

# Fully convolutional neural networks

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# Contents

- 1 Introduction
- 2 From classification to image-to-image translation
- 3 Properties of fully-convolutional neural networks
- 4 Image segmentation
- 5 Using fully-convolutional networks
- 6 Conclusion

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# Image definition

## Definition

Here an image is a 2D array of size  $p \times q$ . Each array element belongs to  $\mathbb{R}^d$ . The dimension of the value space  $d$ , is often called the **number of channels** of the image.  
The set of these images is  $\mathcal{I}^d$ .

## Examples

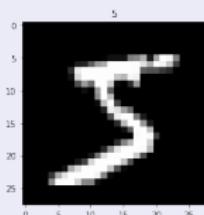
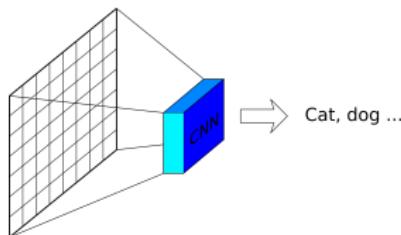


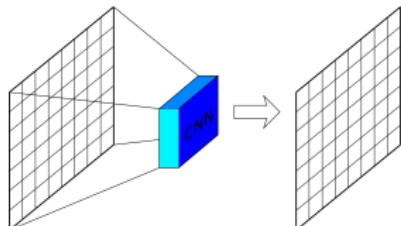
Figure:  $28 \times 28$  grey level image ( $d = 1$ ) from the MNIST data set, and  $481 \times 321$  colour image ( $d = 3$ ) from the Berkeley segmentation data set.

# Learning image transformations

- An image classification task is a function from the set of considered images into a set of labels



- In many applications, we want to transform an image into another image



# Image-to-image translation

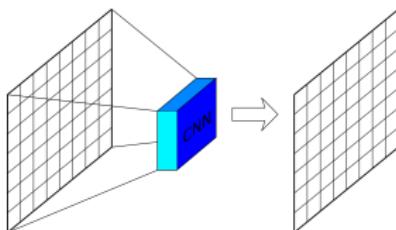
Definition: image-to-image translation

An image-to-image operator is a function that transforms an image into another image of same size:

$$F : \mathcal{I}^{d_1} \longrightarrow \mathcal{I}^{d_2}$$

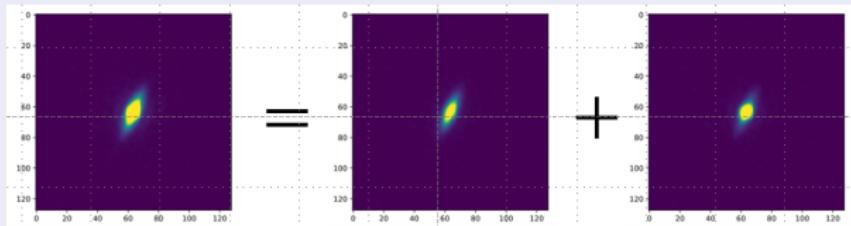
$$I \longmapsto J$$

Note that the number of channels of input and output images can be different.



# Examples

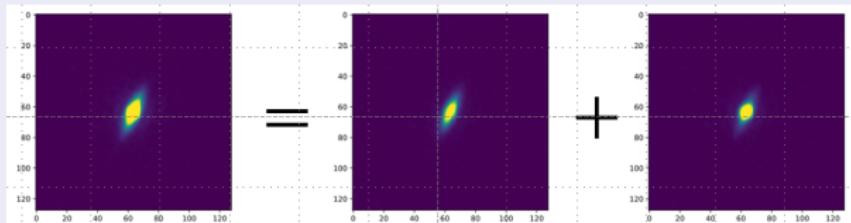
## Bulge / disk decomposition



(Credits: Tuccillo, Huertas-Company, Velasco-Forero, Decencière)

# Examples

## Bulge / disk decomposition



(Credits: Tuccillo, Huertas-Company, Velasco-Forero, Decencière)

## Deblurring network [Hradiš et al., 2015]

where subscript  $j$  indicates  
ated vector, and  $L_j(z; u) =$   
and  $e_j \in \mathbb{R}^{64}$  is the vector  
all others be 0. The coordi  
marized in Algorithm I.

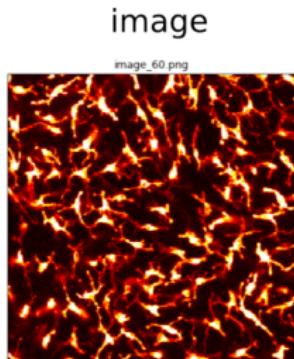
Note that  $g_j(z)$  is not  
we calculate the Newton di  
second-order approximation  
and solve

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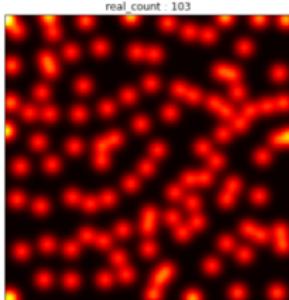
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# Counting cells

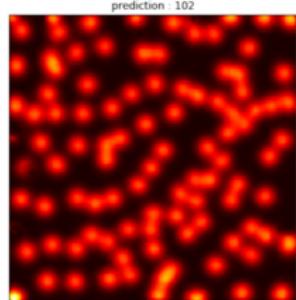
Best count



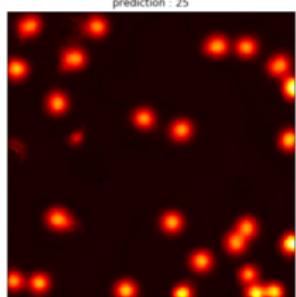
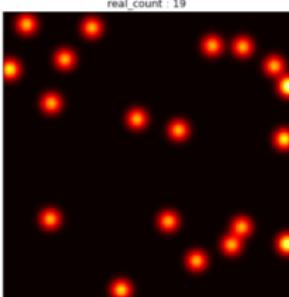
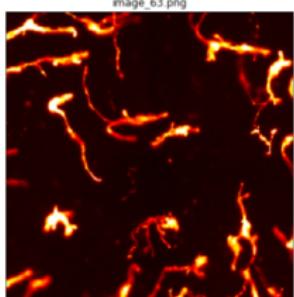
real density map



