

# **CS 4644-DL / 7643-A: LECTURE 16**

## **DANFEI XU**

Deep Learning Application to Computer Vision

- Semantic Segmentation
- Object Detection
- Instance Segmentation

# Administrative

- Milestone rubric released.
- Presentation -> video recording.
- Milestone + presentation due Nov 7<sup>th</sup>.
- NO GRACE PERIOD

# The rest of the semester

W9: Oct 19	Computer Vision: Detection and Segmentation <a href="#">Slides (pdf)</a>	<ul style="list-style-type: none"><li>• <a href="#">Fully Convolutional Networks for Semantic Segmentation</a></li></ul>
W10: Oct 24	Visualizing Neural Networks <a href="#">Slides (pdf)</a>	<ul style="list-style-type: none"><li>• <a href="#">Understanding Neural Networks Through Deep Visualization</a></li><li>• <a href="#">Grad-CAM: Visual Explanations from Deep Networks via Gradient-based Localization</a></li></ul>
W10: Oct 26	Generative Models - Autoregressive Models and Variational Autoencoders (VAE) <a href="#">Slides (pdf)</a>	
W11: Oct 31	Generative Models - Denoising Diffusion Probabilistic Models <a href="#">Slides (pdf)</a>	
W11: Nov 2	Self-Supervised Learning <a href="#">Slides (pdf)</a>	
W12: Nov 7	Embodied Reasoning Through Planning with Language and Vision Foundation Models Guest Lecture by <a href="#">Fei Xia</a> , Google DeepMind	
W12: Nov 9	TBD	

# The rest of the semester

W13: Nov 14 Graph Neural Networks

Guest Lecture by [Jiaxuan You](#), NVIDIA Research

W13: Nov 16 Reinforcement Learning 1: MDP, Value Iteration, Deep Q Learning.

PS/HW4 due Nov 11th 11:59pm

[Slides \(pdf\)](#).

- [Sutton & Bartow Chapter 1](#)

- [Survey paper on Deep RL](#)

- [MDP Notes \(courtesy Byron Boots\)](#)

W14: Nov 21 Reinforcement Learning 2: Actor-Critic, Frontiers.

[Slides \(pdf\)](#).

- [Sutton & Bartow Chapter 1](#)

- [Survey paper on Deep RL](#)

- [MDP Notes \(courtesy Byron Boots\)](#)

W14: Nov 23 Thanksgiving Holiday - No Class

W15: Nov 28 Foundation Models for Robotics

Guest Lecture by [Siddharth Karamcheti](#), Stanford University

W15: Nov 30 Robot Learning Teaser + Conclusion

W16: Dec 5 Poster Session (Klaus Atrium): 5-7PM

# Image Classification: A core task in Computer Vision



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



cat

This image by [Nikita](#) is  
licensed under [CC-BY 2.0](#)

# Computer Vision Tasks

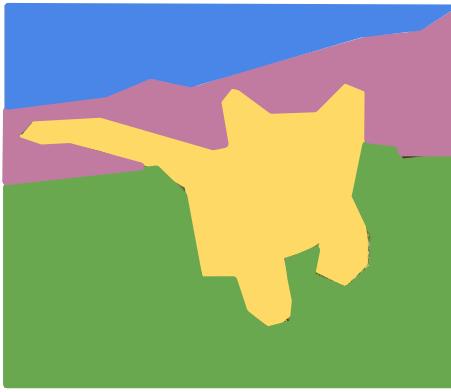
## Classification



CAT

No spatial extent

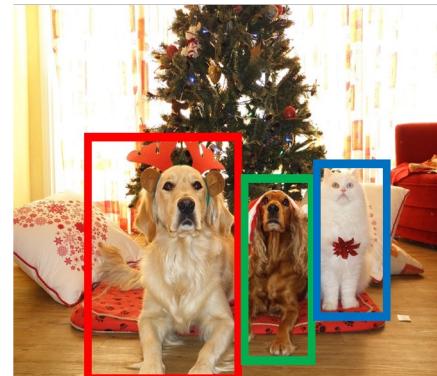
## Semantic Segmentation



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



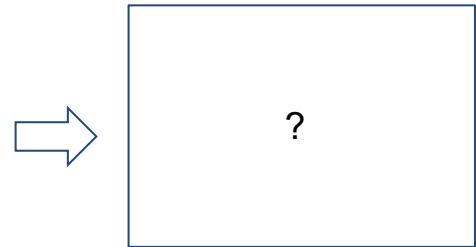
DOG, DOG, CAT

# 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



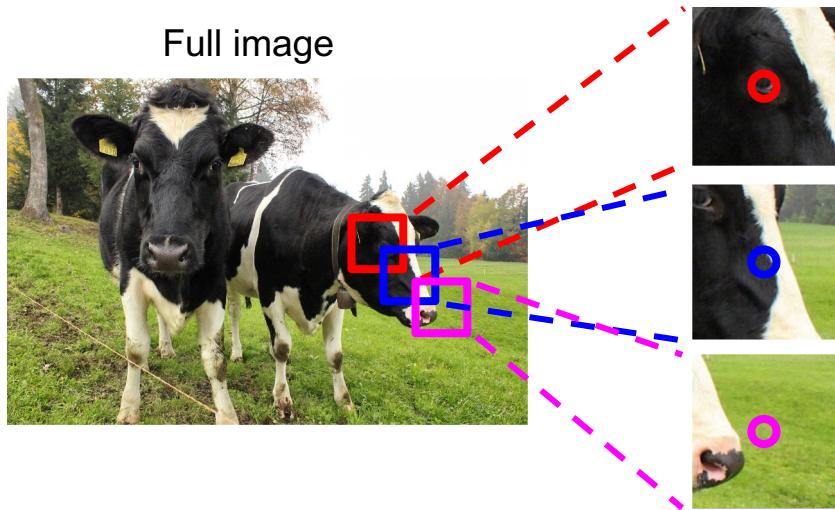
?



Impossible to classify without context

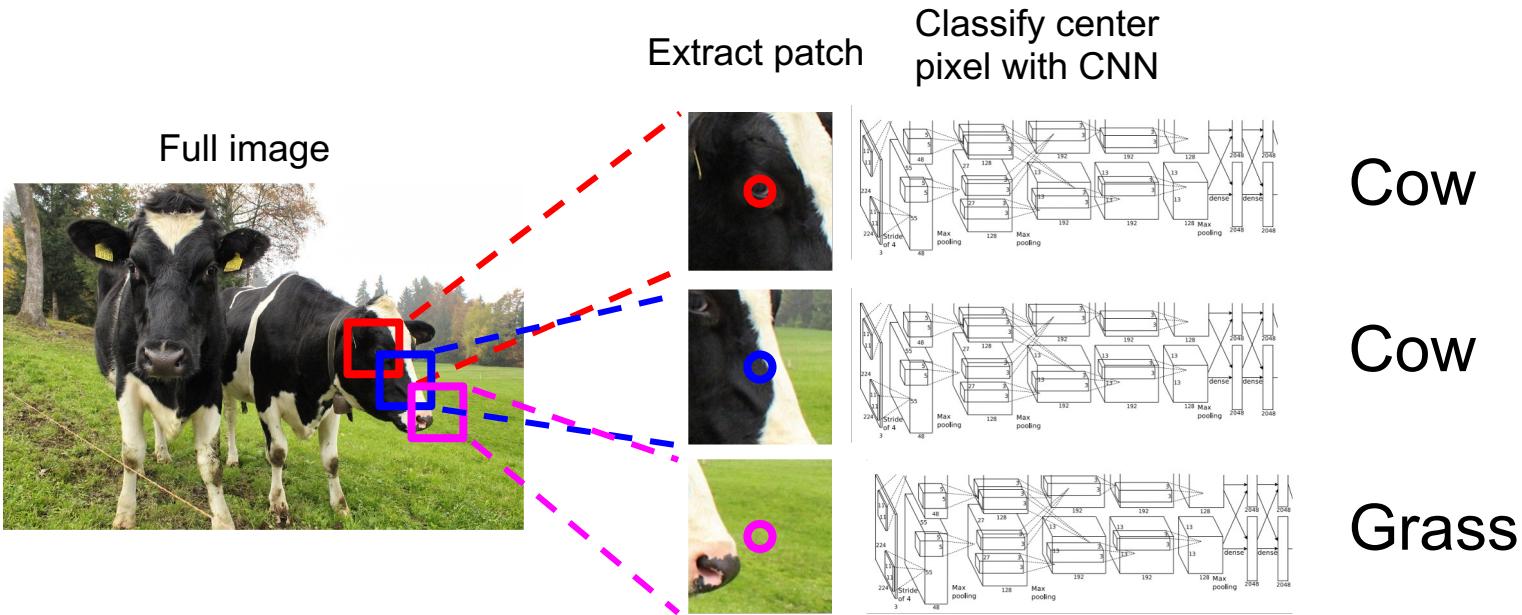
Q: how do we include context?

# Semantic Segmentation Idea: Sliding Window



Q: how do we model this?

# Semantic Segmentation Idea: Sliding Window

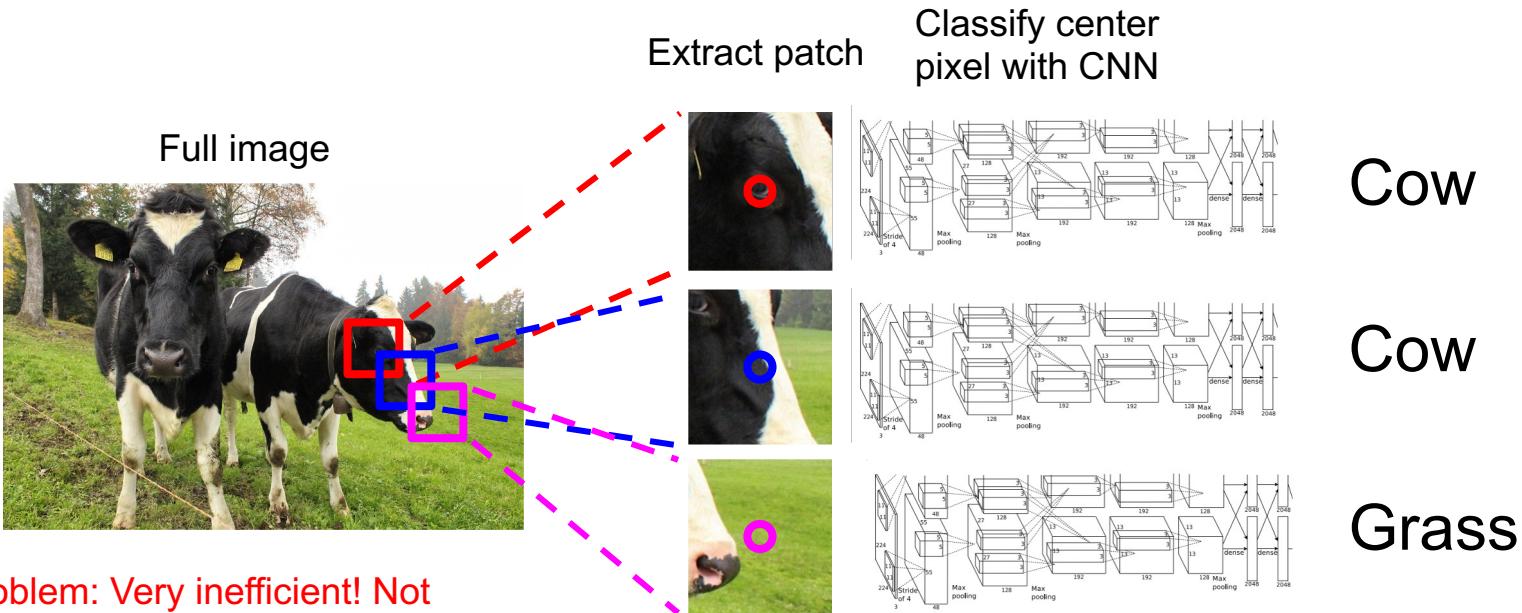


The “sliding window” approach

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



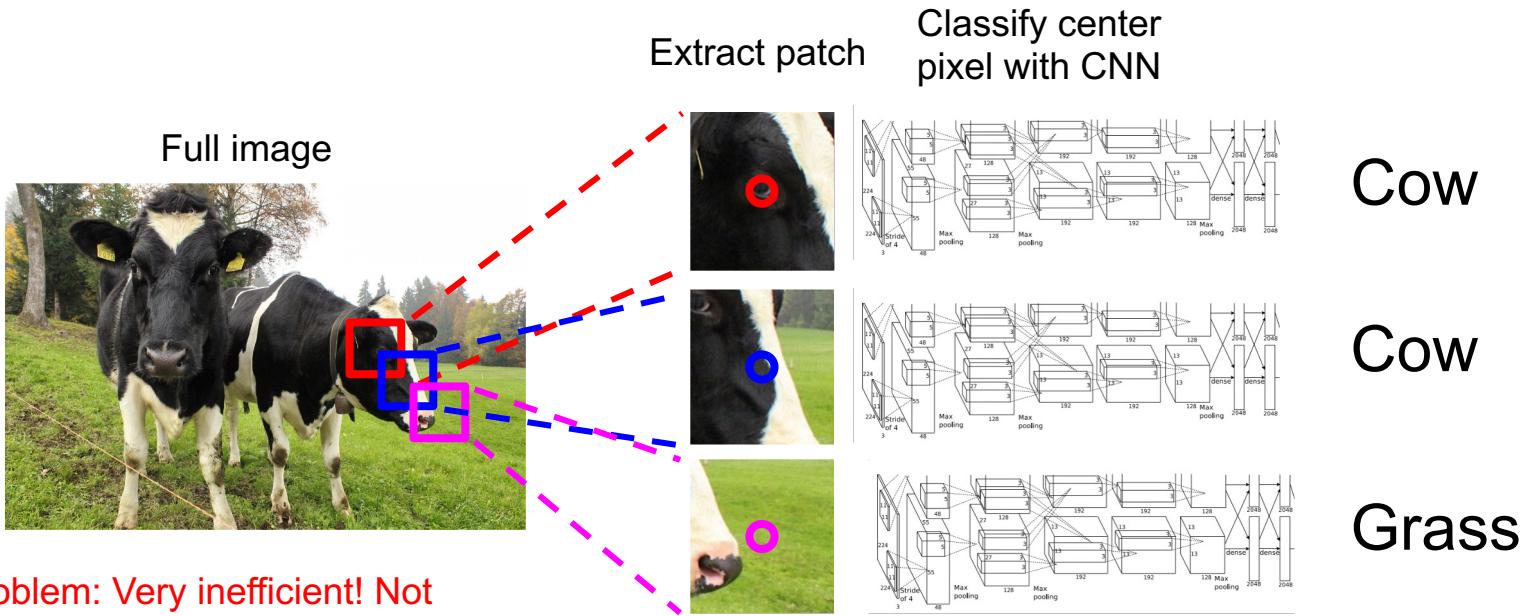
Problem: Very inefficient! Not reusing shared features between overlapping patches

The “sliding window” approach

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



**Observation:** lots of duplicate computation in nearby pixels

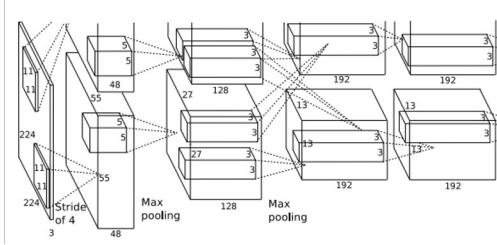
The “sliding window” approach

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

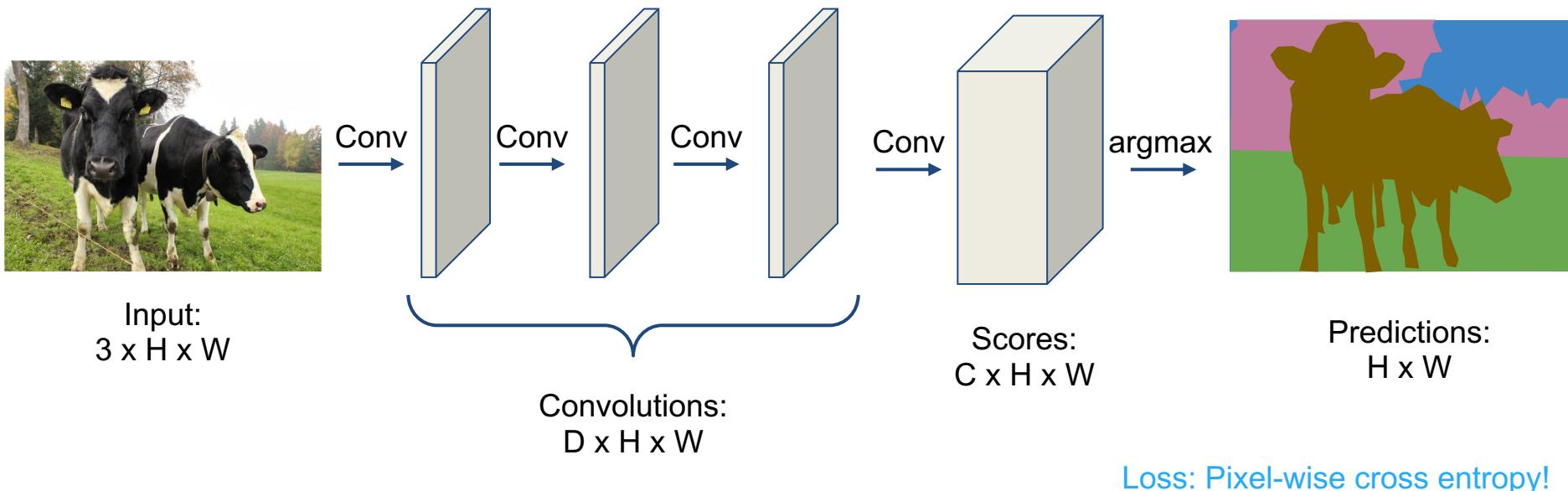


An intuitive idea: encode the entire image with conv net, and do semantic segmentation on top.

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.

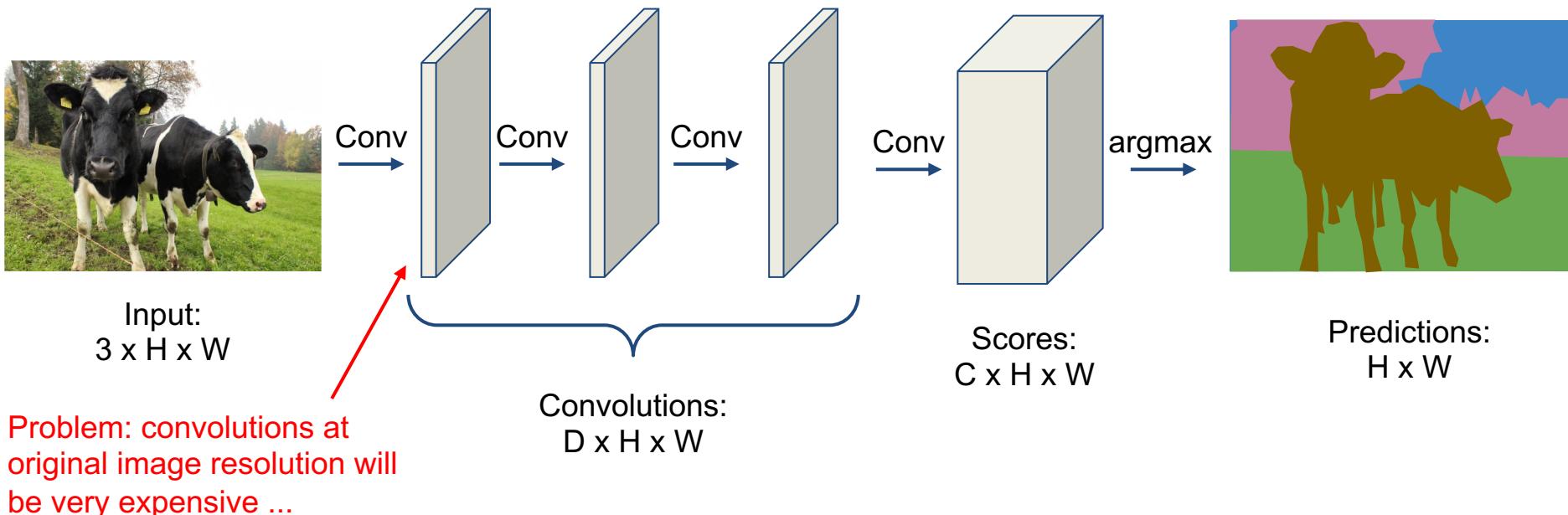
# Semantic Segmentation Idea: Fully Convolutional

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!



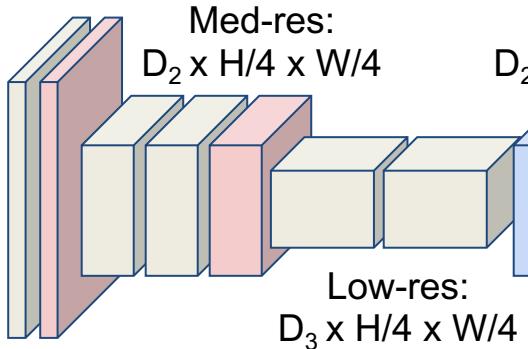
# Semantic Segmentation Idea: Fully Convolutional

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

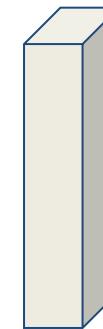
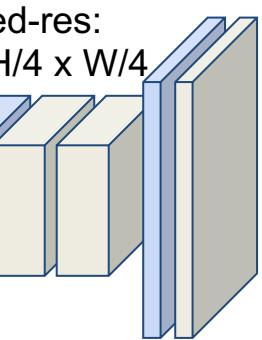


Input:  
 $3 \times H \times W$

High-res:  
 $D_1 \times H/2 \times W/2$



High-res:  
 $D_1 \times H/2 \times W/2$



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

# Semantic Segmentation Idea: Fully Convolutional

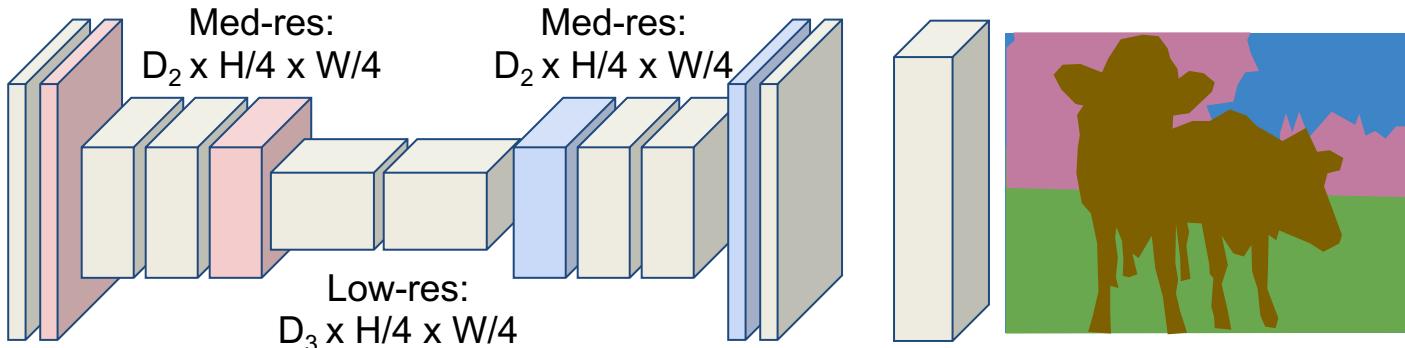
**Downsampling:**  
Pooling, strided  
convolution



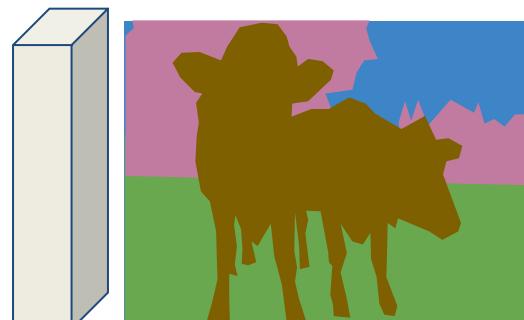
Input:  
 $3 \times H \times W$

High-res:  
 $D_1 \times H/2 \times W/2$

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



**Upsampling:**  
???



High-res:  
 $D_1 \times H/2 \times W/2$

Predictions:  
 $H \times W$

# In-Network upsampling: “Unpooling”

**Nearest Neighbor**

1	2
3	4



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

Input: 2 x 2

Output: 4 x 4

**“Bed of Nails”**

1	2
3	4



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

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

## Max Unpooling

Use positions from pooling layer

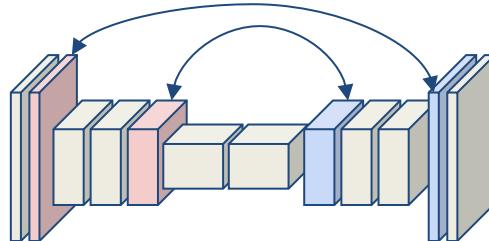
1	2
3	4

Rest of the network

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

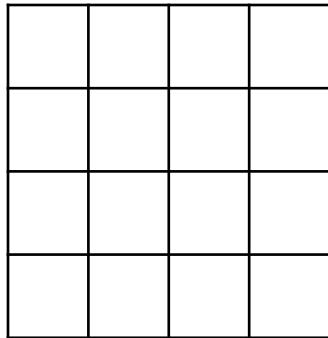
Output: 4 x 4

Corresponding pairs of  
downsampling and  
upsampling layers

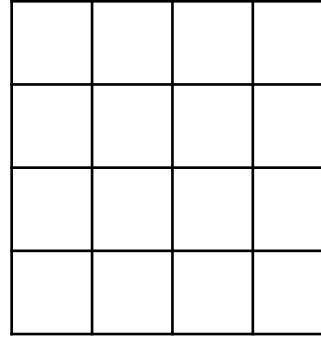


# Learnable Upsampling

**Recall:** Normal  $3 \times 3$  convolution, stride 1 pad 1



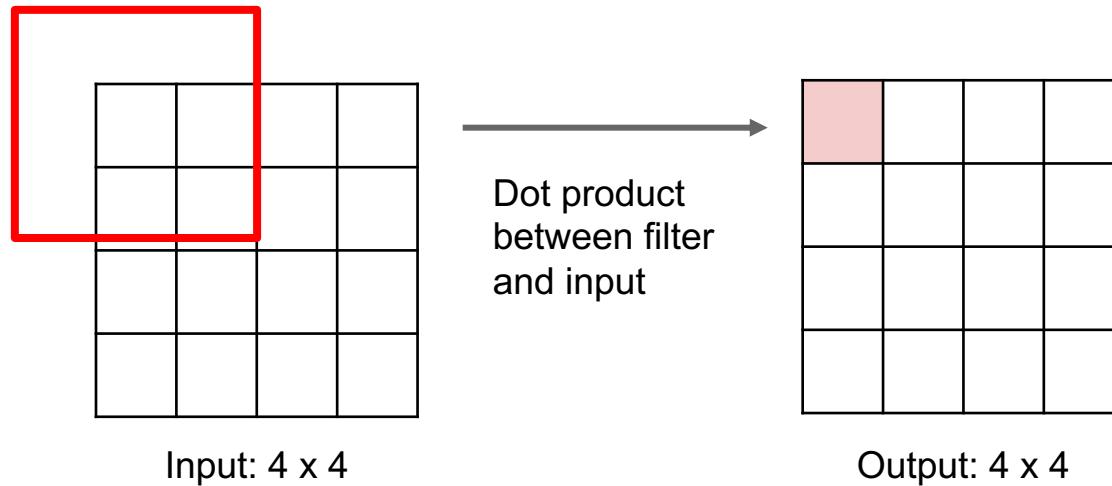
Input:  $4 \times 4$



Output:  $4 \times 4$

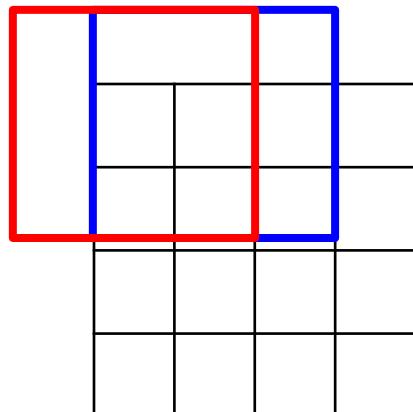
# Learnable Upsampling

**Recall:** Normal  $3 \times 3$  convolution, stride 1 pad 1



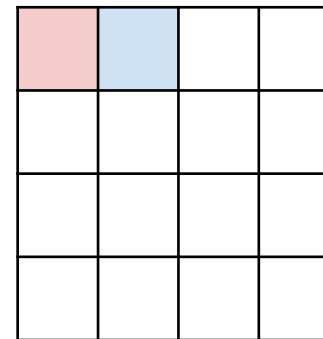
# Learnable Upsampling

**Recall:** Normal  $3 \times 3$  convolution, stride 1 pad 1



Input:  $4 \times 4$

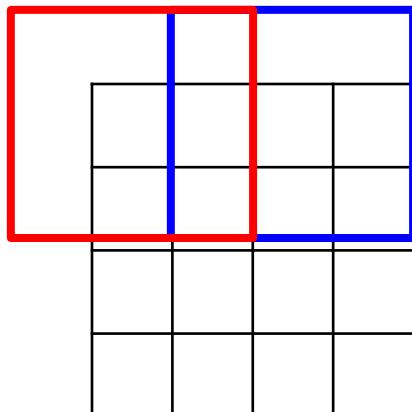
Dot product  
between filter  
and input



