

A Reinforcement-Learning-Based Energy-Efficient Framework for Multi-Task Video Analytics Pipeline

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Abstract—Deep-learning-based video processing has yielded transformative results in recent years. However, the video analytics pipeline is energy-intensive due to high data rates and reliance on complex inference algorithms, which limits its adoption in energy-constrained applications. Motivated by the observation of high and variable spatial redundancy and temporal dynamics in video data streams, we design and evaluate an adaptive-resolution optimization framework to minimize the energy use of multi-task video analytics pipelines. Instead of heuristically tuning the input data resolution of individual tasks, our framework utilizes deep reinforcement learning to dynamically govern the input resolution and computation of the entire video analytics pipeline. By monitoring the impact of varying resolution on the quality of high-dimensional video analytics features, hence the accuracy of video analytics results, the proposed end-to-end optimization framework learns the best non-myopic policy for dynamically controlling the resolution of input video streams to achieve globally optimize energy efficiency. Governed by reinforcement learning, optical flow is incorporated into the framework to minimize unnecessary spatio-temporal redundancy that leads to re-computation, while preserving accuracy. The proposed framework is applied to video instance segmentation which is one of the most challenging machine vision tasks, and the energy consumption efficiency of the proposed framework has significantly surpassed all baseline methods of similar accuracy on the YouTube-VIS dataset.

Index Terms—energy-efficient, vision, multi-task application, reinforcement learning

I. INTRODUCTION

Recently, deep learning has achieved great success on video-based machine vision tasks [1], [2], [3]. Deep models such as MaskTrack R-CNN [2] are widely employed for multi-task video analytics, such as object detection, object classification, and segmentation. Deep models are generally energy-intensive due to the high amount of video stream data to process, which

constrains their adoption in energy-constrained scenarios such as edge computing [4]. However, the ability to perform intelligent video analytics in energy-constrained edge devices is becoming increasingly important with the fast expansion of the artificial intelligence of things [4], [5]. There is an urgent need to develop energy-efficient multi-task video analytics techniques.

This work aims to optimize the energy efficiency of video analytics tasks using a variable-resolution strategy. This is inspired by the observation that abundant data redundancy potentially exists in multi-task video analytics applications. As illustrated in Fig. 1, this enables two widely used machine vision tasks, i.e., object detection and semantic segmentation, to optimize efficiency while maintaining acceptable accuracy across a wide range of data resolutions. Real-world data redundancy offers us opportunities to optimize energy efficiency via variable-resolution analysis.

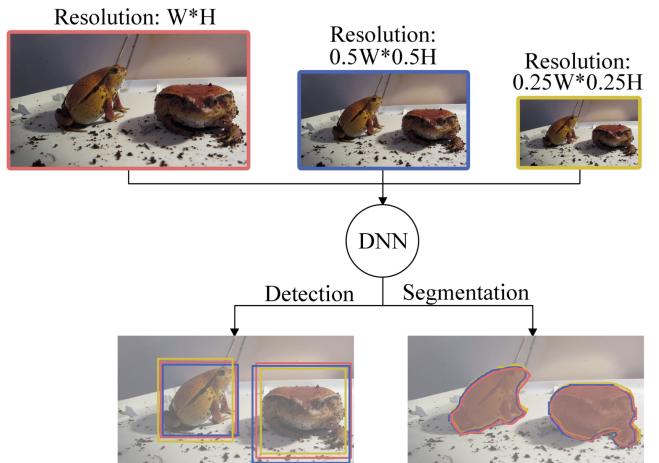


Fig. 1: Object detection and segmentation results of a sample input image with different resolutions: The red/blue/yellow edges indicate the results of the same image with resolution $W * H$, $\frac{W}{2} * \frac{H}{2}$, and $\frac{W}{4} * \frac{H}{4}$. We can see that the detection and segmentation results are very similar for the three resolutions, and the general performance is acceptable across different resolution settings.

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Another example is shown in Fig. 3, and we can see that even for the same task, i.e. face detection shown in Fig. 3), it is still difficult to find appropriate frame resolutions due to the varying frame analysis difficulty. We aim to make online decisions on frame resolutions that can lead to globally optimized energy efficiency.

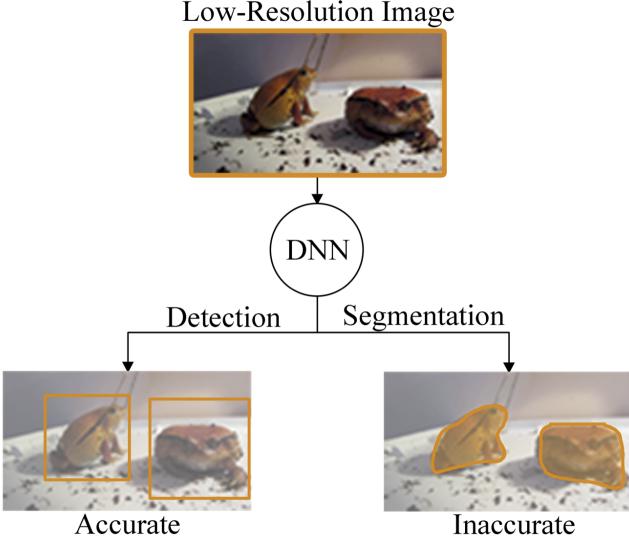


Fig. 2: Object detection and segmentation results for a low-resolution frame: the bounding boxes of the detection task are still accurate, while the predicted segmentation mask becomes less accurate with unsatisfying visual qualities. Different tasks may require different resolutions to produce adequate results.

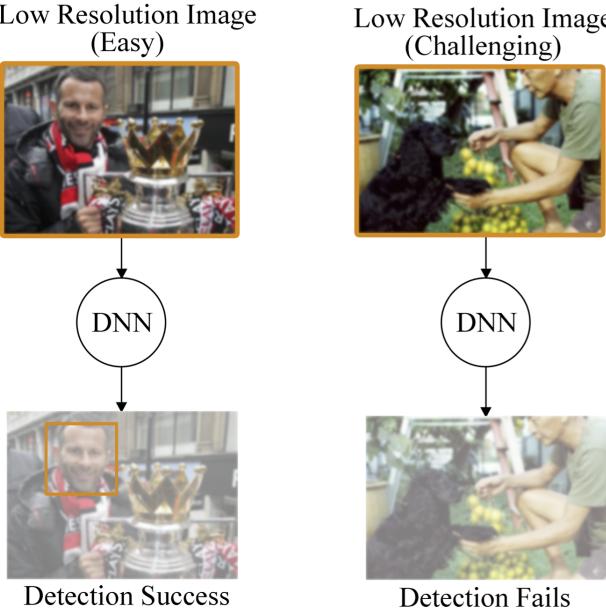


Fig. 3: For two facial images with identical low resolutions, face detection accuracy may be adequate on one (*Left Column*) and fail on another (*Right Column*). This indicates that even for the same video analytics task, the suitable frame resolutions vary with frame analysis difficulty.

The complicated temporal dynamics of video streams also pose a challenge. Reducing resolution has the potential to reduce accuracy. However, such accuracy loss can be effectively compensated by an estimator that is aware of the historical

temporal information in video streams. As shown in Fig. 4, our estimator additionally incorporates the historical information from earlier, high-resolution frames to generate more robust and more accurate predictions, despite that the current frame with reduced resolution can be misleading to DNN models. Therefore, accurate estimation requires the online analysis of video temporal changes.

In this paper, we propose to use reinforcement learning (RL) to holistically overcome these challenges: (1) complexity variations among different tasks, (2) variable difficulty of different samples, and (3) complicated temporal dynamics. To globally optimize energy efficiency, our RL network learns the best non-myopic policy of determining the spatio-temporal frame resolution of incoming video stream data. Compared with other energy-efficient single-task video analytics solutions [6], [7] that were designed for still images without utilizing temporal information, our work is the first to address the energy consumption optimization problem for multi-task video analytic pipeline, and it is also the first to leverage RL to holistically tackle all the challenging problems and to do end-to-end global efficiency policy optimization.

Our analysis pipeline is illustrated in Fig. 5. Frame images have variable resolution (e.g., $\frac{W}{2} * \frac{H}{2}$, $\frac{W}{4} * \frac{H}{4}$ and $\frac{W}{8} * \frac{H}{8}$, and denoted as non-key frames), or remain unchanged (key frames with resolution $W * H$). To leverage temporal information and compensate for the performance reduction introduced by lower resolution, we incorporate contextual optical flow [8] for feature estimation as suggested by Zhu *et al.* [9]. The energy optimization problem, specifically, determining frame resolutions with respect to multiple tasks and temporal dynamics, is considered as an end-to-end optimization problem and is modeled as a Markov Decision Process (MDP), which is solved using RL [10].

To evaluate the proposed framework, we have applied it to video instance segmentation [2], a synthesis video analytics pipeline consisting of simultaneous detection, segmentation, and tracking of object instances. Video instance segmentation is considered as one of the most challenging multi-task video analytics applications, as it requires the predictions of instance-level segmentation masks while tracking and identifying each instance at the same time. Our experimental results on the YouTube-VIS dataset [2] indicate that our proposed solution achieves the best energy efficiency among all baseline methods.

