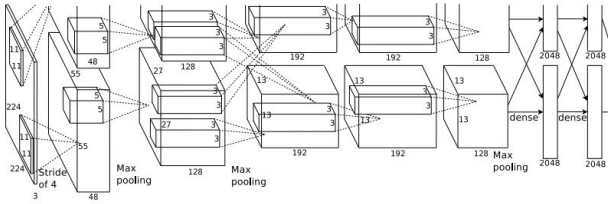

Fully Connected: 4096 to 1000

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

Vector: 4096

Fully Connected: 4096 to 4

Box Coordinates
(x, y, w, h)

Treat localization as a regression problem!

Classification + Localization

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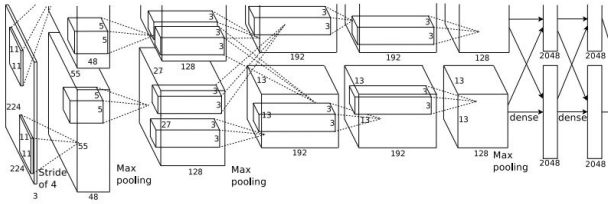

Fully Connected: 4096 to 1000

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

Softmax Loss

Correct label:
Cat

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!

Classification + Localization

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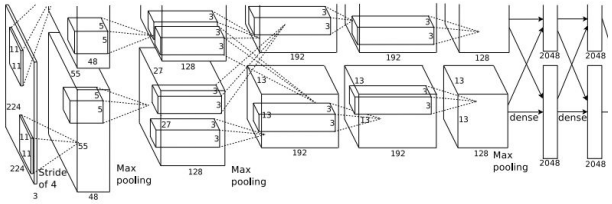

bounding box = localization.

Fully Connected: 4096 to 1000

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

Correct label: Cat

Softmax Loss

Multitask Loss

+ → **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!

Classification + Localization

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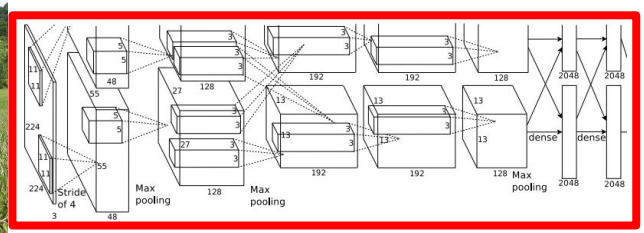


Often pretrained on ImageNet
(Transfer learning)

Vector: 4096

Fully Connected: 4096 to 1000

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

Softmax Loss

Correct label:
Cat

Fully Connected: 4096 to 4

Box Coordinates
(x, y, w, h)

L2 Loss

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

Loss

Treat localization as a regression problem!

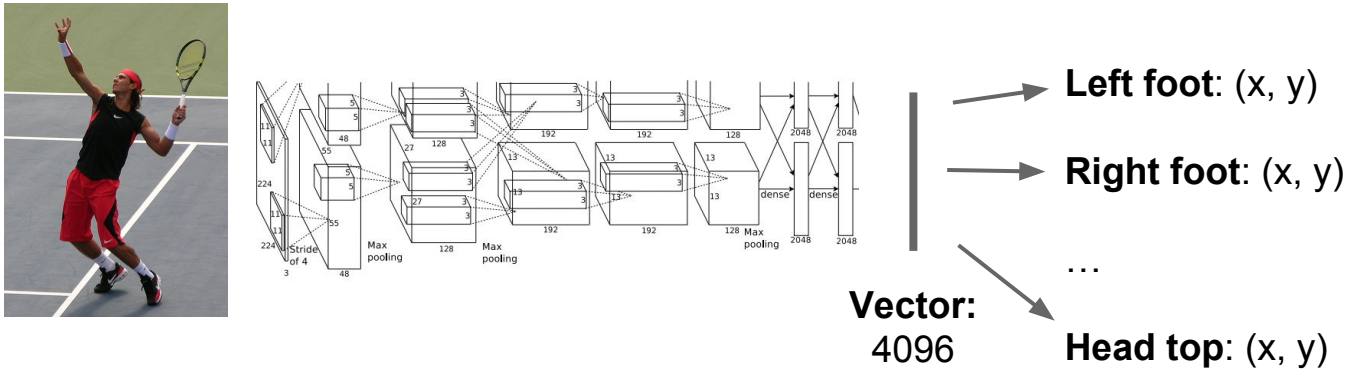
Aside: Human Pose Estimation

Represent pose as a set of 14 joint positions:

Left / right foot
Left / right knee
Left / right hip
Left / right shoulder
Left / right elbow
Left / right hand
Neck
Head top

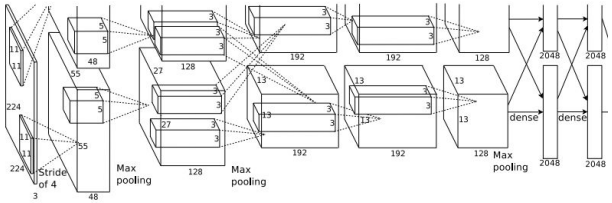
Johnson and Everingham, "Clustered Pose and Nonlinear Appearance Models for Human Pose Estimation", BMVC 2010

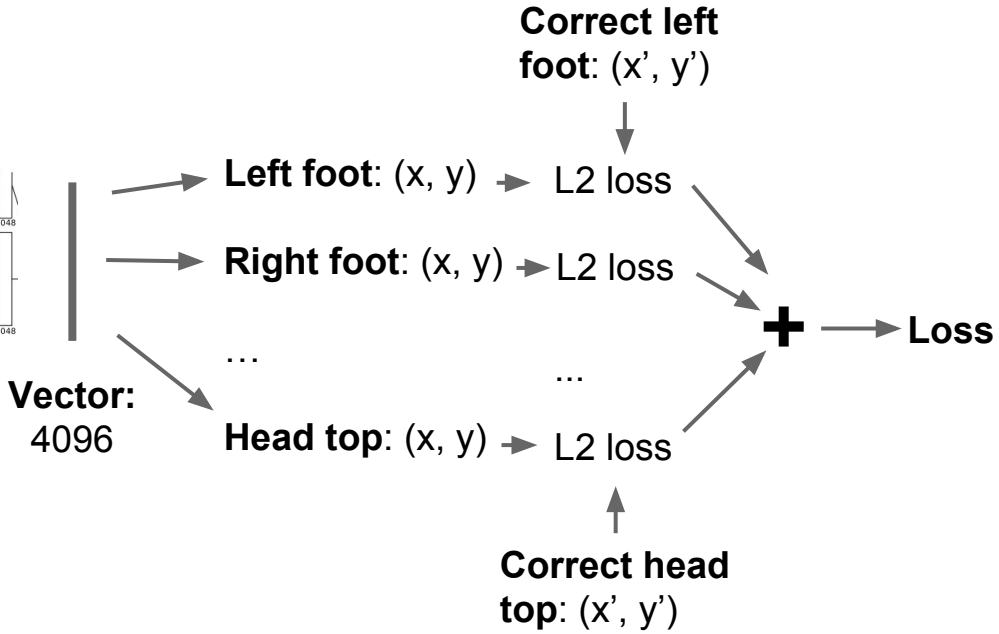
Aside: Human Pose Estimation



Toshev and Szegedy, “DeepPose: Human Pose Estimation via Deep Neural Networks”, CVPR 2014

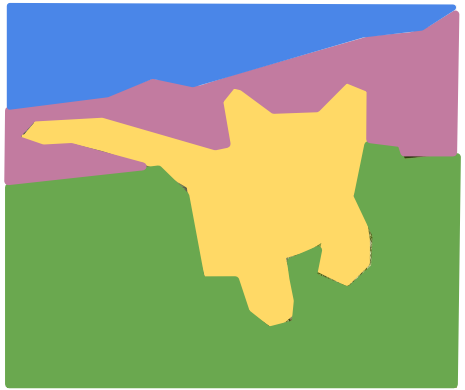
Aside: Human Pose Estimation





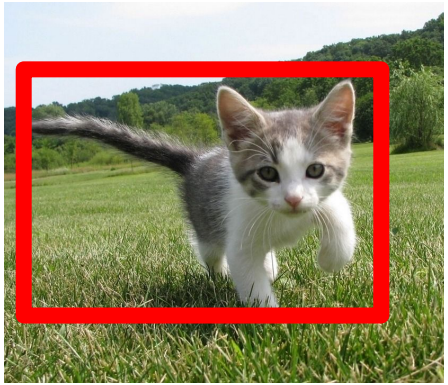
Toshev and Szegedy, "DeepPose: Human Pose Estimation via Deep Neural Networks", CVPR 2014