Output:  $4 \times 4$

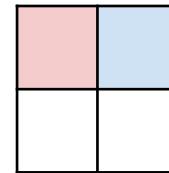
# Learnable Upsampling

**Recall:** Normal  $3 \times 3$  convolution, stride 2 pad 1



Input:  $4 \times 4$

Dot product  
between filter  
and input



Output:  $2 \times 2$

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: Transposed Convolution

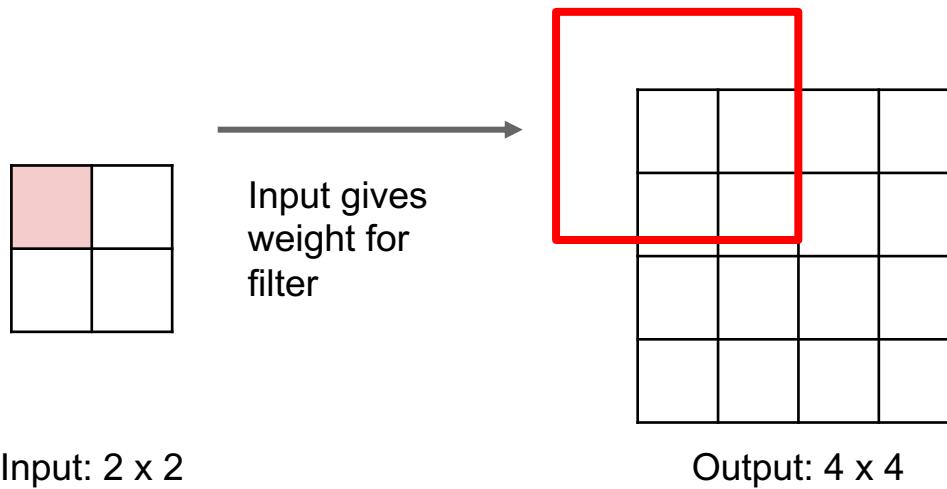
$3 \times 3$  **transpose** convolution, stride 2 pad 1


Input:  $2 \times 2$


Output:  $4 \times 4$

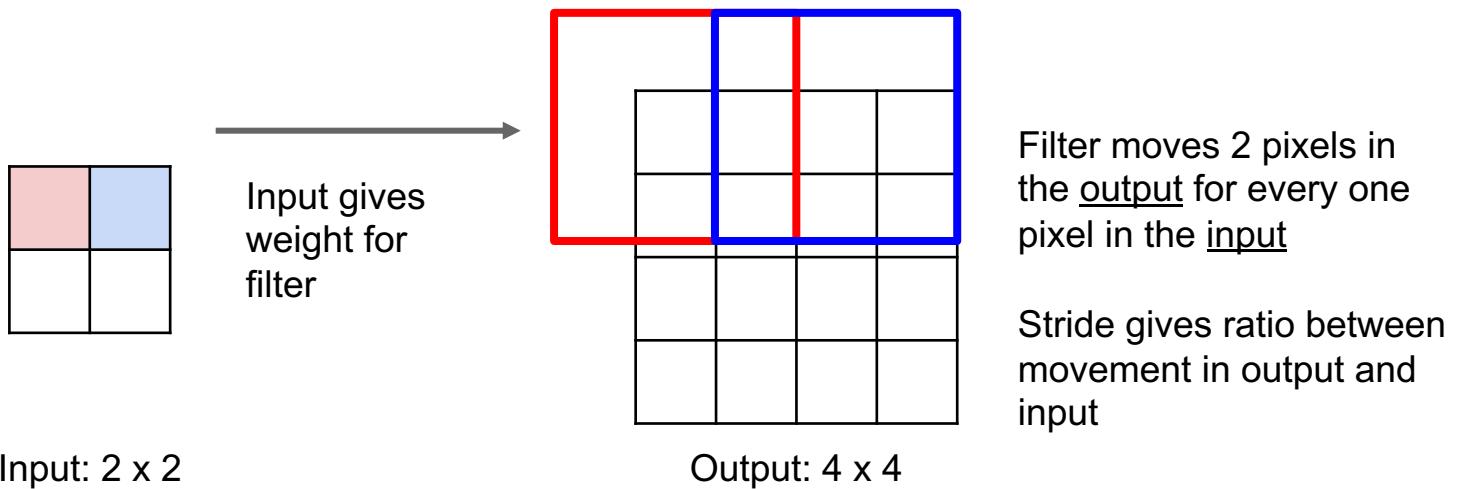
# Learnable Upsampling: Transposed Convolution

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



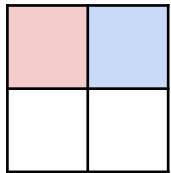
# Learnable Upsampling: Transposed Convolution

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



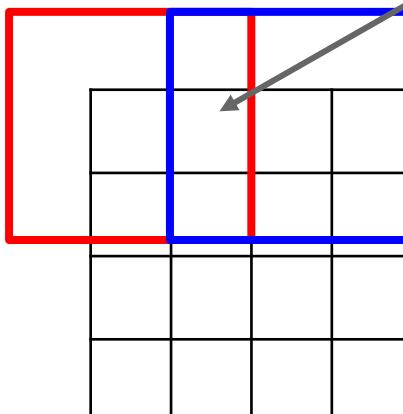
# Learnable Upsampling: Transposed Convolution

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



Input gives weight for filter

Input: 2 x 2



Output: 4 x 4

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

Stride gives ratio between movement in output and input

Sum where output overlaps

# Semantic Segmentation Idea: Fully Convolutional

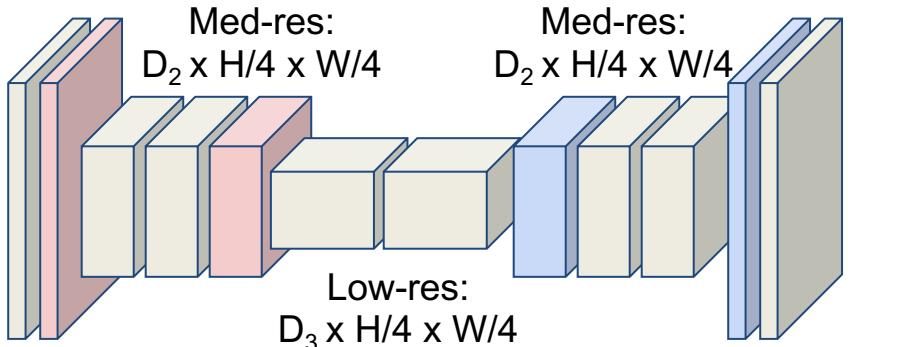
**Downsampling:**  
Pooling, strided convolution



Input:  
 $3 \times H \times W$

High-res:  
 $D_1 \times H/2 \times W/2$

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



High-res:  
 $D_1 \times H/2 \times W/2$

**Upsampling:**  
Unpooling or strided transpose convolution

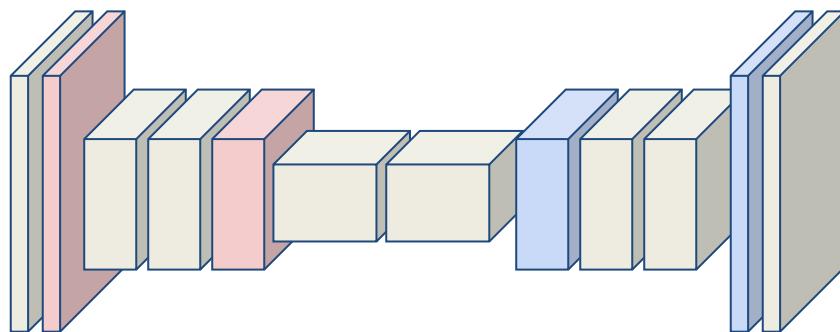
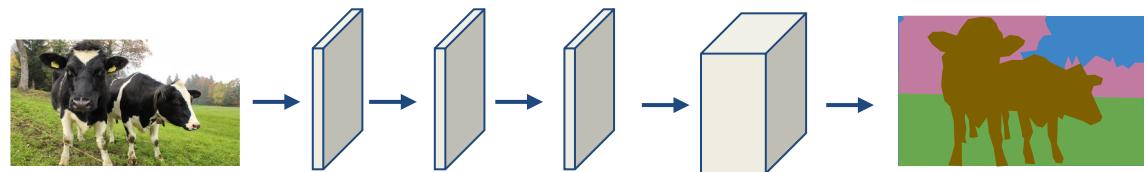
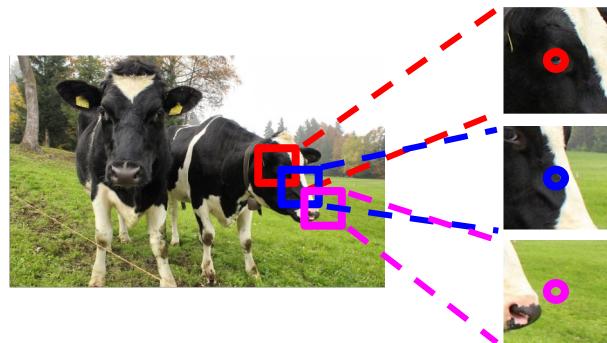


Predictions:  
 $H \times W$

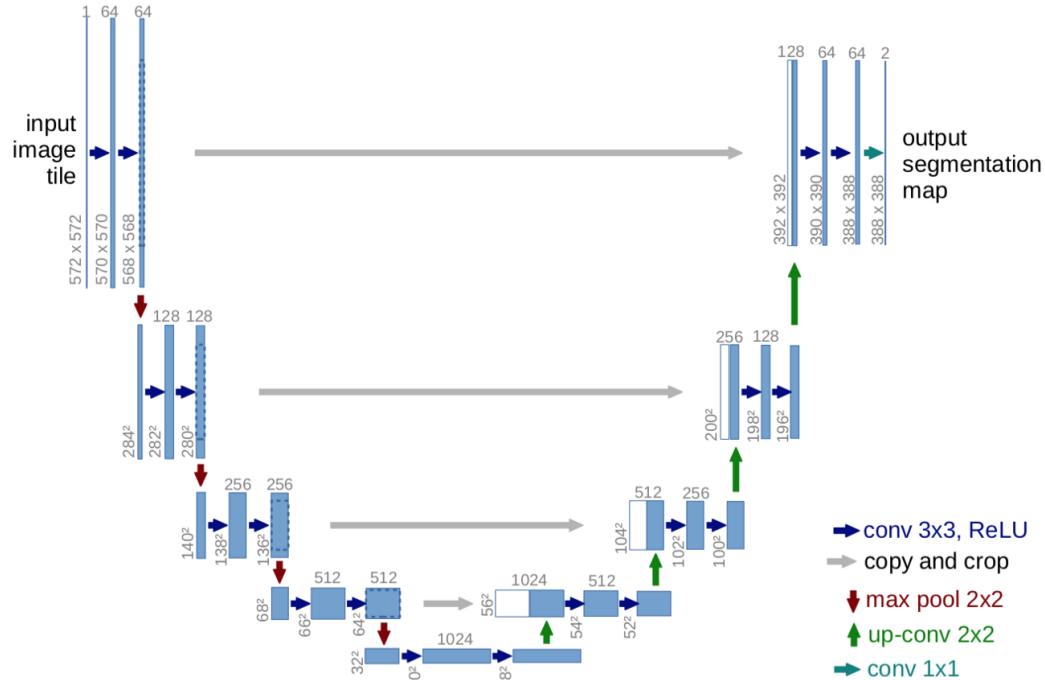
Long, Shelhamer, and Darrell, "Fully Convolutional Networks for Semantic Segmentation", CVPR 2015

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

# Semantic Segmentation: Summary



# Semantic Segmentation: U-Net



Idea: Concatenate feature maps from the downsampling stage with the features in the upsampling stage.

Very commonly used today!

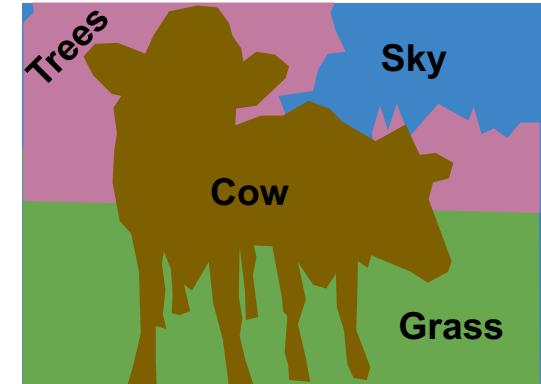
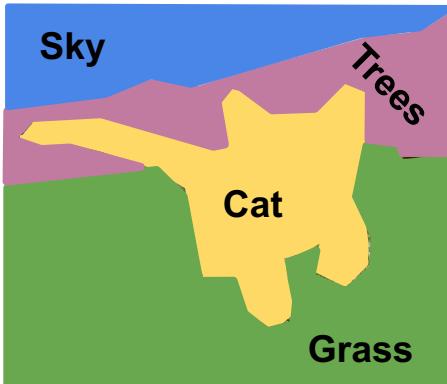
# Semantic Segmentation

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

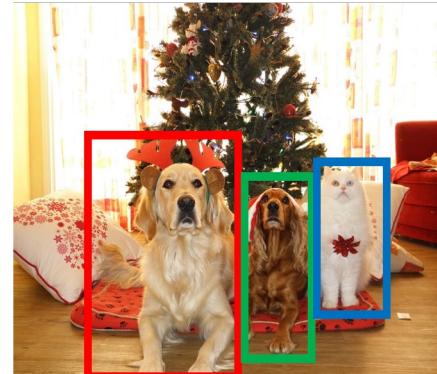
Semantic Segmentation



GRASS, CAT,  
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No objects, just pixels

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DOG, DOG, CAT

Instance  
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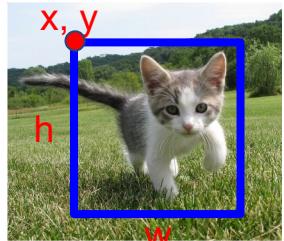


DOG, DOG, CAT

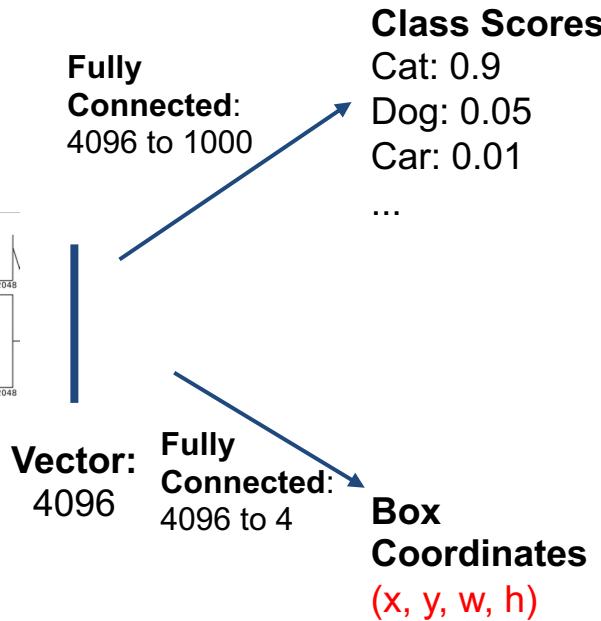
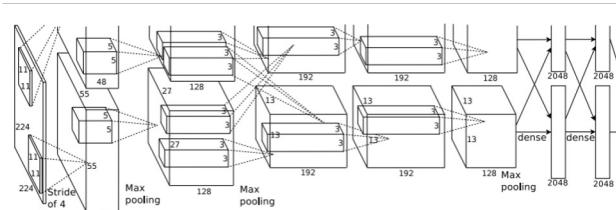
Multiple Object

# Object Detection: Single Object

(Classification + Localization)

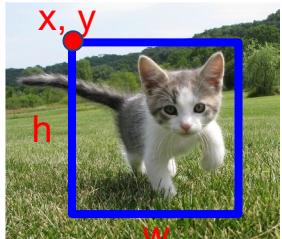


This image is [CC0 public domain](#)

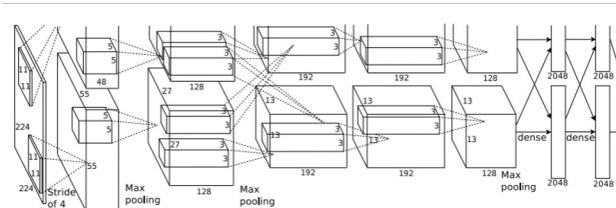


# Object Detection: Single Object

(Classification + Localization)



This image is CC0 public domain



**Vector:**  
4096  
Fully Connected:  
4096 to 4

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

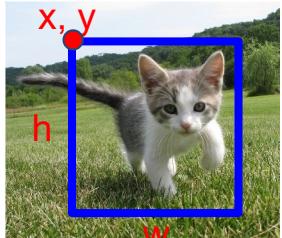
**Box Coordinates**  $\rightarrow$  **L2 Loss**  
( $x, y, w, h$ )  
  
**Correct box:**  
( $x', y', w', h'$ )

**Correct label:**  
Cat  
  
**Softmax Loss**

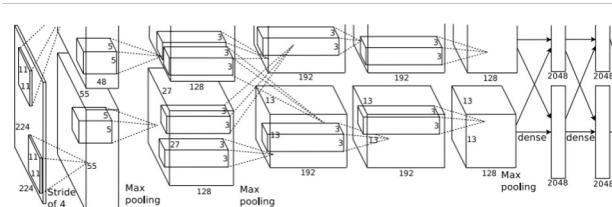
Treat localization as a  
regression problem!

# Object Detection: Single Object

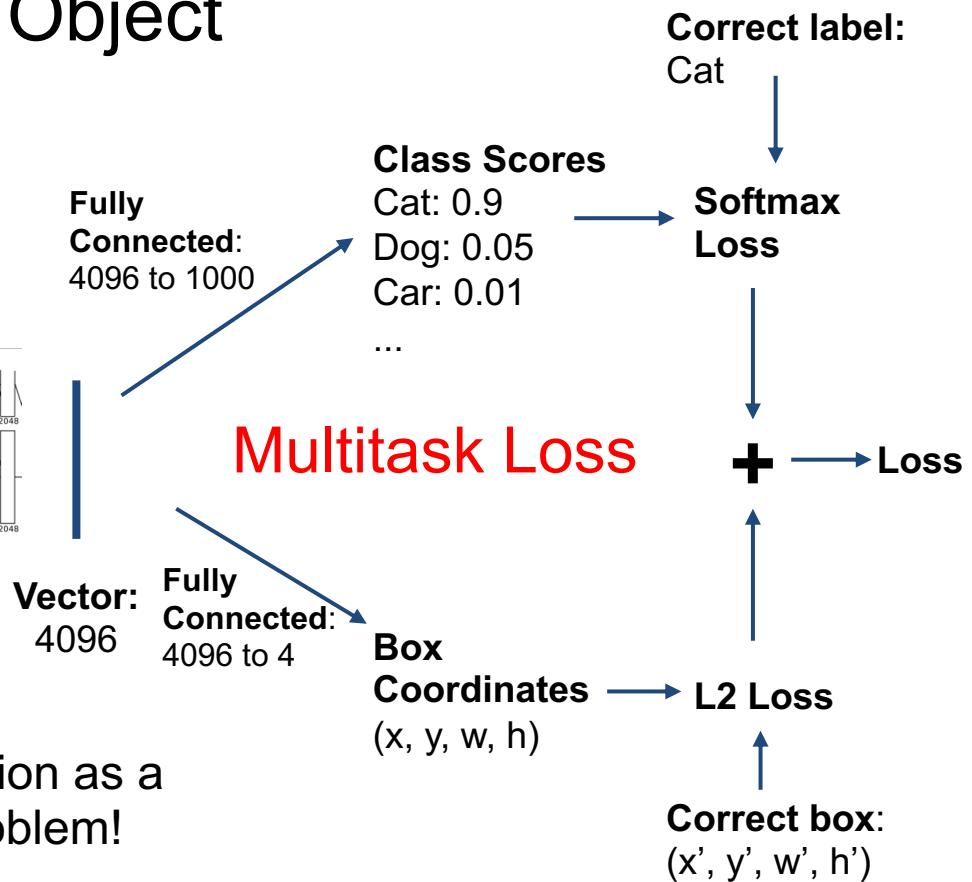
(Classification + Localization)



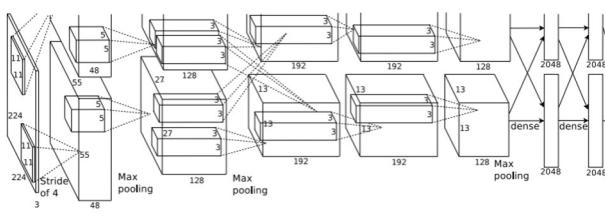
This image is CC0 public domain



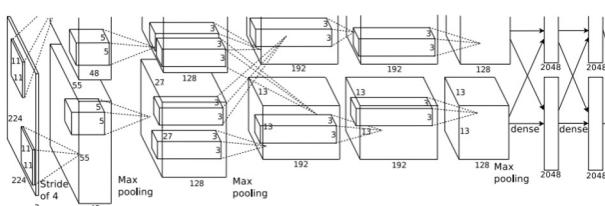
Treat localization as a  
regression problem!



# Object Detection: Multiple Objects



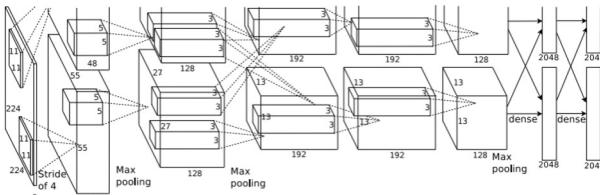
CAT: (x, y, w, h)



DOG: (x, y, w, h)

DOG: (x, y, w, h)

CAT: (x, y, w, h)



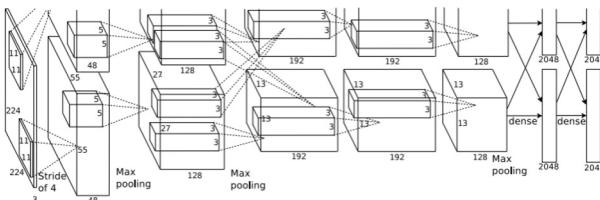
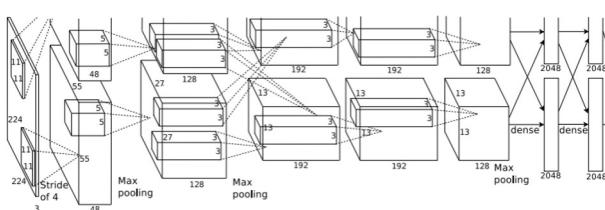
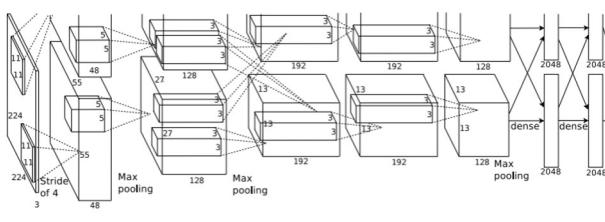
DUCK: (x, y, w, h)

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)

12 numbers

CAT: (x, y, w, h)

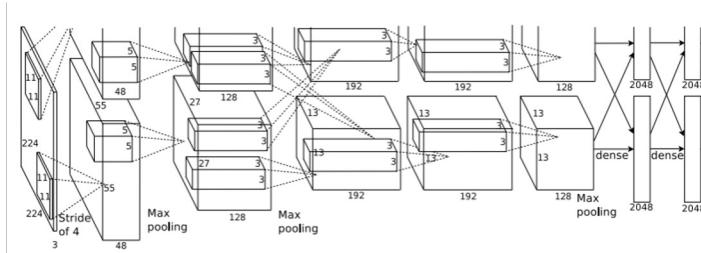
DUCK: (x, y, w, h)

Many  
numbers!