In summary, this work makes the following contributions:

- 1) This work presents an adaptive-resolution framework for multi-task video analytics under energy-constrained scenarios. The raised challenges are managed and end-to-end analyzed by Reinforcement Learning (RL) algorithms aiming to globally optimize the energy efficiency. To the best of our knowledge, this is the first time that RL has been employed to learn a non-myopic policy for such an energy-efficient framework.
- 2) We have applied the proposed framework to video instance segmentation [2], one of the most challenging multi-task machine vision tasks, and it is shown that the energy efficiency of the proposed framework sig-

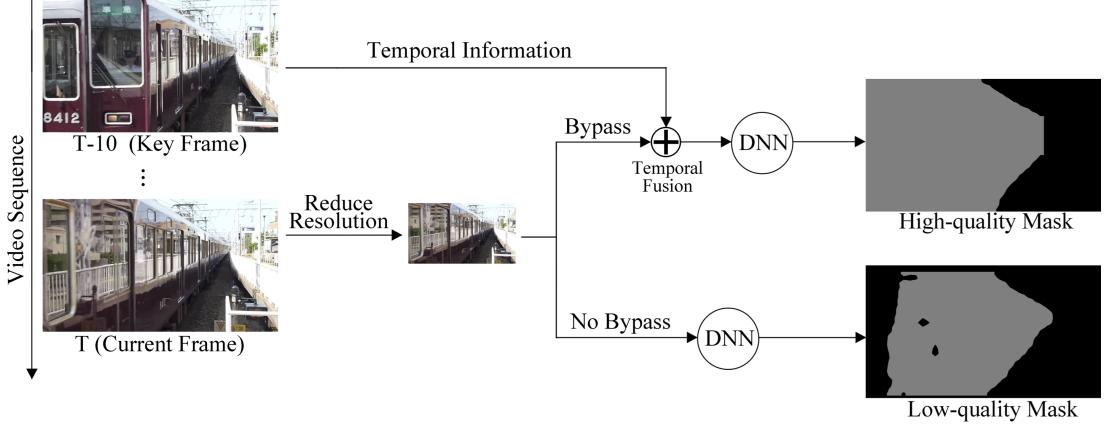


Fig. 4: An illustration of the temporal estimation mechanism for the semantic segmentation task. Without estimation, a low resolution frame (e.g., T in the figure) may lack important semantic information and can lead to low-quality segmentation masks. However, we can compensate by exploiting spatio-temporal redundancy to estimate the missing high-resolution information (e.g., $T-10$ in the figure), which can produce segmentation results with high visual qualities.

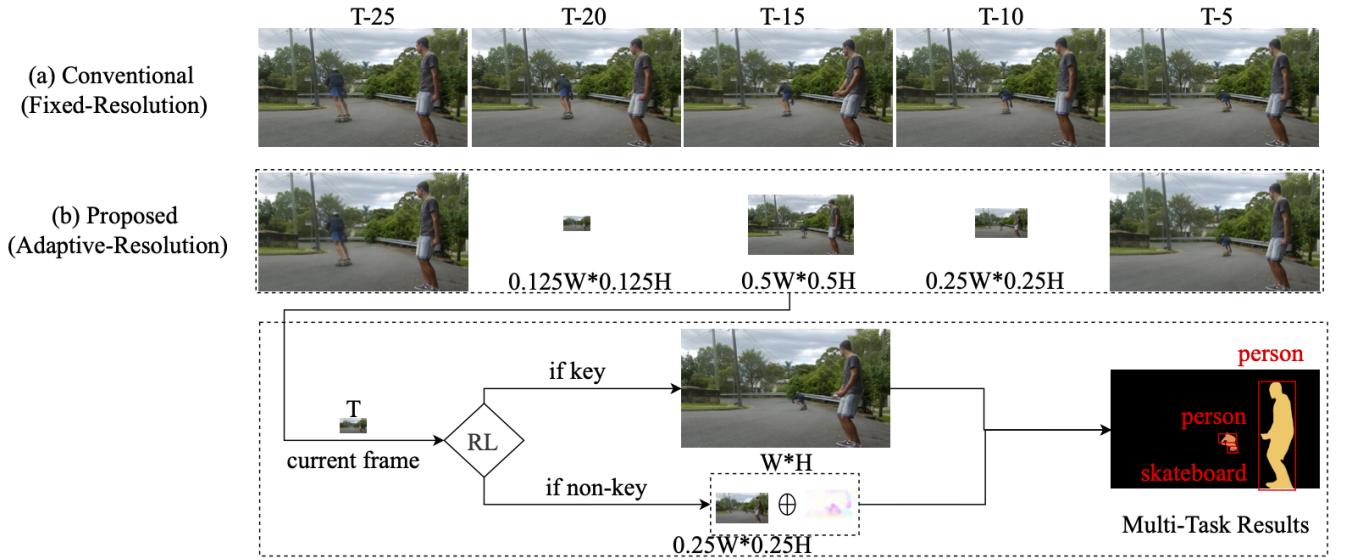


Fig. 5: An illustration of the proposed framework where video frames are shown in every 5 frames. (a) Common fixed-resolution frames in multi-task video analytics pipeline. (b) The proposed adaptive-resolution multi-task video analytics pipeline.

nificantly outperforms all baseline methods of similar accuracy.

The rest of this paper is organized as follows. Section II surveys related work. Section III analyzes the spatio-temporal data redundancy in video stream. Section IV characterizes the energy consumption of imaging systems. Section V provides the problem definition. Section VI describes the energy-efficient framework. Section VII presents experimental results. Section VIII concludes this work.

II. RELATED WORK

The most relevant works are those on energy-efficient machine vision and feature propagation with optical flows.

Energy-Efficient Machine Vision: Kulkarni *et al.* proposed to optimize energy efficiency by varying frame resolution in a multi-camera surveillance network [11], which significantly reduced energy usage (85% or more) while providing comparable reliability. LiKam Wa *et al.* proposed a power model based only on hardware [12]. This model reduces

power consumption by 30% for video capturing by optimizing camera clock frequency. Based on the power model proposed in [12], Ekdeep *et al.* analyzed sensing energy and proposed the energy model for imaging systems [6]. This work indicated that system energy consumption depends significantly on the transferred resolutions in imaging systems, and thus they proposed to optimize energy usage by using a multi-phase capture-and-analysis approach in which low-resolution, wide-area captures are used to guide high-resolution, narrow captures, thus eliminating task-irrelevant image data capture, transfer, and analysis. Later, Lubana *et al.* [7] proposed an application-aware compressive sensing framework, which reduces channel bandwidth requirements and signal communication latency without substantial performance drop by reducing unimportant data (i.e., pixels) transmission and analysis, thereby compressing application-related data representation. Additionally, a two-stage variant-resolution solution is proposed by Wang *et al.* [13], which implemented object detection using low-resolution images and

conducted recognition using high-resolution images. Their experimental results demonstrated that the resolution can be reduced by 51.4% with comparable recognition accuracy. Feng *et al.* proposed to detect and track moving objects in video to reduce the data volume in video-based machine vision applications [14].

Our method differs from the prior works in two ways: (1) we consider the complicated temporal dynamics in video streams and leverage a temporal bypassing system to better estimate high-resolution spatial information and (2) our work is end-to-end, considering all the challenging factors in multi-task video analytics (e.g., the complexity variations among different tasks and spatial and temporal dynamics in video data) as a complete system using RL to optimize the energy efficiency of the entire multi-task video analytics pipeline.

Feature Propagation Methods: Zhu *et al.* [9] presented a Deep Feature Flow (DFF) method which propagates the intermediate features between video frames via optical flow [15]. DFF accelerates the computation time of the video analytics pipeline by using cheap optical flow calculation instead of computation-intensive feature extraction with backbone networks. Their work schedules the key frames at a fixed interval. In contrast, Wang *et al.* [16] presented a more flexible key-frame scheduler to accelerate semantic segmentation [17], [18], [19] in videos while preserving the segmentation accuracy. They modeled the key decision process as a deep RL problem and learned an efficient scheduling policy by maximizing the global return, hence the global performance.

Xu *et al.* demonstrated a dynamic video segmentation network (DVSNet) for fast and efficient video semantic segmentation [20]. They designed a light-weight decision net to determine whether the current frame is sent to the fast warping path or the computational-intensive segmentation path. Xu *et al.* [20] considered deviations from the current frame and the last key frame to judge whether it is appropriate to schedule a key frame.

In contrast with prior work focusing on single computer vision tasks, we tackle the more challenging multi-task video analytics problem and use feature propagation with the optical flow to exploit temporal redundancy to estimate high-resolution spatial information. This is controlled by RL-based policy network, concurrently with other challenging components.

III. DATA REDUNDANCY ANALYSIS

Video data is inherently redundant, both spatially and temporally. In this section, we characterize the data redundancy of video data at different resolutions, and demonstrate that it is possible to apply lower-resolution settings to help reduce data redundancy, hence the energy consumption of video analytics tasks, while maintaining acceptable task performance.

A. Redundancy Analysis

We first analyze spatial data redundancy by varying frame resolutions and then evaluate the resulting impacts on the performance of video analytics tasks. We consider two commonly used machine vision tasks: face detection with still

images and video-based object detection. For each task, we uniformly subsample the original image/video frames at several reduced resolutions and determine the resulting accuracy. The downsampling factor is defined as the ratio of resized image pixels to original image pixels. For face detection, we evaluate the performance of the S³FD architecture [21] on the WIDERFACE [22] dataset, and for video-based object detection, the MaskTrack R-CNN architecture is utilized and its object detection performance on YouTube-VIS dataset [2] is reported. Since both are detection tasks, we employ the mean Average Precision (mAP) as the performance metric and follow the COCO evaluation metrics¹ to average 10 Intersection over Union (IoU) thresholds from 50% to 95% in 5% intervals. Note that the WIDERFACE dataset divides the samples into three difficulty categories: *easy*, *medium*, and *hard*, which are plotted separately.