Inferred density map

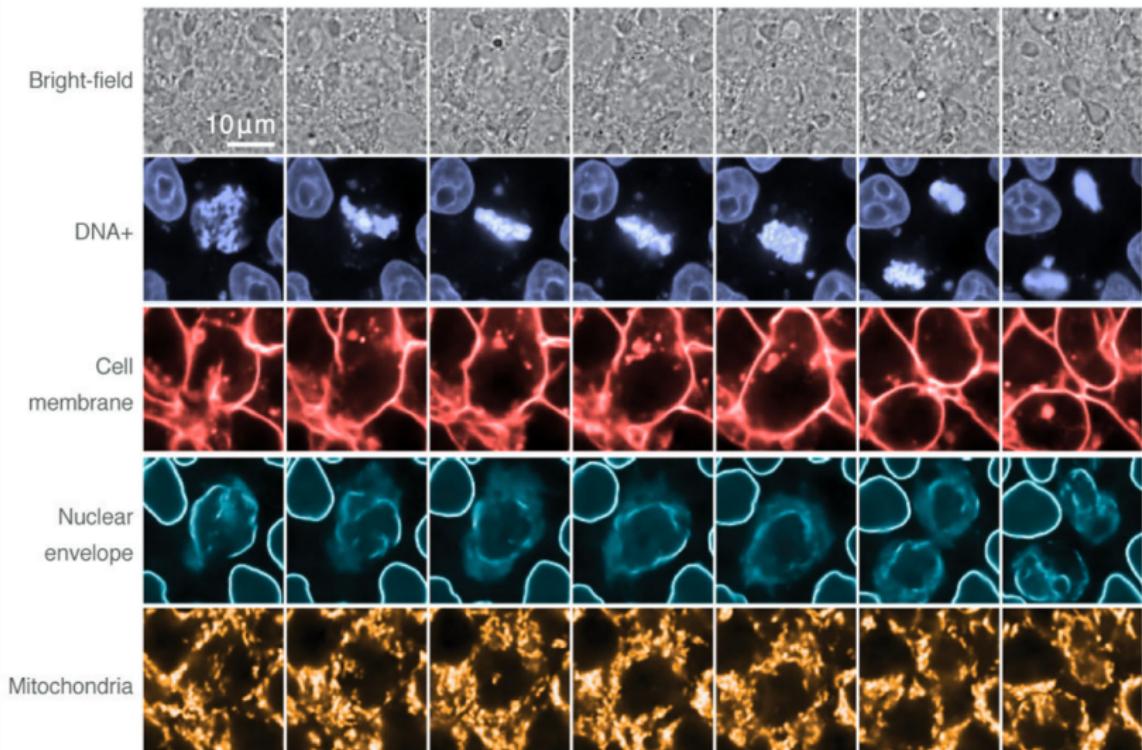


Worst count



Credits: Tristan Lazard, master thesis.  
Images: L'Oréal.

# Microscopy cross-modality prediction [Ounkomol et al., 2018]



# Image segmentation

- Image segmentation is often an important step in an image processing work flow
- Image segmentation has been a very active deep learning research field

## Example



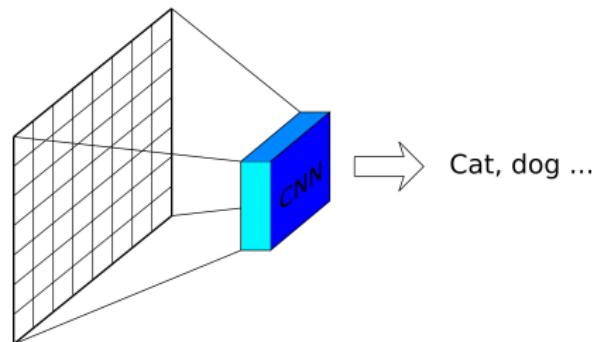
## Other applications

- Image filtering
- High dynamic range
- Style modification
- Motion estimation

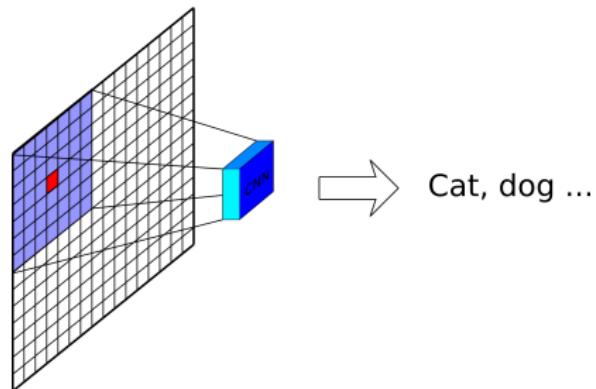
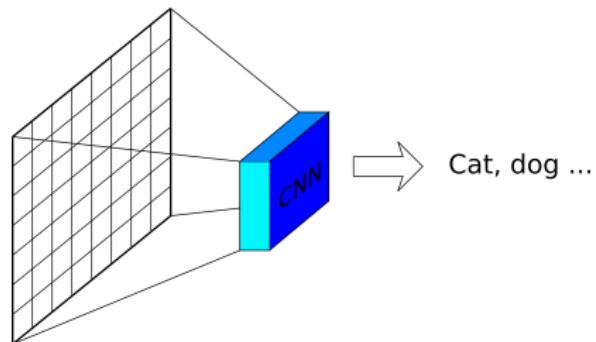
# Contents

- 1 Introduction
- 2 From classification to image-to-image translation
- 3 Properties of fully-convolutional neural networks
- 4 Image segmentation
- 5 Using fully-convolutional networks
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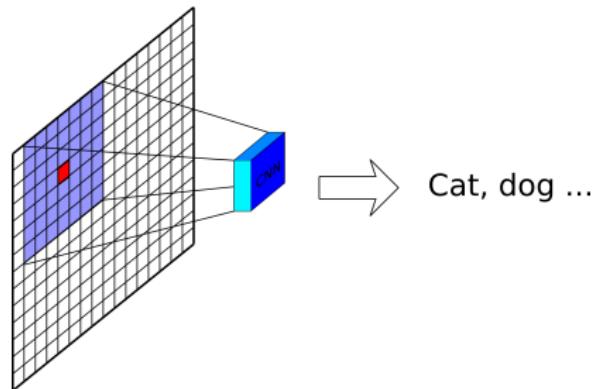
## From classification nets to image-to-image nets



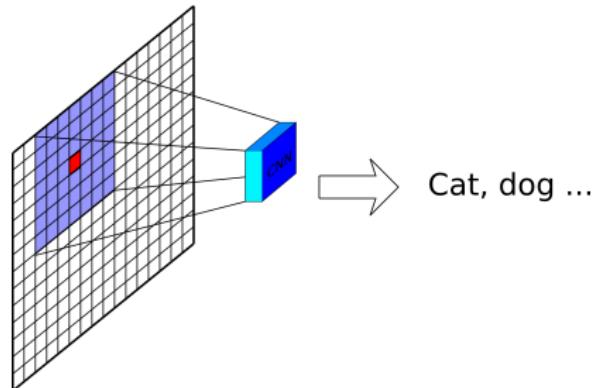
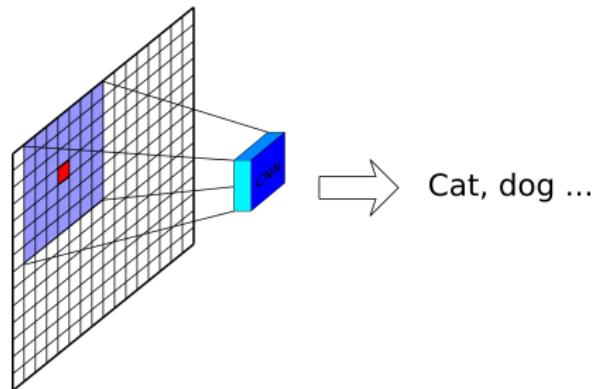
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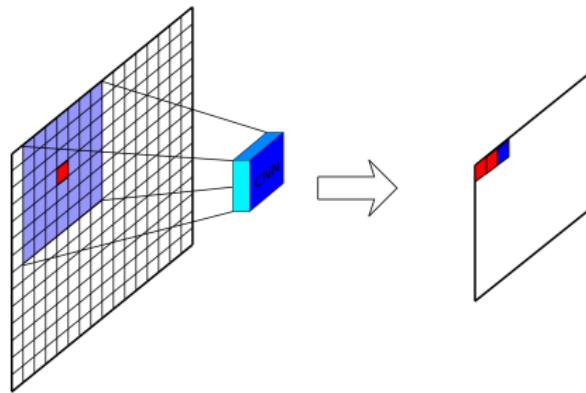
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## From classification nets to image-to-image nets