• • •

# Object Detection: Multiple Objects

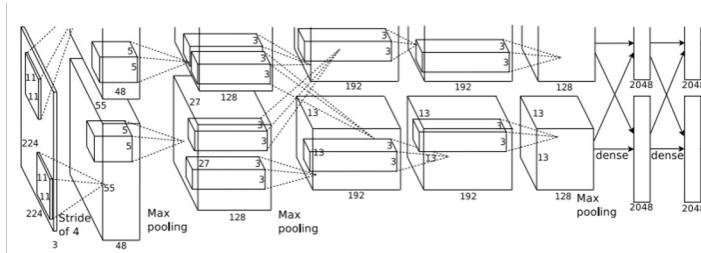
Apply a CNN to many different crops of the image, CNN classifies each crop as object or background



Dog? NO  
Cat? NO  
Background? YES

# Object Detection: Multiple Objects

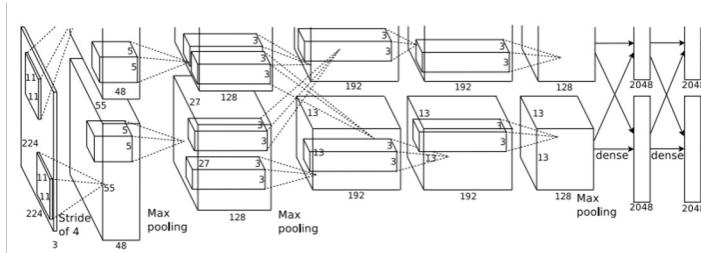
Apply a CNN to many different crops of the image, CNN classifies each crop as object or background



Dog? YES  
Cat? NO  
Background? NO

# Object Detection: Multiple Objects

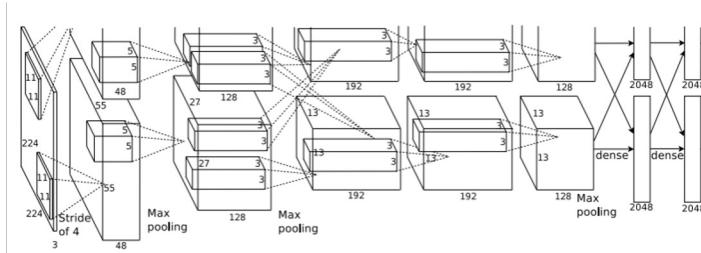
Apply a CNN to many different crops of the image, CNN classifies each crop as object or background



Dog? YES  
Cat? NO  
Background? NO

# Object Detection: Multiple Objects

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

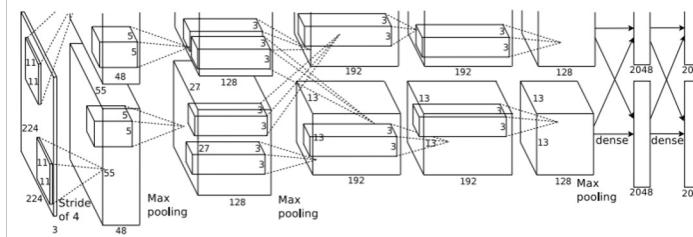
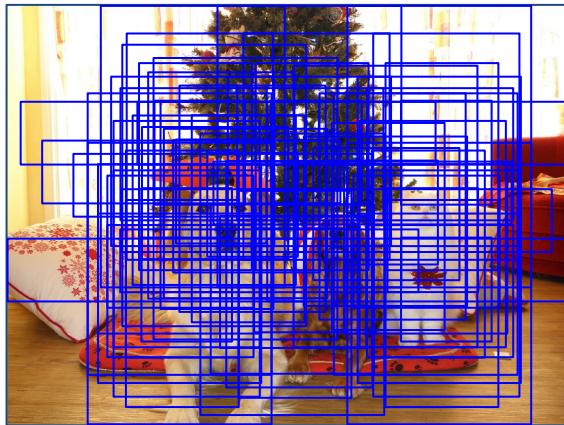


Dog? NO  
Cat? YES  
Background? NO

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



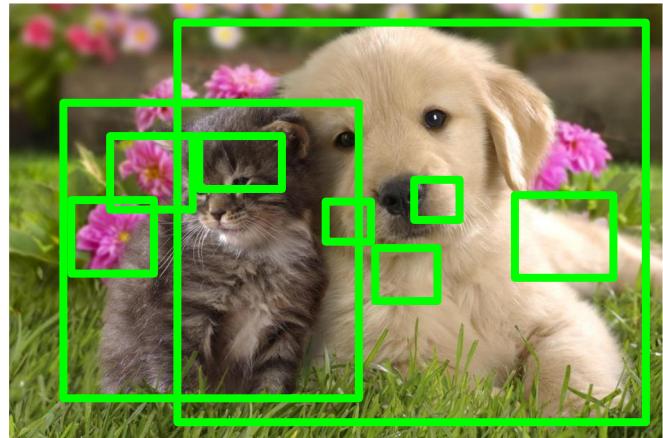
Dog? NO  
Cat? YES  
Background? NO

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

Need to find **promising regions**

# 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

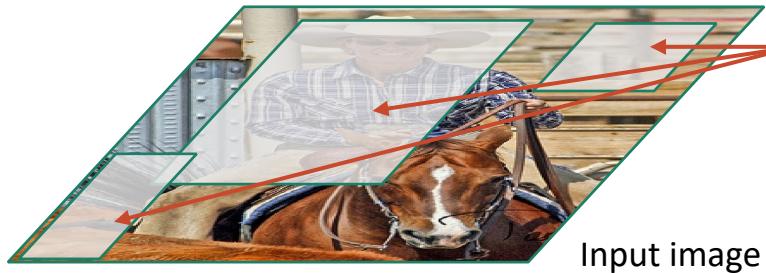


Input image

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

Figure copyright Ross Girshick, 2015; [source](#). Reproduced with permission.

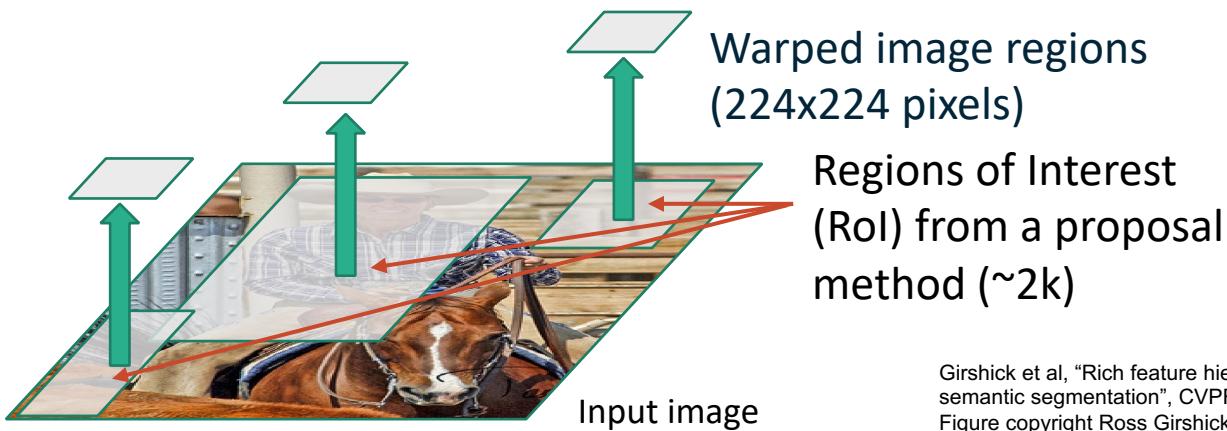
# R-CNN



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

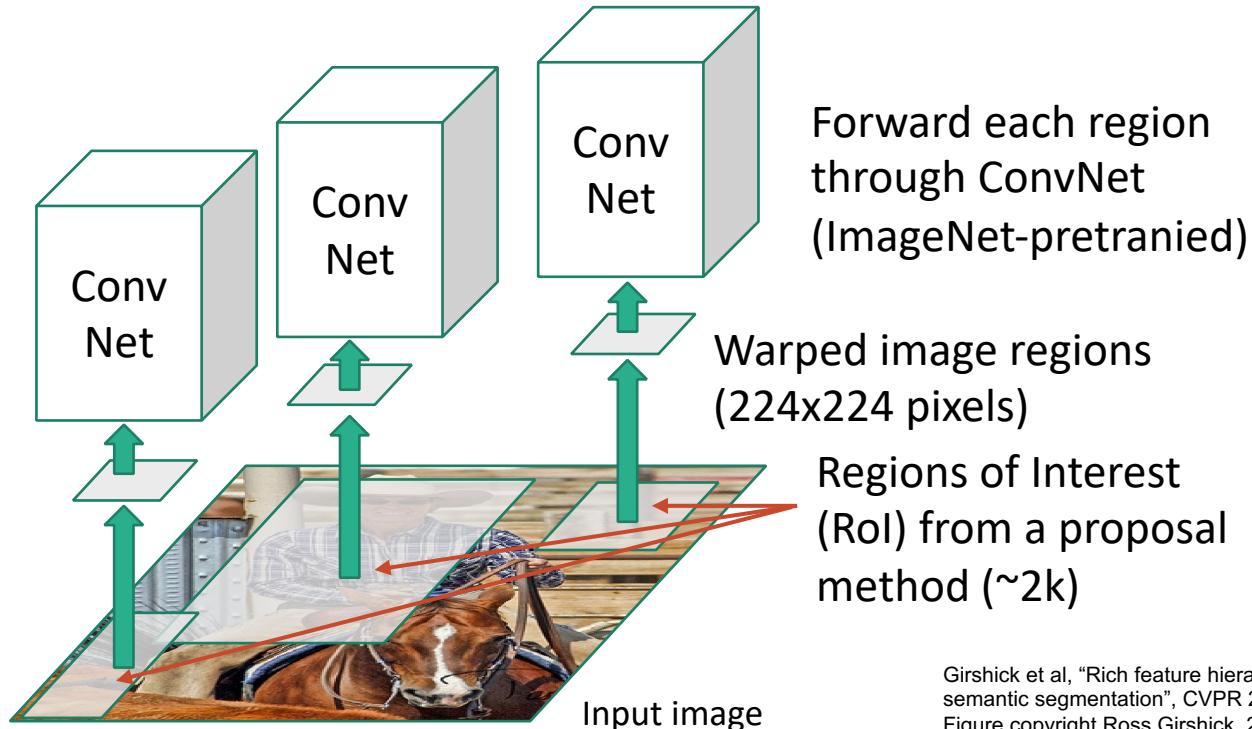
Girshick et al, “Rich feature hierarchies for accurate object detection and semantic segmentation”, CVPR 2014.  
Figure copyright Ross Girshick, 2015; [source](#). Reproduced with permission.

# R-CNN



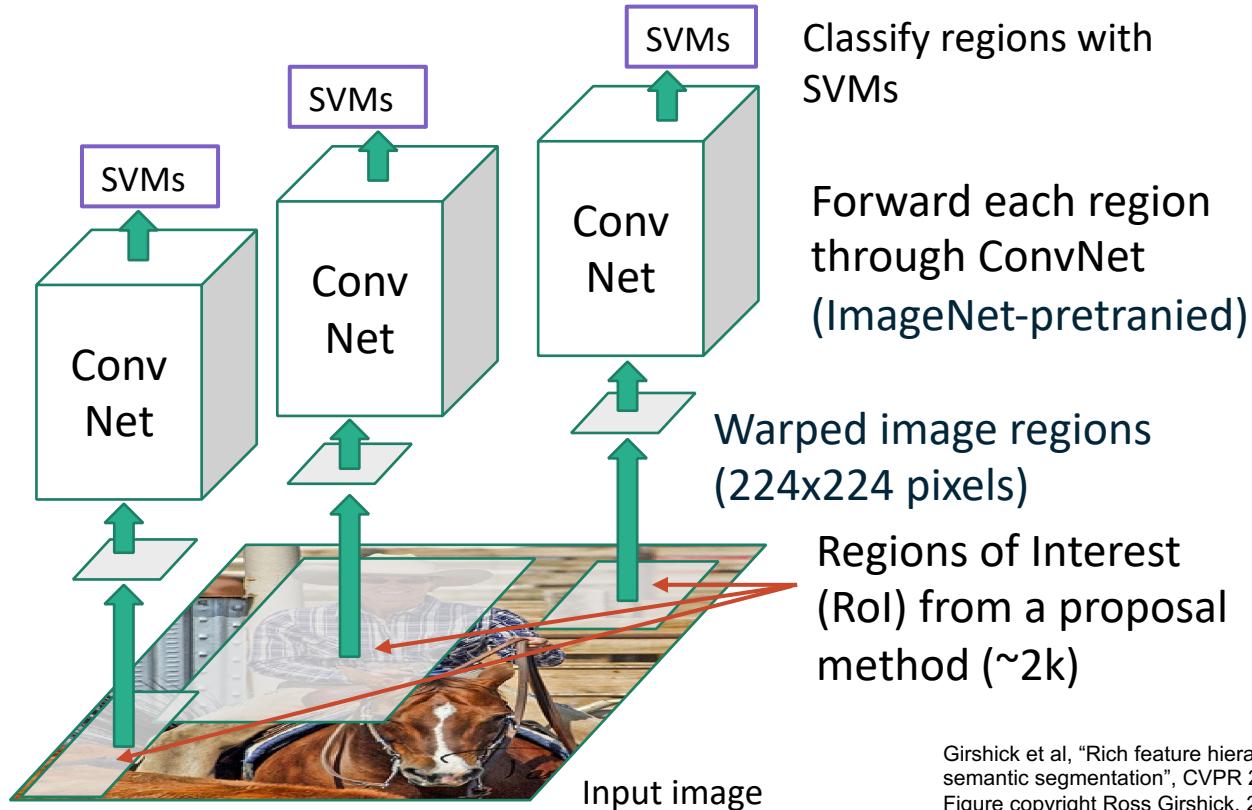
Girshick et al, “Rich feature hierarchies for accurate object detection and semantic segmentation”, CVPR 2014.  
Figure copyright Ross Girshick, 2015; [source](#). Reproduced with permission.

# 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

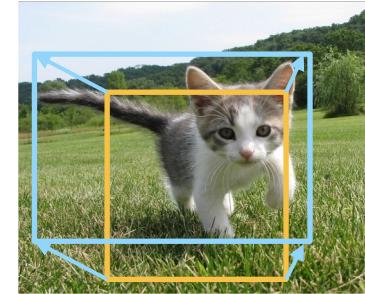
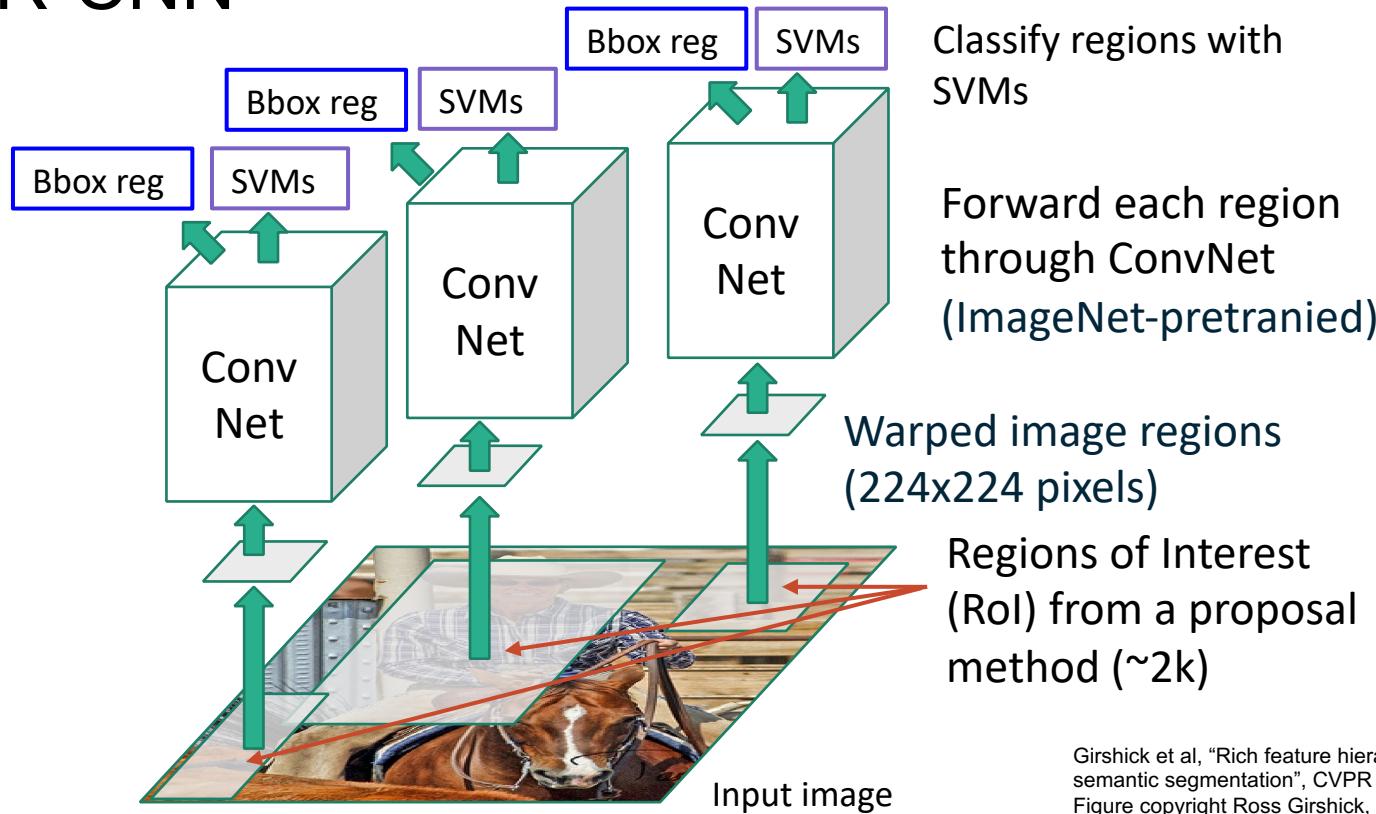


Girshick et al, "Rich feature hierarchies for accurate object detection and semantic segmentation", CVPR 2014.

Figure copyright Ross Girshick, 2015; [source](#). Reproduced with permission.

# R-CNN

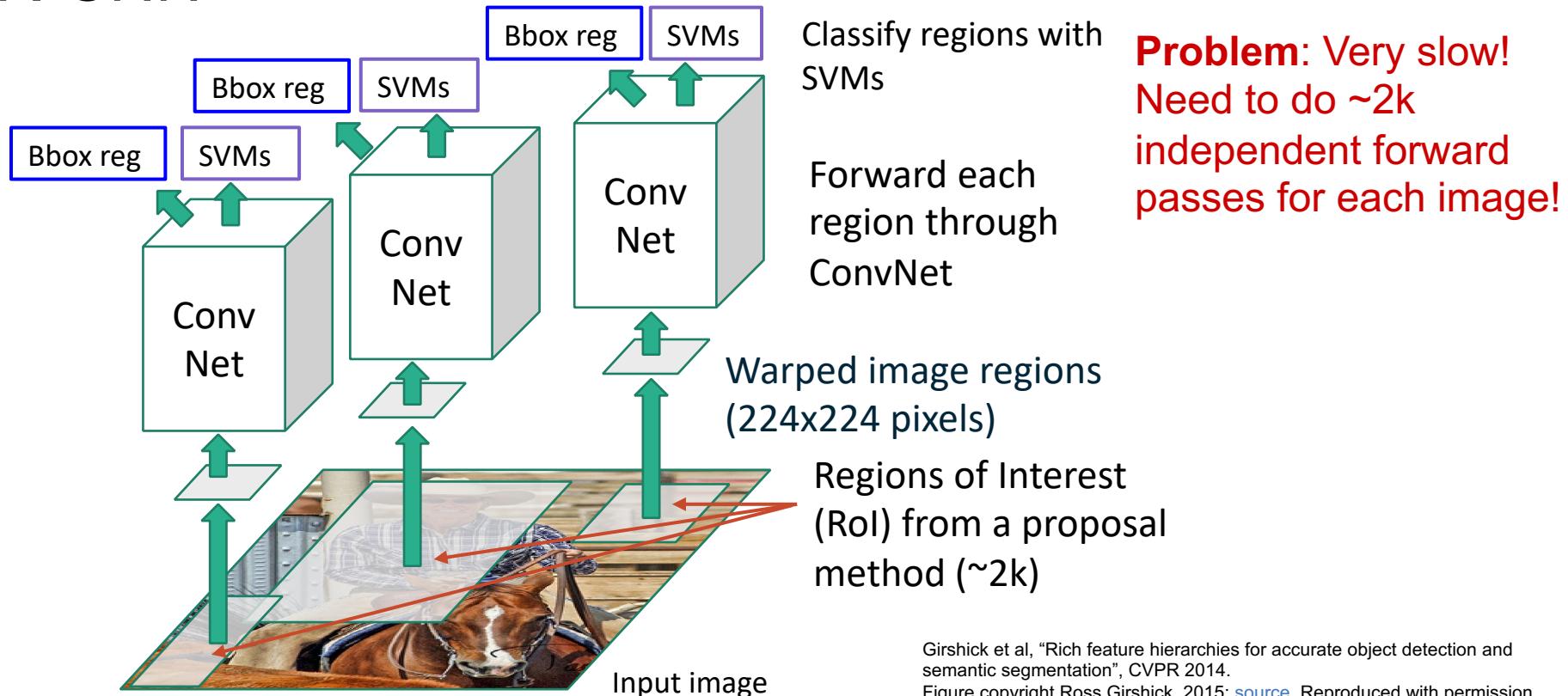
Predict “**corrections**” to the RoI: 4 numbers: (dx, dy, dw, dh)



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)

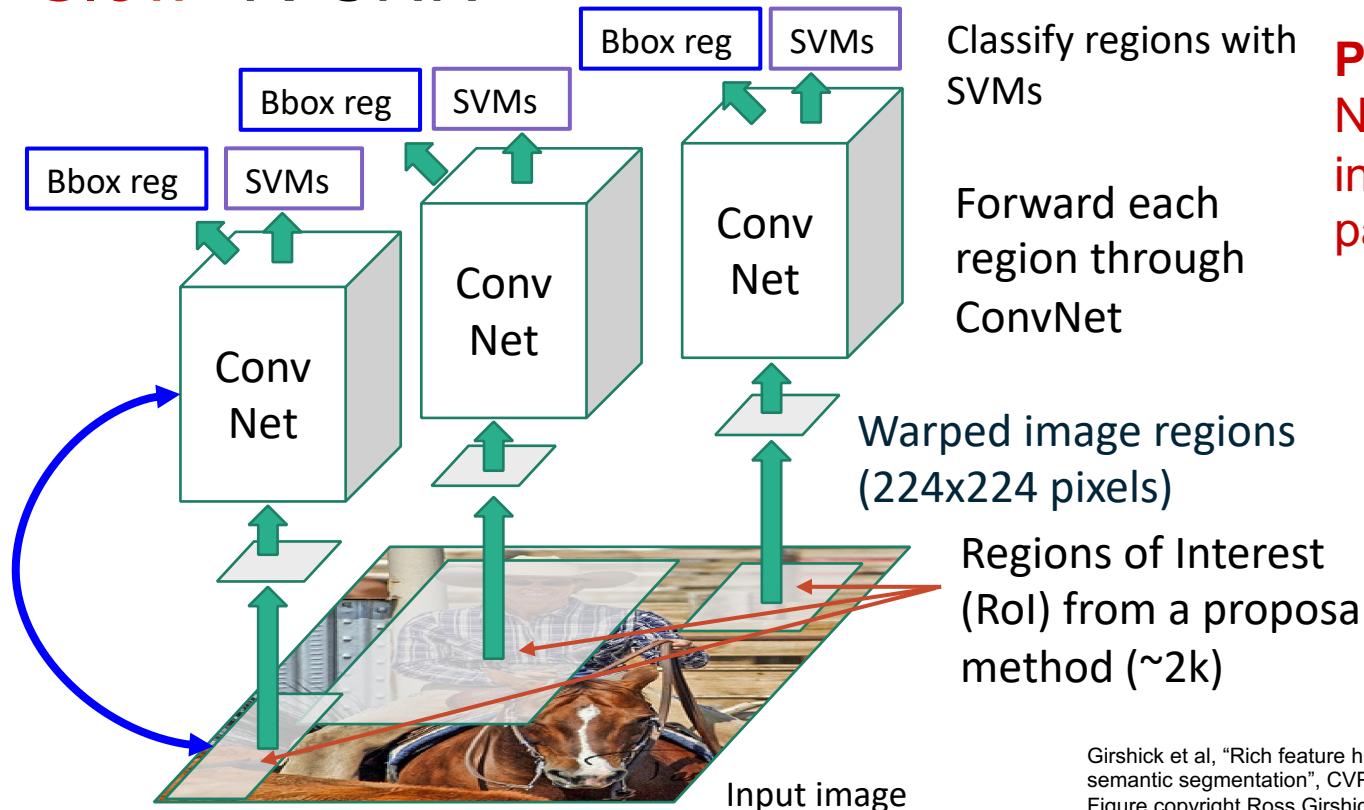


Girshick et al, “Rich feature hierarchies for accurate object detection and semantic segmentation”, CVPR 2014.

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.

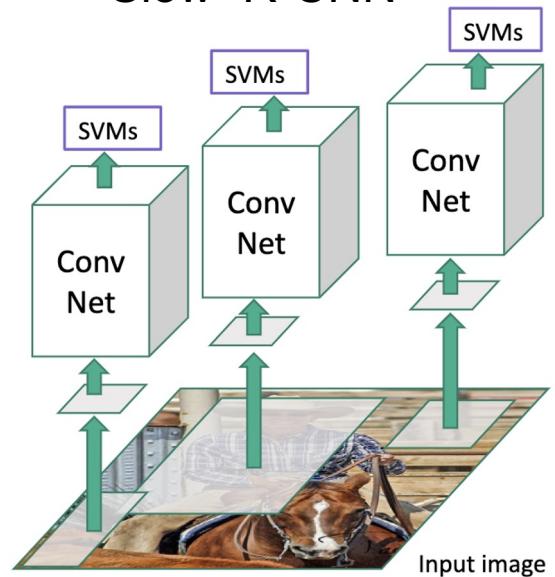
Figure copyright Ross Girshick, 2015; [source](#). Reproduced with permission.