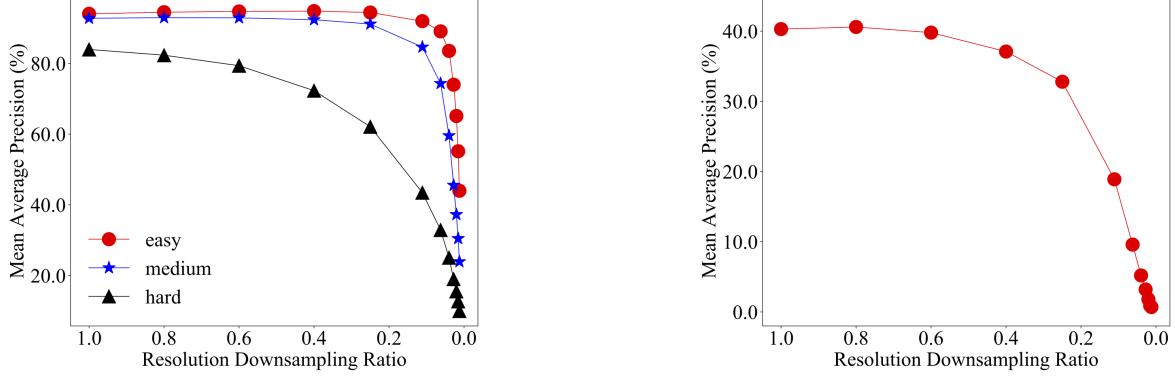
As demonstrated in Fig. 6a and Fig. 6b, the task performance (mAP) degrades gracefully with the decrease of data resolution. For instance, when the resolution downsampling ratio is greater than 0.3 (30% of the original pixels), the performance degradation remains insignificant (e.g., 0.4% for the *medium* data). In short, discarding 70% of the original data greatly improves energy consumption with little impact on accuracy. In addition, Fig. 6a demonstrates that, for the *easy* data set, the task performance remains acceptable until the resolution reduces to approximately 0.1 (e.g., 10% of the original pixels), while the accuracy of the *hard* data set deteriorates significantly as the resolution approaches 0.5. This study demonstrates that it is possible to apply spatial resolution reduction with limited impact on performance, yet it remains a challenge to determine the appropriate resolution for individual frames with varying difficulties.

B. Dynamics Analysis

Consecutive video frames generally share a large fraction of similar pixels, which can lead to high temporal redundancy in video stream data. Fig. 7 shows one such example. Technically, it is unnecessary to re-compute the whole current frame given that we have already obtained the features of previous frames, i.e., we can utilize the features in the previous frames to accelerate the analysis of the current frame. Such techniques have been studied in the field of video segmentation, and we have adopted the Deep Feature Flow [9] framework following [20], [16] to address temporal redundancy. Specifically, if a current frame is determined as a non-key frame with low resolution, we use FlowNet [8] to obtain the optical flow between the current frame and the last key frame, and the computed optical flow is used to propagate features from the last key frame into the current one such that the performance drop caused by low-resolution frames can be effectively compensated for. More details can be found in Section VI.

To demonstrate the effectiveness of using Deep Feature Flow [9] to address the temporal redundancy, we integrate FlowNetC [8] into the MaskTrack R-CNN model and evaluate its performance on object detection and instance segmentation tasks using the YouTube-VIS dataset. As shown in Fig. 8a,

¹<https://github.com/cocodataset/cocoapi>

(a) Face detection using the S³FD method on the WIDERFACE dataset.

(b) Object detection using the MaskTrack R-CNN method on the YouTube-VIS dataset.

Fig. 6: Resolution versus mAP on different tasks.

the performance of a solo MaskTrack R-CNN model on object detection task will drop significantly when resolution downsampling ratio is extremely low (e.g. lower than 0.15). However, when optical flow has been integrated (“MaskTrack R-CNN+FlowNetC” in Fig. 8a), the resulting model can be much more tolerant to low-resolution images, demonstrating the importance of utilizing temporal information to eliminate spatio-temporal redundancy in video stream. A similar trend can be observed in Fig. 8b for the instance segmentation task. As a result, we utilize MaskTrack R-CNN+FlowNet for the non-key frames with lower resolutions, while for key frames, we still use MaskTrack R-CNN model that has shown better performance on higher-resolution images.

When bypassing temporal information, we can also potentially eliminate a great amount of temporal redundancy while retaining acceptable performance, which further demonstrates the feasibility of the adaptive resolution strategy. However, the temporal dynamics in video stream data are usually complicated and therefore difficult to analyze, highlighting the challenges of obtaining suitable frame resolutions. Such observations motivate us to propose the RL-based optimization framework.

IV. ENERGY CONSUMPTION ANALYSIS

In this section, we first characterize the energy consumption of imaging systems. Then, we demonstrate that the amount of energy consumption is highly related to the volume of input data.

A. Conventional Image Analysis Framework

A typical imaging pipeline starts with an image sensor that captures and converts the incoming light into electrical signals via a 2-D sensor array, and transfers the signals in the form of data frames to an image signal processor (ISP) and an application processor for digital signal processing and machine vision tasks [6]. Prior work indicates that data transfer, digital signal processing, and machine vision tasks account for more than 90% of the total energy [7], which depends strongly on the amount of data.

B. Energy Model

The energy consumption E of an imaging system (per image frame) is mainly due to data sensing, communication, and computation [6], as follows:

$$E = E_{\text{sensor}} + E_{\text{ISP}} + E_{\text{host}} + E_{\text{comm}}, \quad (1)$$

where E_{sensor} , E_{ISP} , E_{host} , and E_{comm} denote the energy consumption of image sensor, ISP, host application processor, and the communication interface between the sensor and ISP/application processor, respectively.

(1) Energy consumption of image sensing. The energy consumption of an image sensor is state-dependent (i.e., idle state, active state, and standby state). In the exposure phase (T_{exp}), the image sensor is idle and its power is modeled as $P_{\text{sensor},\text{idle}}$. In the active phase (T_{active}), the image sensor processes and outputs pixels, with one pixel per clock period [6]. The time duration T_{active} is therefore determined by the ratio of image frame resolution R_{frame} to the external clock frequency f , and the power consumption of the active state $P_{\text{sensor},\text{active}}$ is a linear function of sensor resolution R ($R \geq R_{\text{frame}}$). The image sensor consumes negligible power in standby mode [12] (0.5–1.5 mW, typically) so no corresponding term is required in the energy model. Equation 2 defines E_{sensor} as follows:

$$E_{\text{sensor}} = P_{\text{sensor},\text{active}}T_{\text{active}} + P_{\text{sensor},\text{idle}}T_{\text{exp}}, \quad (2)$$

where R and $P_{\text{sensor},\text{idle}}$ are sensor-specific parameters.

(2) Energy consumption of the ISP. The ISP is active during image processing (T_{ISP}), and idle during image sensing ($T_{\text{exp}} + R_{\text{frame}}/f$) and other machine vision tasks (T_{app}), as shown in Equation 3 [6].

$$E_{\text{ISP}} = P_{\text{ISP},\text{active}}T_{\text{ISP}} + P_{\text{ISP},\text{idle}}(T_{\text{exp}} + R_{\text{frame}}/f + T_{\text{app}}), \quad (3)$$

where $P_{\text{ISP},\text{idle}}$ and $P_{\text{ISP},\text{active}}$ are the idle and active power of the ISP, respectively. Prior work has shown that T_{ISP} is a nearly linear function of image resolution, and T_{app} is also strongly dependent on image resolution [6]. Therefore, the energy consumption of the ISP depends strongly on image

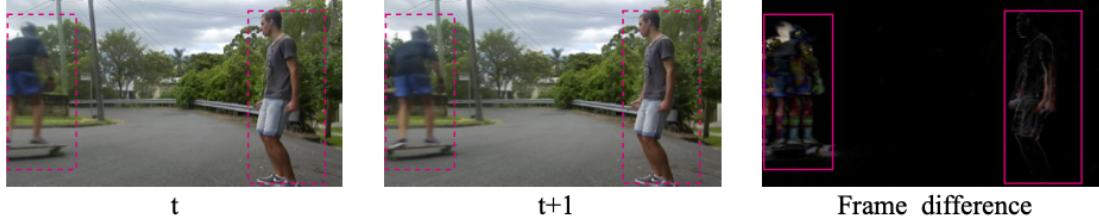


Fig. 7: Comparison of two frames at timestamps t and $t + 1$ in a video sequence. *Left* and *Middle*: Two consecutive video frames selected from the YouTube-VIS dataset. *Right*: Difference between the two frames. The dashed and solid red rectangles highlight the different parts, and we can see that those two frames share a large proportion of similar pixels.

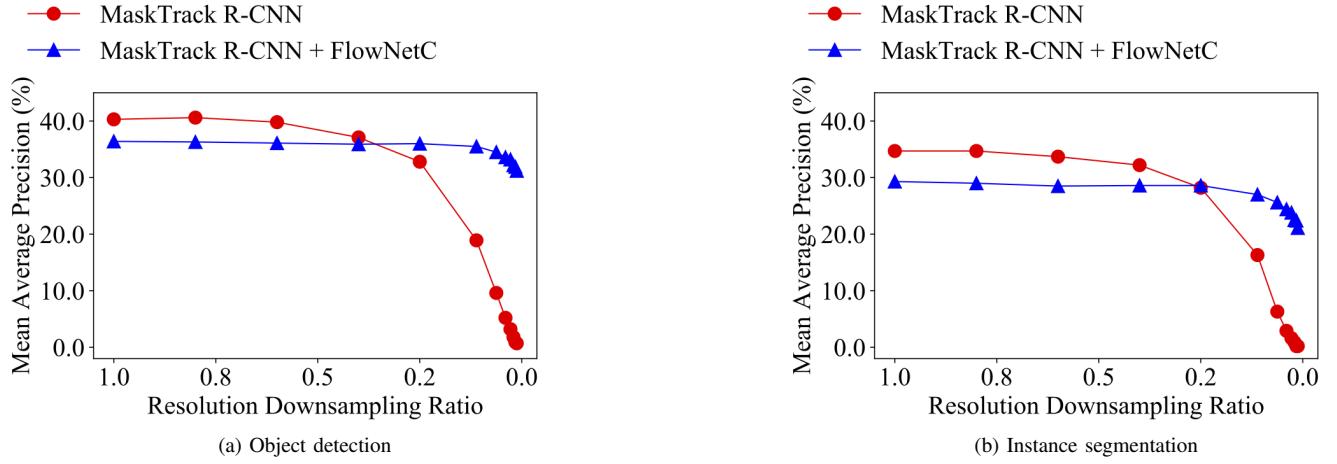


Fig. 8: mAP of MaskTrack R-CNN without and with FlowNetC (i.e., temporal bypassing with optical flow) on the YouTube-VIS dataset.

resolution.