Object Detection



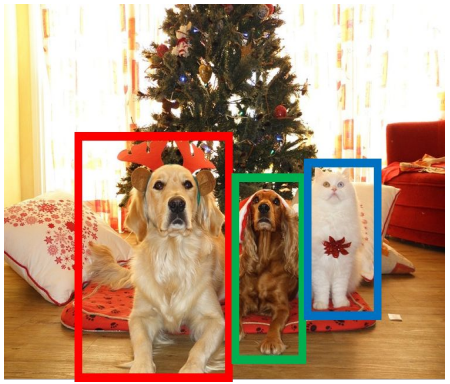
GRASS, CAT, TREE, SKY

No objects, just pixels

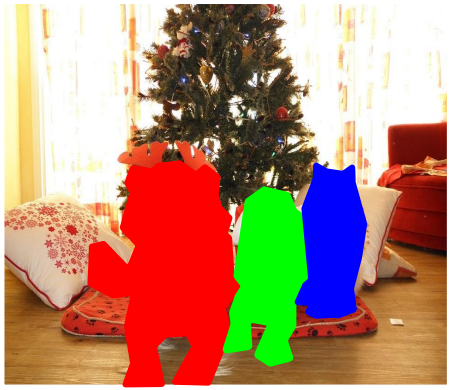


CAT

Single Object



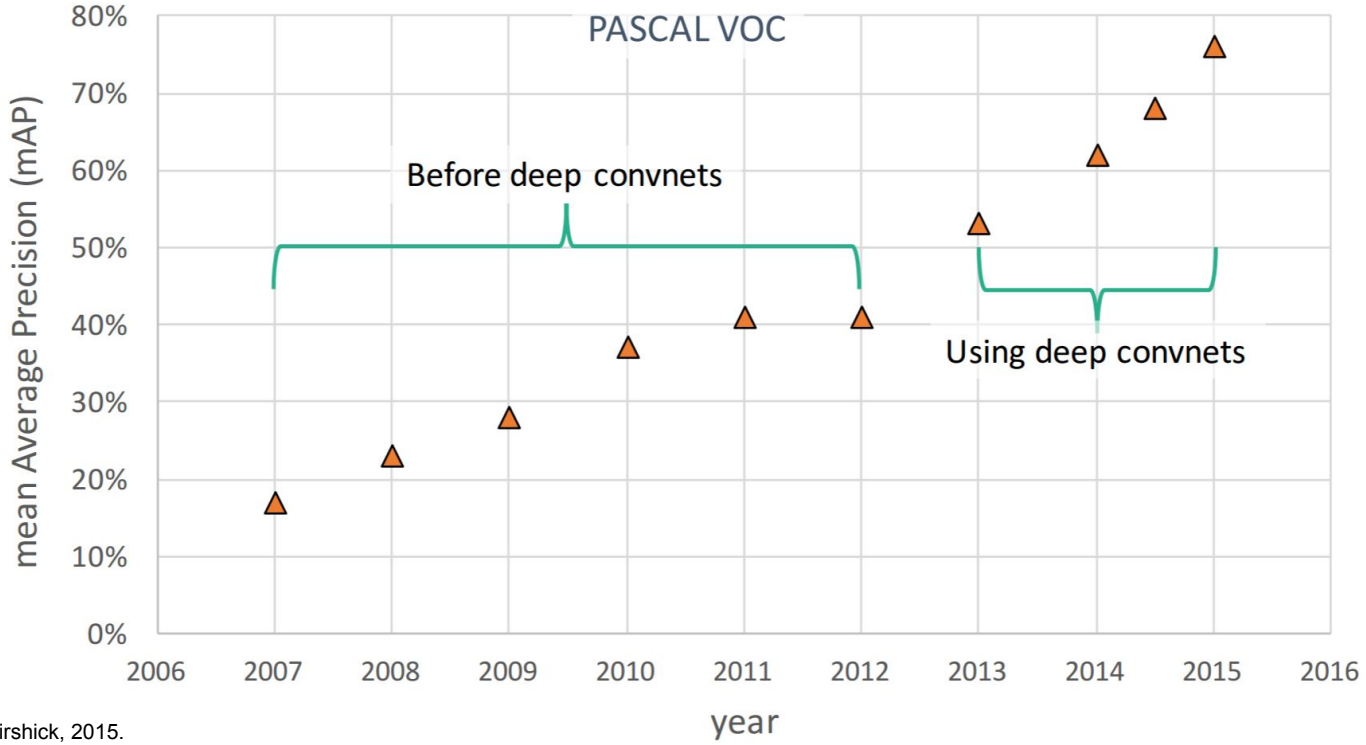
DOG, DOG, CAT



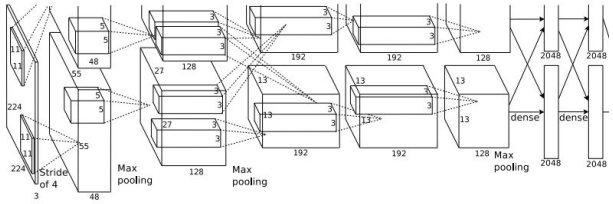
DOG, DOG, CAT

Multiple Object

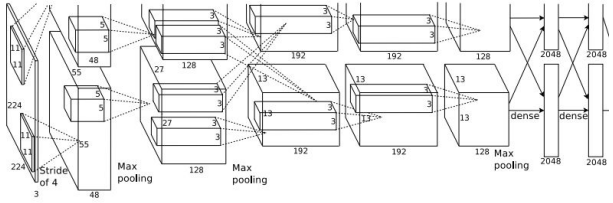
Object Detection: Impact of Deep Learning



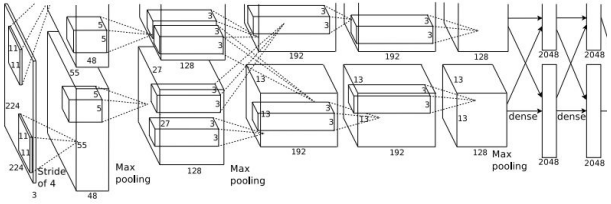
Object Detection as Regression?



CAT: (x, y, w, h)



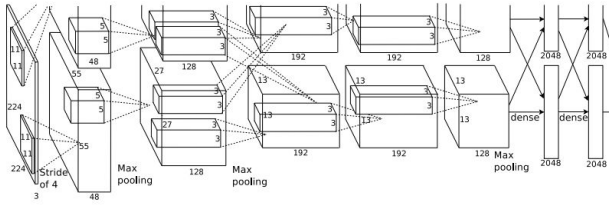
DOG: (x, y, w, h)
DOG: (x, y, w, h)
CAT: (x, y, w, h)



DUCK: (x, y, w, h)
DUCK: (x, y, w, h)
….

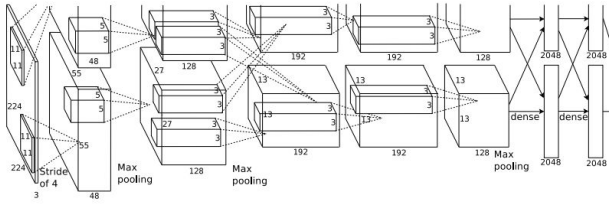
Object Detection as Regression?

Each image needs a different number of outputs!



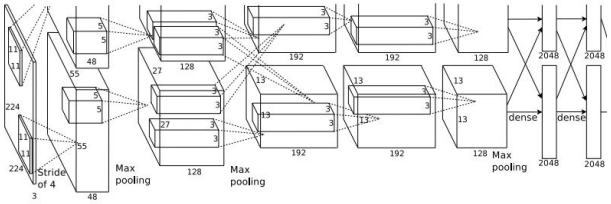
CAT: (x, y, w, h)

4 numbers



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

16 numbers

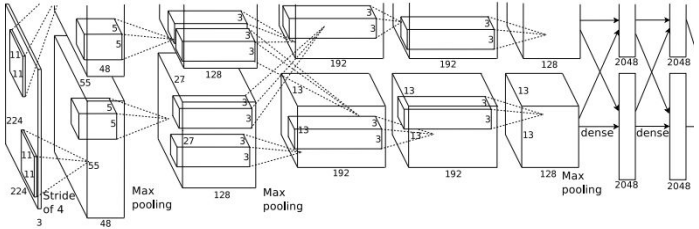


DUCK: (x, y, w, h)
DUCK: (x, y, w, h)
....

Many numbers!

Object Detection as Classification: Sliding Window

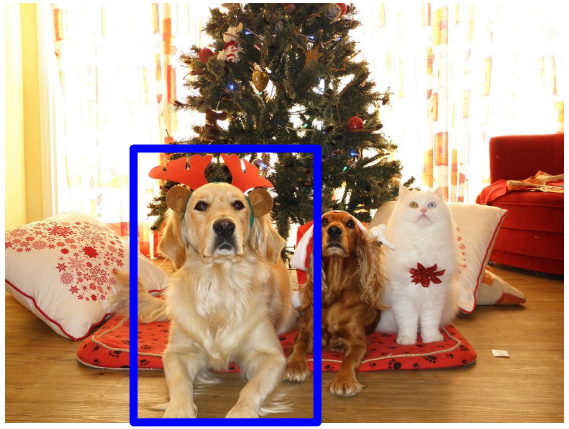
Apply a CNN to many different crops of the image, CNN classifies each crop as object or background

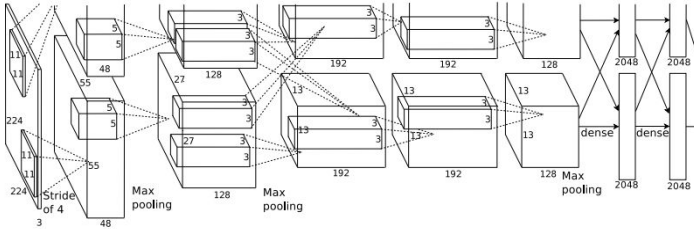


Dog? NO
Cat? NO
Background? YES

Object Detection as Classification: Sliding Window

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

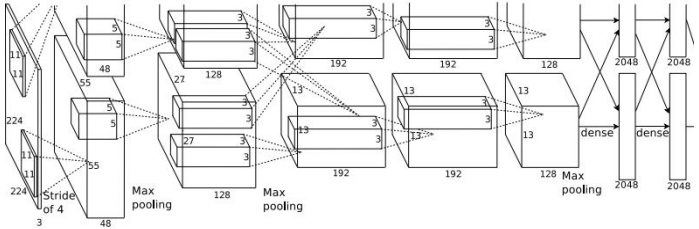




Dog? YES
Cat? NO
Background? NO

Object Detection as Classification: Sliding Window

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



Dog? YES
Cat? NO
Background? NO

Object Detection as Classification: Sliding Window

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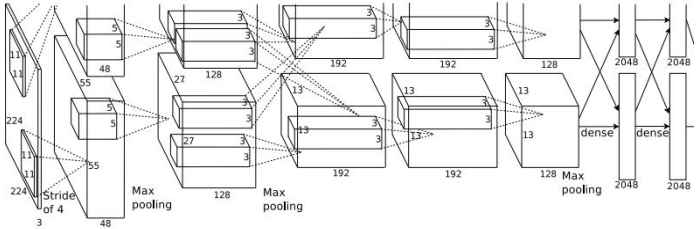
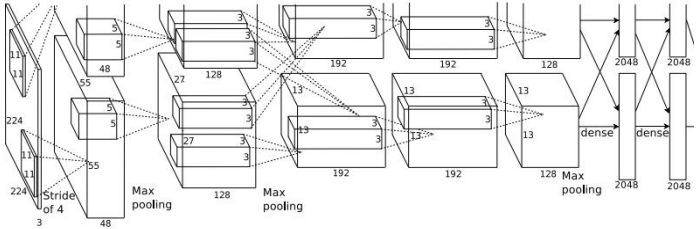


Dog? NO
Cat? YES
Background? NO

Object Detection as Classification: Sliding Window

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

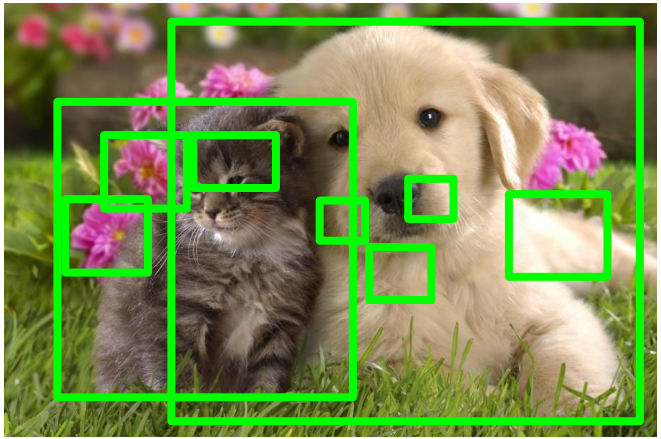


Dog? NO
Cat? YES
Background? NO

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

Region Proposals

- Find “blobby” image regions that are likely to contain objects
- Relatively fast to run; e.g. Selective Search gives 1000 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.