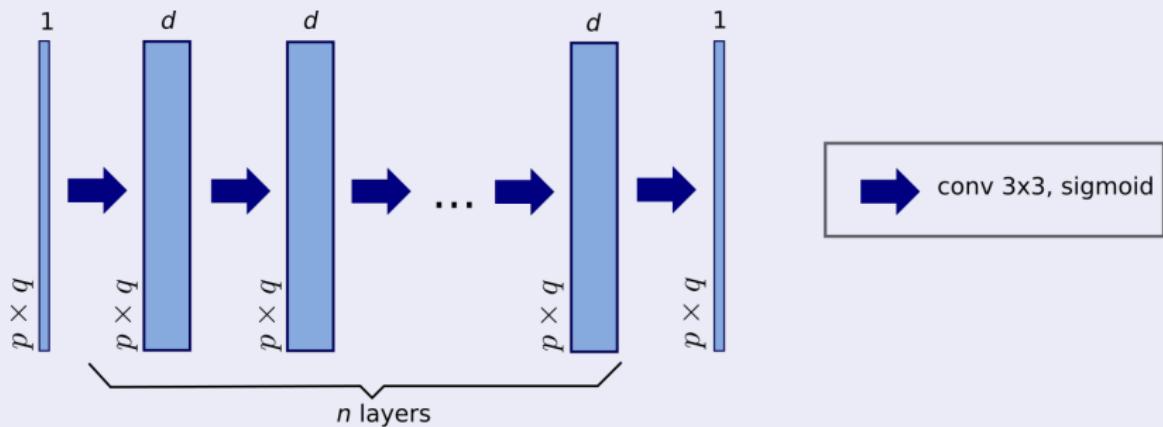
## From classification nets to image-to-image nets



- The neuron membrane segmentation challenge winner [Ciresan et al., 2012] used this strategy. It is inefficient.
- The idea to compute the whole output image with a single pass through the network had already been proposed [Feng Ning et al., 2005, Jain et al., 2007] (but with architectures more complex than those used today).

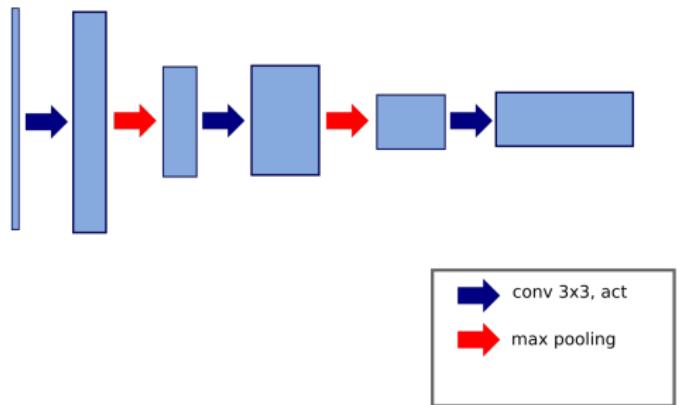
# The simplest image-to-image architecture

Example: plain CNN [Pang et al., 2010]

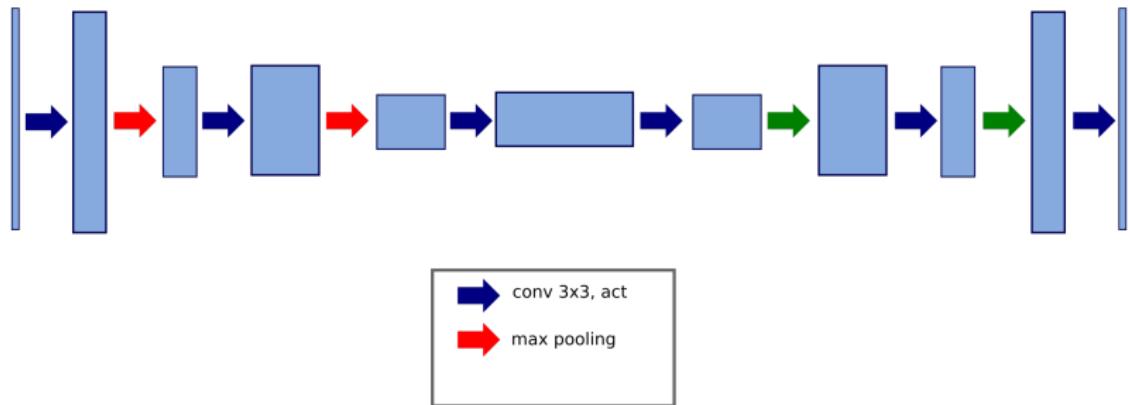


Note that today we would use ReLU activations on all layers except the last.

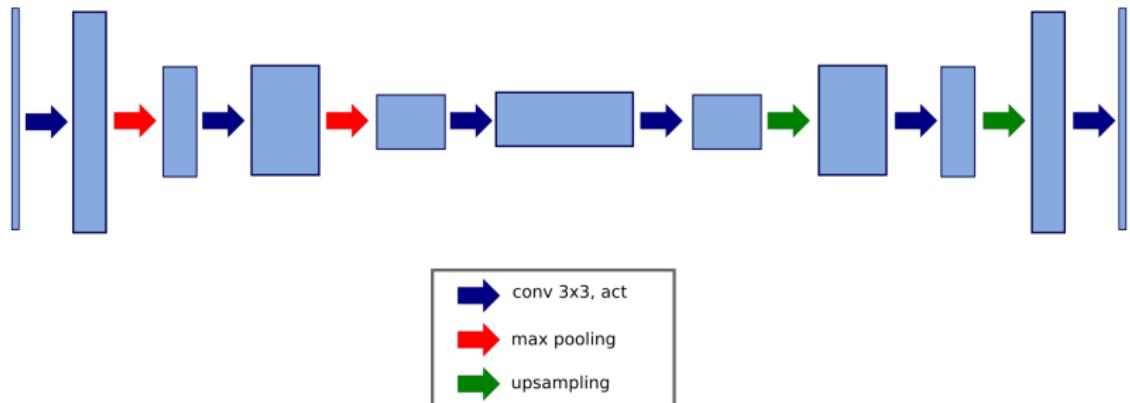
## Going back to the original image size



## Going back to the original image size



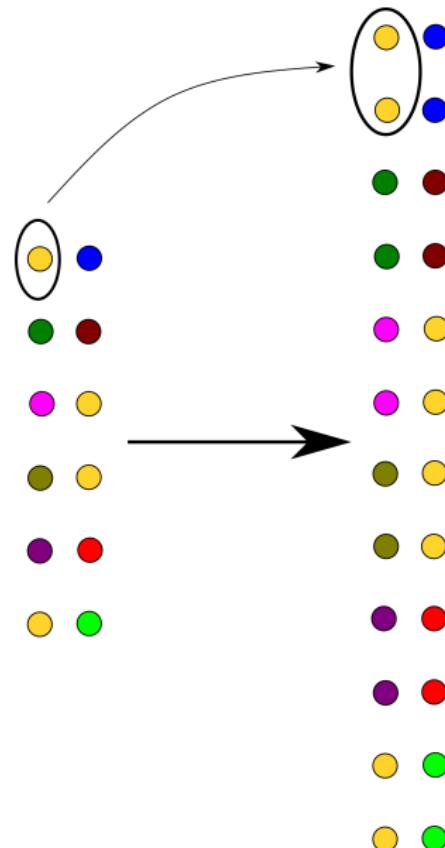
## Going back to the original image size