(3) Energy consumption of application processor. The host application processor is active during machine vision task processing and idle otherwise, as shown in Equation 4 [6].

$$E_{host} = P_{host,active}T_{app} + P_{host,idle}(T_{exp} + R_{frame}/f + T_{ISP}), \quad (4)$$

where $P_{host,active}$ and $P_{host,idle}$ are processor dependent. Equation 4 also suggests that the energy usage of machine vision tasks strongly depends on image resolution.

(4) Energy consumption of communication interface. E_{comm} is a linear function of the total amount of data transferred (in pixels) [6], which is defined in Equation 5.

$$E_{comm} = k \cdot R_{frame}, \quad (5)$$

where k is a communication interface specific constant.

Equations 1–5 demonstrate that the energy consumption of an imaging system is a strong function of image data resolution, specifically, spatial resolution per frame as well as frame rate. Therefore, data reduction offers the most promising first-line treatment for imaging system energy optimization. However, data reduction may negatively affect video analytics accuracy, which motivates the following study on data redundancy and the impact on video analytics accuracy.

V. PROBLEM DEFINITION

The energy model in Section IV demonstrates that it is feasible to improve the energy usage efficiency by reducing frame resolutions. In Section III, we illustrate that the strategy

of adopting reasonably low-resolution frames can be potentially applied to energy-constrained scenarios, since it can effectively reduce the spatial and temporal data redundancy while preserving acceptable accuracy.

However, determining a suitable resolution for each video frame in the multi-task video analytic pipeline is a challenging problem, as we need to consider: (1) varying difficulties in different frames, (2) different levels of task complexities, and (3) complicated temporal dynamics in the video stream. If we fail to consider any of those factors, we may end up with resolution decisions that will lead to unsatisfying energy consumption efficiency.

In this work, we propose a holistic approach that simultaneously considers all those factors in an end-to-end fashion. Specifically, we define the process of estimating the energy-optimal frame resolutions as a Markov Decision Process (MDP), which is explained below.

A. Cumulative Reward

Let $\mathcal{A} = \{a^1, a^2, \dots, a^n\}$ be the set of n potential actions where each action represents using a certain frame resolution, e.g., 1/4 of the original size. We denote the policy of determining frame resolutions as π . Let s_t be the state to be considered by π at time step t , and let $a_t \in \mathcal{A}$ be the decision on the t^{th} frame's resolution, i.e., $a_t = \pi(s_t)$. Let ACC_{a_t} be the performance with a certain metric achieved by decision a_t on that frame, and let E_{a_t} be the energy consumption of that

decision, we can define the reward r_t at this time step as

$$r_t = ACC_{a_t} + \lambda \frac{1}{E_{a_t}}, \quad (6)$$

where λ is a hyper-parameter to trade off accuracy ACC_{a_t} and energy consumption E_{a_t} . A larger r_t is generally more desirable. For a video sequence of length m , our goal is to learn an optimal policy π for maximizing the cumulative rewards G that can be written as

$$G = \sum_{t=1}^m \gamma^{t-1} r_t = \sum_{t=1}^m \gamma^{t-1} \left(ACC_{a_t} + \lambda \frac{1}{E_{a_t}} \right), \quad (7)$$

where $\gamma^{t-1} \in [0, 1]$ and $a_t = \pi(s_t)$. However, it is difficult to determine a non-myopic policy π for realistic video analytics applications. In this paper, we adopt RL to maximize Equation 7, which is described in detail in Section VI.

B. Video Instance Segmentation

For evaluation purposes, we select video instance segmentation [2], a synthesis and challenging multi-task video analytics pipeline that has broad application scenarios. Specifically, instance segmentation consists of three major targets: (1) *object detection* to localize all objects in video frames; (2) *object classification* to assign category labels to the detected objects; and (3) *instance segmentation* to perform pixel-level classification for each instance. For video-based instance segmentation, an additional task named *object tracking* is defined in [2], which traces the object trajectory in video sequences. Currently, the YouTube-VIS [2] dataset is the widely-used public dataset that can be used for video instance segmentation task evaluation and thus is adopted in our evaluation.

MaskTrack R-CNN, a variant of Mask R-CNN [1], is proposed in [2] as the baseline method to solve the video instance segmentation problem. Fig. 9 illustrates the video instance segmentation framework based on MaskTrack R-CNN [2]. An input image of arbitrary size is first fed into the backbone network (or feature extractor) to obtain appropriate feature descriptors, and then a Region Proposal Network (RPN) [23] is leveraged to generate several potential Regions of Interest (RoIs) on those descriptors. RoI align [1] is utilized to convert each RoI candidate with variable size into fixed-size feature maps, e.g., 7×7 . After that, those fixed-size feature maps are fed into three branches of networks (referred to as “heads” [1]): (1) a Fully Connected (FC) network head to localize instances with bounding boxes and perform classifications; (2) a Fully Convolutional Network (FCN) to predict segmentation masks for each instance; and (3) a tracking network head for tracking instances in a video sequence. Note that the tracking head is not included in the original Mask R-CNN framework [1] and is inserted by Yang *et al.* [2] to meet the need of video instance segmentation tasks. For a fair comparison, we use this MaskTrack R-CNN model as the baseline method in this work.

VI. METHODOLOGY

In this section, we describe the proposed reinforcement-based adaptive-resolution framework for video instance segmentation in detail.

A. Framework Overview

As described in Section V, our goal is to develop an adaptive-resolution multi-task video analytics framework that optimizes energy consumption and accuracy. We model the adaptive resolution selection problem as an MDP. To maximize the cumulative reward G in Equation 7, we adopt the RL method to dynamically govern the spatial resolution and temporal dynamics of the complete video instance segmentation pipeline.

Let $\mathbf{I} = \{\mathbf{I}_1, \mathbf{I}_2, \dots, \mathbf{I}_m\}$ be a video sequence of length m , where \mathbf{I}_t denotes the frame image at time step $t \in \mathbb{Z} \cap [1, m]$. For a frame image \mathbf{I}_t of resolution $w_t * h_t$, where w_t and h_t refer to its width and height, respectively, we define the action set $\mathcal{A} = \{a^1, a^2, \dots, a^k\}$, where a^1 stands for using its original frame size $w_t * h_t$. a^2, \dots, a^k refer to downsampling \mathbf{I}_t to a lower resolution, e.g., $\frac{w_t}{2} * \frac{h_t}{2}$, $\frac{w_t}{4} * \frac{h_t}{4}$ and $\frac{w_t}{8} * \frac{h_t}{8}$. We denote the frame where action a^1 is used (i.e., without downsizing the frame image) as the key frame and others as the non-key frames. Therefore, our goal is to find a policy network π_θ that can map the state s_t at each time step t to an appropriate action a_t such that the cumulative reward G described in Equation 7 can be maximized. The RL with Double Q-learning (DDQN) [24] is used for optimization. Although various machine vision problems can be solved using this framework, we focus on video instance segmentation.

Specifically, given an incoming frame \mathbf{I}_t at time step t , video instance segmentation performs the following prediction tasks: (1) bounding box prediction \mathbf{b}_t , (2) object classification \mathbf{c}_t , (3) segmentation mask \mathbf{s}_t , and (4) tracking prediction \mathbf{d}_t . We follow the MaskTrack R-CNN approach [2] to perform these predictions with several modifications. The first step is to use a feature extractor denoted as \mathcal{N}_{feat} to extract representative feature descriptors \mathbf{f}_t , i.e., $\mathbf{f}_t = \mathcal{N}_{feat}(\mathbf{I}_t)$. After that, a Regional Proposal Network (RPN) \mathcal{N}_{RPN} and a RoI Align operation [1] *RoIA* are applied to obtain RoI features \mathbf{f}'_t with identical sizes, i.e., $\mathbf{f}'_t = \text{RoIA}(\mathcal{N}_{RPN}(\mathbf{f}_t))$. \mathbf{f}'_t is then fed into three task-related branches (i.e., heads): (1) the Bounding Boxes Head (BBbox Head) \mathcal{N}_{bbox} ; (2) the Segmentation Head \mathcal{N}_{mask} ; and (3) the Tracking Head \mathcal{N}_{track} . These three heads generate the required predictions, i.e., $\{\mathbf{b}_t, \mathbf{c}_t\} = \mathcal{N}_{bbox}(\mathbf{f}'_t)$, $\mathbf{s}_t = \mathcal{N}_{mask}(\mathbf{f}'_t)$ and $\mathbf{d}_t = \mathcal{N}_{track}(\mathbf{f}'_t)$. To evaluate the overall performance on frame \mathbf{I}_t , we use the metric described by Yang *et al.* [2]: the mAP score integrating the performance of all four predictions. mAP is higher for more similar bounding boxes. This MaskTrack R-CNN pipeline is illustrated in Figure 9.