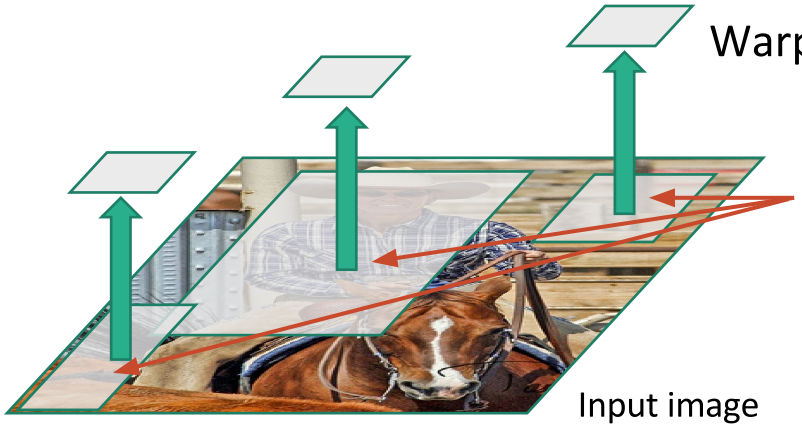
R-CNN

Input image

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

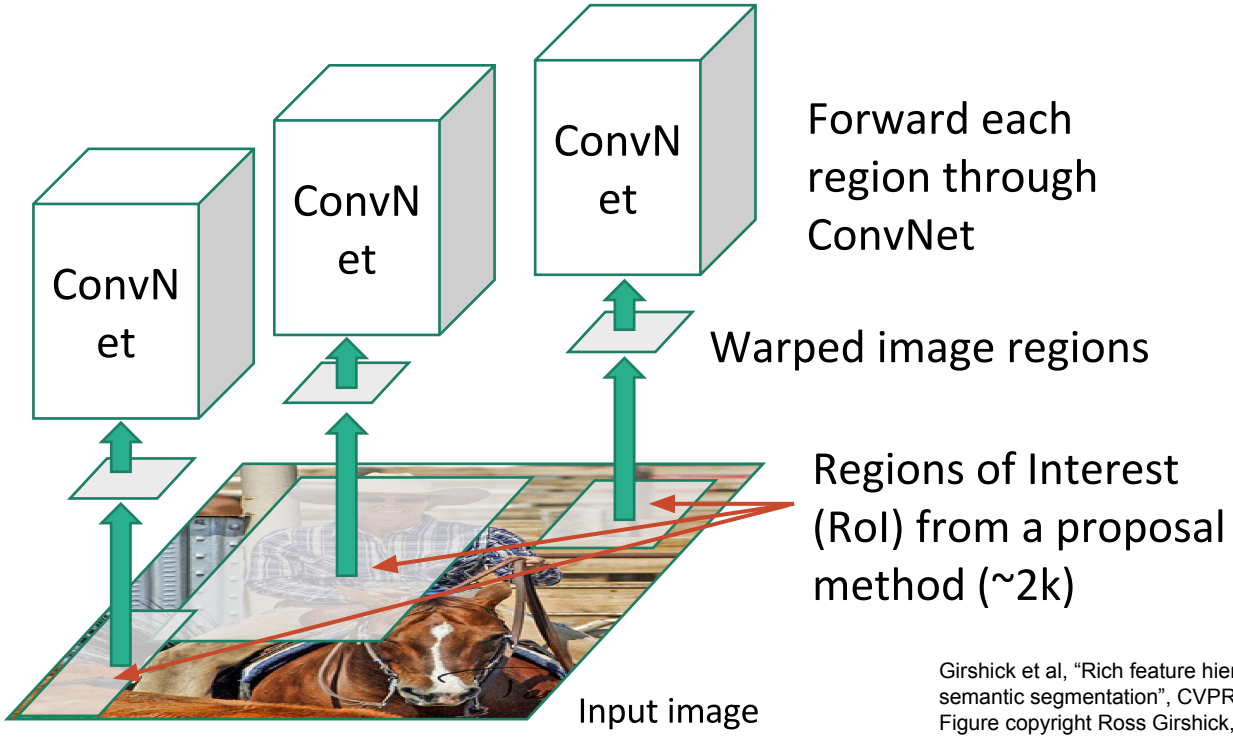
Girshick et al, “Rich feature hierarchies for accurate object detection and semantic segmentation”, CVPR 2014.

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.
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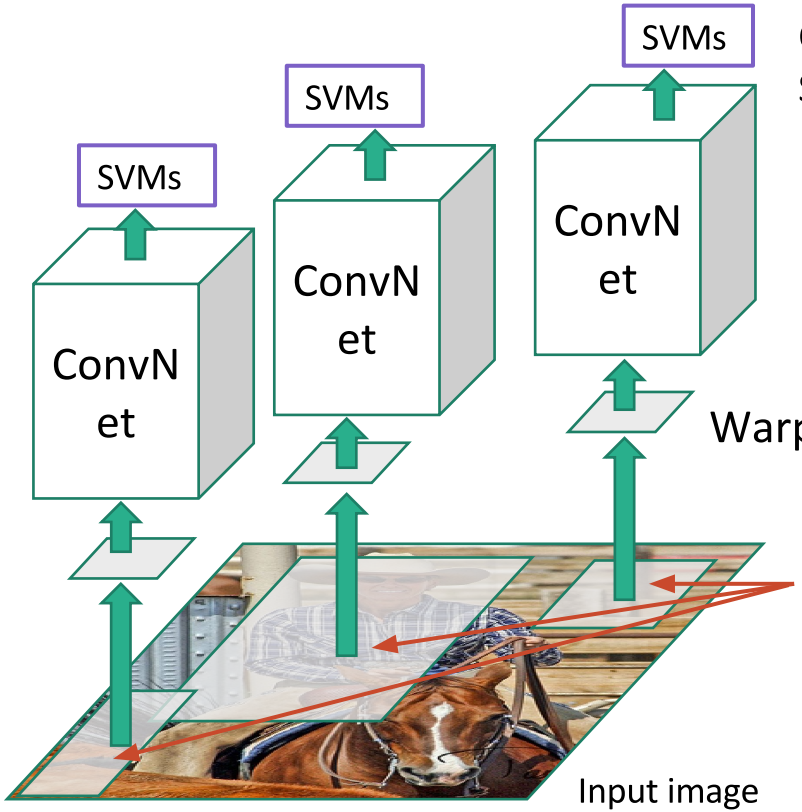
R-CNN



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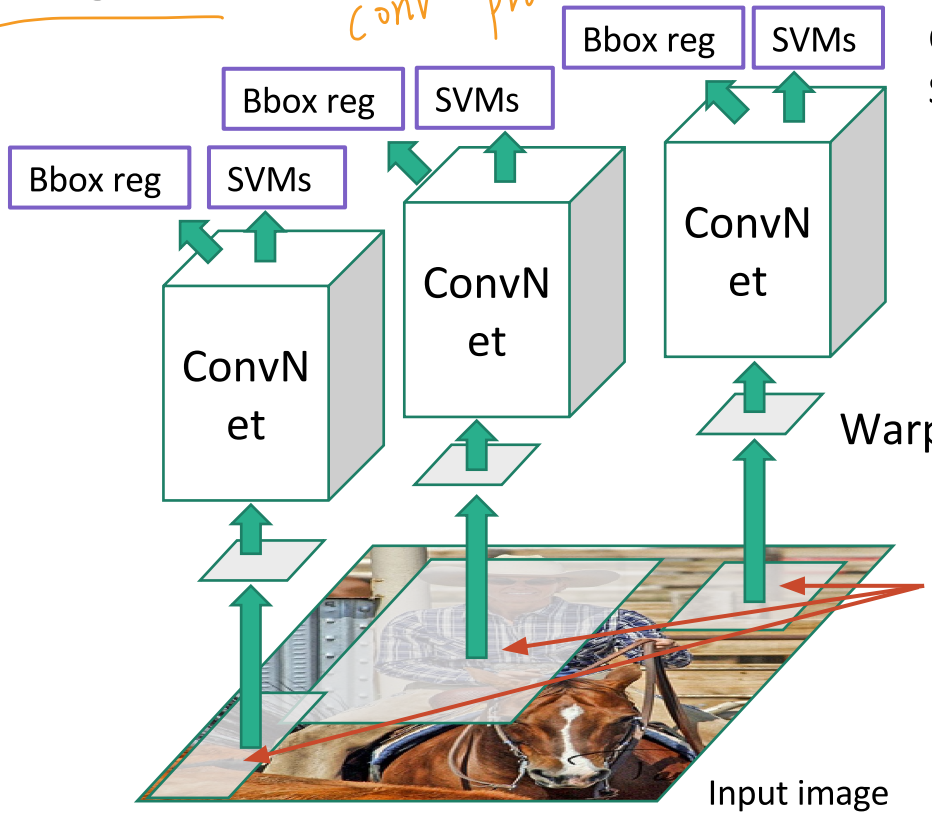
R-CNN

fixed not region proposal network. conv process



Linear Regression for bounding box offsets

Classify regions with SVMs

Forward each region through ConvNet

Warped image regions

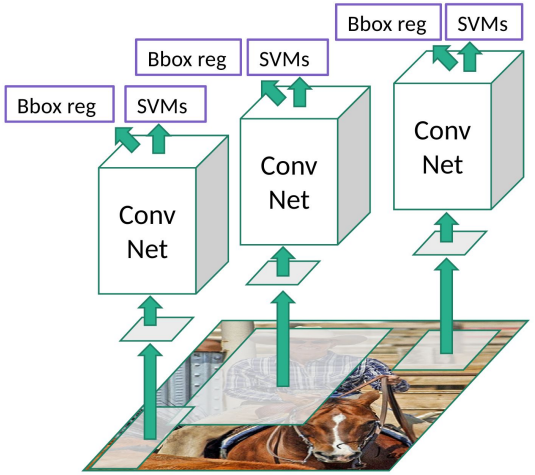
Regions of Interest (RoI) from a proposal method (~2k)

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: Problems

- Ad hoc training objectives
  - Fine-tune network with softmax classifier (log loss)
  - Train post-hoc linear SVMs (hinge loss)
  - Train post-hoc bounding-box regressions (least squares)
- Training is slow (84h), takes a lot of disk space
- Inference (detection) is slow
  - 47s / image with VGG16 [Simonyan & Zisserman. ICLR15]
  - Fixed by SPP-net [He et al. ECCV14]