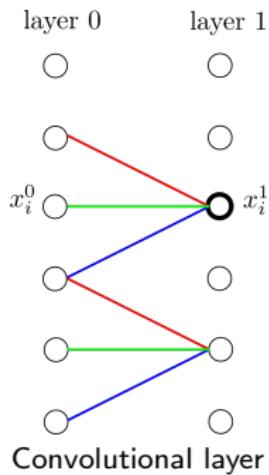
## Upsampling techniques

- Replication
- Transposed convolution
- Pooling index memorization

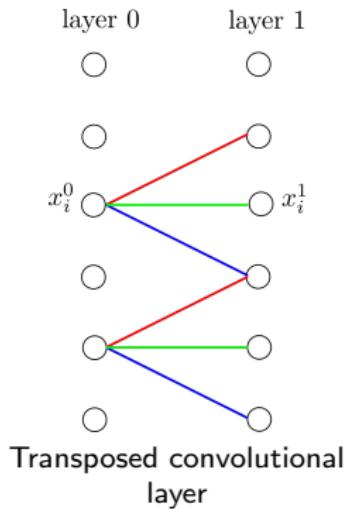
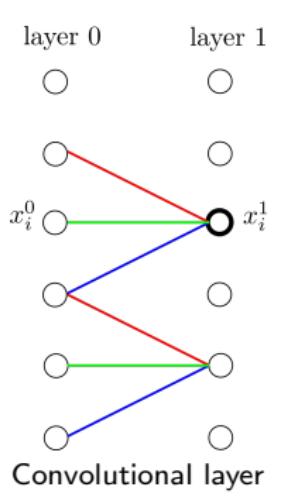
## Upsampling through replication



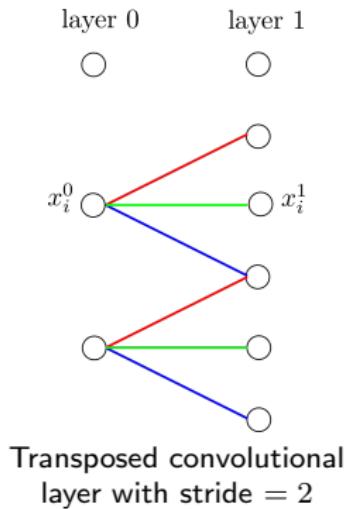
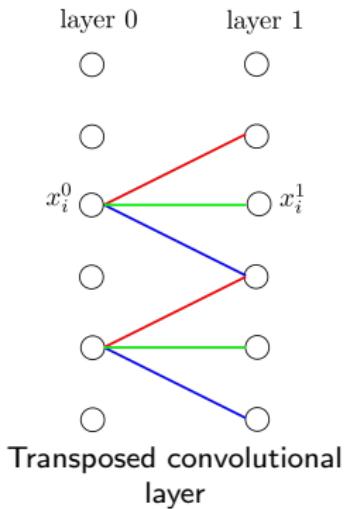
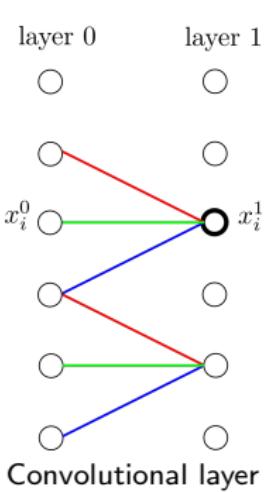
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# Contents

- 1 Introduction
- 2 From classification to image-to-image translation
- 3 Properties of fully-convolutional neural networks
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# Contents

- 1 Introduction
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# Receptive field

Definition: links between neurons

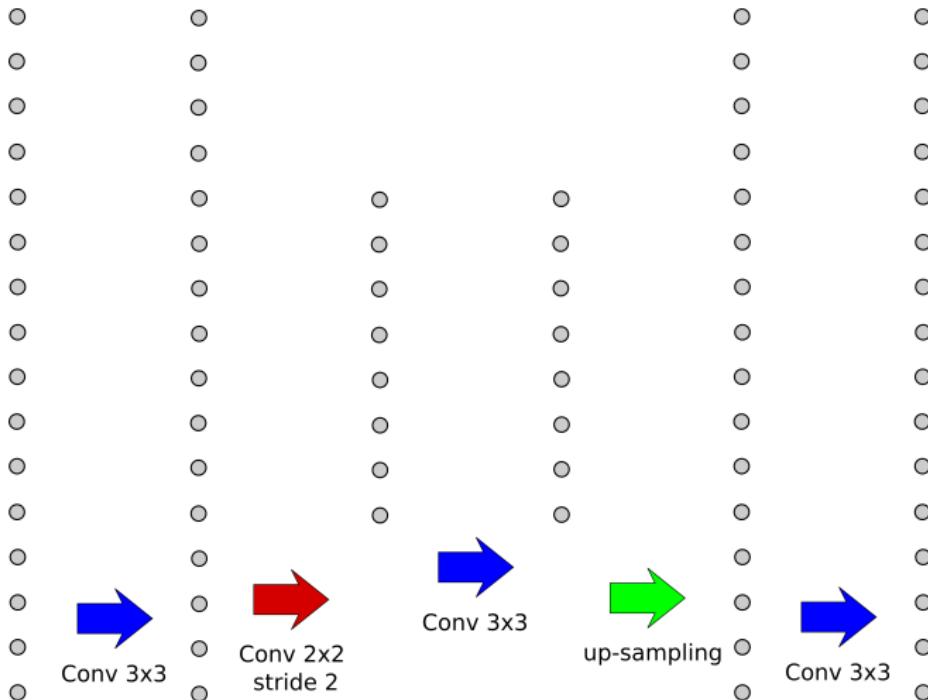
In a NN, we say that neuron  $a$  is linked to neuron  $b$  if there is an oriented path in the corresponding graph going from  $a$  to  $b$ .

Definition

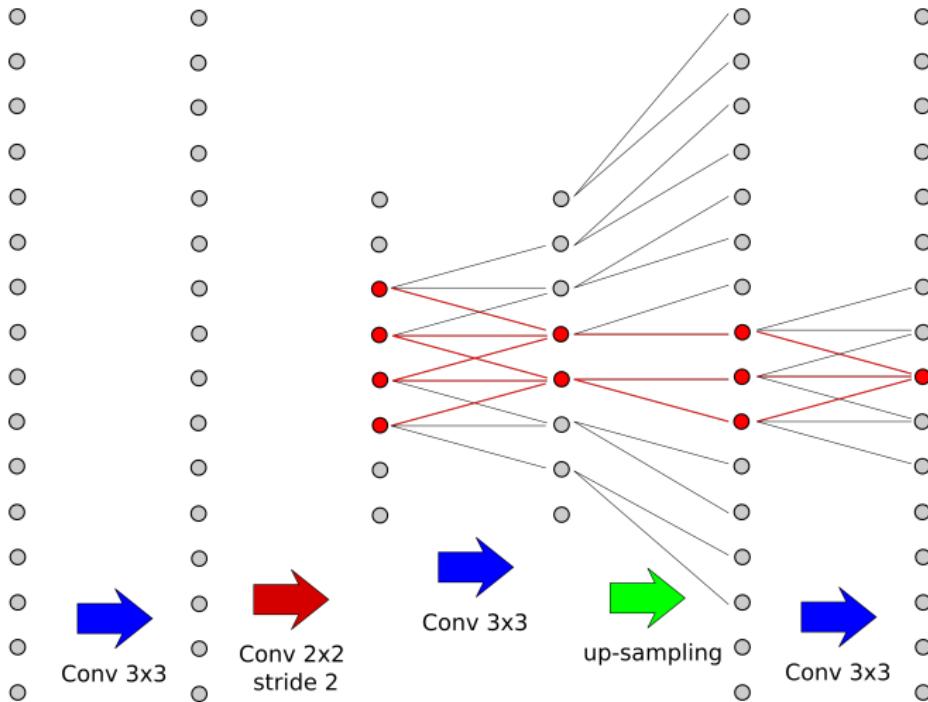
The **receptive field** of a neuron in a NN is the set of *input neurons* that are linked to that neuron.

The size of the receptive field is an essential property when designing a fully-convolutional NN architecture.