# Fast R-CNN



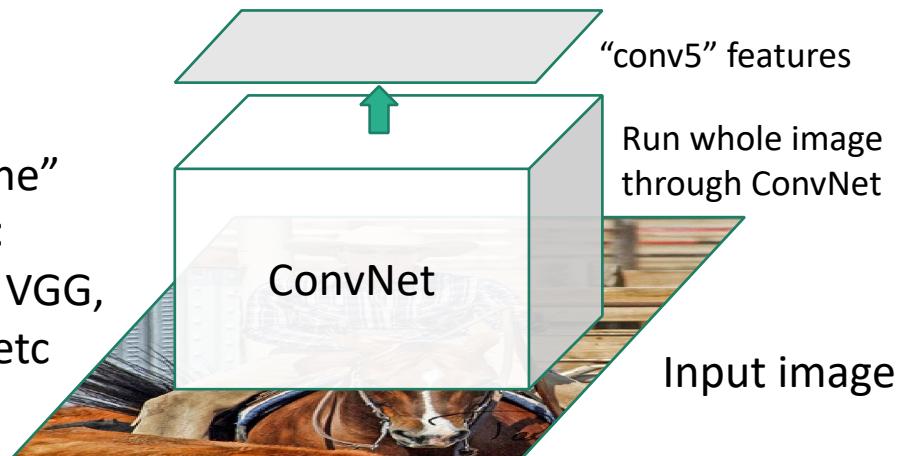
Input image

## “Slow” R-CNN



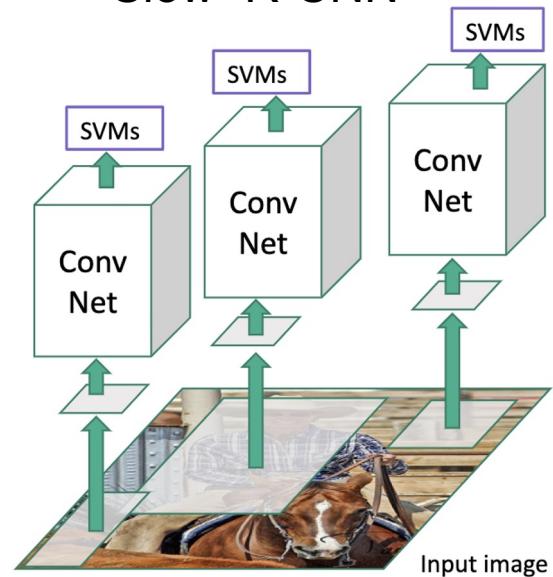
# Fast R-CNN

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

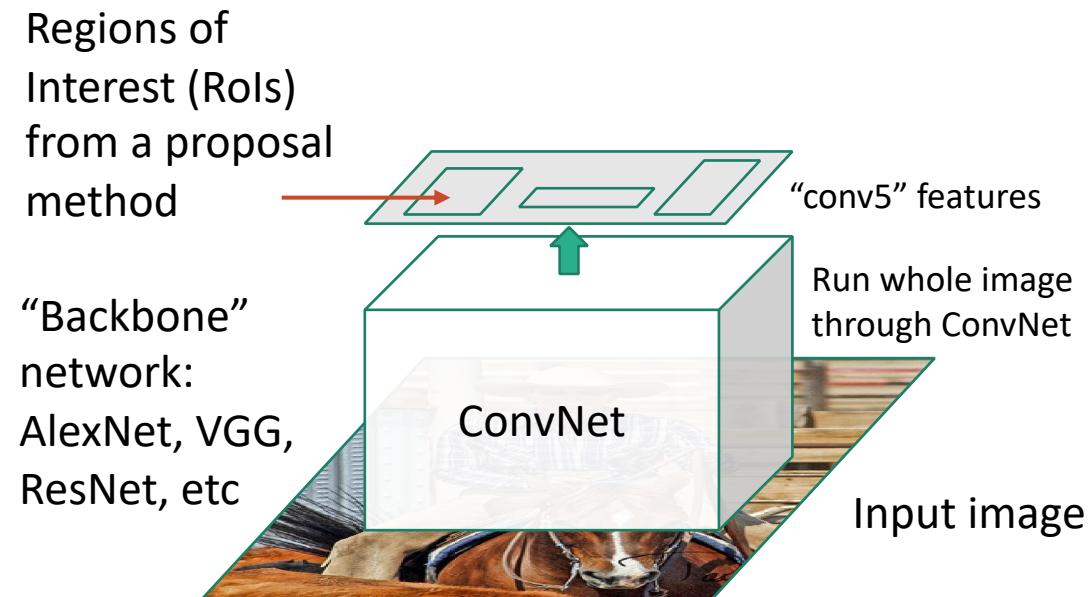


Girshick, “Fast R-CNN”, ICCV 2015. Figure copyright Ross Girshick, 2015; [source](#). Reproduced with permission.

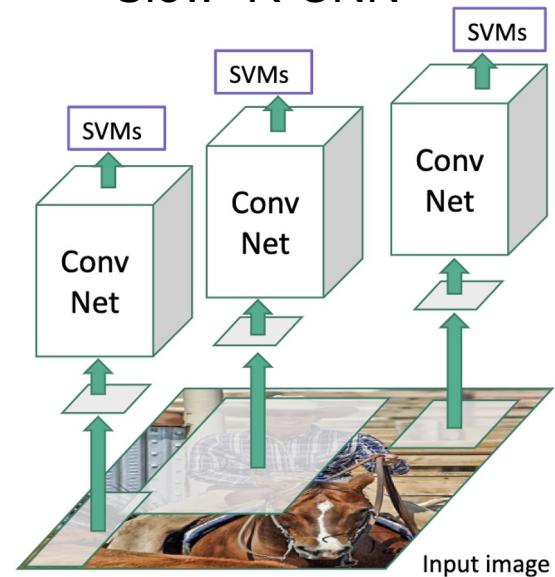
## “Slow” R-CNN



# Fast R-CNN



## “Slow” R-CNN

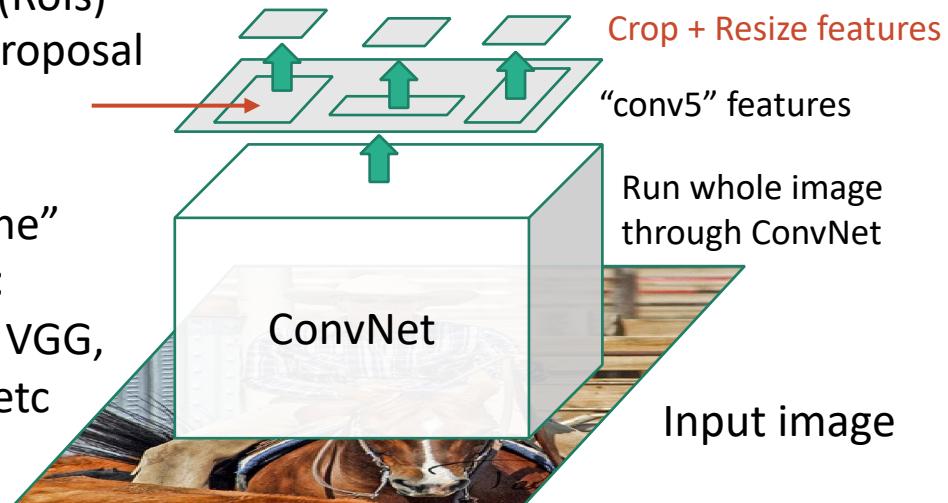


Girshick, “Fast R-CNN”, ICCV 2015. Figure copyright Ross Girshick, 2015; [source](#). Reproduced with permission.

# Fast R-CNN

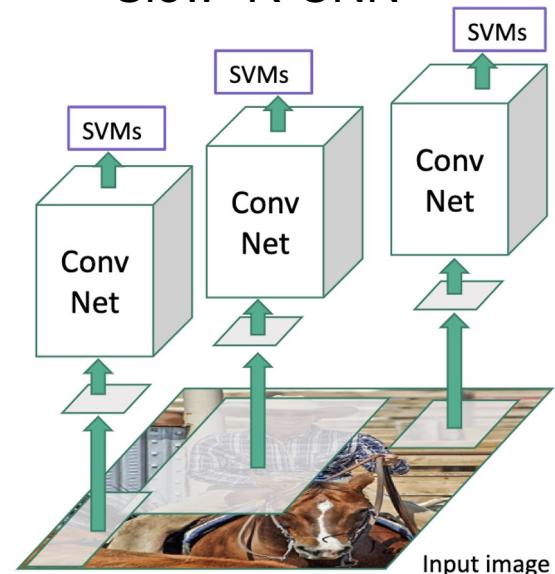
Regions of Interest (RoIs) from a proposal method

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

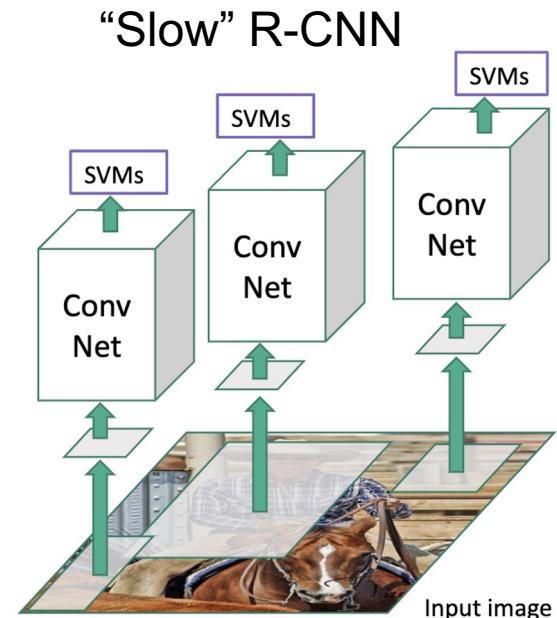
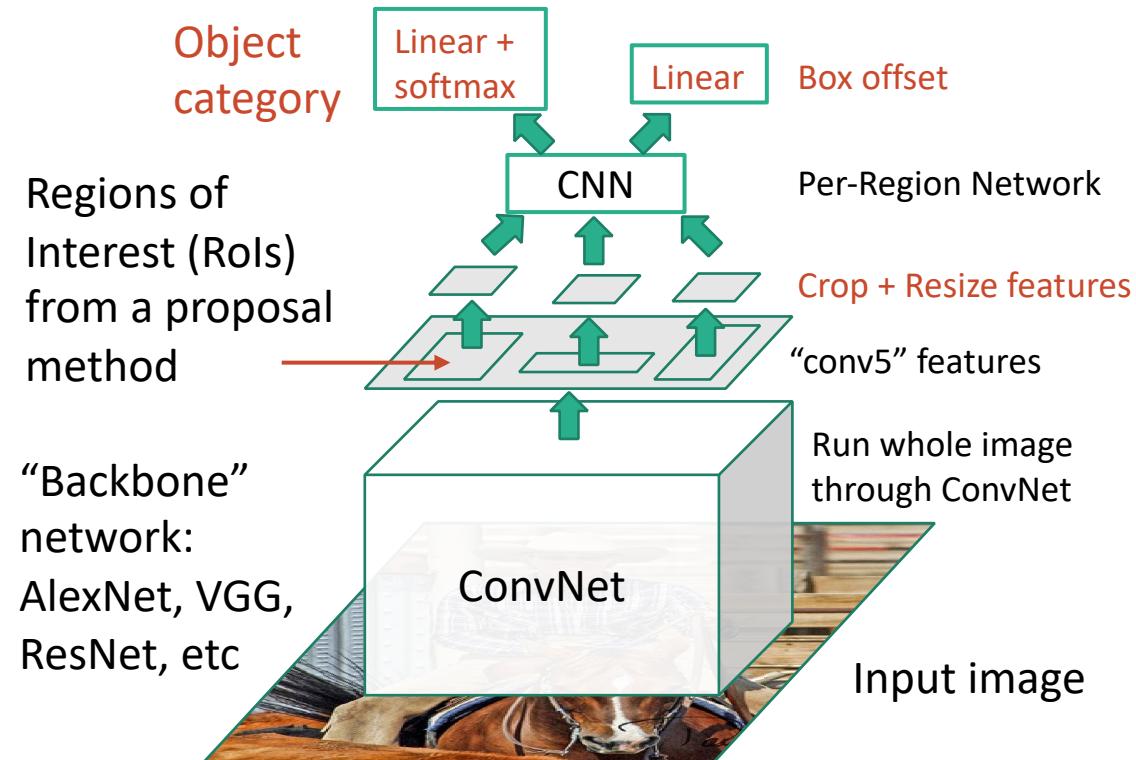


Girshick, “Fast R-CNN”, ICCV 2015. Figure copyright Ross Girshick, 2015; [source](#). Reproduced with permission.

## “Slow” R-CNN

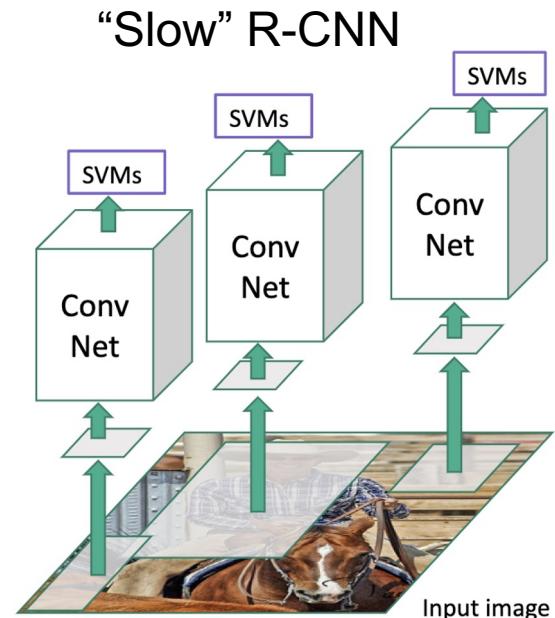
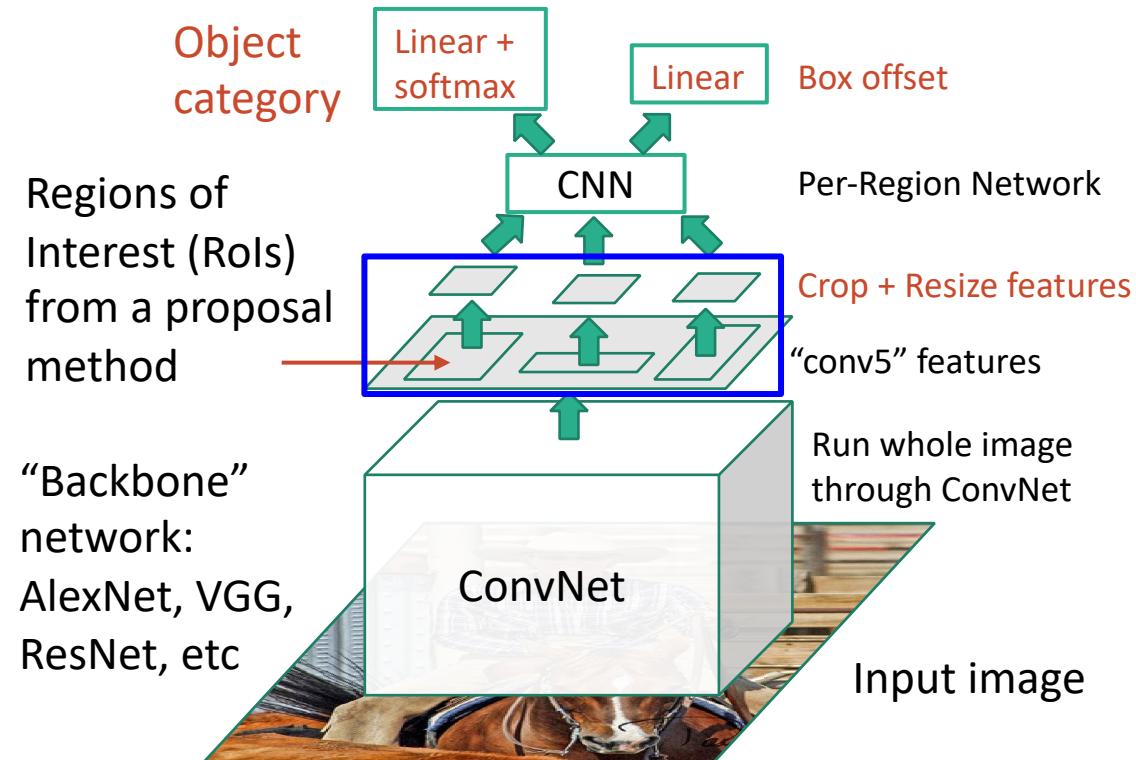


# Fast R-CNN



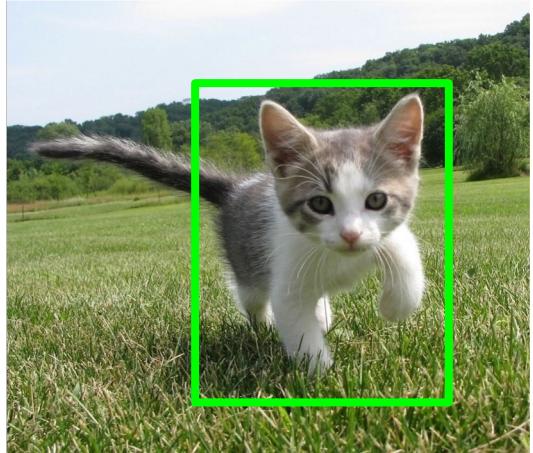
Girshick, “Fast R-CNN”, ICCV 2015. Figure copyright Ross Girshick, 2015; [source](#). Reproduced with permission.

# 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.  $3 \times 640 \times 480$ )

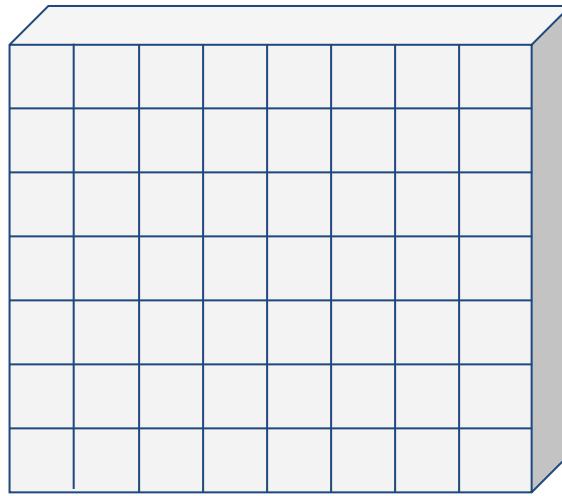
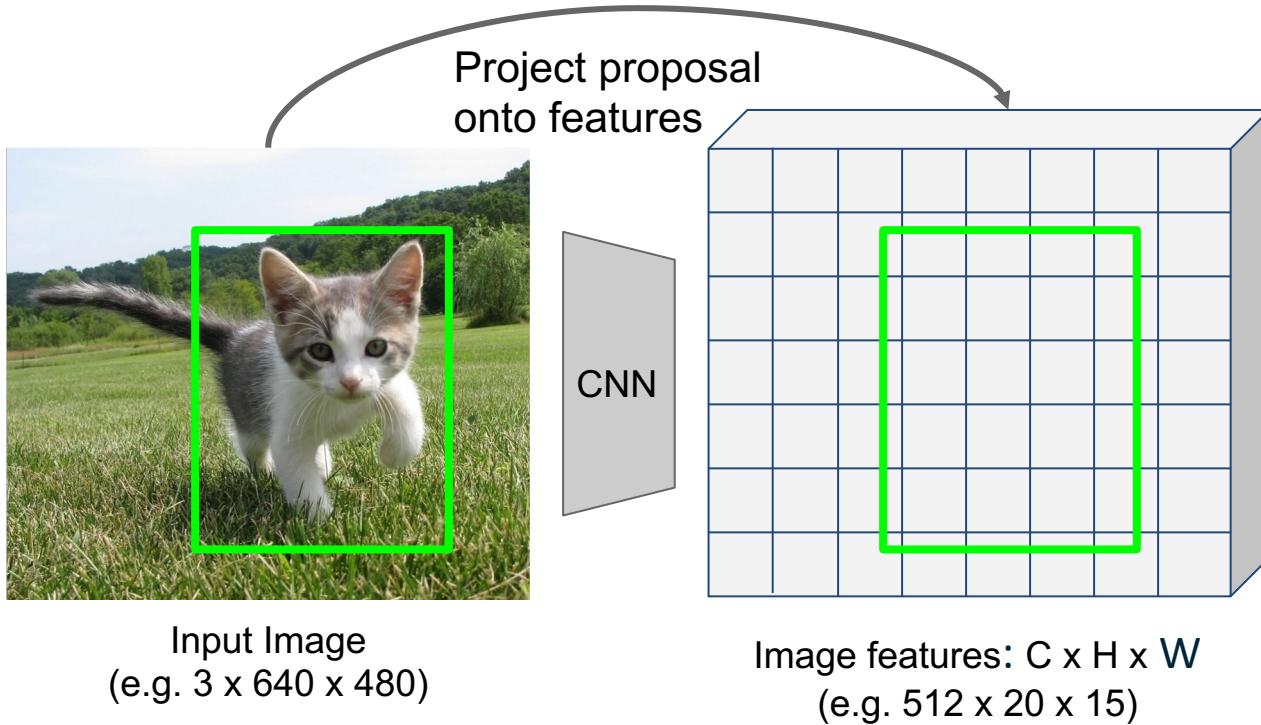
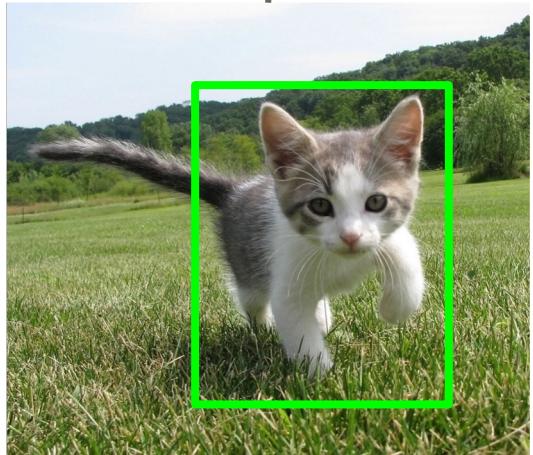


Image features:  $C \times H \times W$   
(e.g.  $512 \times 20 \times 15$ )

# Cropping Features: RoI Pool

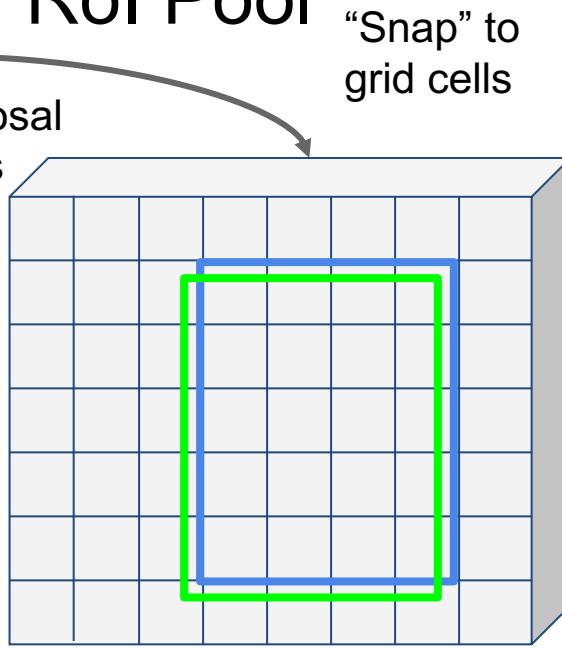


# Cropping Features: RoI Pool

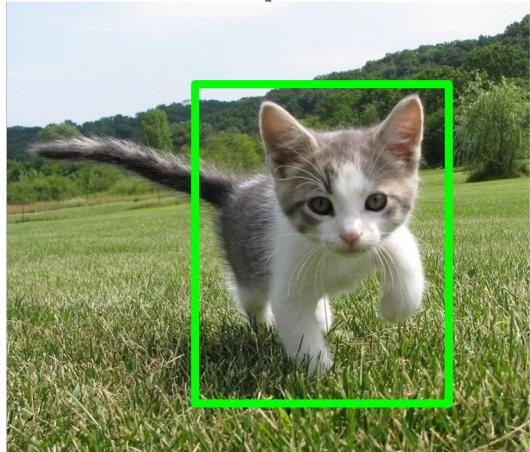


Input Image  
(e.g.  $3 \times 640 \times 480$ )

Project proposal  
onto features



# Cropping Features: RoI Pool



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

Project proposal  
onto features

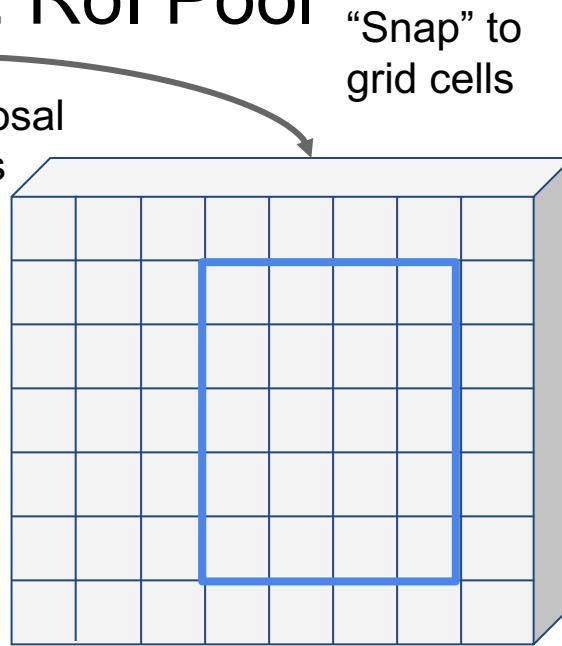
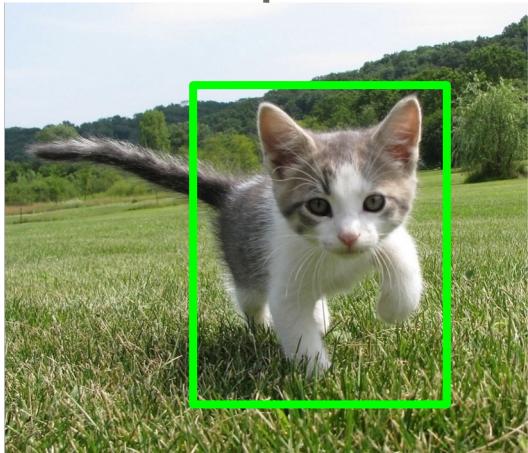


Image features:  $C \times H \times W$   
(e.g.  $512 \times 20 \times 15$ )

“Snap” to  
grid cells

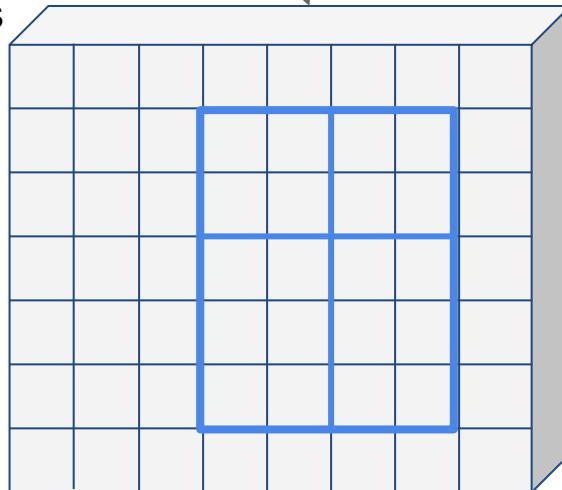
Q: how do we resize the  $512 \times 20 \times 15$  region to, e.g., a  $512 \times 2 \times 2$  tensor?