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

Input image

Girshick, “Fast R-CNN”, ICCV 2015.
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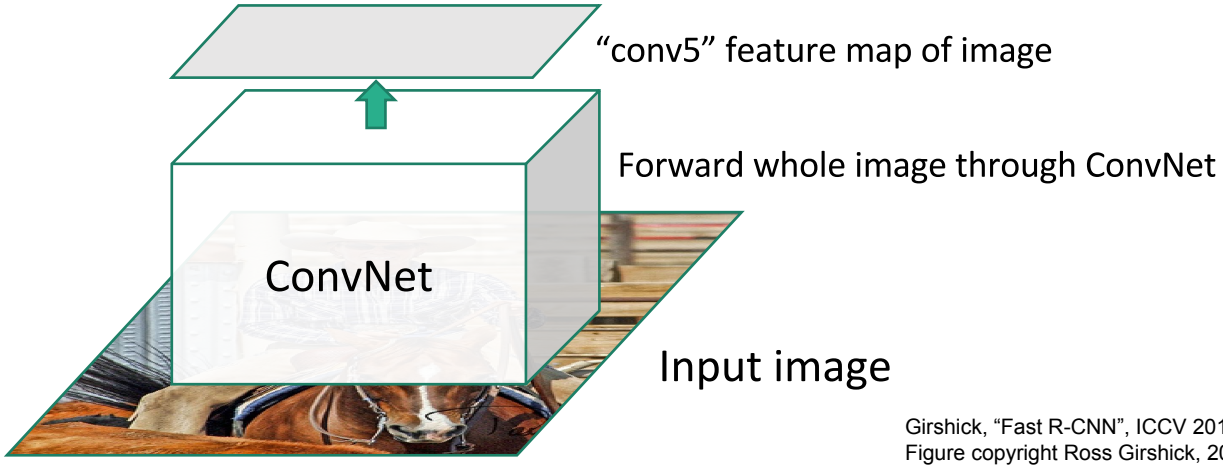
Fast R-CNN



Girshick, “Fast R-CNN”, ICCV 2015.
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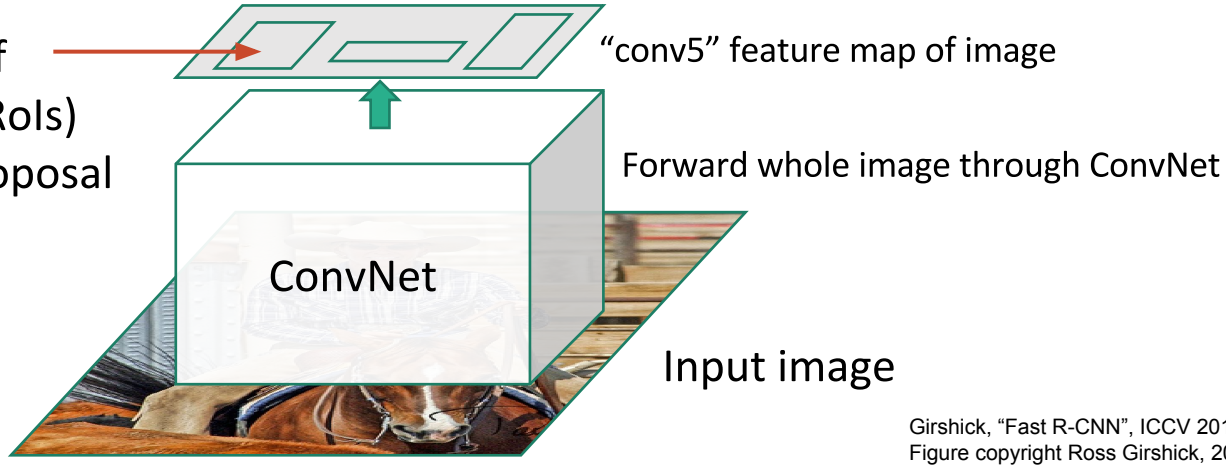
Fast R-CNN



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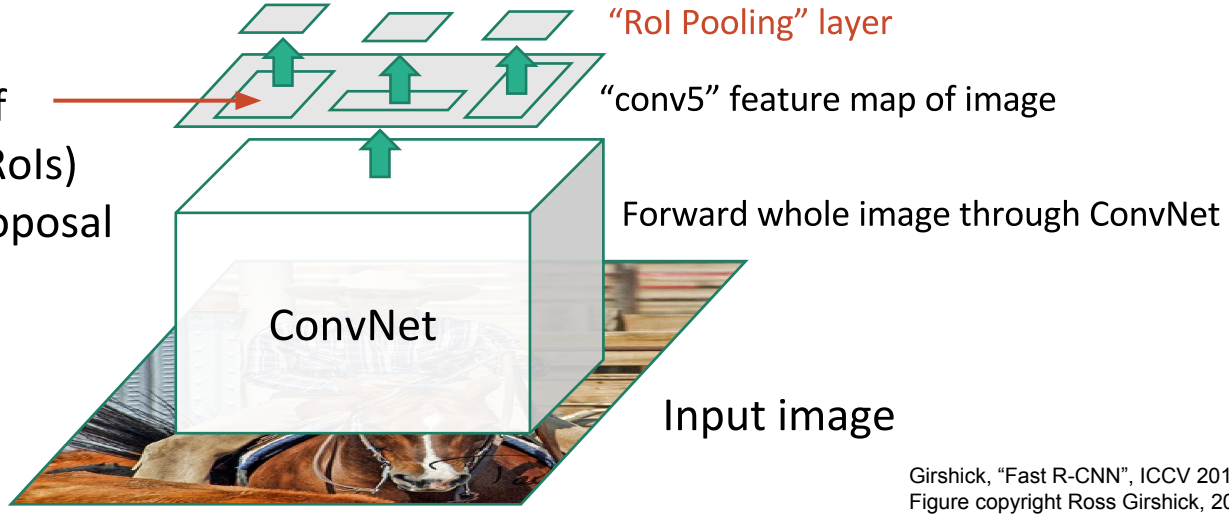
Fast R-CNN



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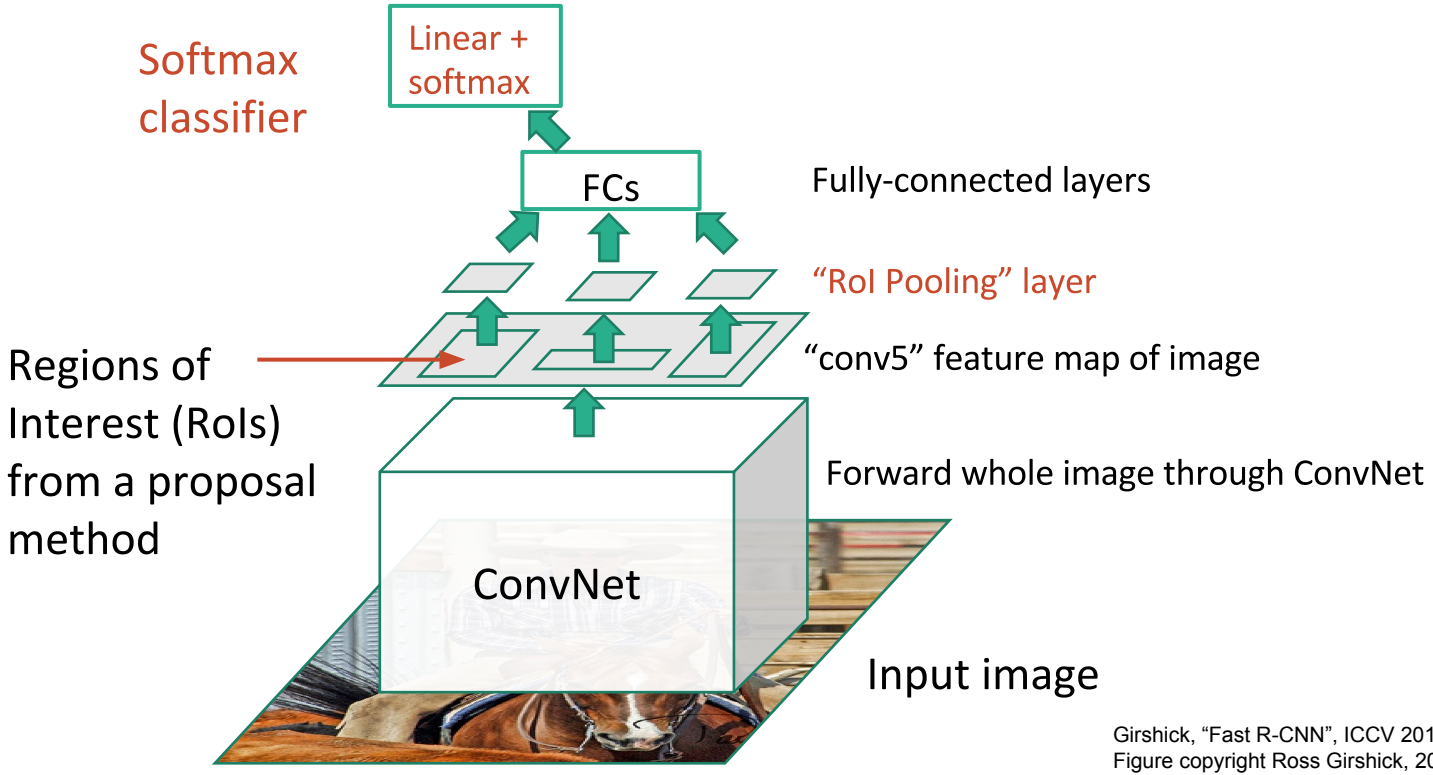
Fast R-CNN



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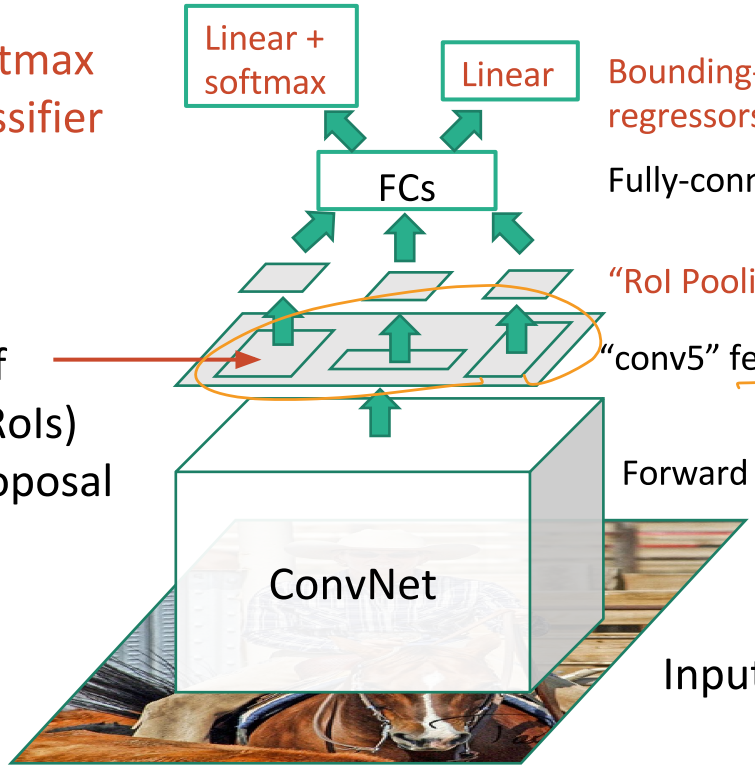
Fast R-CNN