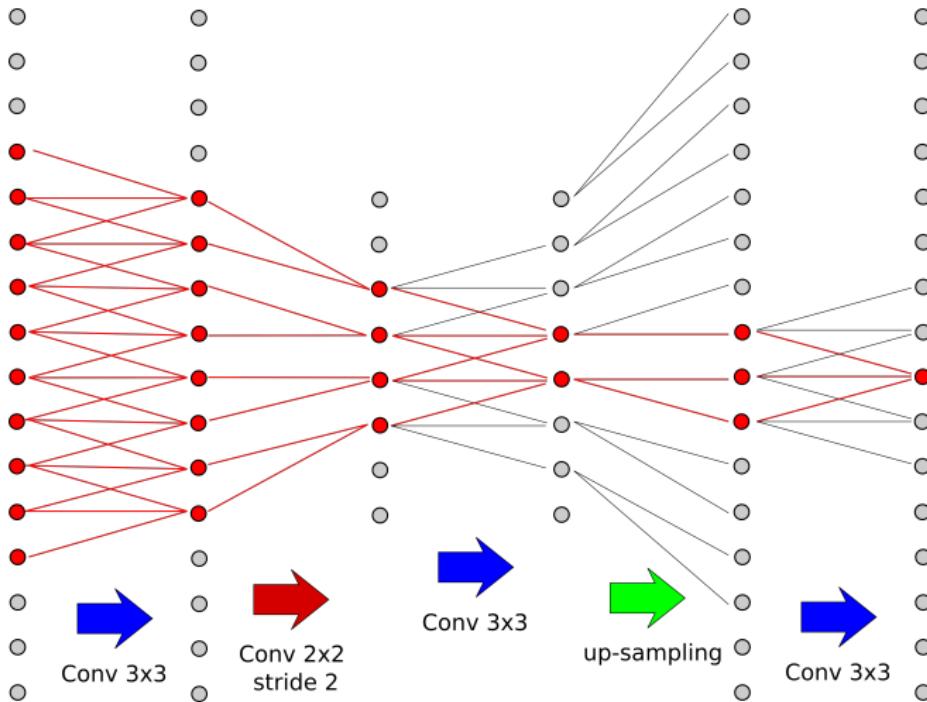
## Illustration



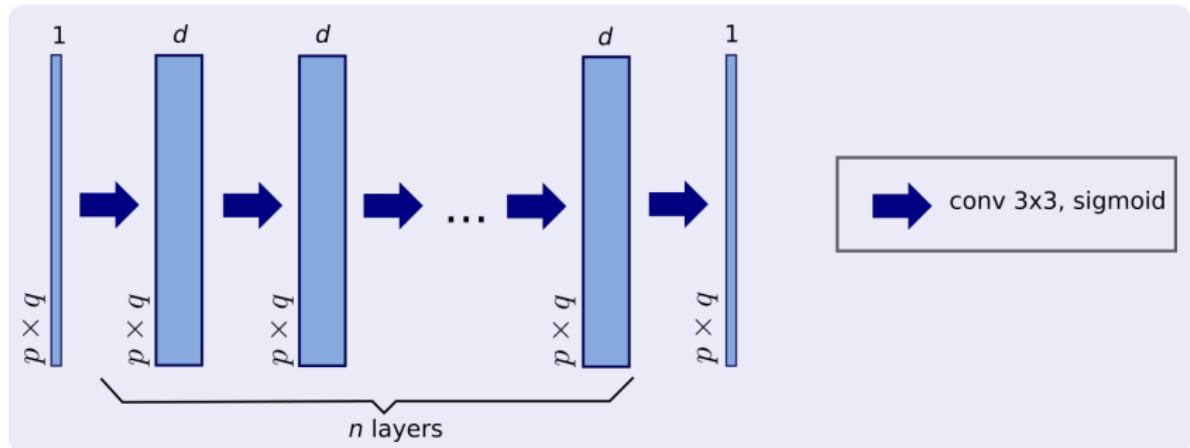
## Illustration



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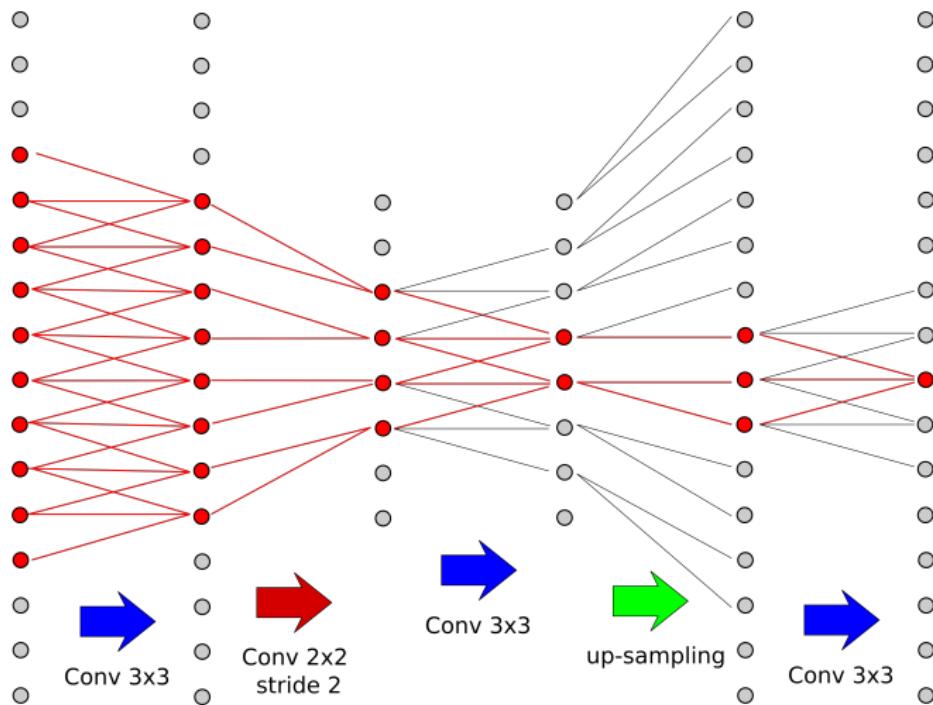
## Example



What is the size of the receptive field of the neurons in the last layer?

- A/  $n$
- B/  $1 + 2 \times n$
- C/  $1 + 2 \times (n + 1)$
- D/ It depends on the input image

## Effective receptive field: intuition



## Quizz

For a given output neuron  $y$ , what criterion seems sound to estimate the impact of a pixel  $x_{i,j}$  of its receptive field on its value?

A/  $\frac{\partial L}{\partial x_{i,j}}$

B/  $\frac{\partial y}{\partial x_{i,j}}$

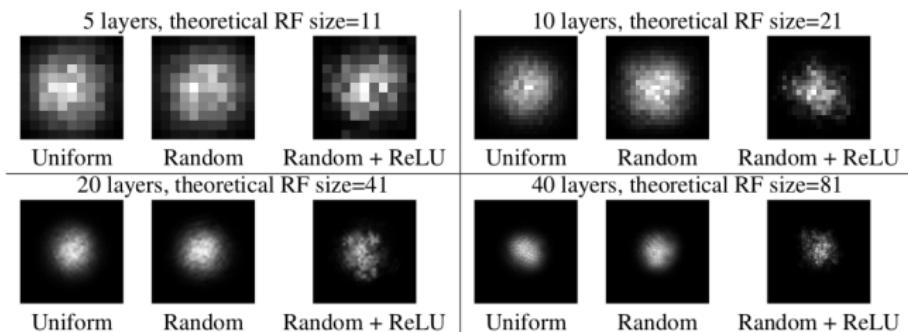
C/

D/

# Effective receptive field

## Shape of the effective receptive field

- Under some simplification hypotheses, the authors of [Luo et al., 2017] have shown that the effective receptive field has a gaussian shape.
- They have experimentally checked that this is (approximately) the case
- Moreover, as the network gets deeper, the size of the effective receptive field gets proportionally smaller



## Conclusion on the receptive field

- Establish its minimal required size with respect to the application
- Make it larger than that...