# Cropping Features: RoI Pool



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

Project proposal  
onto features



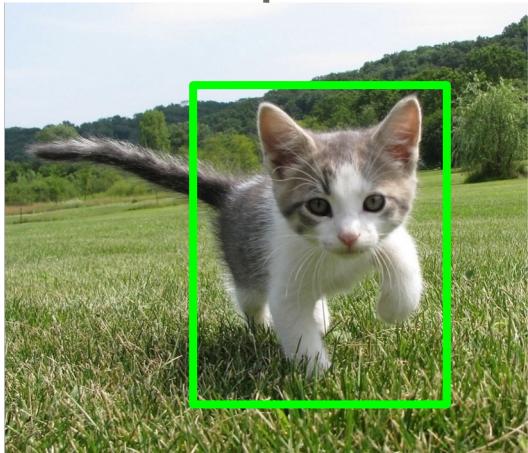
“Snap” to  
grid cells

Divide into  $2 \times 2$   
grid of (roughly)  
equal subregions

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

Image features:  $C \times H \times W$   
(e.g.  $512 \times 20 \times 15$ )

# Cropping Features: RoI Pool



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

Project proposal  
onto features

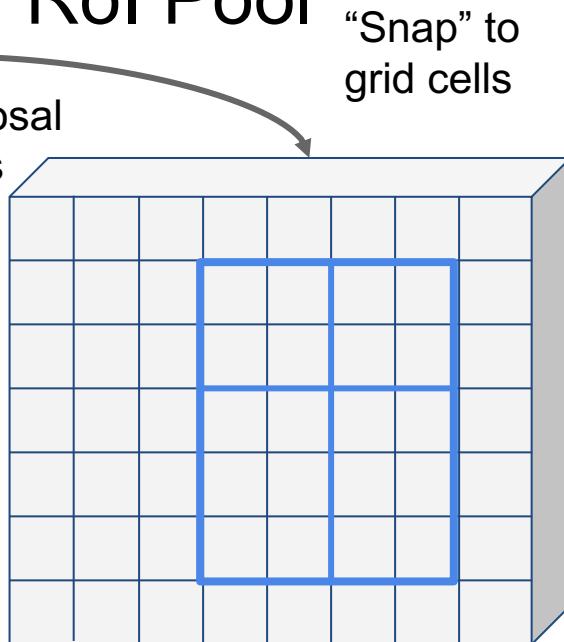
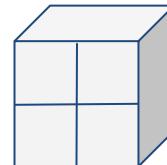


Image features:  $C \times H \times W$   
(e.g.  $512 \times 20 \times 15$ )

“Snap” to  
grid cells

Divide into  $2 \times 2$   
grid of (roughly)  
equal subregions

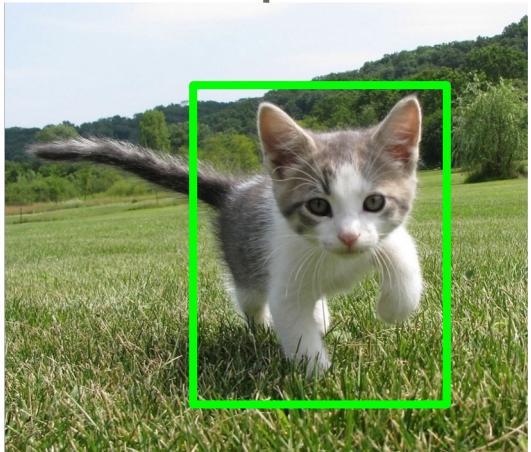
Max-pool within  
each subregion



Region features  
(here  $512 \times 2 \times 2$ ;  
In practice e.g.  $512 \times 7 \times 7$ )

Region features always the  
same size even if input  
regions have different sizes!

# Cropping Features: RoI Pool



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

Project proposal  
onto features

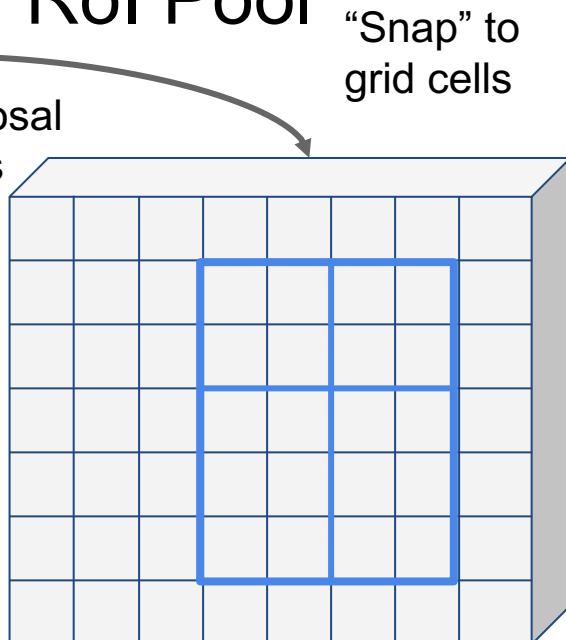
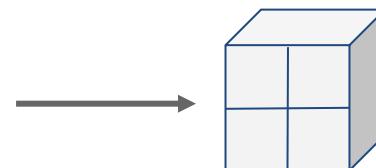


Image features:  $C \times H \times W$   
(e.g.  $512 \times 20 \times 15$ )

“Snap” to  
grid cells  
Divide into  $2 \times 2$   
grid of (roughly)  
equal subregions

Max-pool within  
each subregion

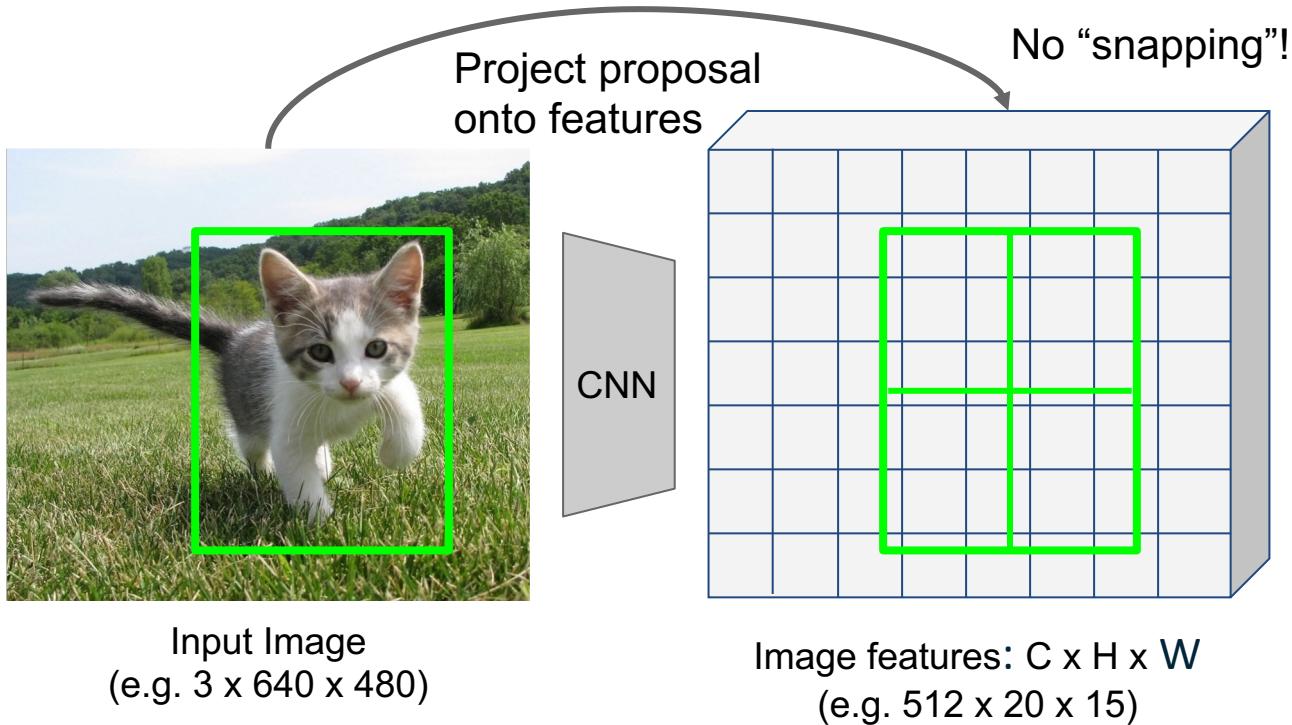


Region features  
(here  $512 \times 2 \times 2$ ;  
In practice e.g.  $512 \times 7 \times 7$ )

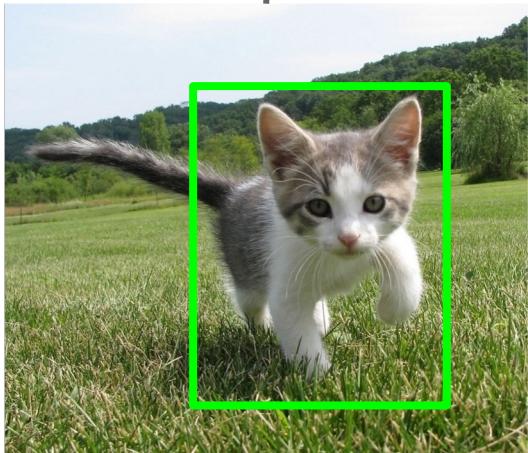
Region features always the  
same size even if input  
regions have different sizes!

**Problem:** Region features slightly misaligned

# Cropping Features: RoI Align



# Cropping Features: RoI Align



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

Project proposal  
onto features



No “snapping”!

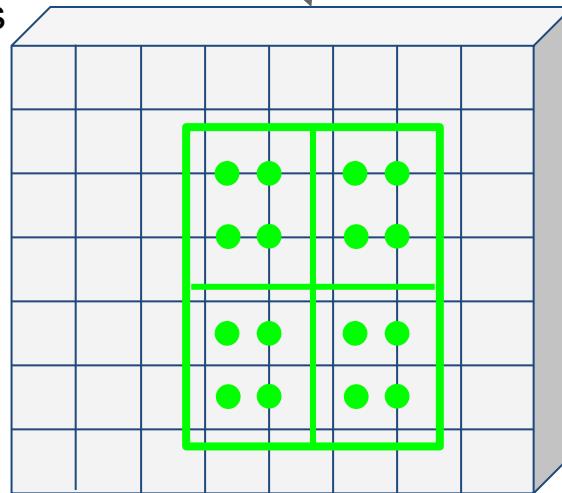
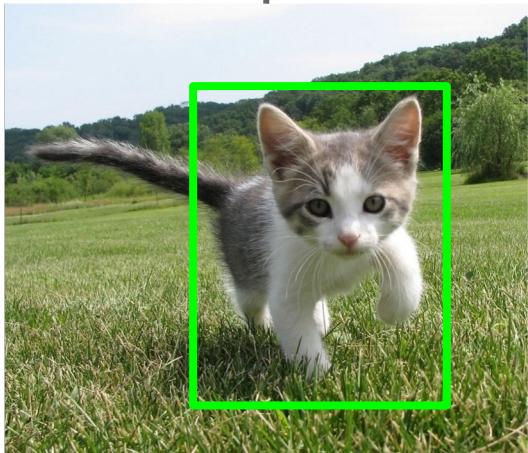


Image features:  $C \times H \times W$   
(e.g.  $512 \times 20 \times 15$ )

Sample at regular points  
in each subregion using  
[bilinear interpolation](#)

# Cropping Features: RoI Align



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

Project proposal  
onto features



No “snapping”!

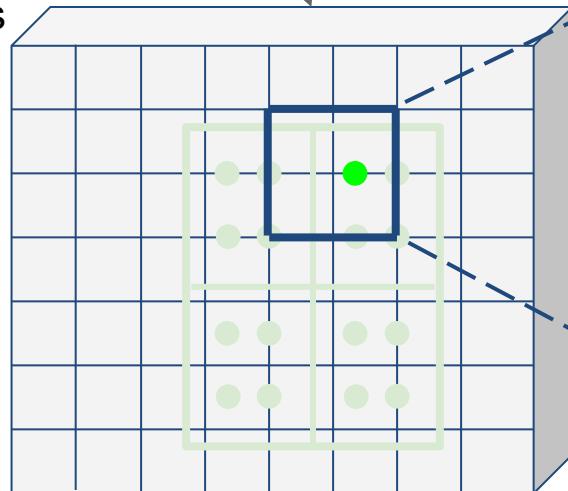
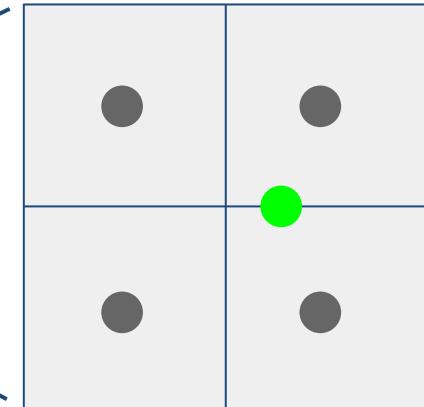


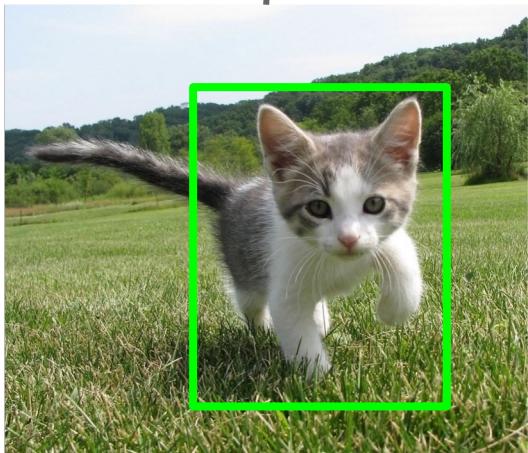
Image features:  $C \times H \times W$   
(e.g.  $512 \times 20 \times 15$ )

Sample at regular points  
in each subregion using  
**bilinear interpolation**



Feature  $f_{xy}$  for point  $(x, y)$   
is a linear combination of  
features at its four  
neighboring grid cells:

# Cropping Features: RoI Align



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

Project proposal  
onto features



No “snapping”!

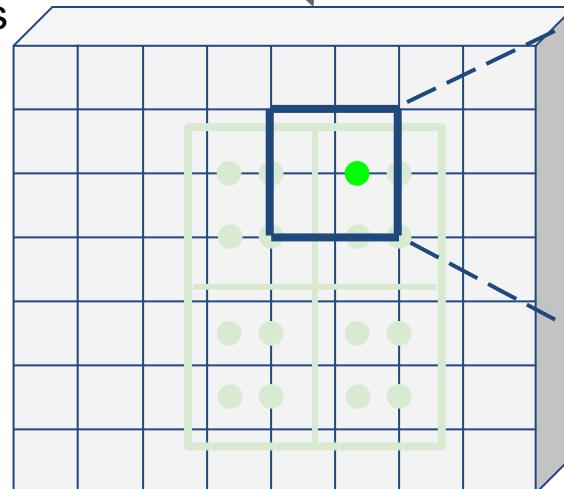
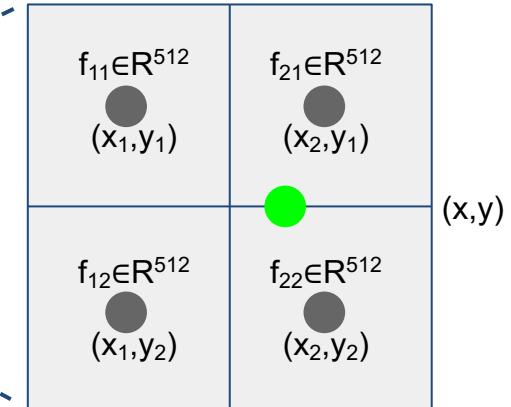


Image features:  $C \times H \times W$   
(e.g.  $512 \times 20 \times 15$ )

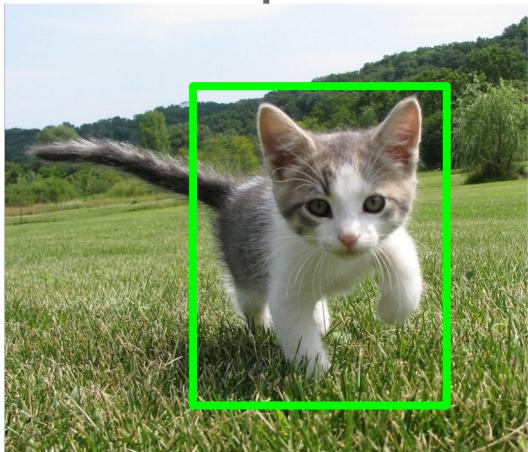
Sample at regular points  
in each subregion using  
**bilinear interpolation**



Feature  $f_{xy}$  for point  $(x, y)$   
is a linear combination of  
features at its four  
neighboring grid cells:

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

# Cropping Features: RoI Align



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

Project proposal  
onto features



No “snapping”!

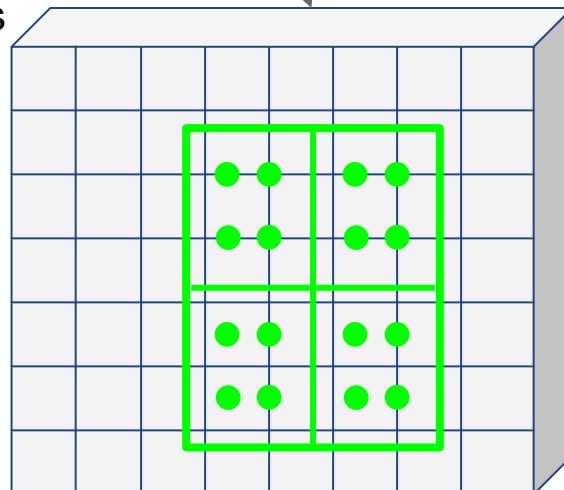
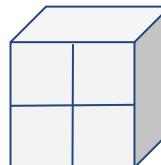


Image features:  $C \times H \times W$   
(e.g.  $512 \times 20 \times 15$ )

Sample at regular points  
in each subregion using  
**bilinear interpolation**

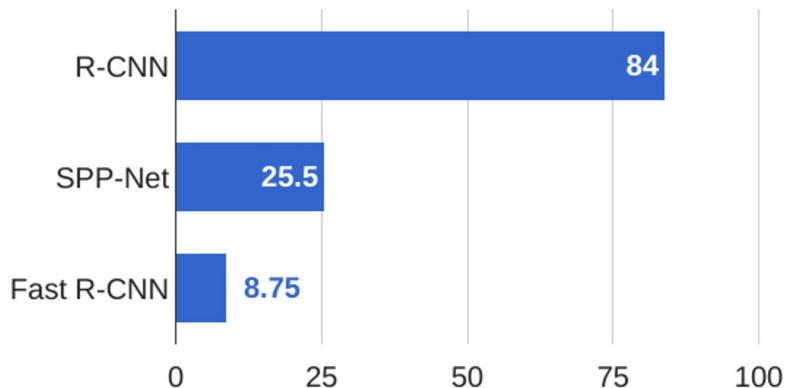
Max-pool within  
each subregion



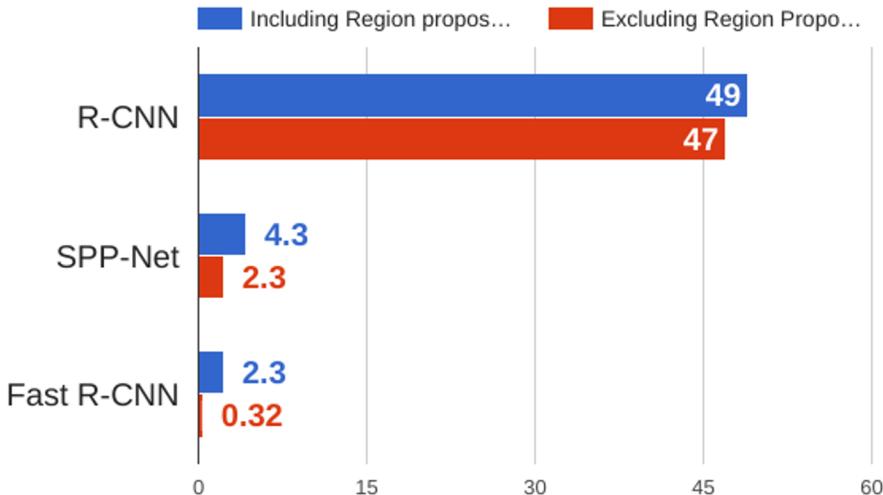
Region features  
(here  $512 \times 2 \times 2$ ;  
In practice e.g.  $512 \times 7 \times 7$ )

# R-CNN vs Fast R-CNN

Training time (Hours)



Test time (seconds)



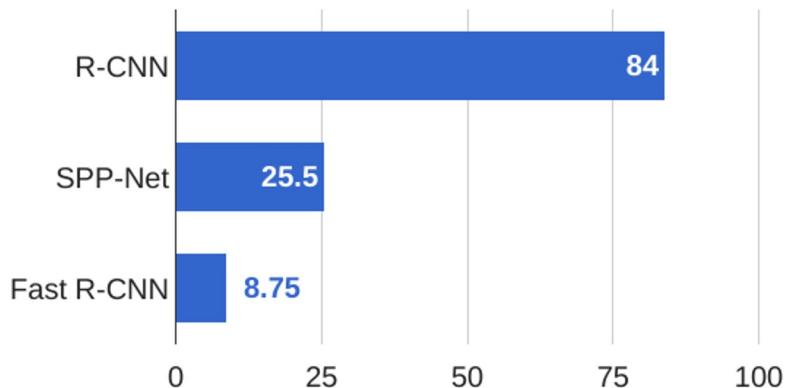
Girshick et al, "Rich feature hierarchies for accurate object detection and semantic segmentation", CVPR 2014.

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

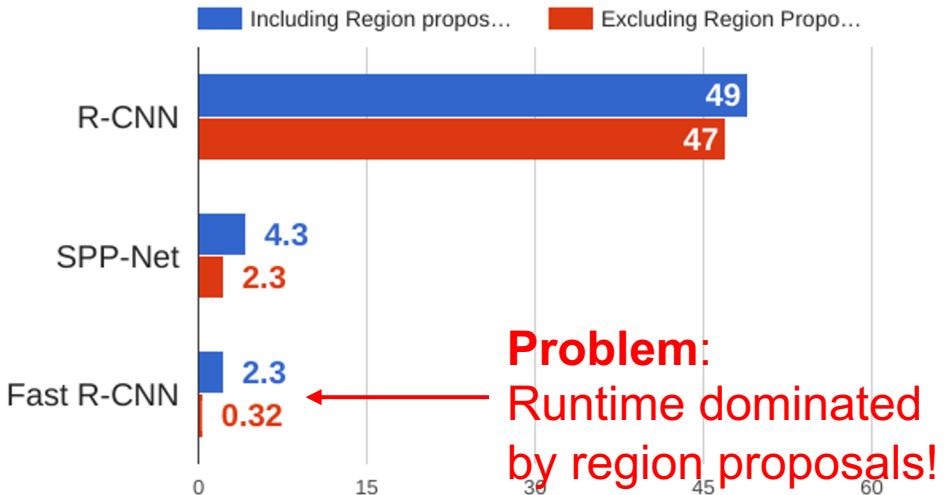
Girshick, "Fast R-CNN", ICCV 2015

# R-CNN vs Fast R-CNN

Training time (Hours)



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

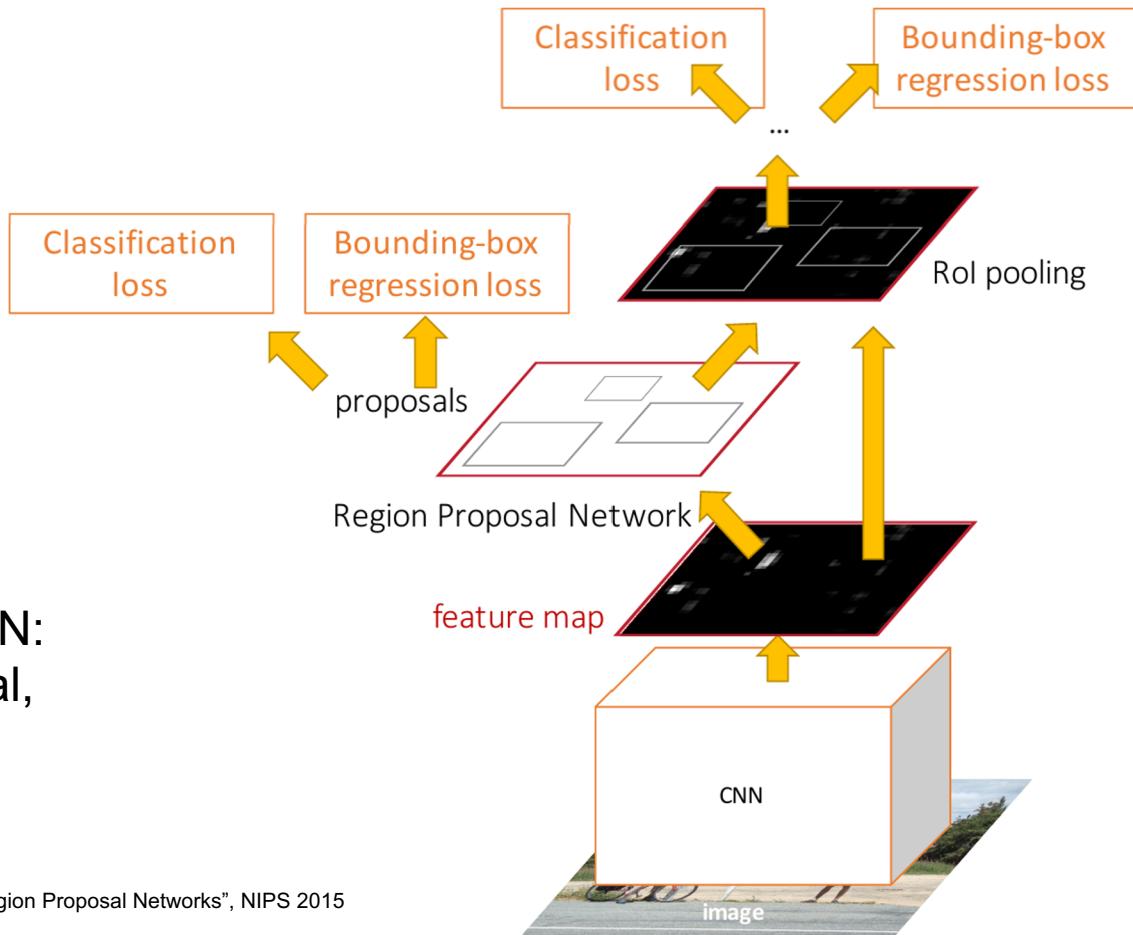
Girshick, "Fast R-CNN", ICCV 2015

# 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



# Region Proposal Network



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

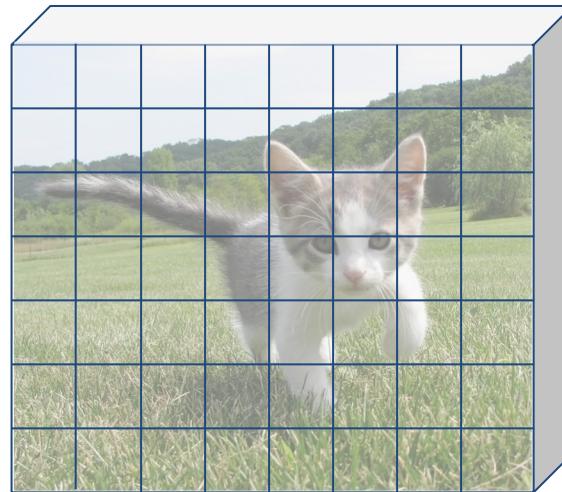
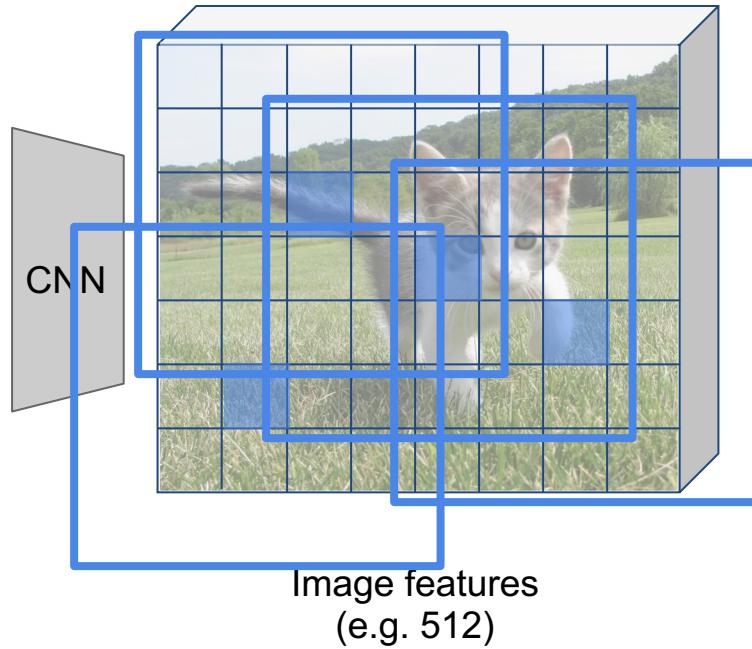