Softmax classifier

Bounding-box regressors

Fully-connected layers

"RoI Pooling" layer

"conv5" feature map of image

Regions of Interest (RoIs) from a proposal method

Forward whole image through ConvNet

ConvNet

Input image

Girshick, "Fast R-CNN", ICCV 2015.
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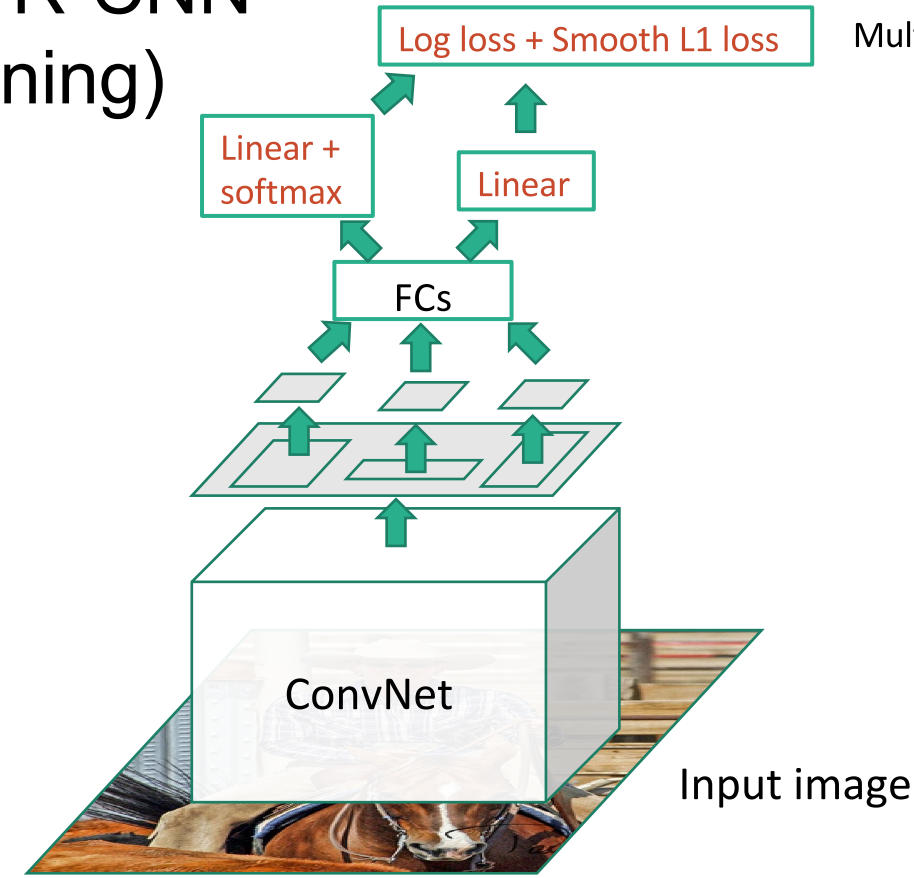
Fast R-CNN (Training)



Girshick, "Fast R-CNN", ICCV 2015.
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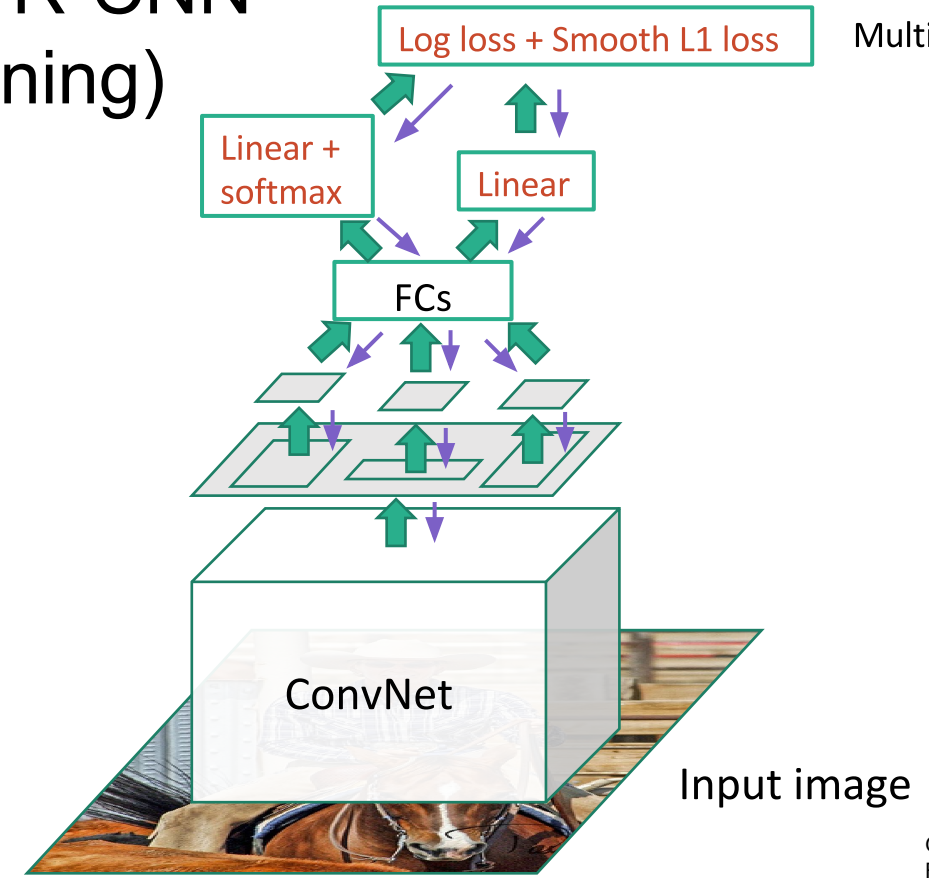
Fast R-CNN (Training)



Multi-task loss

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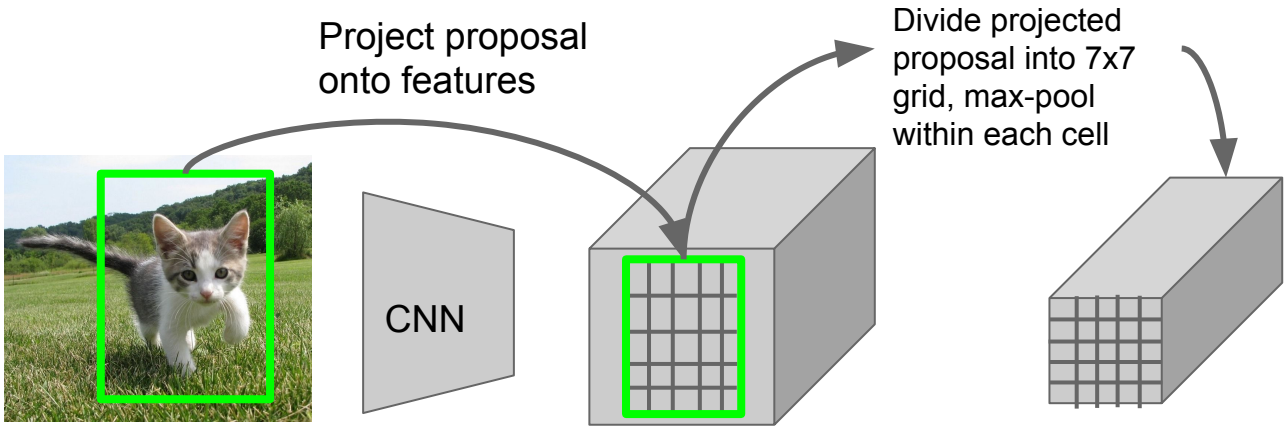
Faster R-CNN: RoI Pooling



Hi-res input image:
3 x 640 x 480
with region proposal

Hi-res conv features:
512 x 20 x 15;

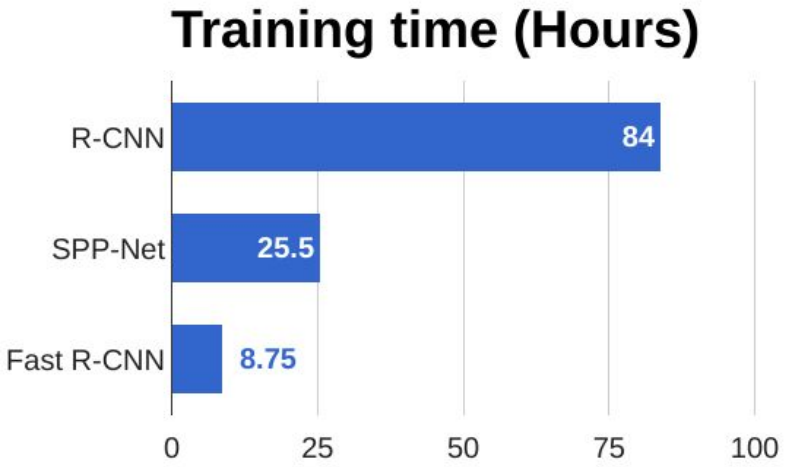
Projected region proposal is e.g.
512 x 18 x 8
(varies per proposal)

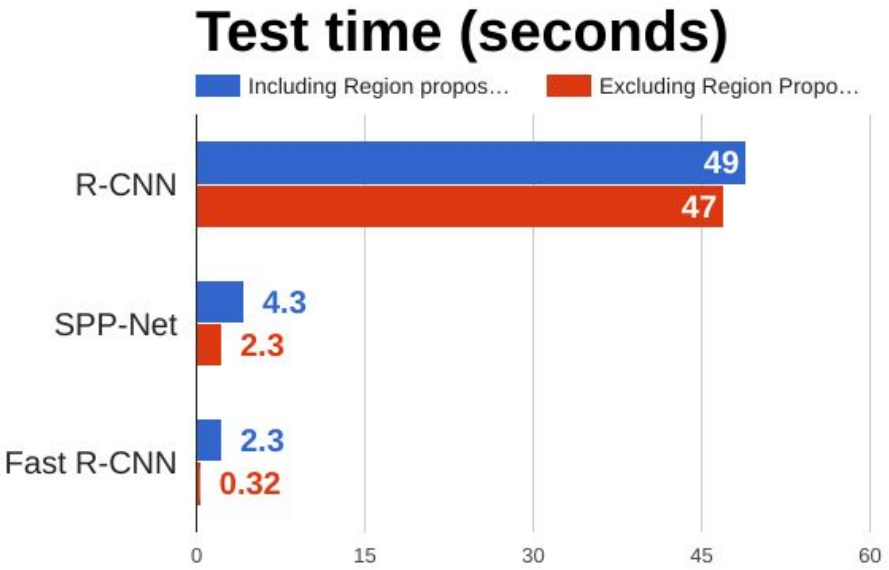
RoI conv features:
512 x 7 x 7
for region proposal