Following the idea of Deep Feature Flow [9], we also integrate the FlowNet [15] architecture into the MaskTrack R-CNN framework for temporal information inference. Let \mathcal{F} be the FlowNet model, and let \mathbf{I}_k be the last key frame ($a_k = a^1$) where the feature descriptor \mathbf{f}_k is already computed. If the current frame \mathbf{I}_t is determined to be a non-key frame, i.e., $a_t \neq a^1$, we use \mathcal{F} to estimate the optical flow from \mathbf{I}_k to \mathbf{I}_t denoted as $\mathbf{OF}_{k \rightarrow t}$, i.e., $\mathbf{OF}_{k \rightarrow t} = \mathcal{F}(\mathbf{I}_t, \mathbf{I}_k)$, and the feature descriptor \mathbf{f}_t is calculated as follows: $\mathbf{f}_t = \mathcal{W}(\mathbf{OF}_{k \rightarrow t}, \mathbf{f}_k, \mathbf{S}_{k \rightarrow t})$, where \mathcal{W} is a warping function and $\mathbf{S}_{k \rightarrow t}$ is the scale field from I_k to I_t . Zhu *et al.* [9] give details

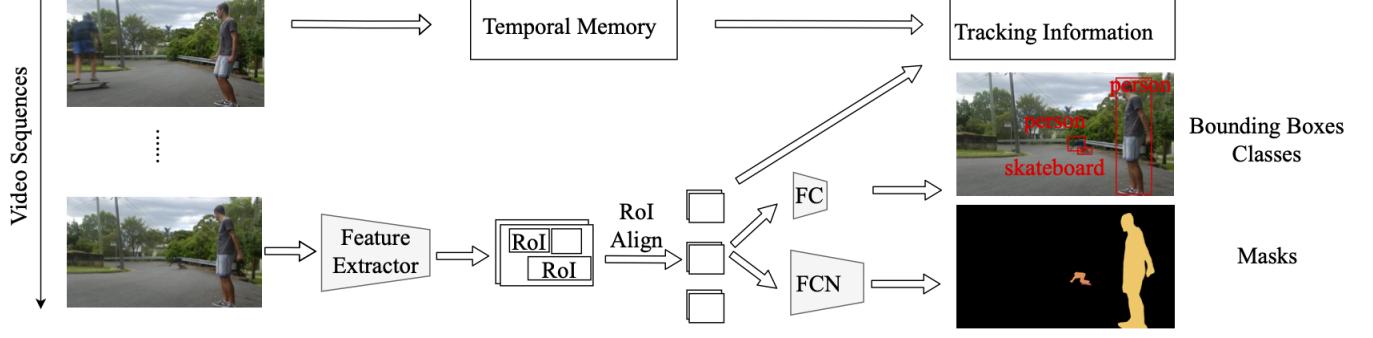


Fig. 9: Video instance segmentation pipeline based on the MaskTrack R-CNN framework.

on the warping function and scale field. If \mathbf{I}_t is determined to be a key frame ($a_k = a^1$), \mathbf{f}_t will be obtained from the feature extractor \mathcal{N}_{feat} . The main advantage of using optical flow for non-key frames is that it can compensate for accuracy reductions due to downsampling, as demonstrated in Section III. We refer to the MaskTrack R-CNN + FlowNet architecture as MaskTrackFlow R-CNN, and Fig. 10 illustrates the structure of our MaskTrackFlow R-CNN.

Building on the MaskTrackFlow R-CNN, we design a reinforcement-based policy network π_θ with parameters θ to learn appropriate actions a_t such that the cumulative reward G in Equation 7 can be maximized, which is explained in detail below.

B. Policy Network

For a video frame \mathbf{I}_t of resolution $w_t * h_t$, our policy network π_θ gathers useful information at time step t and uses it as the state s_t to determine an appropriate action $a_t \in \mathcal{A}$. As indicated in Section VI-A, we define the action space \mathcal{A} as

$$\mathcal{A} = \{a^1, a^2, a^3, a^4\}, \quad (8)$$

where a^1 refers to using original frame resolution $w_t * h_t$, a^2 , a^3 and a^4 stand for resizing the frame image to lower resolution settings (e.g., $\frac{w_t}{2} * \frac{h_t}{2}$, $\frac{w_t}{4} * \frac{h_t}{4}$ and $\frac{w_t}{8} * \frac{h_t}{8}$). Let $\mathbf{I}_t^{a_t}$ be the frame image after applying action a_t , we define the state s_t as

$$s_t = \{\mathbf{f}_t^{a^4}, \mathbf{f}_k - \mathbf{f}_t^{a^4}, \xi\}, \quad (9)$$

where $\mathbf{f}_t^{a^4} = \mathcal{N}_{feat}(\mathbf{I}_t^{a^4})$ represents the feature descriptor for $\mathbf{I}_t^{a^4}$, \mathbf{f}_k is the feature descriptor for the last key frame \mathbf{I}_k ($a_k = a^1$) that was already computed, and ξ is the summary information for historical resolution decisions. Intuitively, the first two terms $\mathbf{f}_t^{a^4}$ and $\mathbf{f}_k - \mathbf{f}_t^{a^4}$ provide the necessary spatial and temporal information for making resolution decisions, and the last term ξ informs the policy network π_θ of the historical decisions. Since the spatial resolution of \mathbf{f}_k and $\mathbf{f}_t^{a^4}$ are not identical, we resize $\mathbf{f}_t^{a^4}$ to the shape of \mathbf{f}_k through bi-linear interpolation such that $\mathbf{f}_k - \mathbf{f}_t^{a^4}$ can be implemented and also to avoid information loss in \mathbf{f}_k of larger size.

The policy network π_θ contains one convolution layer (Conv0) and four fully connected (FC) layers: FC0, FC1, FC2, and FC3, as illustrated in Fig. 11. The tensor $\mathbf{f}_t^{a^4}$ (256 channels) is concatenated with tensor $\mathbf{f}_k - \mathbf{f}_t^{a^4}$ (256 channels)

as the input to the first $1*1$ convolution layer (Conv0) with 256 output channels. The input channels are squeezed gradually from FC0 to FC2 layers, which are 15,360, 4,096 and 1,024 channels. Following Wang *et al.* [16], we append the decision history ξ to the input tensor of the FC3 layer, while ξ depends on two terms: a vector with 20 channels containing the last 10 resolution decisions (we use two binary digits to encode a decision since we have a total of four actions here), and a scalar denoting the distance of the current t -th frame from the last key frame (i.e., action is a^1). Appending ξ increases the input channels of the FC3 layer from 256 to 277, which are summarized into four estimated Q values, i.e., $Q(s_t, a^i)$ ($i = 1, \dots, 4$). Equation 10 defines how to estimate the Q values.

$$Q^\pi(s, a) = \mathbb{E}[G_t | s_t = s, a_t = a]. \quad (10)$$

For video instance segmentation, however, a more task-specific reward function than Equation 6 needs to be defined. We define the reward r_{a_t} of an action a_t on frame \mathbf{I}_t as

$$r_{a_t} = \begin{cases} \lambda \frac{1}{E_{a_t}} + C_0 & a_t = a^1 \\ U_{a_t} - U_{\arg \max_x U_x^t} + \lambda \frac{1}{E_{a_t}} + C_0 & a_t \neq a^1 \end{cases}, \quad (11)$$

where E_{a_t} refers to the energy consumption of using action a_t , U_{a_t} refers to the mAP score for the video instance segmentation task achieved on the frame \mathbf{I}_t by action a_t , and $U_{\arg \max_x U_x^t}$ stands for the highest potential mAP on this time step, which is typically obtained when $a_t = a^1$. C_0 is a positive constant added to ensure $r_{a_t} \geq 0$.

Additionally, let P be the total number of episodes in the training process, and let T be the maximum time steps in one episode, we can see that the computational complexity of DDQN is $O(mTP)$, since the agent needs to determine one action (with the maximum Q value) from m actions at each time step, while there can be a maximum of TP time steps during the training process.

The algorithm for the proposed reinforcement-learning-based energy-efficient framework is described in Algorithm 1.

VII. EXPERIMENTS AND RESULTS

This section describes the experimental evaluation of the proposed energy-efficient video analysis pipeline.

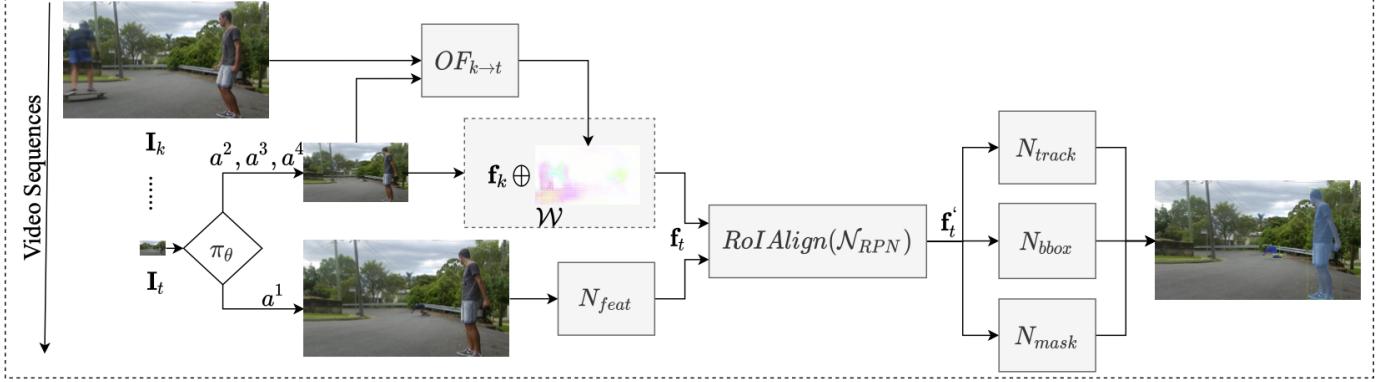


Fig. 10: Flowchart of the proposed MaskTrackFlow R-CNN. We use a policy network π_θ to govern the complete system. For each frame I_t , this policy network π_θ determines an appropriate action from the action set \mathcal{A} that aims to maximize the global objective function. If a non-key action (a^2 , a^3 or a^4) is selected, the optical flow between the last key frame I_k and the current frame I_t will be used to estimate high resolution information using temporal redundancy. In effect, this propagates key features from f_k to f_t to maintain accuracy in the presence of downsampling. Here, $f_k = \mathcal{N}_{feat}(I_k)$, and f_t represents the features of the current frame. If π_θ opts for a key action (a^1), f_t (feature of current frame) will be obtained directly from \mathcal{N}_{feat} , i.e., $f_t = \mathcal{N}_{feat}(I_t)$.

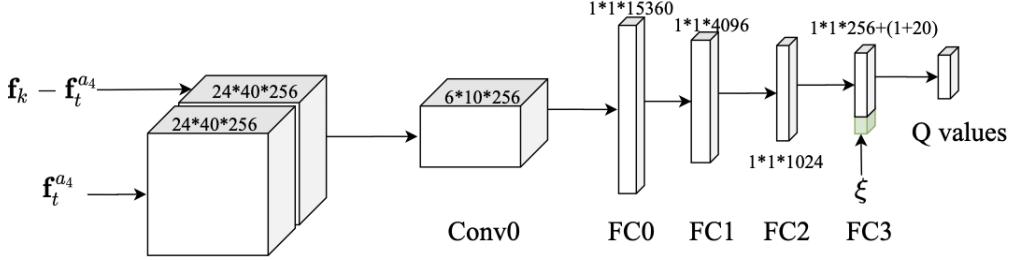


Fig. 11: The architecture of the policy network π_θ that determines an appropriate resolution (based on which action to take) for each frame I_t . The input tensor consists of two parts: (1) the feature descriptor $f_t^{a^4}$ obtained from the resized frame $I_t^{a^4}$, and (2) the tensor $f_k - f_t^{a^4}$ which is the element-wise difference between the key feature f_k and the first component $f_t^{a^4}$. The historical decision information ξ is concatenated to the last fully connected layer (FC3). The output of π_θ is a tensor with four channels. Each channel contains a Q value, and each Q value corresponds to taking a certain action in the action set \mathcal{A} . We select the action with the largest Q value as the action to take.