Image features  
(e.g.  $512 \times 20 \times 15$ )

# Region Proposal Network



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

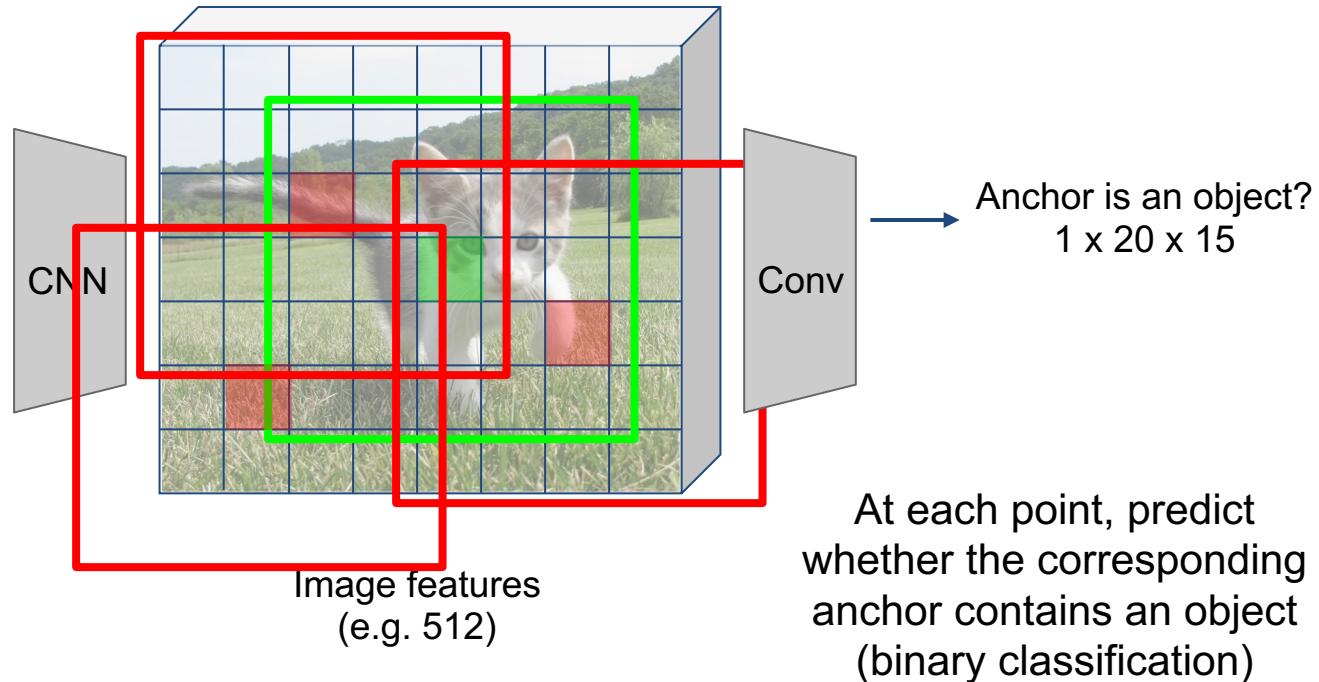


Imagine an **anchor box** of fixed size at each point in the feature map

# Region Proposal Network



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



# Region Proposal Network



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

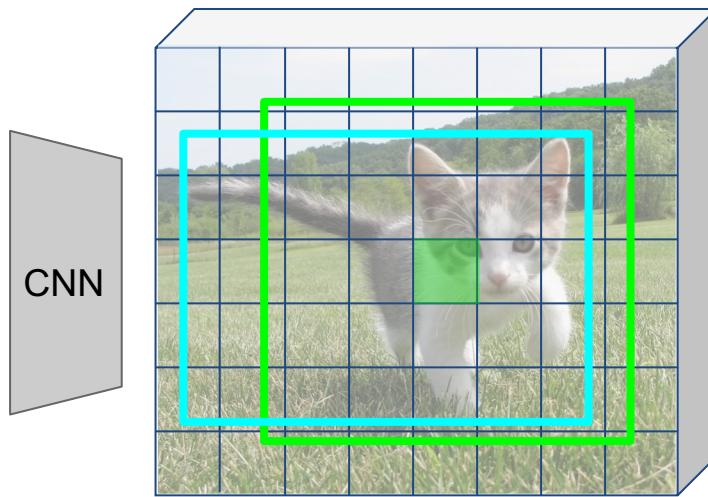
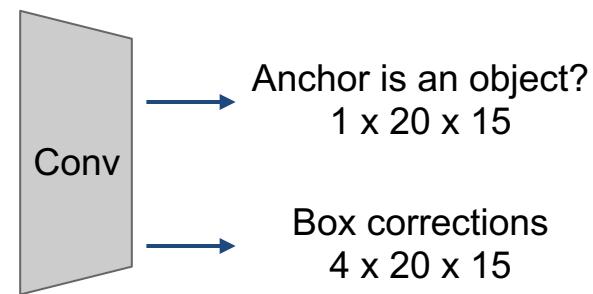


Image features  
(e.g. 512)

Example:  $20 \times 15$   
**anchor box** uniformly  
sampled on the feature  
map



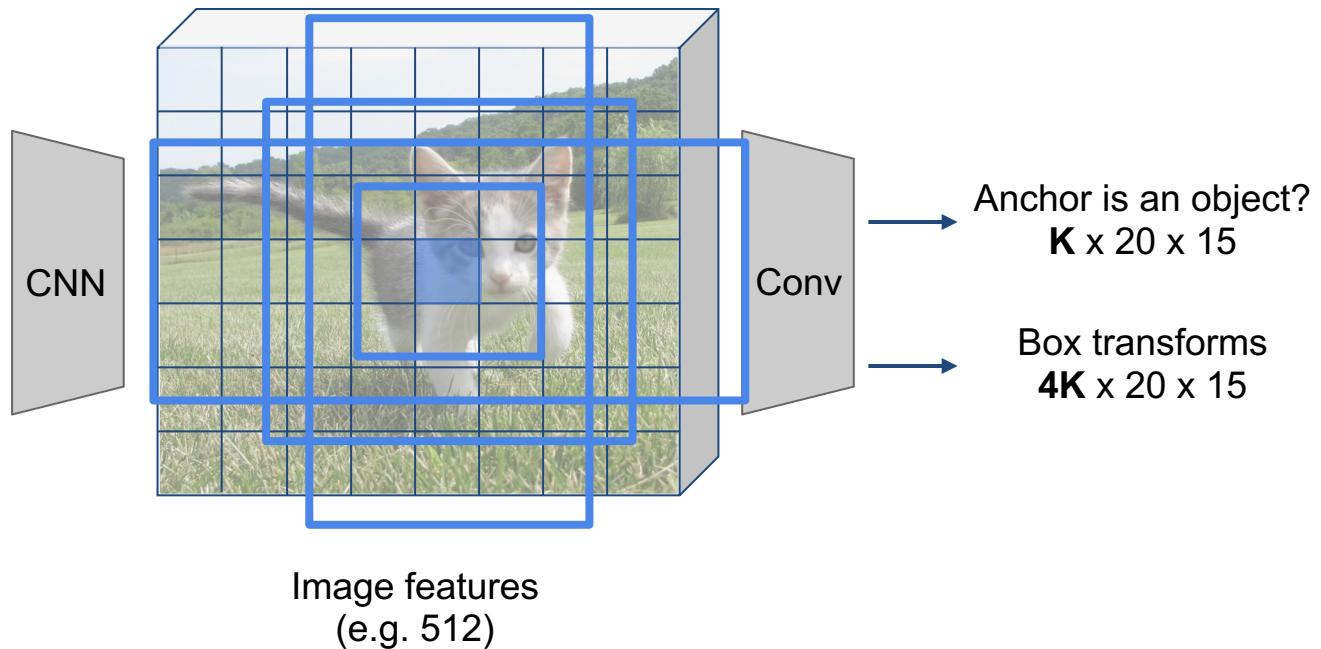
For positive boxes, also predict  
a corrections from the anchor  
to the ground-truth box (regress  
4 numbers per pixel)

# Region Proposal Network

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



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

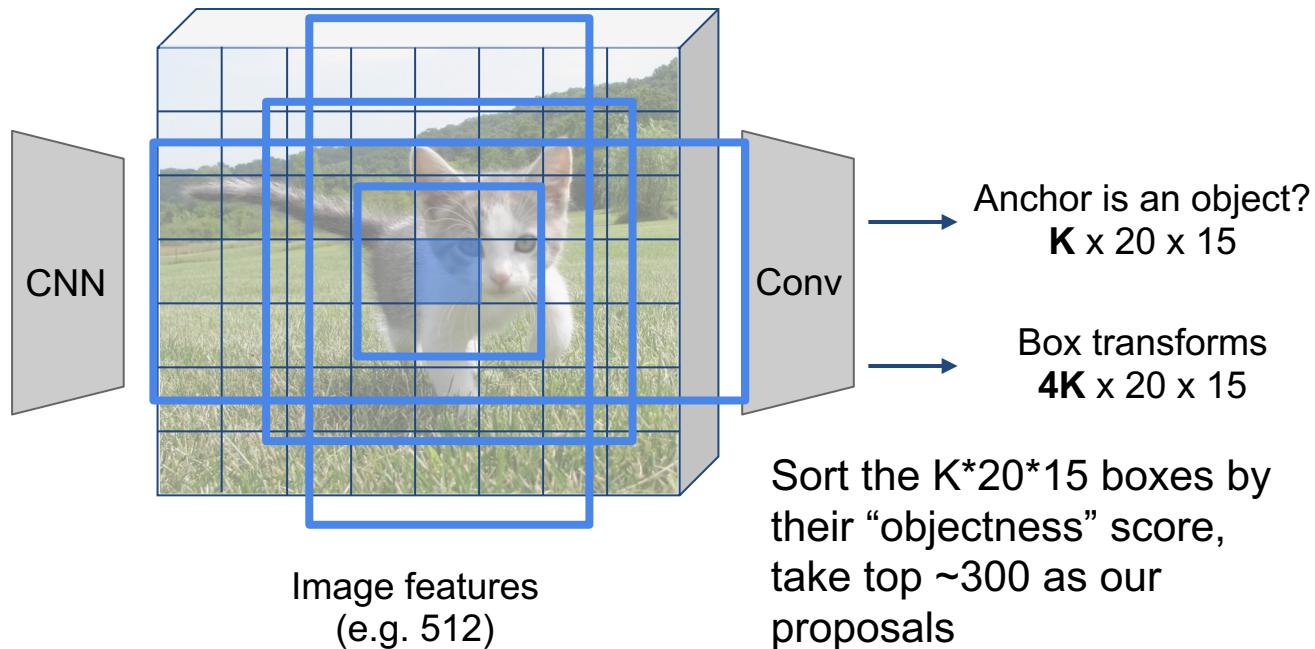


# Region Proposal Network

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



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

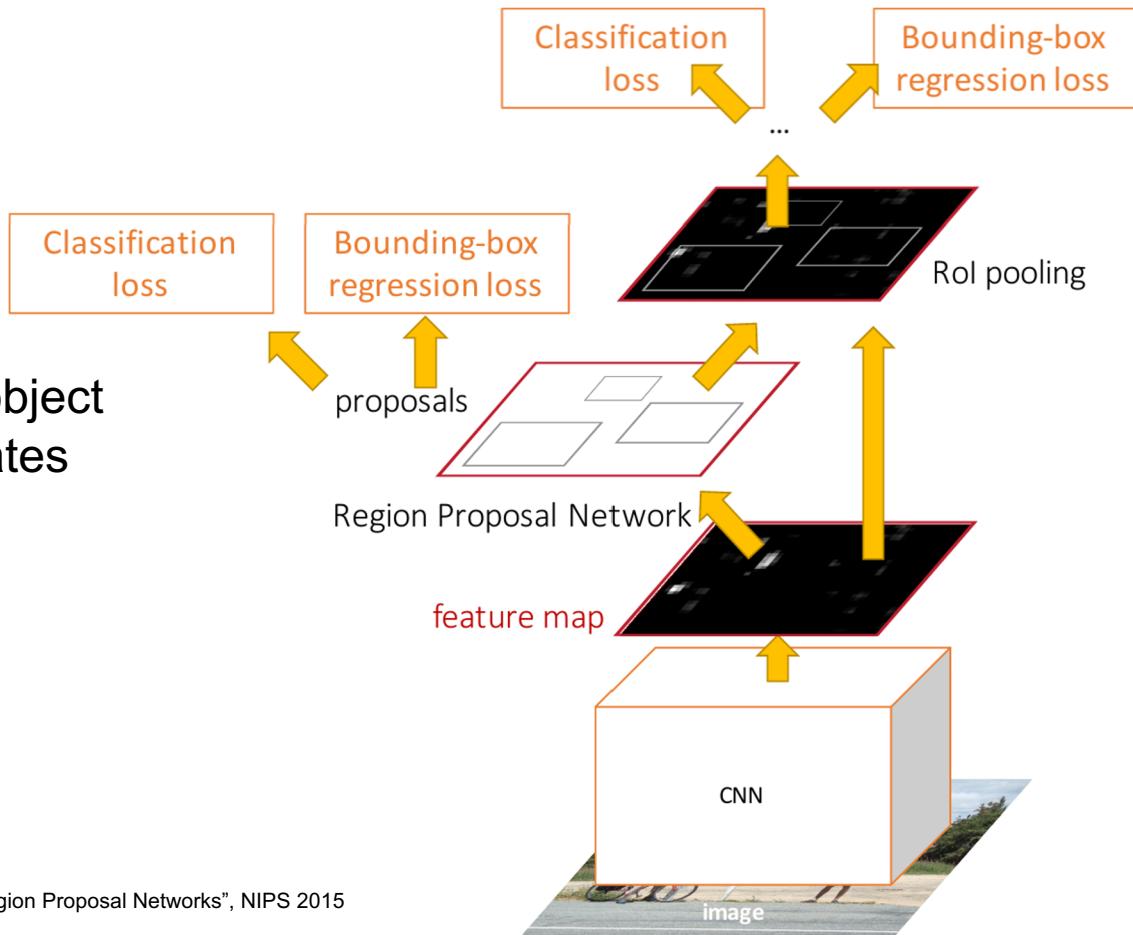


# Faster R-CNN:

Make CNN do proposals!

Jointly train with 4 losses:

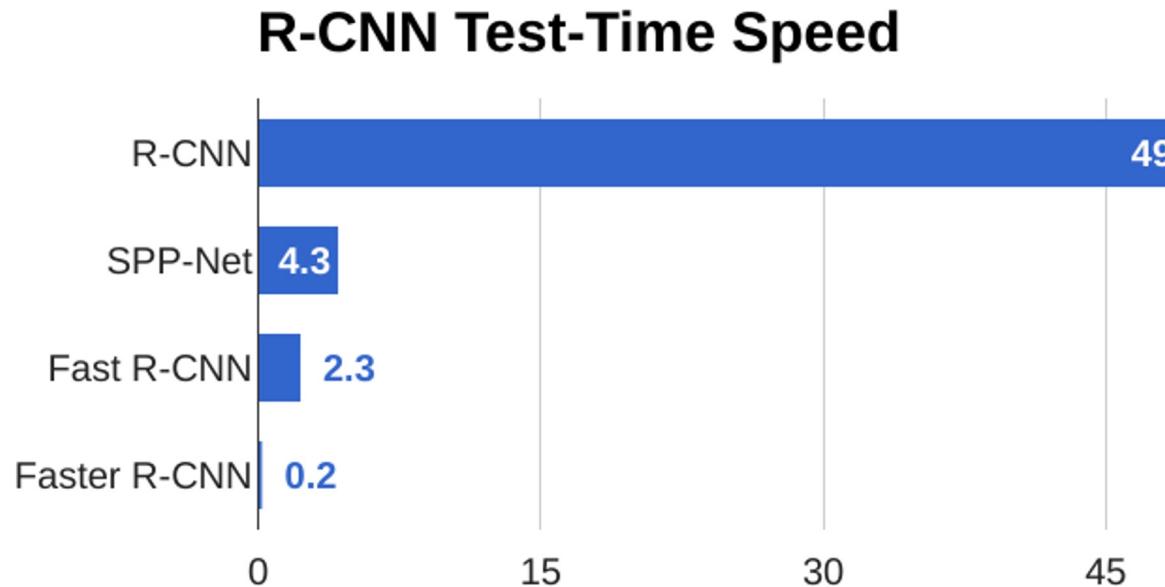
1. RPN classify object / not object
2. RPN regress box coordinates
3. Final classification score  
(object classes)
4. Final box coordinates



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!

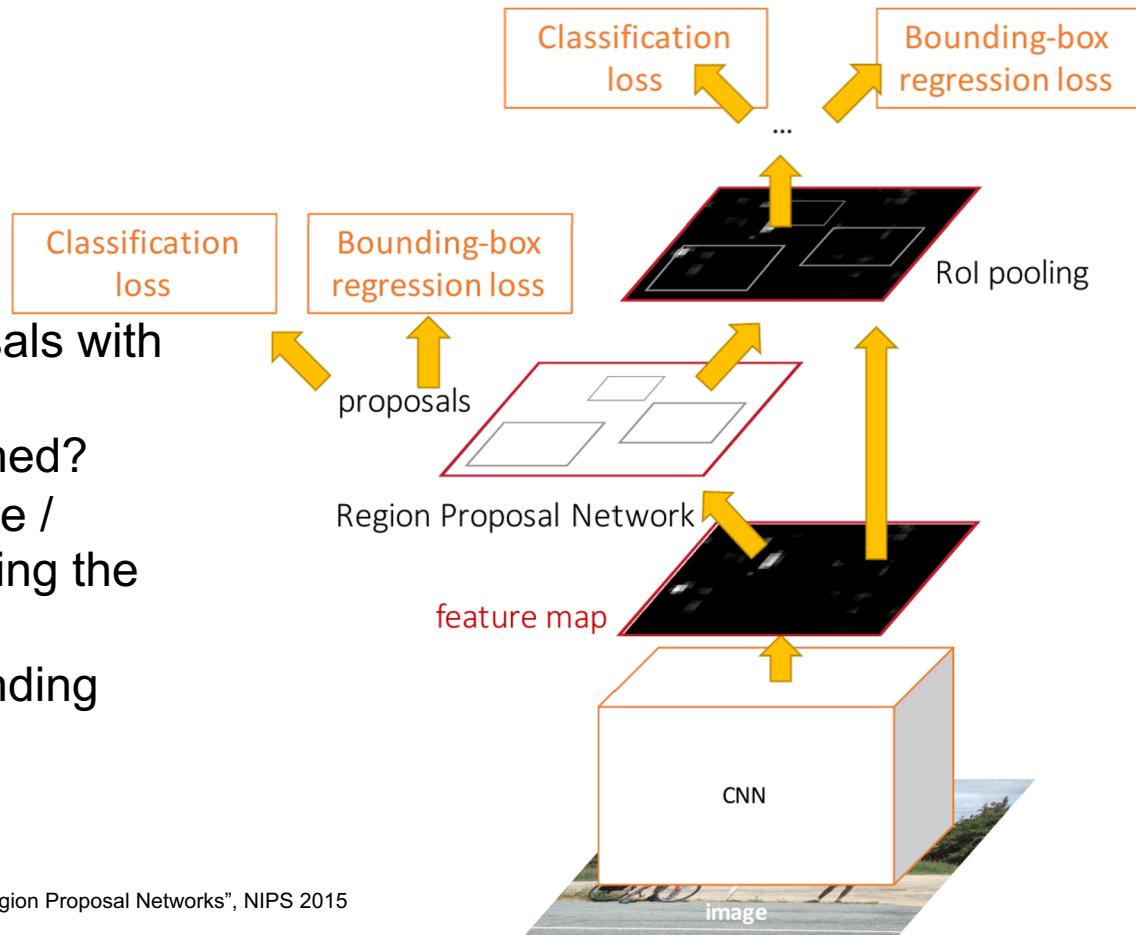


# Faster R-CNN:

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?



# Faster R-CNN:

Make CNN do proposals!

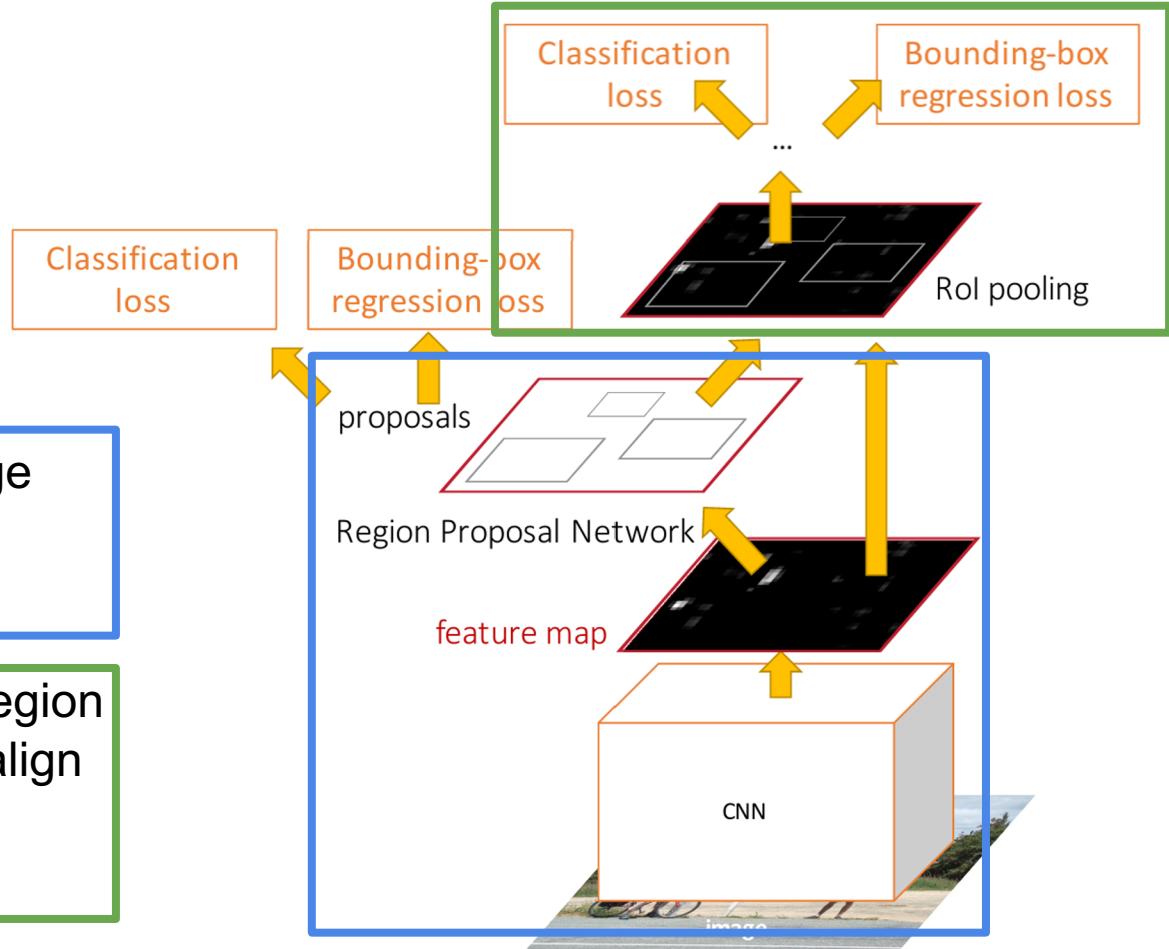
Faster R-CNN is a  
**Two-stage object detector**

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**

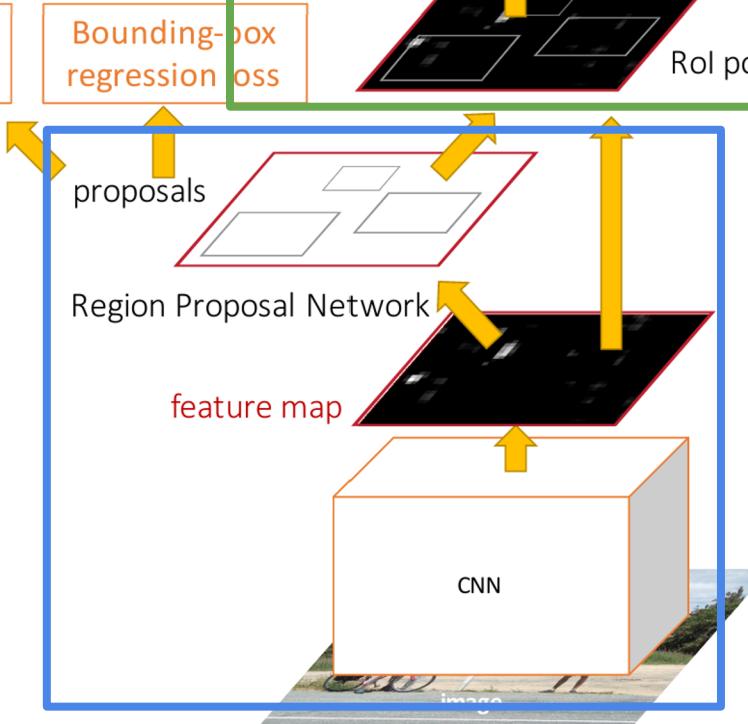
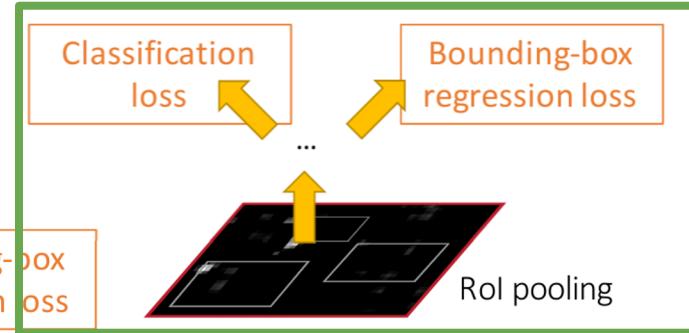
First stage: Run once per image

- Backbone network
- Region proposal network

Second stage: Run once per region

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

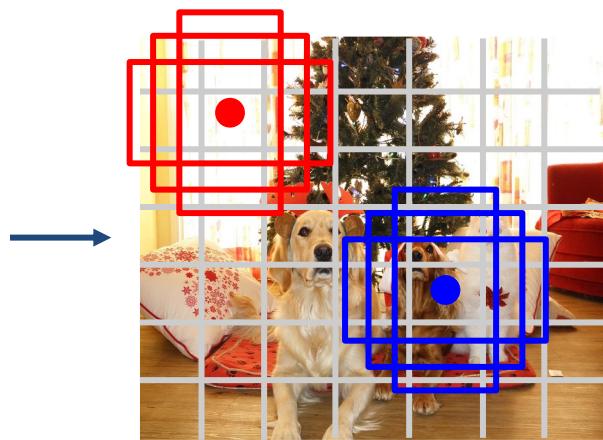
Do we really need  
the second stage?