Fully-connected layers expect low-res conv features:
512 x 7 x 7

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

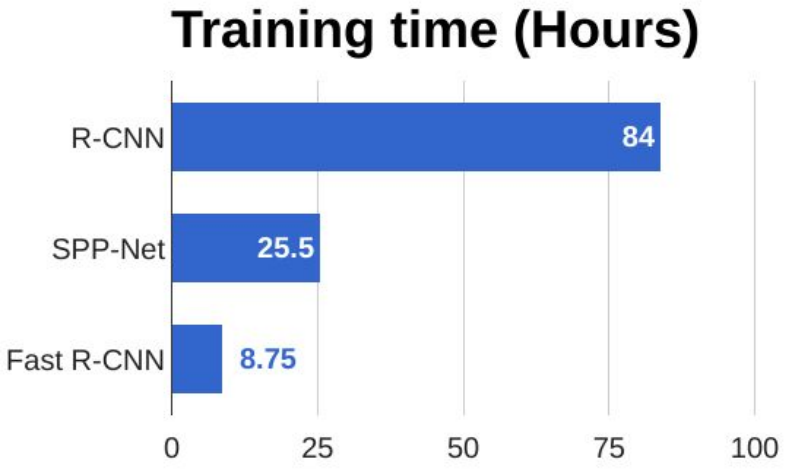
R-CNN vs SPP vs Fast R-CNN

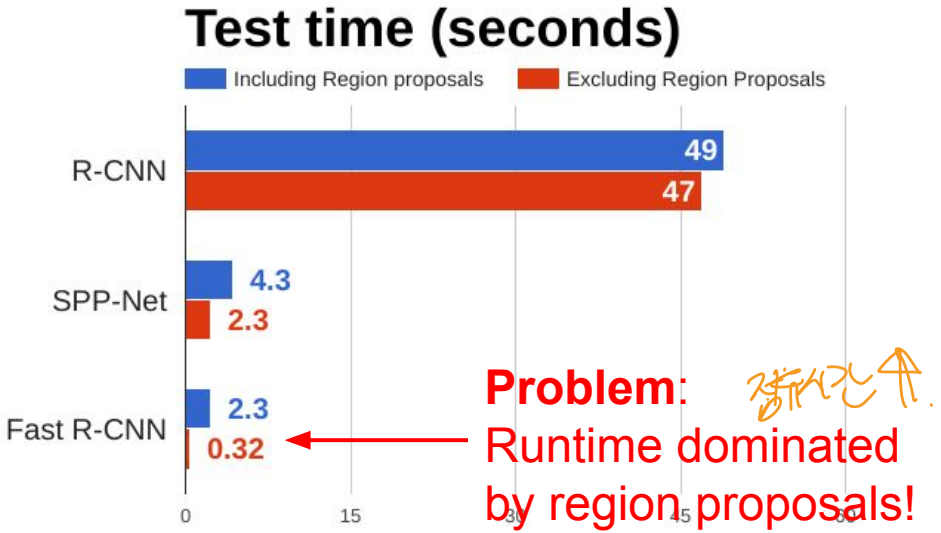




Girshick et al, “Rich feature hierarchies for accurate object detection and semantic segmentation”, CVPR 2014.
He et al, “Spatial pyramid pooling in deep convolutional networks for visual recognition”, ECCV 2014
Girshick, “Fast R-CNN”, ICCV 2015

R-CNN vs SPP vs Fast R-CNN





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He et al, “Spatial pyramid pooling in deep convolutional networks for visual recognition”, ECCV 2014
Girshick, “Fast R-CNN”, ICCV 2015

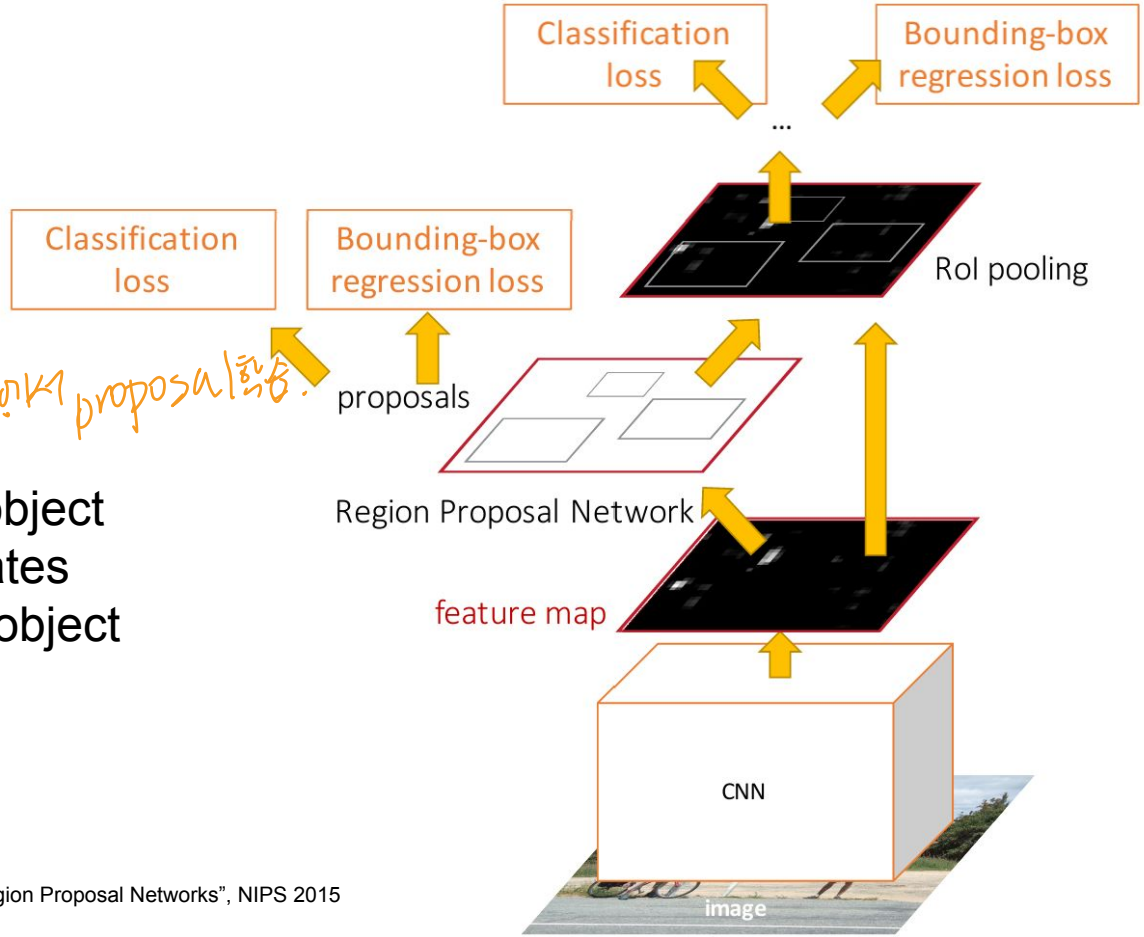
Faster R-CNN:

Make CNN do proposals!

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

Jointly train with 4 losses:

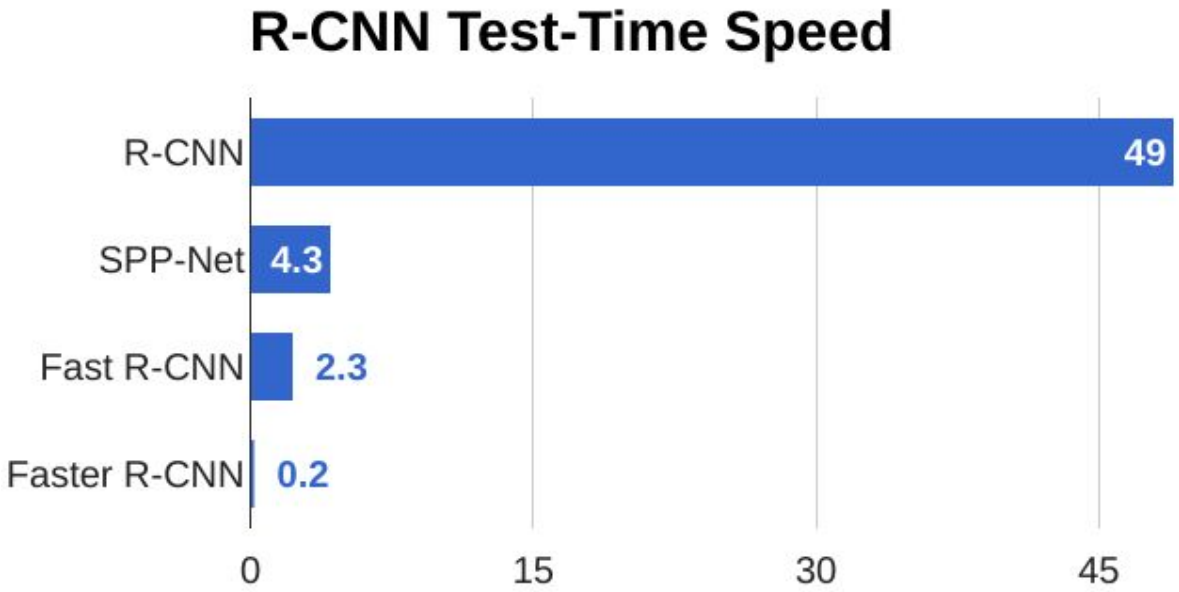
1. RPN classify object / not object
2. RPN regress box coordinates
3. Final classification score (object classes)
4. Final box coordinates



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

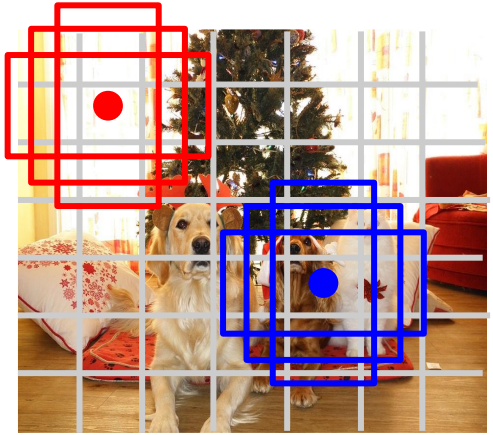
Faster R-CNN:

Make CNN do proposals!



Detection without Proposals: YOLO / SSD

Input image
3 x H x W



Divide image into grid
7 x 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)

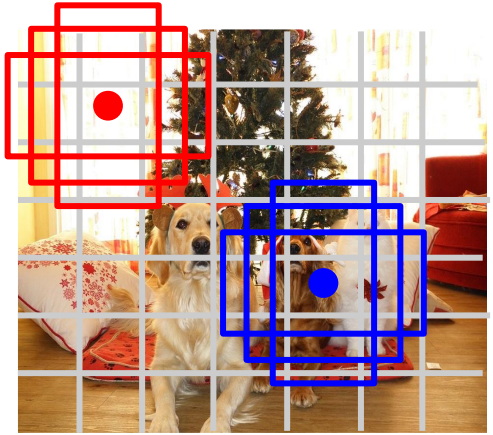
Output:
7 x 7 x (5 * B + C)

Redmon et al, "You Only Look Once: Unified, Real-Time Object Detection", CVPR 2016
Liu et al, "SSD: Single-Shot MultiBox Detector", ECCV 2016

Detection without Proposals: YOLO / SSD

Go from input image to tensor of scores with one big convolutional network!