A. Dataset

We utilize the YouTube-VIS dataset² [2] to evaluate the performance of the proposed framework. This dataset consists of 2,883 videos, a 40-category label set and 131k instance masks, while the train/validation/test set contains 2,238/302/343 videos, respectively. The 5th frame for each video snippet is annotated. Each video snippet lasts for 3 to 6 seconds with a 30 fps frame rate. The maximum resolution of the original frame is $1,280 \times 720$. Since only the training set's annotation is released, we divide the training set with a 90%/5%/5% ratio for training/validation/testing in the following study.

B. Experimental Settings

1) *Evaluation platform:* The proposed framework is designed for energy-constrained edge devices. For evaluation purposes, following Lubana *et al.* [6], we consider an embedded hardware configuration including a Raspberry Pi 3 equipped with a Sony IMX219 image sensor with variable resolution support. The Sony IMX219 supports a maximum $3,280 \times 2,464$ resolution with 12 MHz clock frequency. As pointed out by Lubana *et al.* [6], the power consumption in state $P_{sensor,idle}$ is 141.8 mW and that in $P_{sensor,active}$ is

$8.27 \text{ mW}/\text{MP}\cdot R + 17.364 \text{ mW} + 113.03 \text{ mW}$. We use a T_{exp} of 20 ms in the following study.

The Raspberry Pi 3 is equipped with an embedded GPU consisting of a dedicated image signal processing pipeline [6]. Following prior work [6], we approximate P_{ISP} using the GPU's power consumption. P_{CPU} and P_{GPU} (W-level, typically) can be directly measured by an ammeter. Time required by the Raspberry Pi ISP pipeline is approximately linear in R_{frame} [6], $T_{ISP} = 0.095 \times R_{frame} + 0.032$ (R_{frame} unit is MP).

The following study focuses on evaluating the energy efficiency and accuracy of our framework compared with existing work. We use the mean Average Precision (mAP) [2] as the performance metric for video instance segmentation. We also define energy reduction as the ratio of the energy consumption of our method to that of existing work. The energy consumption is calculated using the energy model described in Section IV-B.

2) *Training MaskTrackFlow R-CNN:* In the MaskTrackFlow R-CNN architecture, we employ the ResNet-50-FPN [25], [1] as the feature extractor \mathcal{N}_{feat} and we use the Regional Proposal Network described by Yang *et al.* [2]. We also adopt the same structures for the three heads \mathcal{N}_{bbox} , \mathcal{N}_{mask} , and \mathcal{N}_{track} . For the FlowNet model \mathcal{F} , we use the FlowNetC architecture [15], and apply the warping function \mathcal{W} from Deep Feature Flow [9]. Considering the complexity

²<https://youtube-vos.org/dataset/vos/>

Algorithm 1 A Reinforcement-Learning-based Energy-Efficient Framework

Input: N Video Frames $\{\mathbf{I}_0, \mathbf{I}_1, \dots, \mathbf{I}_N\}$ of Resolutions $\{w_0 * h_0, w_1 * h_1, \dots, w_N * h_N\}$

- 1: $k \leftarrow 0$ ▷ initialize key frame
- 2: $\mathbf{f}_k = \mathcal{N}_{feat}(\mathbf{I}_k)$ ▷ obtain key feature
- 3: $\mathbf{f}'_k = RoIAlign(\mathcal{N}_{RPN}(\mathbf{f}_k))$ ▷ obtain key ROI feature
- 4: $\{\mathbf{b}_k, \mathbf{c}_k\} \leftarrow \mathcal{N}_{bbox}(\mathbf{f}'_k)$ ▷ obtain key bbox and class
- 5: $\mathbf{s}_k \leftarrow \mathcal{N}_{mask}(\mathbf{f}'_k)$ ▷ obtain key segmentation mask
- 6: $\mathbf{d}_k \leftarrow \mathcal{N}_{track}(\mathbf{f}'_k)$ ▷ obtain key tracking prediction
- 7: $\mathbf{Y}_k \leftarrow \{\mathbf{b}_k, \mathbf{c}_k, \mathbf{s}_k, \mathbf{d}_k\}$ ▷ put together key predictions
- 8: Initialize ξ ▷ initialize historical information
- 9: **for** $t = 1$ to N **do**
- 10: $\mathbf{f}'_t = \mathcal{N}_{feat}(\mathbf{I}_t^{a^4})$ ▷ obtain low-resolution feature
- 11: $s_t \leftarrow \{\mathbf{f}'_t, \mathbf{f}_k - \mathbf{f}'_t, \xi\}$ ▷ collect current state
- 12: Estimate Q values and select action using policy network π_θ ▷ determine current action
- 13: $a_t = \max_a Q(s_t, a; \theta)$ ▷ update historical information
- 14: Update ξ with a_t ▷ if key action
- 15: **if** $a_t = a^1$ **then** ▷ if key action
- 16: $\mathbf{f}_t = \mathcal{N}_{feat}(\mathbf{I}_t)$ ▷ obtain current feature
- 17: $k \leftarrow t$ ▷ update key with current
- 18: **else** ▷ if non-key action
- 19: $\mathbf{OF}_{k \rightarrow t} = FlowNet(\mathbf{I}_k^{a^4}, \mathbf{I}_t^{a^4})$ ▷ obtain optical flow
- 20: $\mathbf{S}_{k \rightarrow t} = \mathcal{S}(\mathbf{I}_k^{a^4}, \mathbf{I}_t^{a^4})$ ▷ obtain scale fields
- 21: $\mathbf{f}_t = \mathcal{W}(\mathbf{OF}_{k \rightarrow t}, \mathbf{f}_k, \mathbf{S}_{k \rightarrow t})$ ▷ obtain current feature
- 22: **end if**
- 23: $\mathbf{f}'_t = RoIAlign(\mathcal{N}_{RPN}(\mathbf{f}_t))$ ▷ obtain current ROI feature
- 24: $\{\mathbf{b}_t, \mathbf{c}_t\} \leftarrow \mathcal{N}_{bbox}(\mathbf{f}'_t)$ ▷ obtain current bbox and class
- 25: $s_t \leftarrow \mathcal{N}_{mask}(\mathbf{f}'_t)$ ▷ obtain current segmentation mask
- 26: $\mathbf{d}_t \leftarrow \mathcal{N}_{track}(\mathbf{f}'_t)$ ▷ obtain current tracking prediction
- 27: $\mathbf{Y}_t \leftarrow \{\mathbf{b}_t, \mathbf{c}_t, \mathbf{s}_t, \mathbf{d}_t\}$ ▷ put together current predictions
- 28: **end for**

Output: Energy-efficient video analytics results $\{\mathbf{Y}_0, \mathbf{Y}_1, \dots, \mathbf{Y}_N\}$

of the proposed MaskTrackFlow model, we use a two-step process to train it. We first train the feature extraction model \mathcal{N}_{feat} and the three heads \mathcal{N}_{bbox} , \mathcal{N}_{mask} and \mathcal{N}_{track} on the video instance segmentation task described by Yang *et al.* [2], without considering the FlowNet model \mathcal{F} . We then train the FlowNet model \mathcal{F} while freezing the other components (i.e., feature extractor \mathcal{N}_{feat} and the three heads), following the design in Deep Feature Flow [9].

3) *Training the policy network:* To avoid unnecessary computation, we separate training of the policy network π_θ from training the MaskTrackFlow model. In other words, the weights of the MaskTrackFlow model are already learned and frozen when we train the policy network π_θ . We use the features extracted by ResNet-50 [1], [25] from the final convolutional layer of the first stage as the feature descriptor for images, e.g., $\mathbf{f}_t^{a^4}$ and \mathbf{f}_k in Equation 9. We use Adam [26] as the optimizer with an initial learning rate of 0.0005. The discount factor (γ) is set to 1, implying that each frame in the video sequence is equally important. The exploration policy uses an ϵ -greedy policy [27] and we set ϵ to decrease from 0.9 to 0.05.

4) *Baselines:* We compare the proposed reinforcement-based approach of selecting frame resolutions with the following baseline methods:

(1) **Digital Foveation Method [6]:** The digital foveation method improves system energy efficiency using a multi-round and variant-resolution strategy, which applies an application-specific accuracy constraint ($cnstrt$) to govern the variant-

resolution sensing process. For a fair comparison, we gradually vary the sensed resolution for frame \mathbf{I}_t from $\frac{w_t}{8} * \frac{h_t}{8}$, $\frac{w_t}{4} * \frac{h_t}{4}$, $\frac{w_t}{2} * \frac{h_t}{2}$ to $w_t * h_t$ if the accuracy reduction has surpassed the constraint $cnstrt$. In this work, we empirically set $cnstrt$ to be 0.2, 0.4, 0.6 and 0.8, respectively.

(2) **Adaptive High-Resolution Frame Scheduling (*AdaptiveHFS*):** This approach selects the key action a^1 for a frame \mathbf{I}_t when the flow magnitude between \mathbf{I}_t and the last key frame \mathbf{I}_k exceeds a certain threshold Thr , otherwise a certain non-key action (i.e., a^2 , a^3 or a^4) is taken. Please refer to Xu *et al.* [20] for the definition of flow magnitude. We select Thr from 8 to 12 with an interval of 2. We have three variants of *AdaptiveHFS*, each of which selects a different non-key action to use: *AdaptiveHFS*(a^2), *AdaptiveHFS*(a^3), and *AdaptiveHFS*(a^4).