# Contents

- 1 Introduction
- 2 From classification to image-to-image translation
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- 4 Image segmentation
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# Equivariance

## Definition

A function  $f : E \longrightarrow F$  is **equivariant** with respect to the functions  $t_E : E \longrightarrow E$  and  $t_F : F \longrightarrow F$  iff  $\forall x \in E$ :

$$f(t_E(x)) = t_F(f(x))$$

## Translation equivariance

- When  $E = F$  and  $t_E$  and  $t_F$  are the same, any, translation, then we have *translation equivariance*.
- Translation equivariance is an often sought property for image processing operators.
- Note that we often abusively say *invariant* to translation instead of *equivariant* to translation.
- Given that in all practical cases images are defined on a bounded set, this property is only true “far enough” from the borders

# Quizz

Which operator is NOT translation invariant?

- A/ Convolution ( $\text{stride} = 1$ )
- B/ Max-pooling ( $\text{stride} > 1$ )
- C/ Transposed convolution ( $\text{stride} \geq 1$ )
- D/ Upsampling ( $\text{stride} > 1$ )

# Translation equivariant operators

Operator	Translation equivariant
Convolution (stride= 1)	
Max-pooling (stride > 1)	
Transposed convolution (stride $\geq$ 1)	
Upsampling (stride> 1)	
Concatenation	
Addition	

# Translation equivariant operators

Operator	Translation equivariant
Convolution (stride= 1)	yes
Max-pooling (stride > 1)	
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Addition	yes

## Translation equivariance: comments

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- If padding is used in the network, border effects can be important.
- Translation equivariance is not always welcome!
- Position information can also be used in the network:
  - Through masks or segmentations
  - Through pixel coordinates

## Illustration

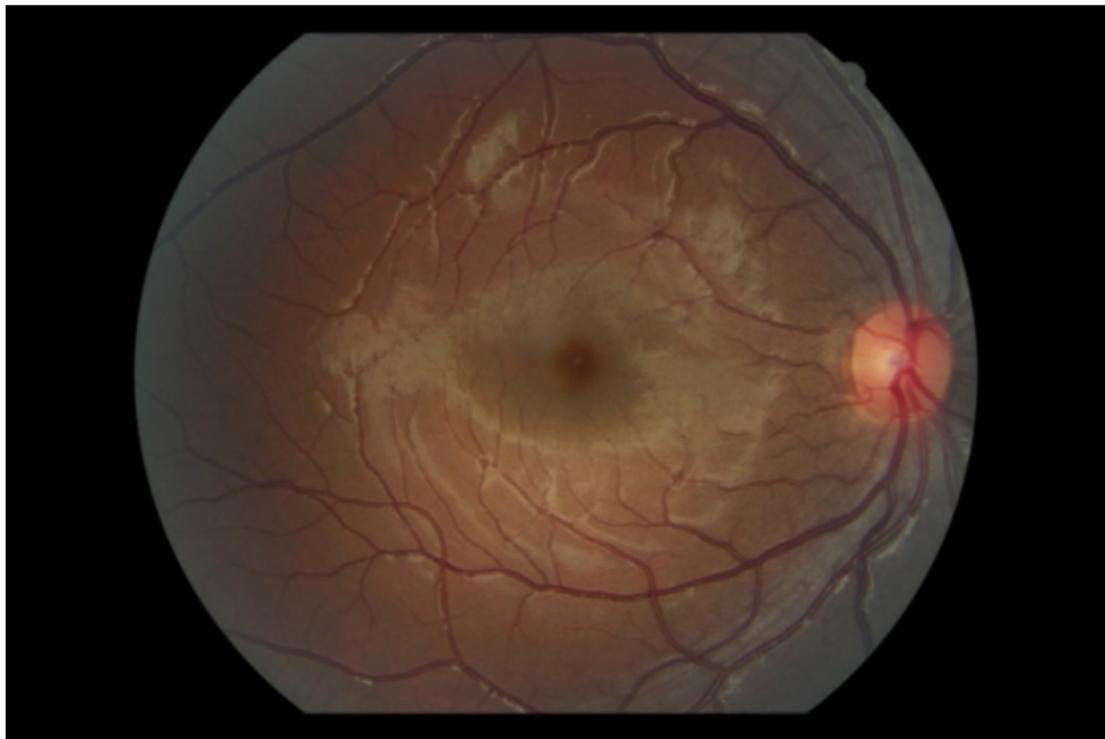


Figure: Eye fundus / retina image

Credits: OPHDIAT database

# Contents

1 Introduction

2 From classification to image-to-image translation

3 Properties of fully-convolutional neural networks

- Receptive field
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4 Image segmentation

5 Using fully-convolutional networks

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## Image size flexibility

- A NN containing fully-connected layers can only process images of a given size
- A fully convolutional NN can be applied to images of any size, as long as its dimensions are compatible with the subsampling steps of the network
- Practical limit: the memory of the system

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# Contents

- 1 Introduction
- 2 From classification to image-to-image translation
- 3 Properties of fully-convolutional neural networks
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# The specific case of image segmentation

## Definition: image segmentation

Let  $I$  be an image defined on  $D$ . A segmentation of  $I$  is a partition of  $D$ . In practice the regions of the segmentation should correspond to the objects in  $I$ , which is application dependant.

- A partition is often represented as a labelled image
- In order to make the segments symmetric, each one is represented by a different channel

## Image segmentation example



Credits: Pascal VOC database

## Some vocabulary on segmentation

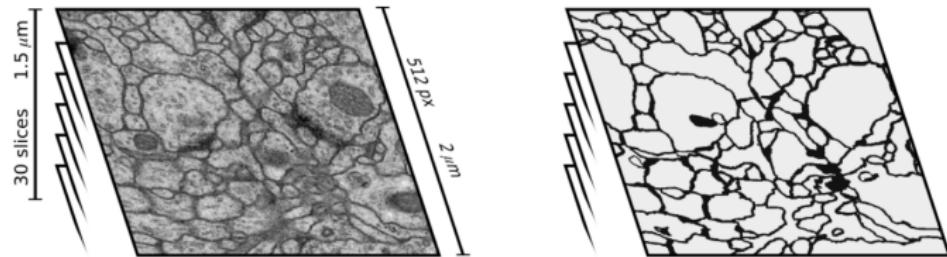
- **Object detection / localization:** bounding box around the object(s).
- **Binary segmentation:** segmentation in 2 classes, background and object.
- **Semantic segmentation:** a label is given to each pixel, according to the object it belongs to.
- **Instance segmentation:** identify each separate object, even if they belong to the same class.

# Contents

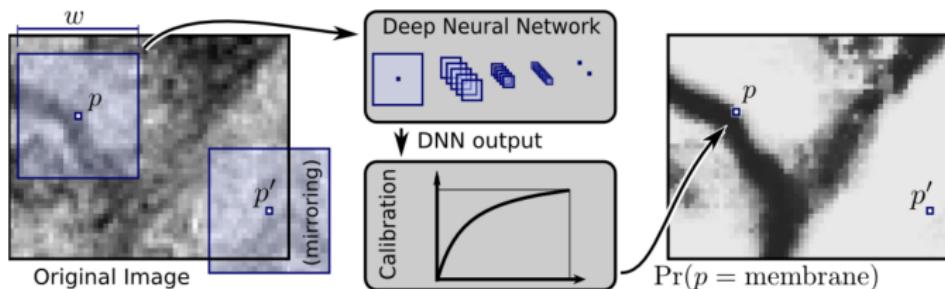
- 1 Introduction
- 2 From classification to image-to-image translation
- 3 Properties of fully-convolutional neural networks
- 4 Image segmentation
  - Binary segmentation
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- 5 Using fully-convolutional networks
- 6 Conclusion

# Neuron membrane segmentation challenge (ISBI 2012)

- Train: single stack of size  $30 \times 512 \times 512$ .
- Test: a second stack of same size.