# 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

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

**Object  
Detection**

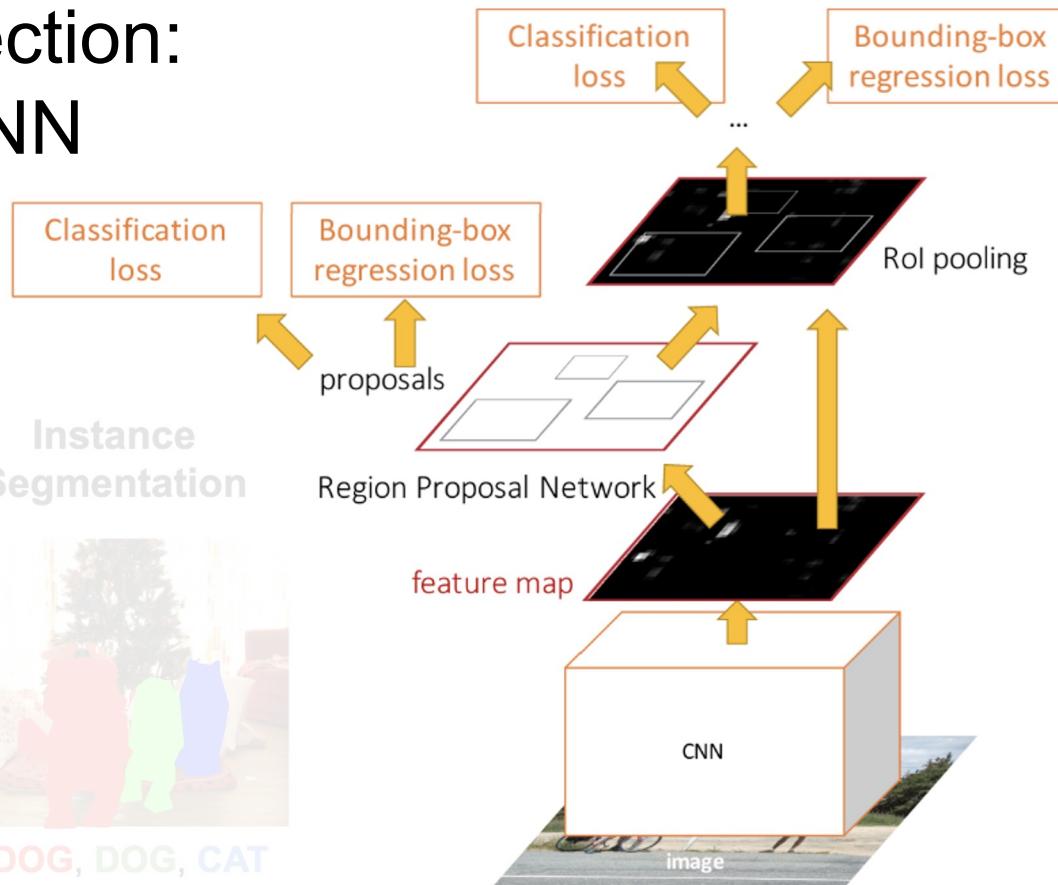


**DOG, DOG, CAT**

**Instance  
Segmentation**



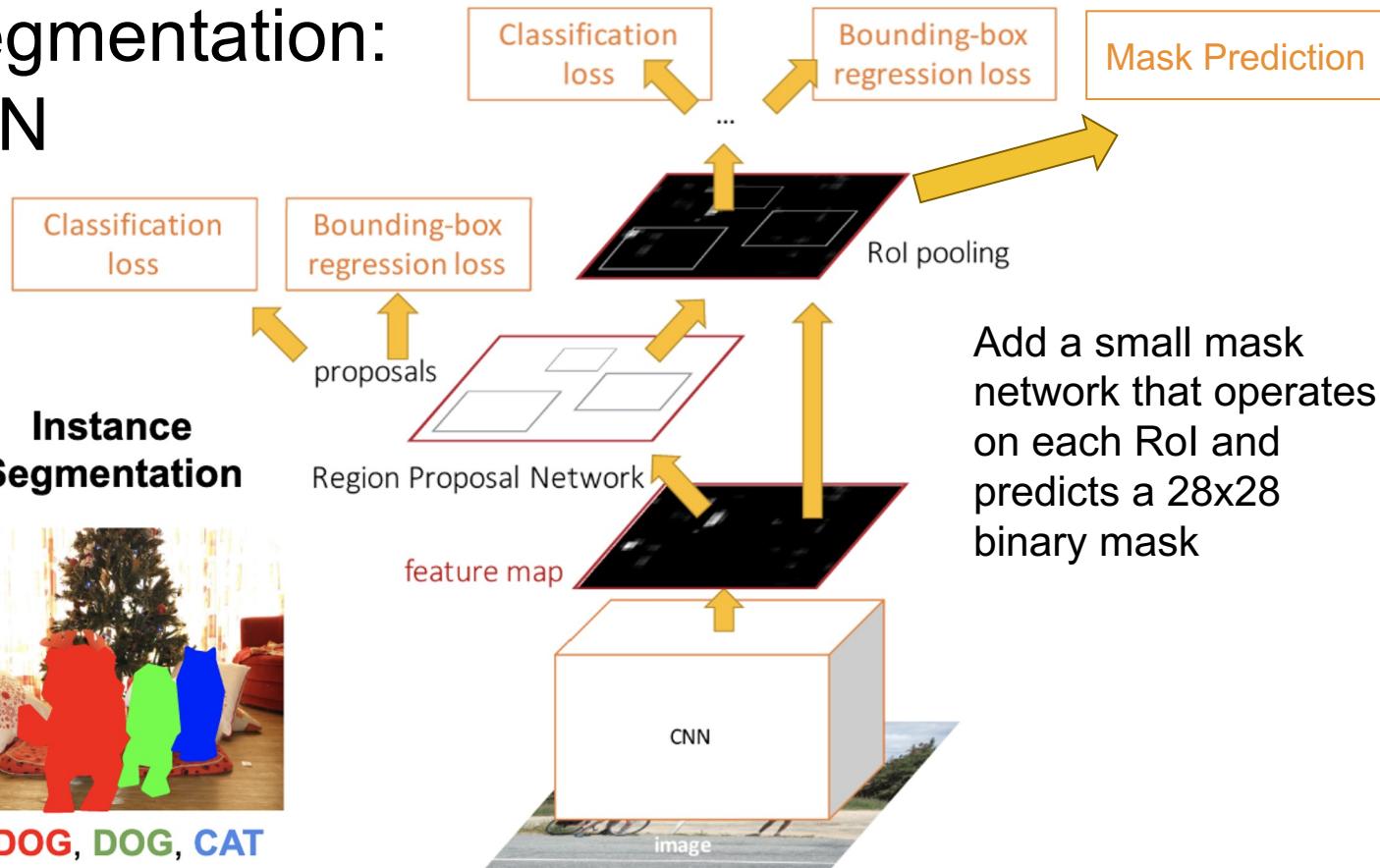
**DOG, DOG, CAT**



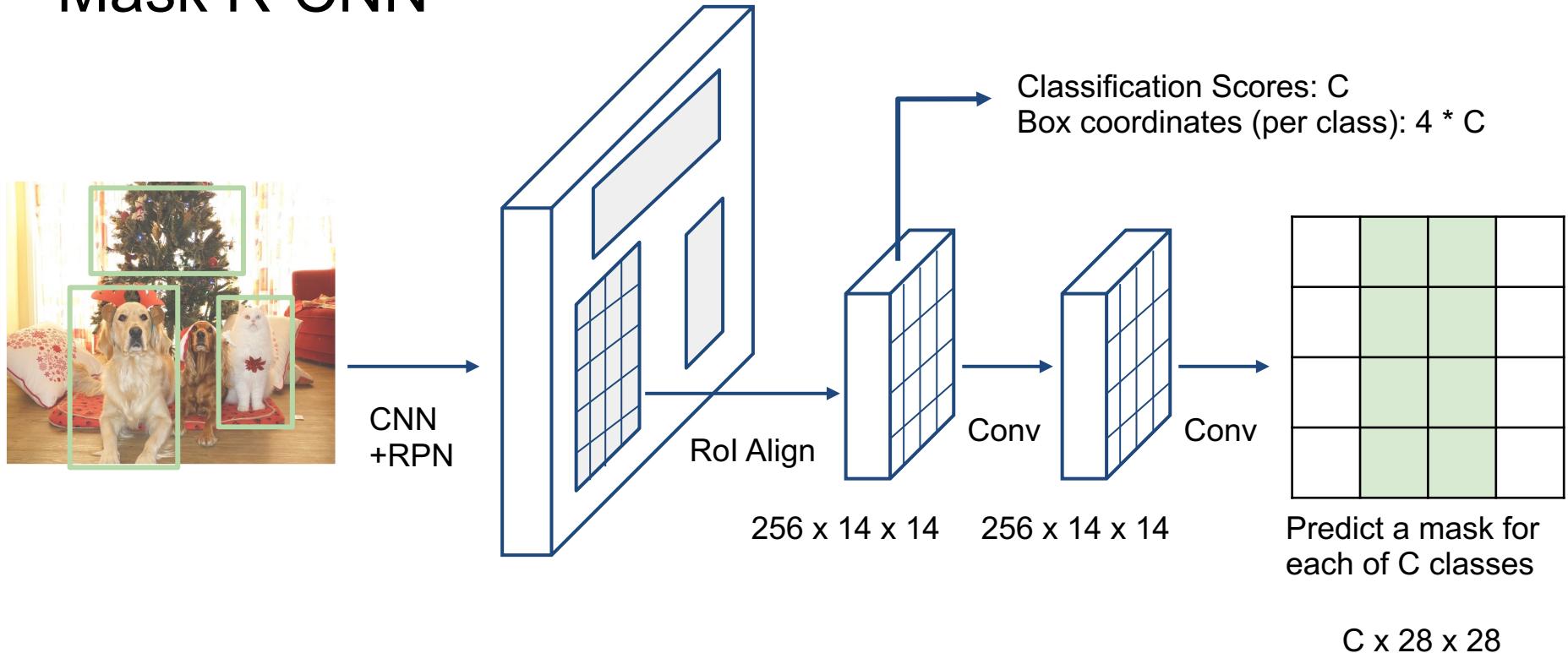
# Instance Segmentation: Mask R-CNN



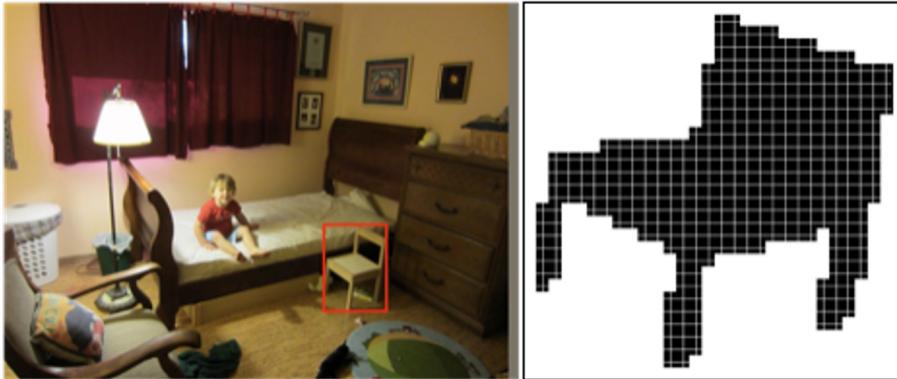
He et al, "Mask R-CNN", ICCV 2017



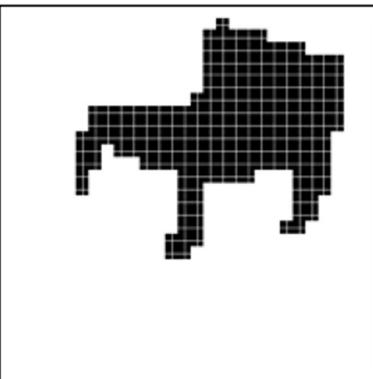
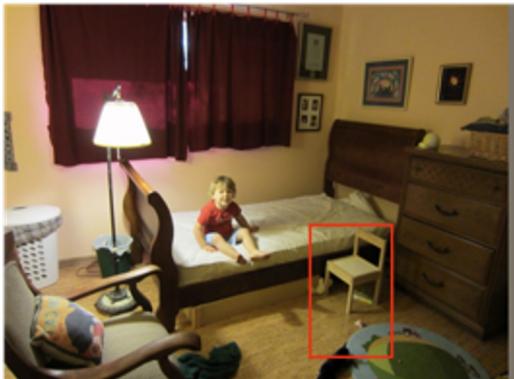
# Mask R-CNN



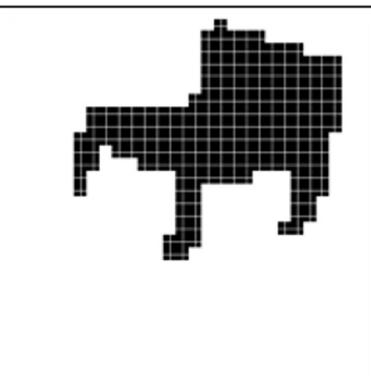
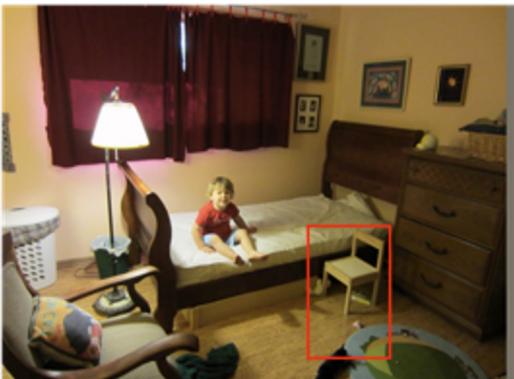
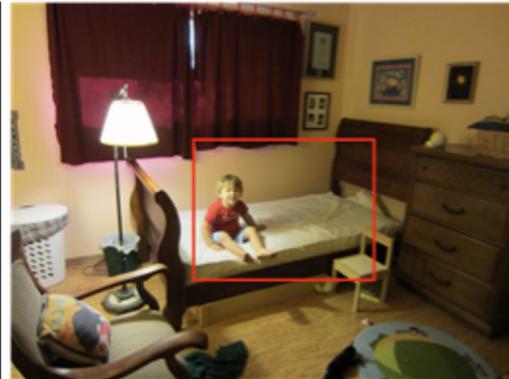
# Mask R-CNN: Example Mask Training Targets



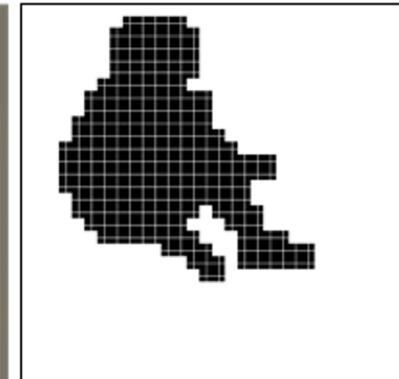
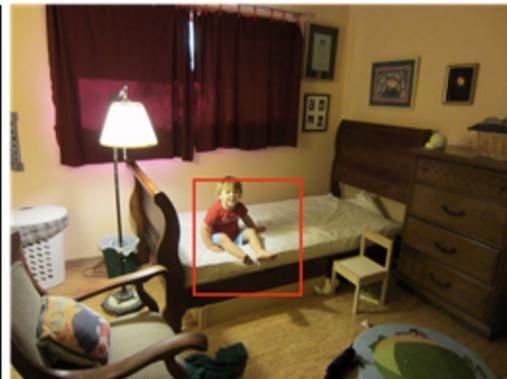
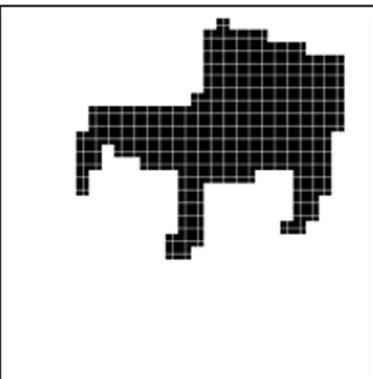
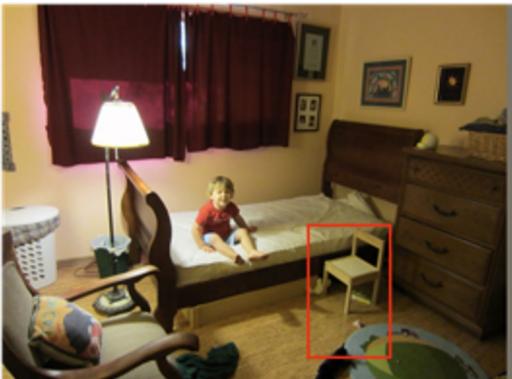
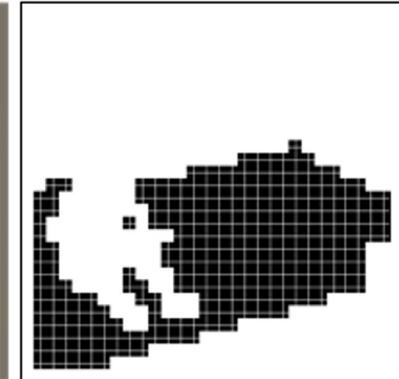
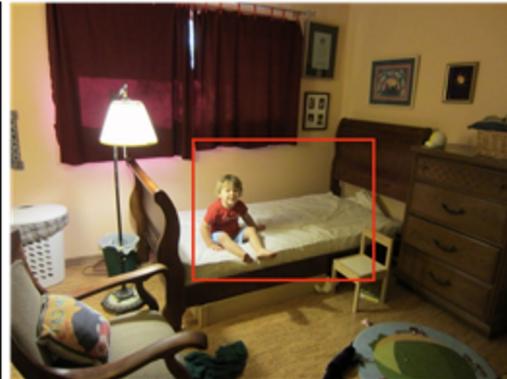
# Mask R-CNN: Example Mask Training Targets



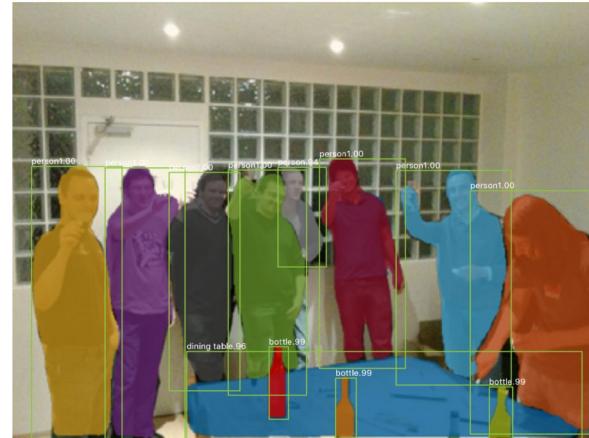
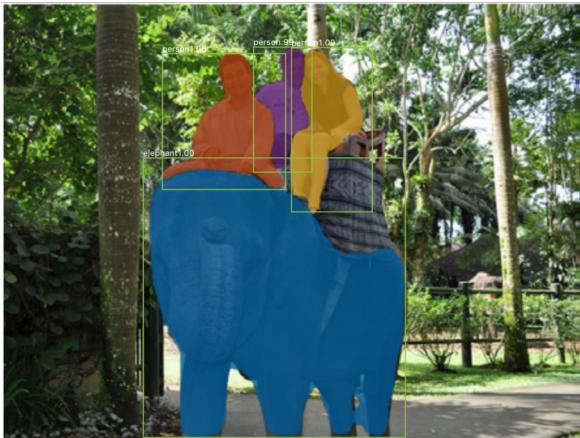
# Mask R-CNN: Example Mask Training Targets



# Mask R-CNN: Example Mask Training Targets



# Mask R-CNN: Very Good Results!



# Mask R-CNN

## Also does pose



# 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, ...

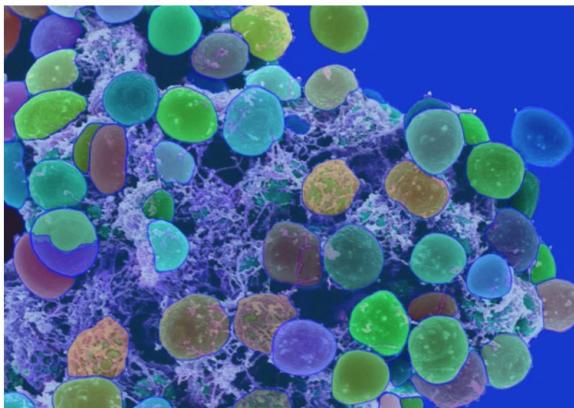
Detectron2 (PyTorch)

<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

# Foundation Image Segmentation Models



SegmentAnything (Meta AI, 2023)

Try it yourself! <https://segment-anything.com/demo#>

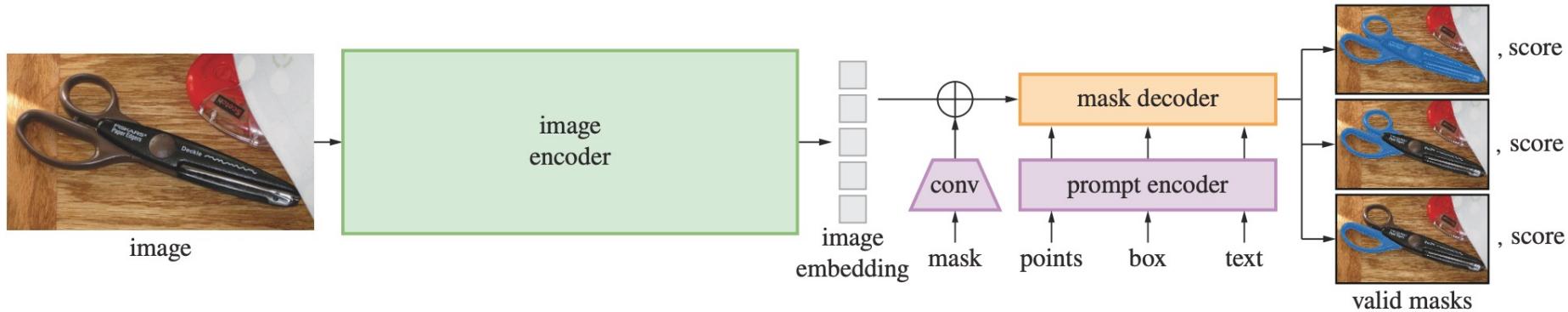
# Foundation Image Segmentation Models



SegmentAnything (Meta AI, 2023)

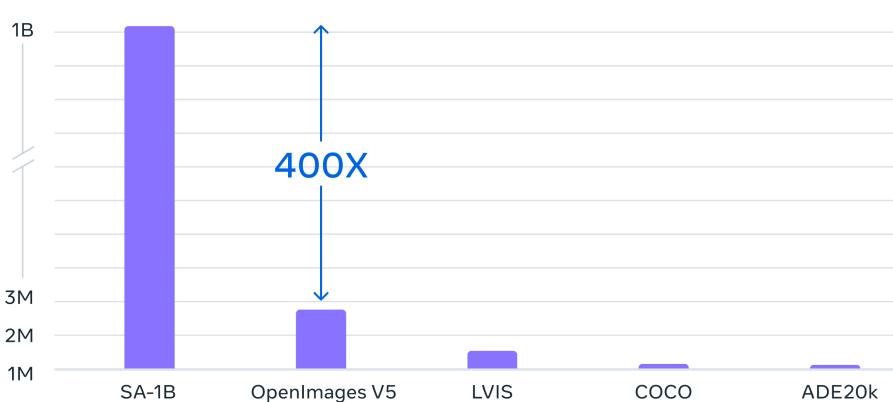
Try it yourself! <https://segment-anything.com/demo#>