(3) **Fixed-Interval High-Resolution Frame Scheduling (*FixIntervalHFS*):** This baseline method selects a certain non-key action (a^2 , a^3 or a^4) for every l ($l \in \{1, 2, 3\}$) frames, and the rest is set as key action (a^1). According to which non-key action to take, we also have three variants for the *FixIntervalHFS* approach, which are *FixIntervalHFS*(a^2), *FixIntervalHFS*(a^3) and *FixIntervalHFS*(a^4).

(4) **Random High-Resolution Frame Scheduling (*RandomHFS*):** This baseline method determines actions for each frame randomly with a hybrid distribution. Specifically, for a frame \mathbf{I}_t , the probability of selecting the key action a^1 is r where $r \in \{0.9, 0.7, 0.5\}$, and the probability of taking other three non-key actions (a^2 , a^3 and a^4) are uniform which sums up to $1 - r$.

C. Results

1) *RL Training Visualization:* Figures 12a, 12b, and 12c illustrate the average return during RL training where $\lambda \in \{0.4, 0.6, 0.8\}$. Note that we set C_0 in Equation 11 to 825 so all sessions can generate positive and comparable returns. Despite the fluctuations, all three curves steadily increase, indicating that the policy network is learning to maximize global return. The fluctuations of the curves plateau for large episodes (e.g., > 500), which suggests that the upper bound is being approached. When λ grows and the energy consumption term in Equation 11 increases, the maximum return achieved by the training curves also increases, which is consistent with expectations.

2) *mAP versus Energy Consumption:* Fig. 13a, Fig. 13b, and Fig. 13c illustrate the mAP (performance) versus energy consumption reduction curves for our method and the baselines. The energy consumption has been reduced significantly (more than 80%) at the cost of slight accuracy drops, no matter which resolution-selection method is used, thus verifying the effectiveness of the proposed adaptive resolution framework. Note that the policy net π_θ only accounts for a very small proportion of the whole energy consumption in Fig. 13, which is around 4.2%, thanks to the low-resolution input and its light-weight architecture. Moreover, our method outperforms all other baseline approaches on all the energy consumption intervals, which shows the superiority of our RL-based resolution selector. For realistic machine vision tasks, we can

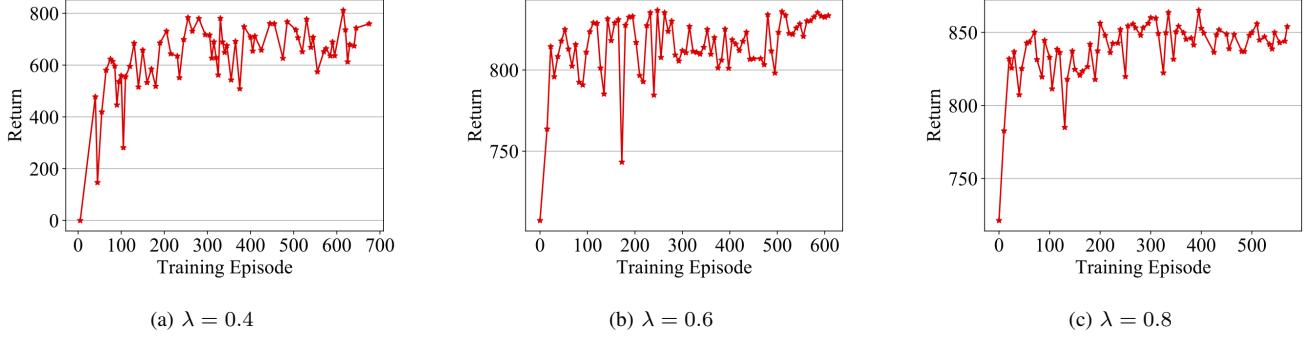


Fig. 12: The training curves of average return where λ value is set to 0.4, 0.6, and 0.8, respectively.

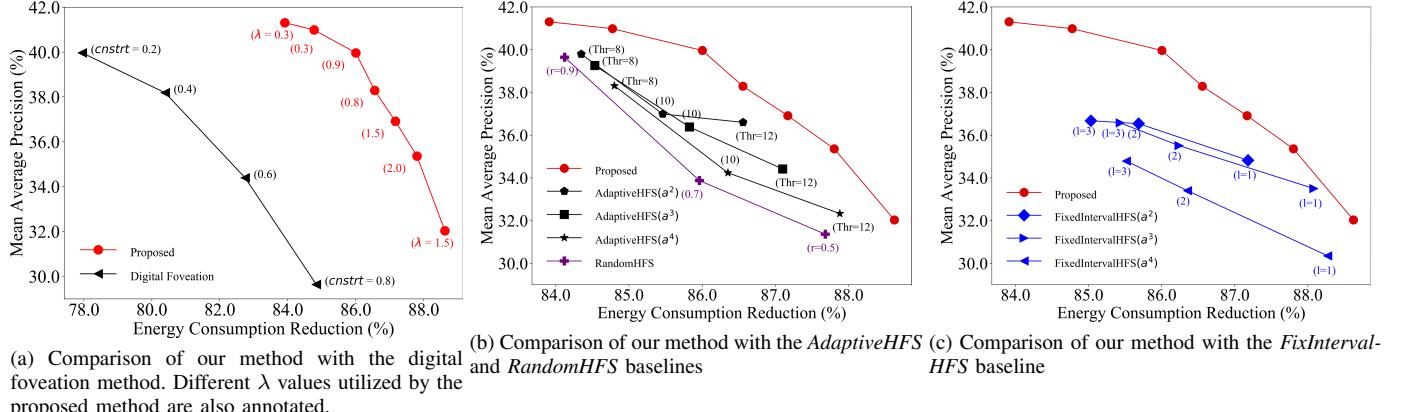


Fig. 13: mAP versus energy consumption reduction between the proposed method and the baselines.

fine-tune the RL models to have different energy consumption rates to suit the varying requirements.

Additionally, as the upper-bound method, MaskTrack R-CNN [2] delivers the highest mAP which is 41.7%. As a comparison, our method greatly saves energy consumption at the cost of slightly reduced accuracy, e.g. our framework achieves 41.4% mAP (only reduced by 0.3%) but saves approximately 84.0% energy consumption at the same time, which is much more energy-efficient.

We also explore how the parameter λ in Equation 6 can affect the proposed framework. λ characterizes the trade-offs between the accuracy and the energy consumption in our system and is thus one of the most important parameters. Generally, the higher λ is, the more important the energy consumption term in Equation 6 will be. The influences of different λ values can be seen in Fig. 13a, and we can discover a general trend that a larger λ value can lead to a higher energy consumption reduction rate, despite several fluctuations of the accuracy. Such observations are generally in line with our theoretical analysis.

3) *Case Studies*: This section further clarifies why the proposed method outperforms the digital foveation method, as well describes three cases to provide intuition on why our RL-based method can outperform others.

(1) Comparison with the digital foveation method:

As shown in Fig. 13a, compared with the digital foveation method [6], our method achieves significantly better trade-offs

between performance and energy reduction. This is because that the digital foveation approach is more energy-intensive as it involves a multi-round heuristic decision process with high computational costs. On the other hand, our method utilizes a light-weight RL-based policy network to dynamically determine appropriate frame resolutions, which can better and more efficiently generalize to complicated video scenarios, e.g., VIS.

(2) Comparison with the *FixIntervalHFS* baseline:

This case study compares our method with the *FixIntervalHFS(a^2)* baseline ($l = 1$) on a video sequence of 90 frames. We first study how the Accumulated Energy Consumption Reduction (AECR, the higher the better) rate varies on this video sequence. As shown in Fig. 14 (up), our method has 82.5% mAP on this sequence, surpassing the 80.0% of *FixIntervalHFS(a^2)*. Our method also demonstrates lower energy consumption with 87.6% AEGR (versus baseline's 87.0%) on the 90th frame. If we inspect the varying trends of AEGR on this sequence, we see that although our method selects multiple key actions (a^1) at the beginning, the non-key actions (a^2, a^3) are frequently selected for frames 50 – 90, thus reducing energy consumption. We plot the prediction results in Fig. 14 (bottom) on this temporal range, where the resolution selected by our method produces accurate results.

(3) Comparison with the *AdaptiveHFS* method:

Similarly, we report the AEGR results between ours and the *AdaptiveHFS(a^3)* method ($Thr = 10$) on a 90-frame video