# Neuron membrane segmentation challenge winner [Ciresan et al., 2012]

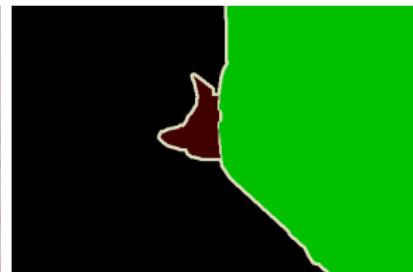


# Contents

- 1 Introduction
- 2 From classification to image-to-image translation
- 3 Properties of fully-convolutional neural networks
- 4 Image segmentation
  - Binary segmentation
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  - Instance segmentation
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- 5 Using fully-convolutional networks
- 6 Conclusion

# Pascal visual object classes segmentation challenge 2012 [Everingham et al., 2014]

- 1464 training and 1449 validation images
- automatic online test, with unknown images
- 20 image categories (cat, sofa, motorbike, person, etc.)



# Convolutional nets for semantic image segmentation

Three papers in 2015:

- Fully convolutional networks for semantic segmentation [Long et al., 2015]
- U-Net: convolutional networks for biomedical image segmentation [Ronneberger et al., 2015]
- SegNet: A Deep Convolutional Encoder-Decoder Architecture for Image Segmentation [Badrinarayanan et al., 2015]

## Remarks

- These architectures easily contain a number of parameters of the order of  $10^7$  (28 million for U-Net)
- Their optimization might be difficult
- But you can reduce the number of filters or the number of layers

# Contents

- 1 Introduction
- 2 From classification to image-to-image translation
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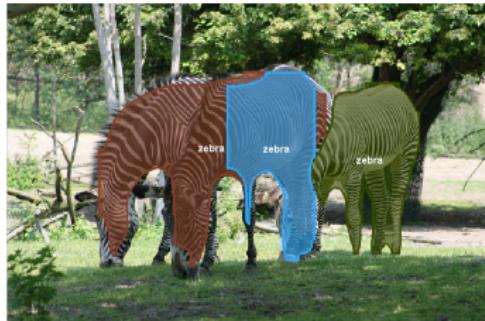
## COCO: common objects in context [Lin et al., 2014]

- 2 million objects, from 80 categories, in 300 000 images

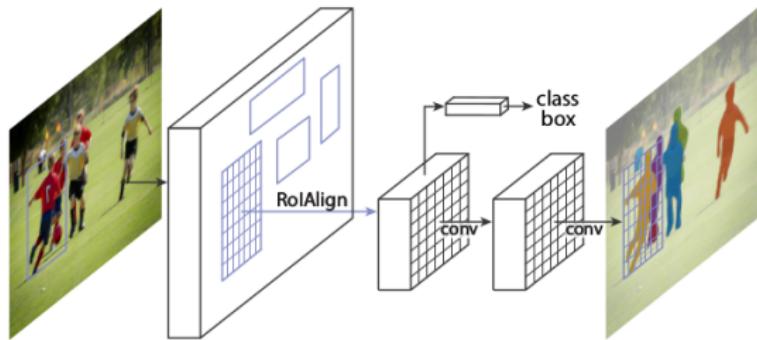


Winner 2016: Fully Convolutional Instance-aware Semantic Segmentation (Microsoft) [Li et al., 2016]

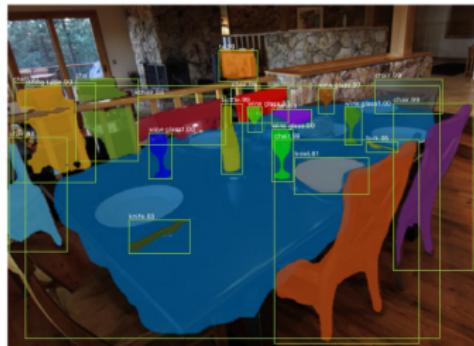
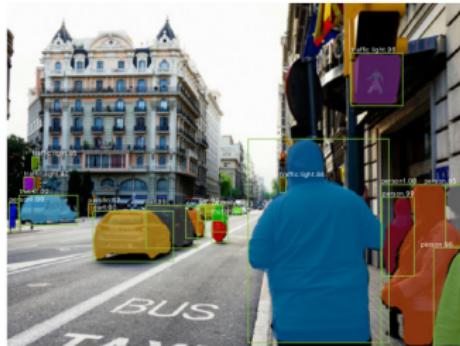
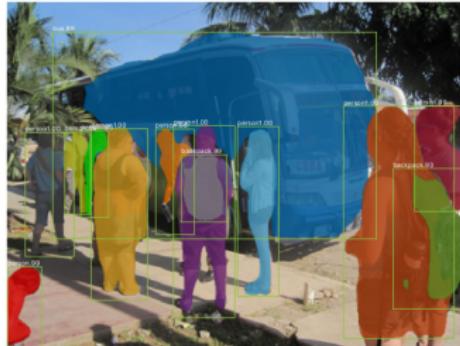
# COCO instance segmentation challenge: examples of 2016 winner results



# State of the art on the COCO database: Mask R-CNN [He et al., 2017]



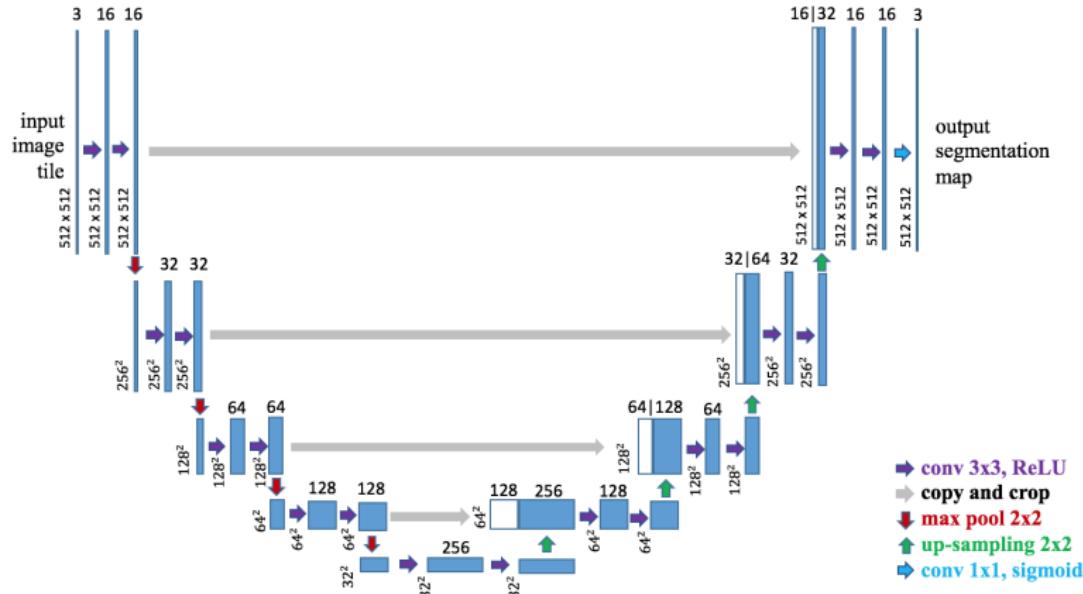
# Mask R-CNN on the COCO database



# Contents

- 1 Introduction
- 2 From classification to image-to-image translation
- 3 Properties of fully-convolutional neural networks
- 4 Image segmentation
  - Binary segmentation
  - Semantic segmentation
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- 5 Using fully-convolutional networks
- 6 Conclusion