Input image
3 x H x W



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Redmon et al, "You Only Look Once:
Unified, Real-Time Object Detection", CVPR 2016
Liu et al, "SSD: Single-Shot MultiBox Detector", ECCV 2016

Object Detection: Lots of variables ...

Base Network
VGG16
ResNet-101
Inception V2
Inception V3
Inception
ResNet
MobileNet

Object Detection architecture
Faster R-CNN
R-FCN
SSD

Image Size
 # Region Proposals
…

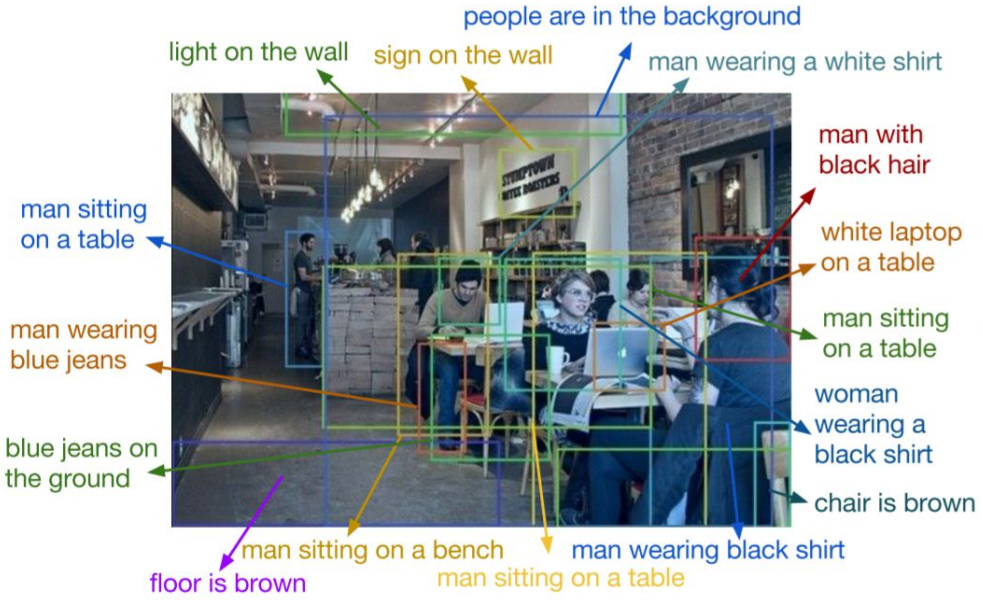
Takeaways
Faster R-CNN is slower but more accurate

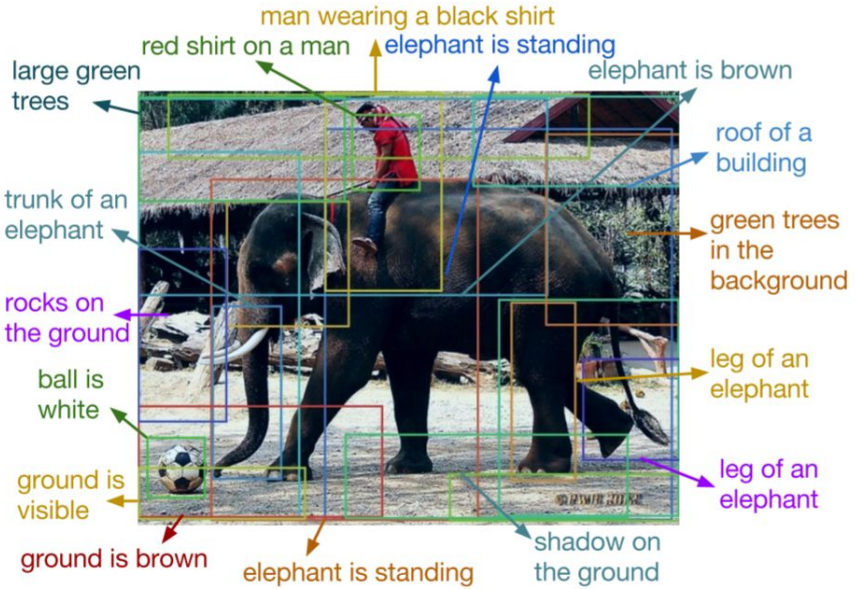
SSD is much faster but not as accurate

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

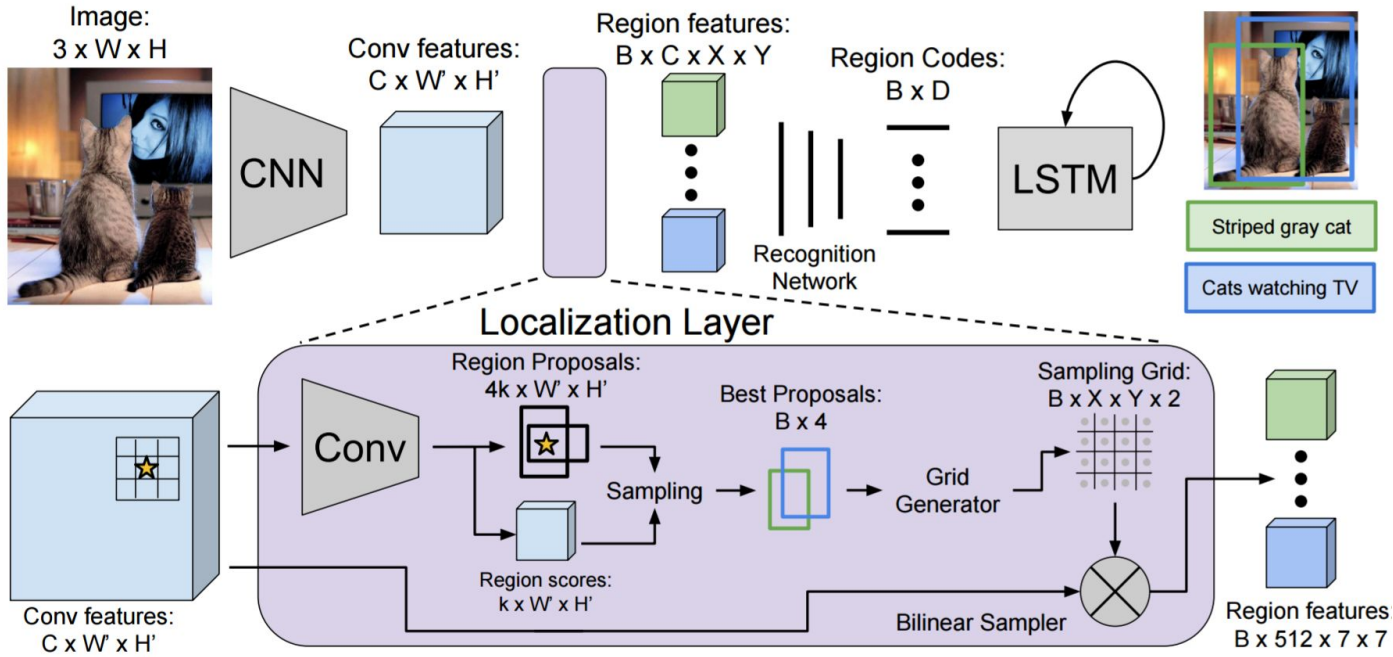
Aside: Object Detection + Captioning = Dense Captioning



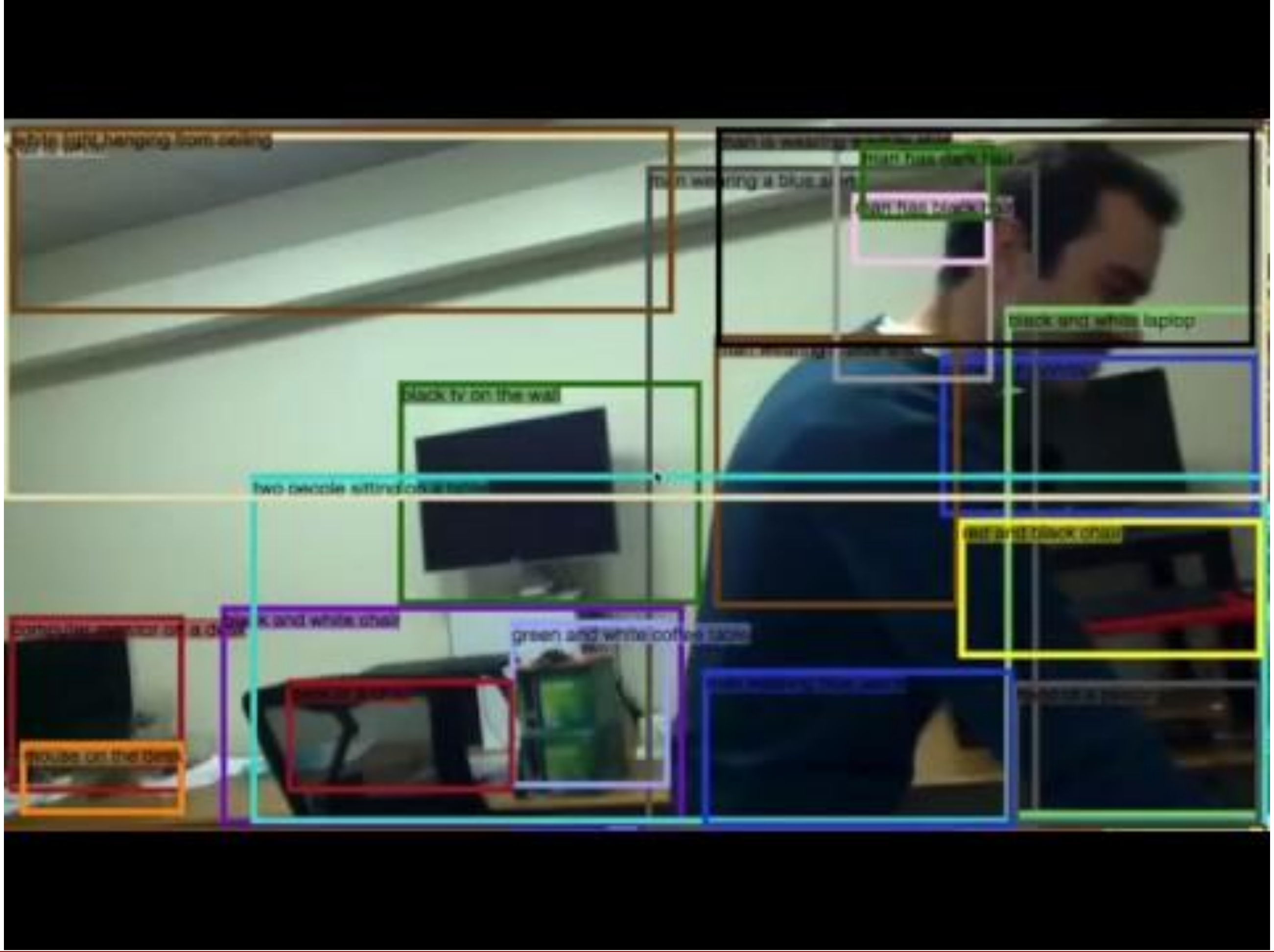


Johnson, Karpathy, and Fei-Fei, "DenseCap: Fully Convolutional Localization Networks for Dense Captioning", CVPR 2016
Figure copyright IEEE, 2016. Reproduced for educational purposes.