# Foundation Image Segmentation Models

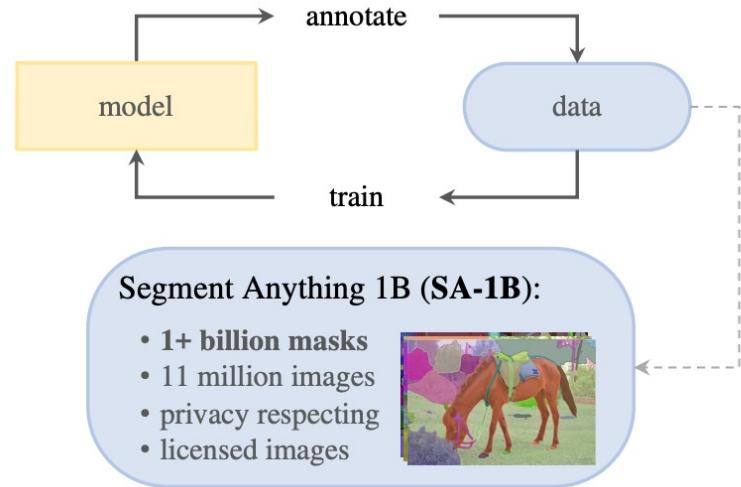


SegmentAnything (Meta AI, 2023)

# Foundation Image Segmentation Models



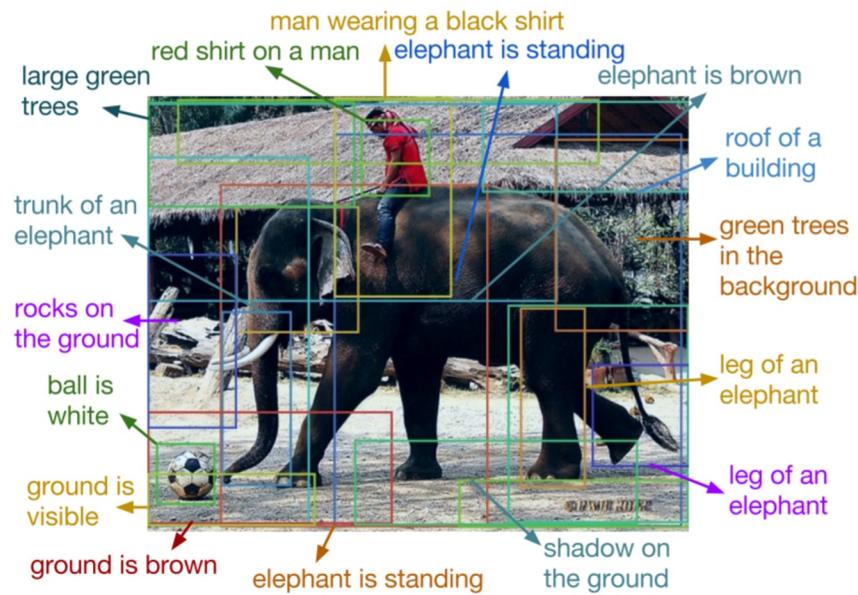
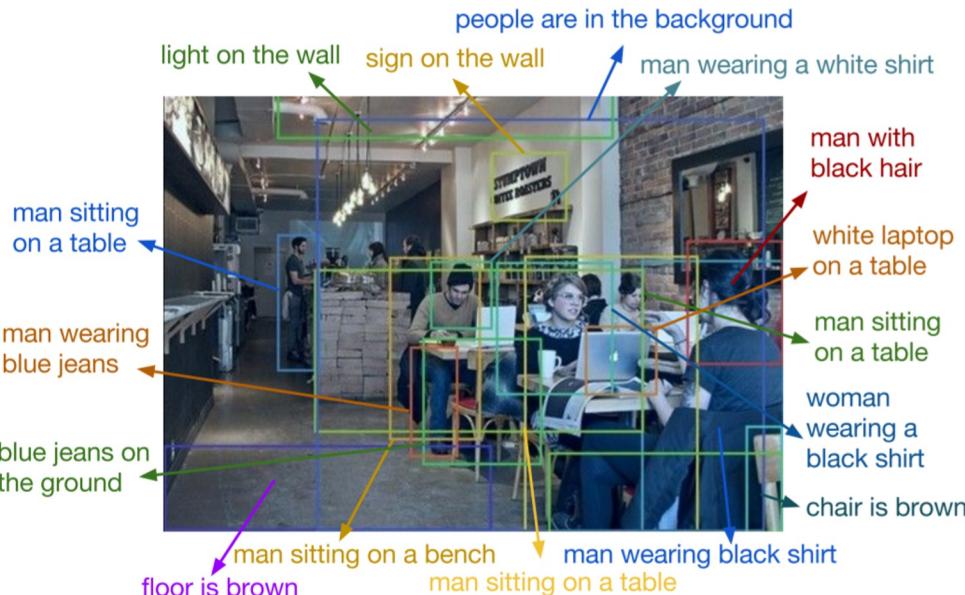
■ masks in dataset



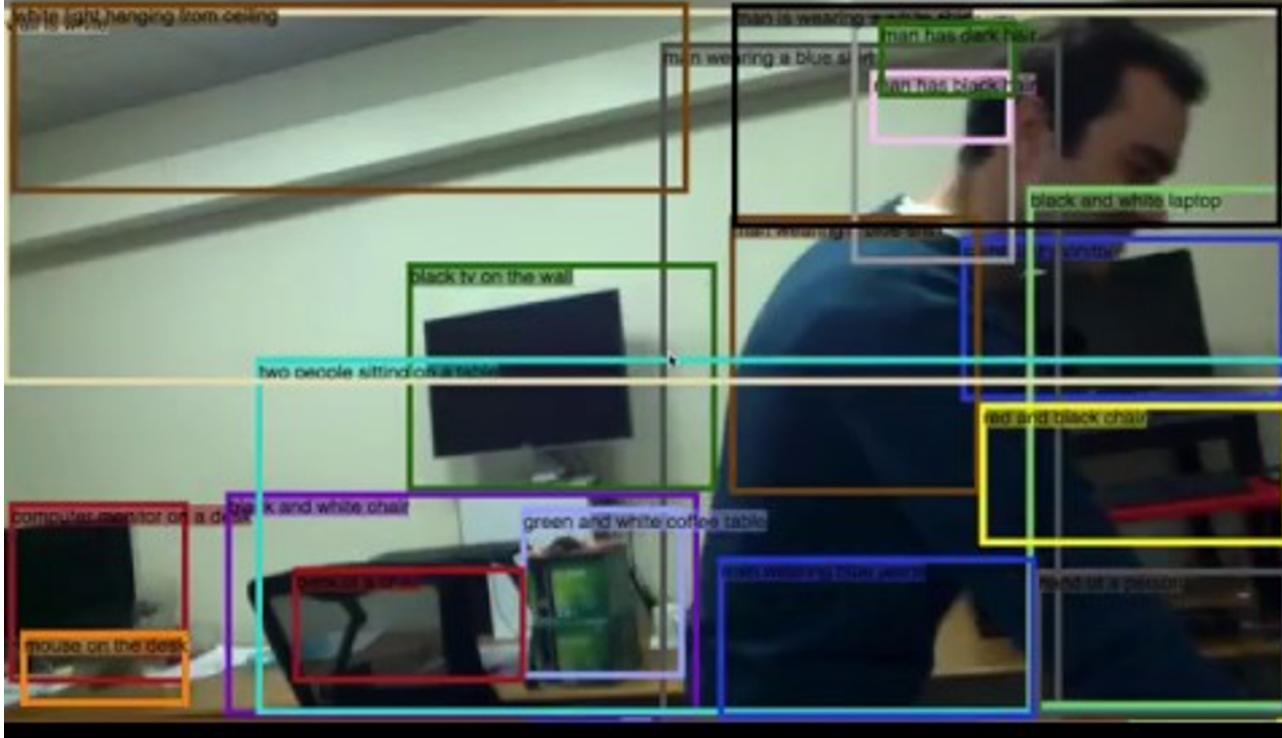
SegmentAnything (Meta AI, 2023)

Beyond 2D Object Detection...

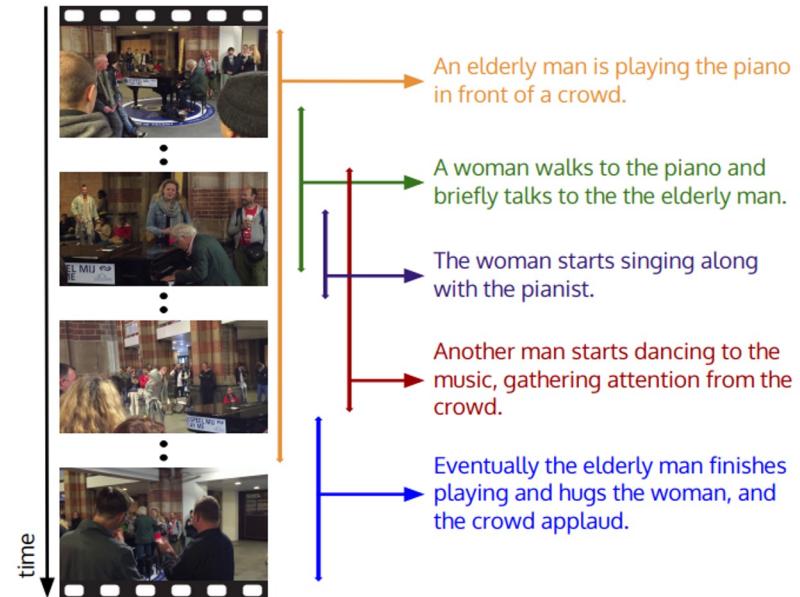
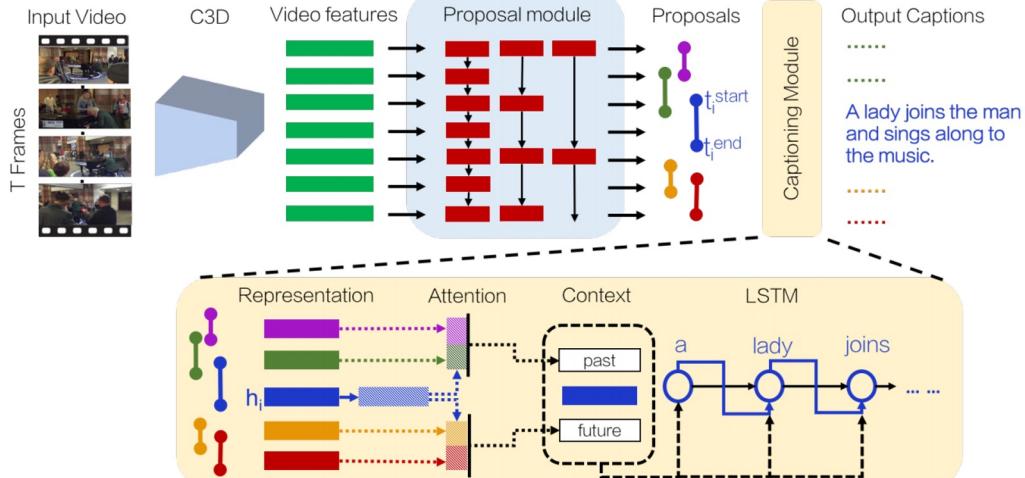
# Object Detection + Captioning = Dense Captioning



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

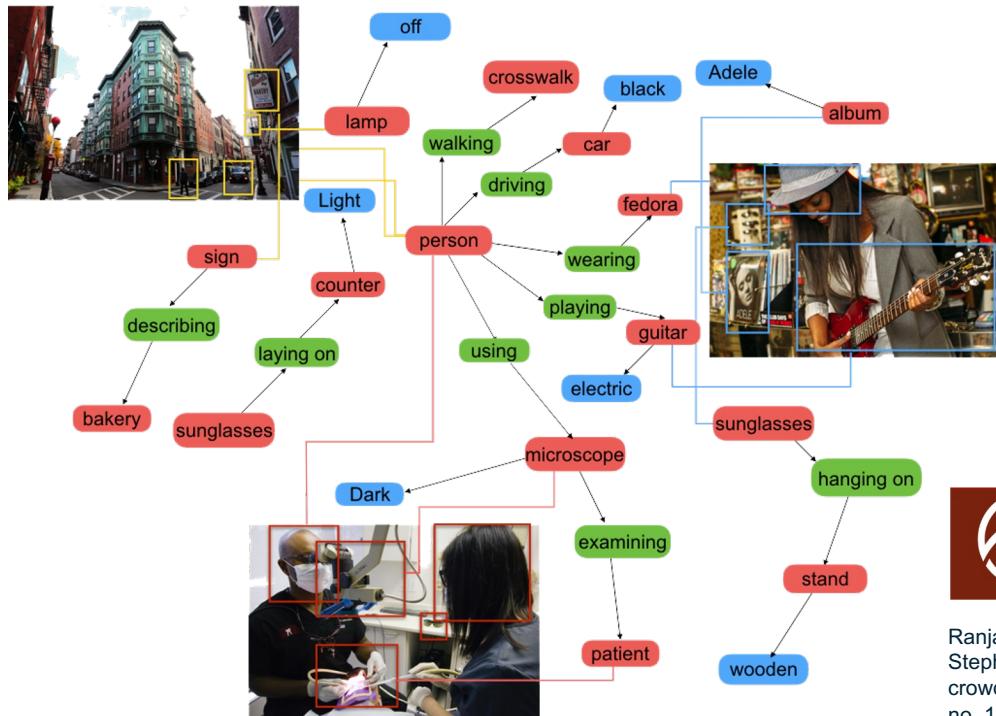


# Dense Video Captioning



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

next to

5.4 Million Region Descriptions

1.7 Million Visual Question Answers

3.8 Million Object Instances

2.8 Million Attributes

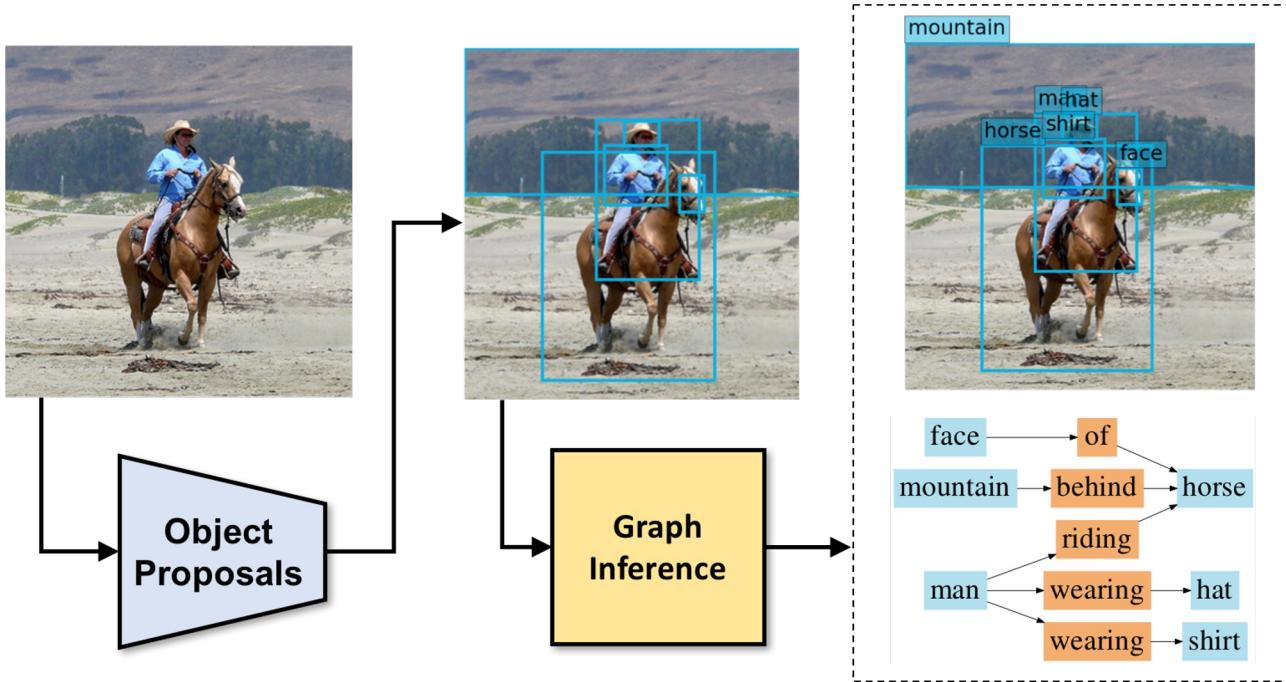
2.3 Million Relationships

Everything Mapped to Wordnet Synsets

 VISUALGENOME

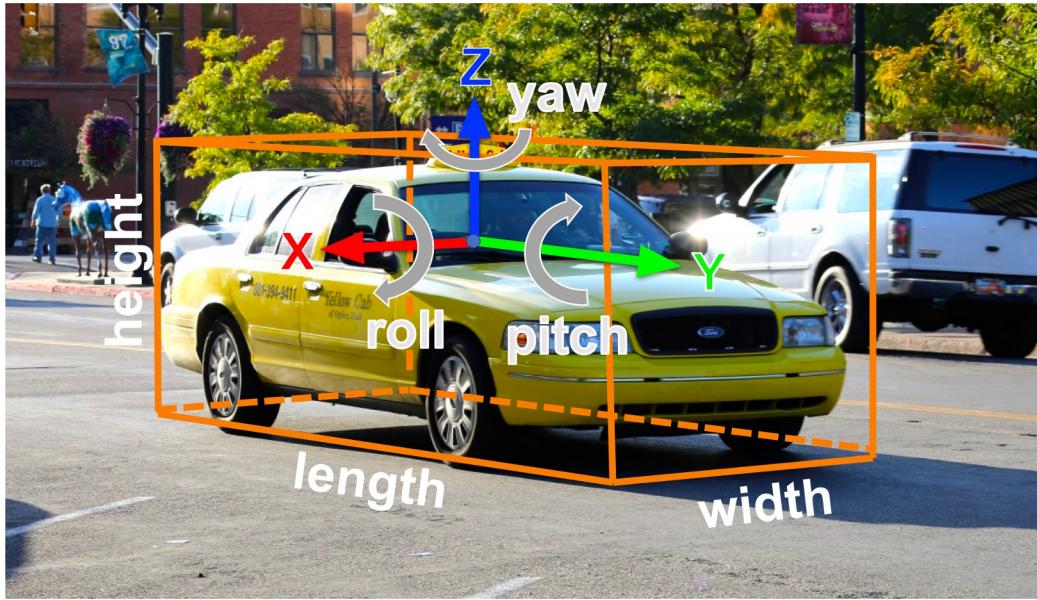
Ranjay Krishna, Yuke Zhu, Oliver Groth, Justin Johnson, Kenji Hata, Joshua Kravitz, Stephanie Chen et al. "Visual genome: Connecting language and vision using crowdsourced dense image annotations." International Journal of Computer Vision 123, no. 1 (2017): 32-73.

# 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:

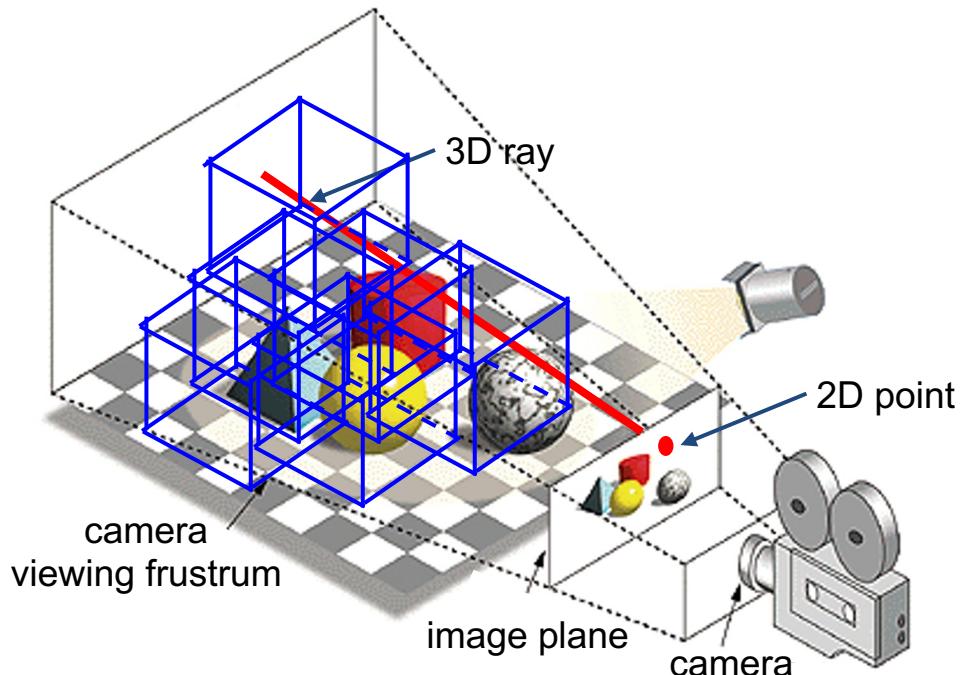
3D oriented bounding box

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

Simplified bbox: no roll & pitch

Much harder problem than 2D object detection!

# 3D Object Detection: Simple Camera Model

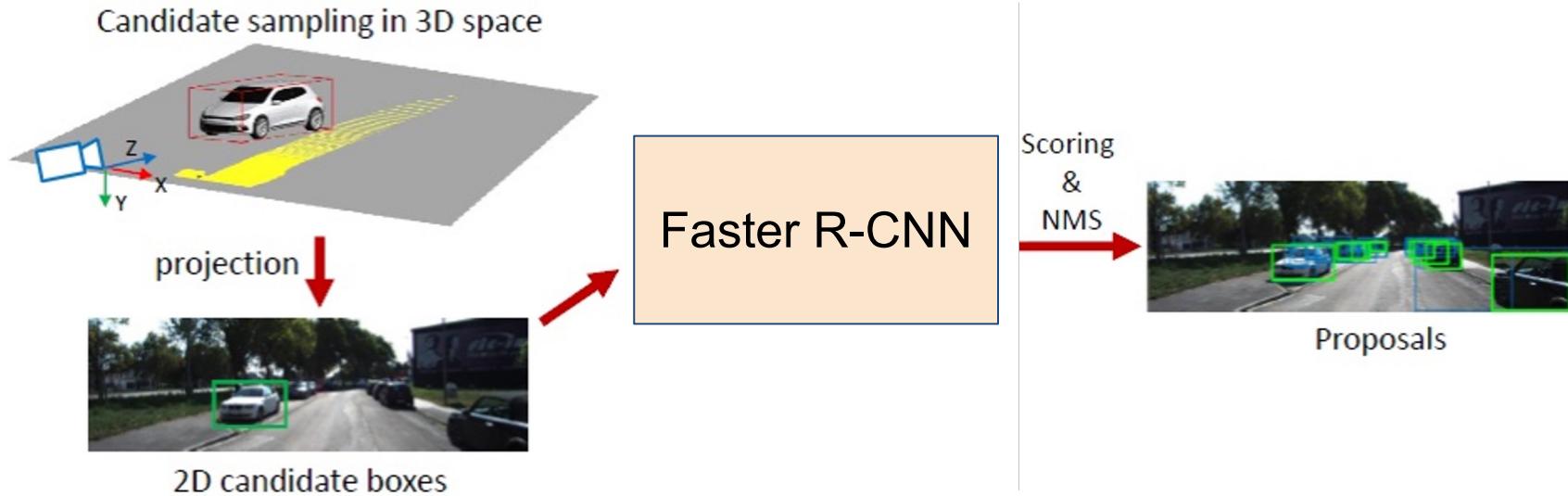


A point on the image plane corresponds to a **ray** in the 3D space

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

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

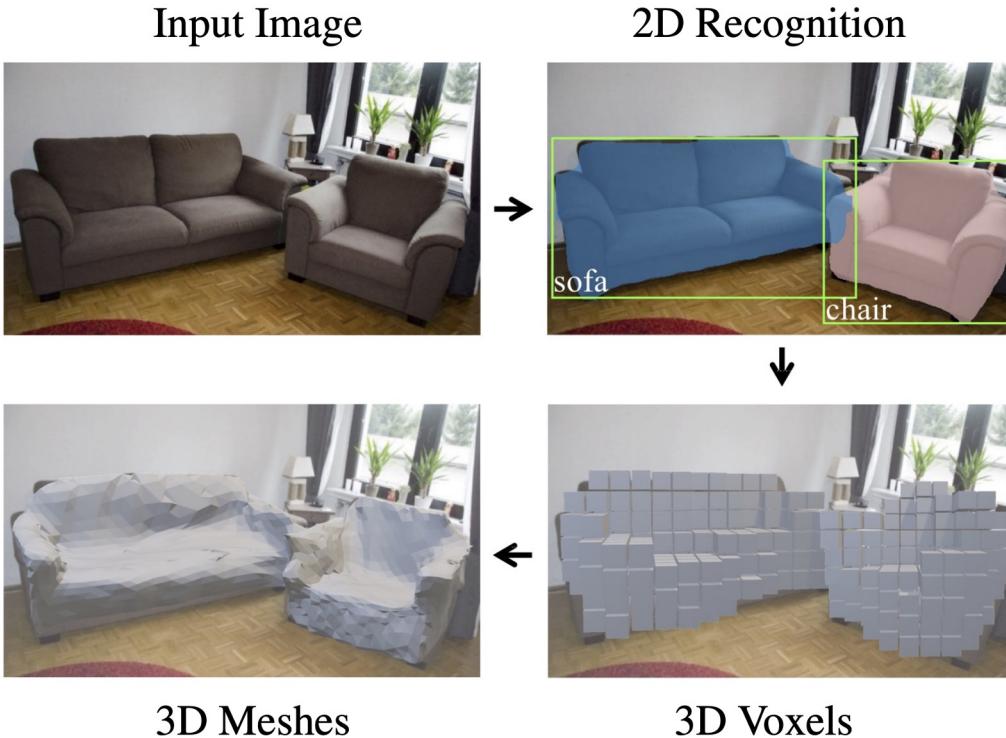
# 3D Object Detection: Monocular Camera



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

Chen, Xiaozhi, 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!

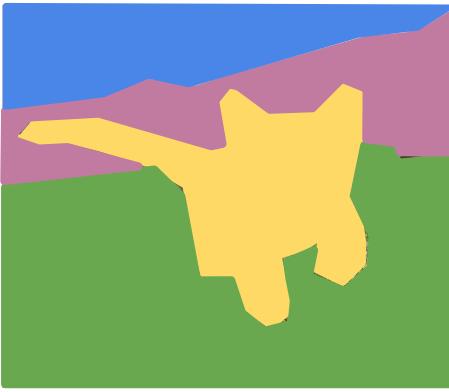
## Classification



CAT

No spatial extent

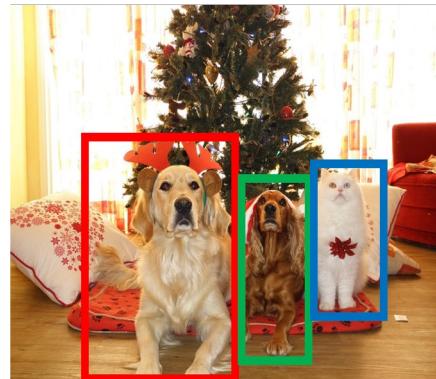
## Semantic Segmentation



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: Visualizing Neural Networks