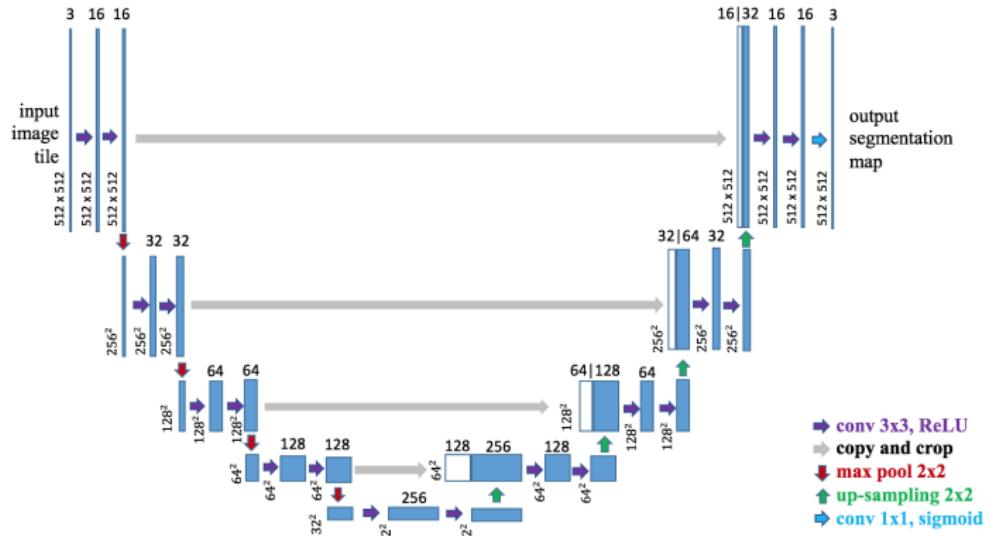
# U-Net architecture [Ronneberger et al., 2015]



## Quizz

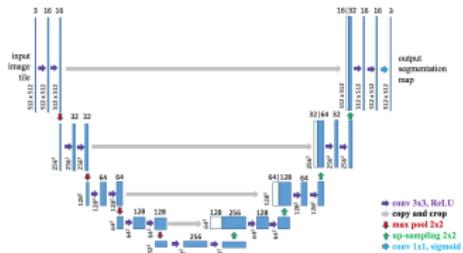
- Size and number of channels of input images?
- Segmentation into how many regions?

# U-Net main ideas



- Encoding branch inspired by classification nets
- Decoding branch is symmetrical
- Skip connections

# U-Net details



- Activation of the last layer: soft-max
- Other activations: ReLU
- Loss used in the original publication: cross entropy with a weight map  $w$  to favor some pixels:

$$L(\theta) = \sum_{M \in D} w(M) \log(\hat{y}_{l(M)}(M))$$

## U-Net improvements

- Convolutions with stride 2 instead of max-pooling in the encoder
- Transposed convolutions instead of simple up-sampling in the decoder
- Using an already optimized classification network as backbone for the encoder

# Contents

- 1 Introduction
- 2 From classification to image-to-image translation
- 3 Properties of fully-convolutional neural networks
- 4 Image segmentation
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  - make them as large as possible, to reduce border effects
  - take a small batch size (1, 2, 4?)

## Loss functions for image segmentation

- $\hat{\mathbf{y}} = (\hat{y}_i)$ : network output
- $\mathbf{y} = (y_i)$ : binary expected output
- We suppose that all  $\hat{y}_i$  are in  $[0, 1]$
- We want the  $\hat{\mathbf{y}}$  to be *as close as possible* to  $\mathbf{y}$

# Loss functions for image segmentation

A loss function inherited from image classification

- Cross-entropy:  $-\sum_i y_i \log(\hat{y}_i)$

# Measures used in image processing

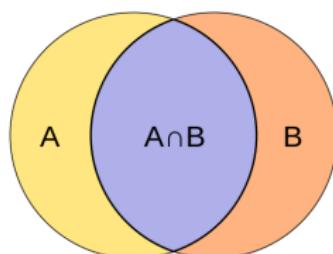
Let  $A$  and  $B$  be two sets, not simultaneously empty.

## Dice coefficient

$$D(A, B) = \frac{2|A \cap B|}{|A| + |B|}$$

## Jaccard index

$$J(A, B) = \frac{|A \cap B|}{|A \cup B|}$$



## Properties

- $\forall A, B : 0 \leq J(A, B) \leq D(A, B) \leq 1$
- If  $A = B$ , then  $D(A, B) = J(A, B) = 1$
- If  $A \cap B = \emptyset$ , then  $D(A, B) = J(A, B) = 0$

## Generalization to $[0, 1]$

$\mathbf{y}$  and  $\hat{\mathbf{y}}$  are in  $[0, 1]^n$ , not simultaneously equal to 0.

### Jaccard similarity

$$J(\mathbf{y}, \hat{\mathbf{y}}) = \frac{\sum_i y_i \hat{y}_i}{\sum_i y_i + \sum_i \hat{y}_i - \sum_i y_i \hat{y}_i}$$

## Corresponding loss function

$\mathbf{y}$  and  $\hat{\mathbf{y}}$  are in  $[0, 1]^n$ , not simultaneously equal to 0.

### Jaccard loss

$$j(\mathbf{y}, \hat{\mathbf{y}}) = 1 - \frac{\sum_i y_i \hat{y}_i}{\sum_i y_i + \sum_i \hat{y}_i - \sum_i y_i \hat{y}_i}$$

## Corresponding loss function - variant

$\mathbf{y}$  and  $\hat{\mathbf{y}}$  are in  $[0, 1]^n$ , not simultaneously equal to 0.

Constant  $\epsilon$ , which is typically “small”, keeps the denominator “far enough” from zero.

### Jaccard loss

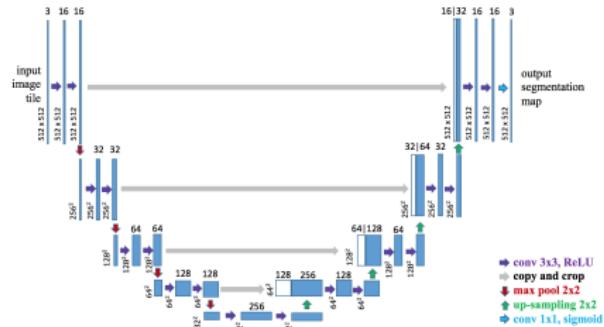
$$j_2(\mathbf{y}, \hat{\mathbf{y}}) = 1 - \frac{\sum_i y_i \hat{y}_i}{\sum_i y_i^2 + \sum_i \hat{y}_i^2 - \sum_i y_i \hat{y}_i + \epsilon}$$

This version works slightly better than the first.

## Conclusion on loss functions

- Use the Jaccard loss as base line for segmentation problems.
- Note that these losses compute their values pixel-wise: they do not take into account any structure (for example, continuity).
- Working on specific losses enforcing structure = interesting research path.

# Applying fully-convolutional networks



## Case study

Suppose that we have satisfactorily optimized this U-Net model, using images of size  $512 \times 512$  during training. Now I want to apply this model to a new image, of size  $1000 \times 1000$ . How should I proceed?

- Resize the image?
- Cut it into  $512 \times 512$  crops, predict and stitch the results together?

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## Image segmentation: a solved problem?

- Progress in image segmentation since 2012 has been enormous
- Several complex problems have now satisfactory solutions
- Training can be a problem (large annotated databases, difficult optimization)
- There are still challenges ahead...

## Some research subjects

- Optimization - a very general, and essential, subject
- Making training databases as small as possible
- Specific losses
- Taking *a priori* structural information into account

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