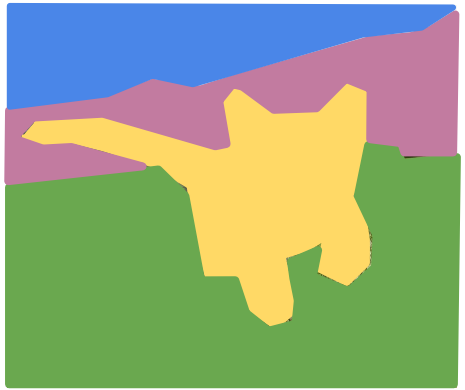
Aside: Object Detection + Captioning = Dense Captioning



Johnson, Karpathy, and Fei-Fei, "DenseCap: Fully Convolutional Localization Networks for Dense Captioning", CVPR 2016
Figure copyright IEEE, 2016. Reproduced for educational purposes.

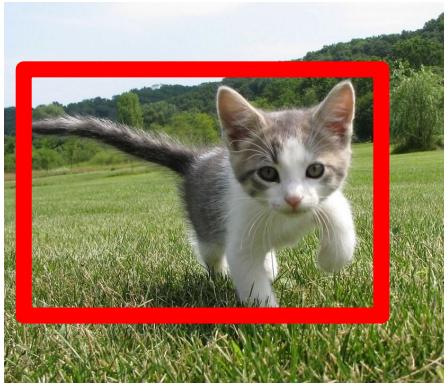

man has dark hair
black and white laptop
black tv on the wall
red and black chair
black and white chair
mouse on the desk

Instance Segmentation



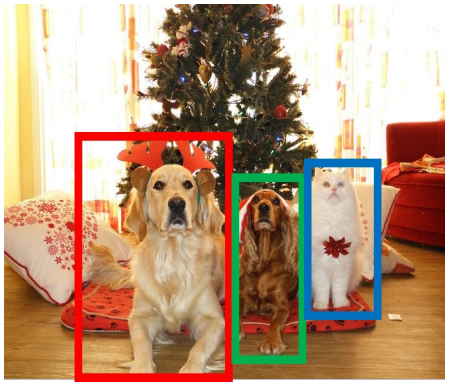
GRASS, CAT, TREE, SKY

No objects, just pixels

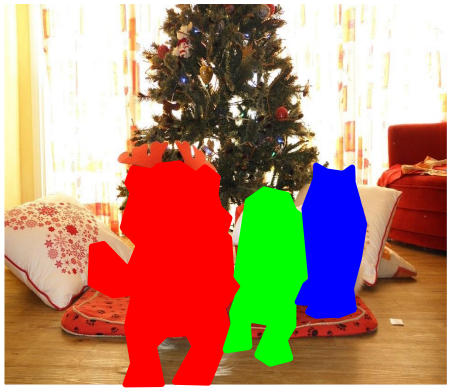


CAT

Single Object



DOG, DOG, CAT

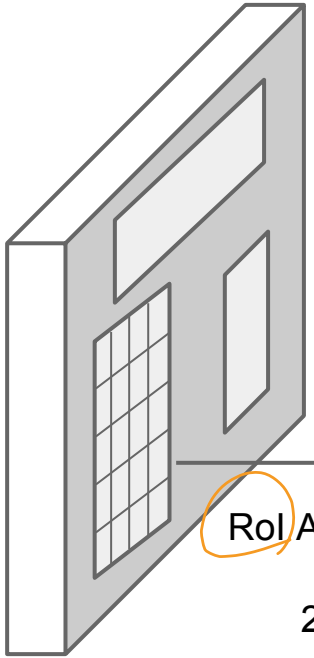


DOG, DOG, CAT

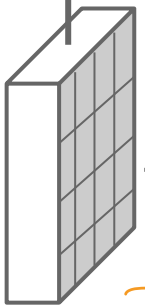
Multiple Object

Mask R-CNN

CNN

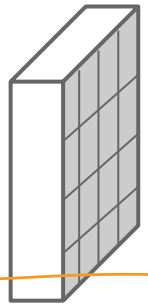


RoI Align



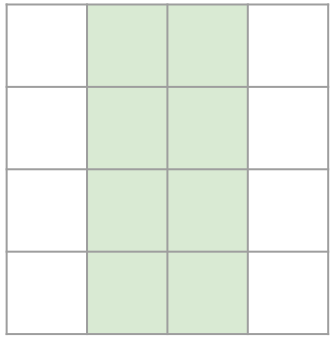
256 x 14 x 14

Conv



256 x 14 x 14

Conv



Predict a mask for each of C classes

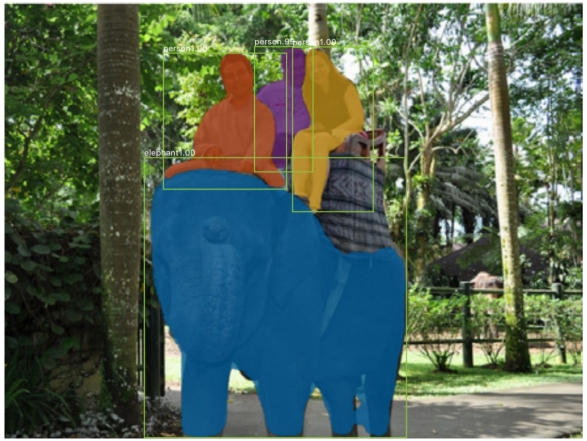
C x 14 x 14

Classification Scores: C
Box coordinates (per class): 4 * C

object detection + segmentation.

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

Mask R-CNN: Very Good Results!



He et al, “Mask R-CNN”, arXiv 2017

Mask R-CNN
Also does pose

CNN

RoI Align

Classification Scores: C
Box coordinates (per class): 4 * C
Joint coordinates

256 x 14 x 14

Conv

256 x 14 x 14

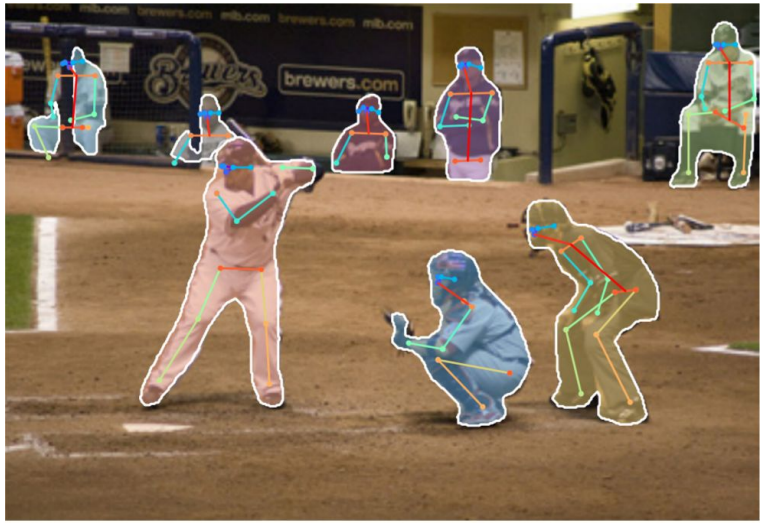
Conv

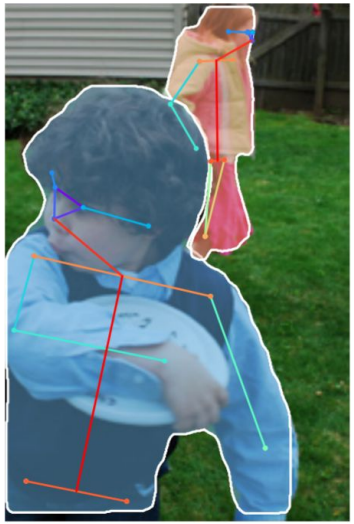
Predict a mask for each of C classes

C x 14 x 14

He et al, “Mask R-CNN”, arXiv 2017

Mask R-CNN
Also does pose





He et al, “Mask R-CNN”, arXiv 2017
Figures copyright Kaiming He, Georgia Gkioxari, Piotr Dollár, and Ross Girshick, 2017.
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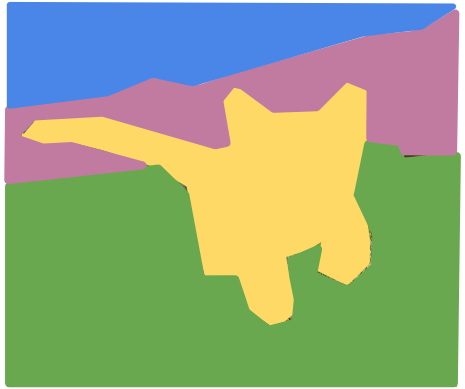
Recap:

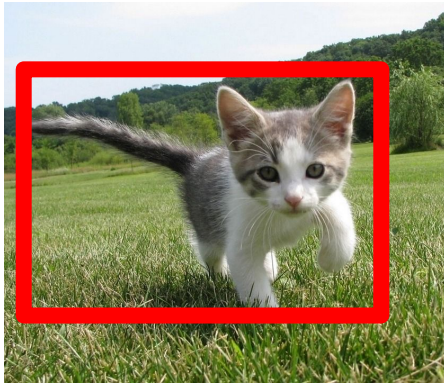
Semantic Segmentation



GRASS, CAT, TREE, SKY

No objects, just pixels

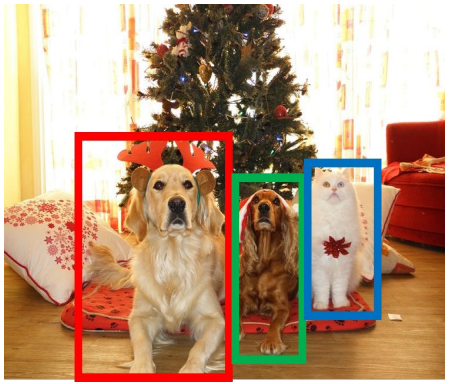
Classification + Localization



CAT

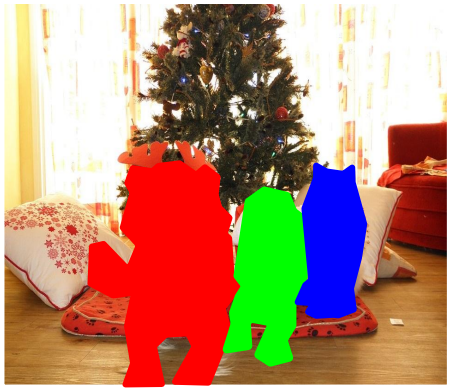
Single Object

Object Detection



DOG, DOG, CAT

Instance Segmentation



DOG, DOG, CAT

Multiple Object

Next time:
Visualizing CNN features
DeepDream + Style Transfer