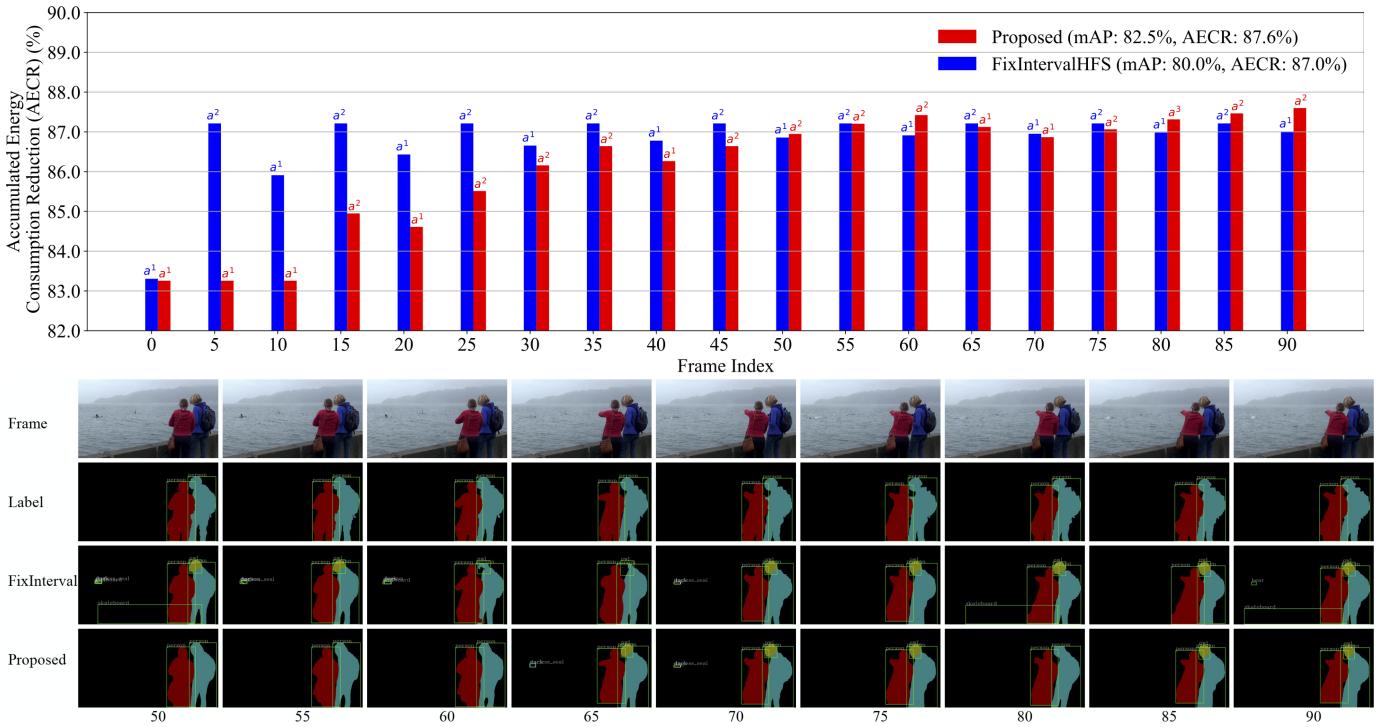


Fig. 14: A comparison between the proposed method and the *FixIntervalHFS*(a^2) ($l = 1$) method.

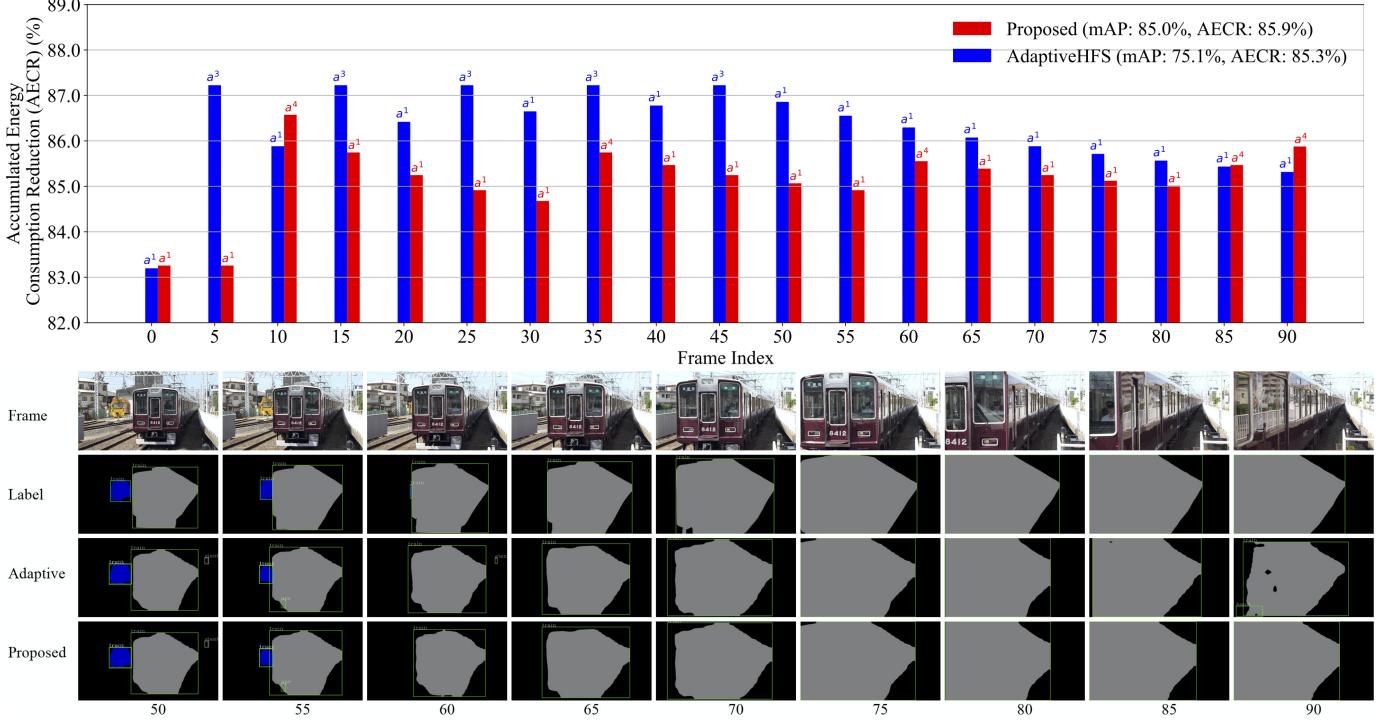


Fig. 15: A comparison between the proposed method and the *AdaptiveHFS*(a^3) ($f = 10$) method.

sequence. As demonstrated in Fig. 15 (up), the mAP of our method on this sequence is 85.0%, which is significantly better than the 75.1% of the baseline, while our energy efficiency is also better than the *AdaptiveHFS* method (85.9% AECCR versus 85.3%). It can be found that although our method has selected multiple key actions (a^1), it also opts for multiple a^4 which are the most energy-saving actions. As a result, our

method produces better prediction results, as shown in Fig. 15 (bottom).

(4) Comparison with the *RandomHFS* method. In Fig. 16, we show the comparison of our method with the *RandomHFS* baseline on a 90-frame video. Fig. 16 (up) shows that our method also outperforms the *RandomHFS* approach in both mAP and energy consumption. In particular, our method has

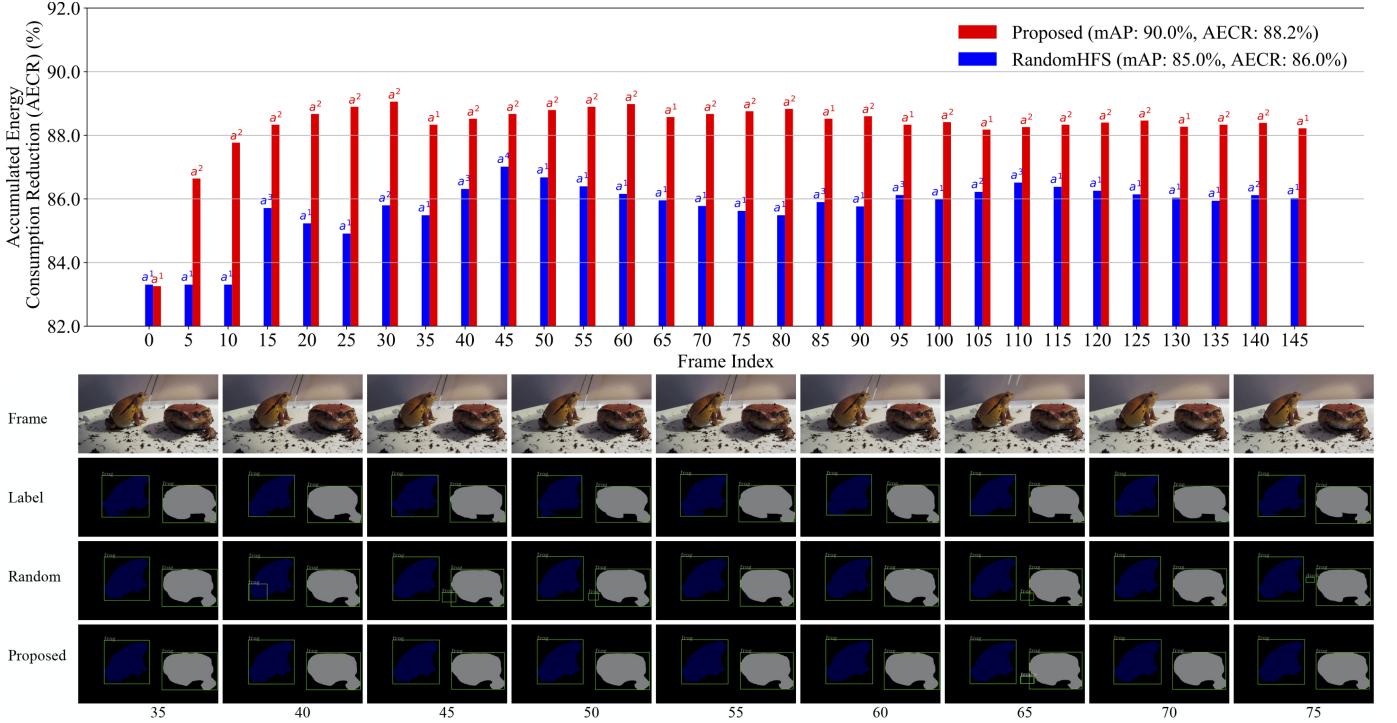


Fig. 16: A comparison between the proposed method and the *RandomHFS* method.

selected a large percentage of a^2 actions, while the baseline has frequently selected the key actions a^1 . However, more key actions do not necessarily lead to better performance. As illustrated in 16 (bottom), our method has obtained better prediction results than the baseline, although the baseline has employed many more key actions. Therefore, we can arguably conclude that our RL-based method can more accurately grasp the global video context and thus makes better resolution decisions.

VIII. CONCLUSIONS

This paper describes an adaptive-resolution energy optimization framework for a multi-task video analytics pipeline in energy-constrained scenarios. We described a reinforcement-learning-based method to govern the operation of the video analytics pipeline by learning the best non-myopic policy for controlling the spatial resolution and temporal dynamics to globally optimize system energy consumption and accuracy. The proposed framework is applied to video instance segmentation which is one of the most challenging video analytics problems. Experimental results demonstrate that our method has better energy efficiency than all baseline methods. This framework can be applied to a wide range of machine vision pipelines with a high demand for efficient energy consumption, e.g., various embedded and Internet-of-Things applications.

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