# Redesign STN Localization Net

## Abstract

Spatial transformer network [15] is a powerful module that improves the spatial invariance of convolutional neural networks. Amid all components, the localization net serves as the backbone as it intakes the feature map and yields the affine transformation parameters, deciding how the transformation to be executed. The design of the localization net is closely correlated to the outcome of transformation consequently influence accuracy. This work experiments through different localization net designs and test them with several prominent models on various datasets. Aiming to discover a modern localization network architecture that boosts the performance of STN transformation with less parameters and computational overhead.

## 1. Introduction

Convolutional neural networks have become the state-of-the-art machine learning approach ever since AlexNet [1] won the ImageNet Challenge: ILSVRC 2012 [2]. The technology been successfully applied to a broad range of machine learning tasks like object detection, tracking [3, 4], super-resolution [5, 6] and document analysis [7]. Although they were introduced roughly in the 90s [8], it wasn’t until recent hardware developments along with model’s architectural improvements that enabled the training of deep neural networks. The pioneering LeNet5 [9] introduced a 5 layered structure at 1998, deep neural networks nowadays have reached a hundred layers or more with the aid of specialized design architecture like Residual Networks [10] or Highway Networks [11].

Most researches focus on finer interconnection methods [12], renewed convolution procedures to reduce computational overhead [13, 14] or specialized layers targeting a subset of training problems. These approaches increase the model’s ability to gather information from the feature map and learn more detail from them. Regrettably, however, about how to transform the input data by the model itself in order to leading a better result draw few concerns.

Attention mechanism applied to the input image is a popular field of study, figuring out where the model should put emphasis on; howbeit, it wasn’t until recently that people starts to hand the job to the model itself. Specialized layers are designed to transform the input image before the image was sent into the main convolutional layers. However, some of the components in such layers are out of date, thereby could not reflect the improvements in convolutional architectural by modern researchers. This work aims to design a renewed structure of such layer to improve its capabilities, and test such re-designed structure on various models to validate its improvements.

## 2. Related Work

Convolutional layers are feature extractors that scan through each pixel with dot product operations. They work very well despite the fact that such operation is not spatially invariant. Features rotated, flipped or scaled may not be captured by the convolution layers thus lead to false judgements. The introduction of pooling layers is capable of spatially transform a feature map, but the effect is still limited nevertheless due to the prevalent small pooling size. On the other hand, it is customary to train the model with transform conducted images, a technique performed during the data preprocessing stage. Remaking training images by cropping, rotating or focus the input image to enlarge the dataset and train the model on them. It could lead to potential hazards: Techniques like so usually work by hand-crafted rules and execute according to the designer’s choice. Designers are limited to come up with details such as the rotational angle or the cropping area of the raw image. The process of remaking new images from raw images inflates the size of the dataset, further prolongs training time. When the dataset is very large, such measure comes with a heavy cost.

### a. Spatial Transformer Network

In order to obtain models with the ability to disentangle object’s pose and size, the best way is to incorporate attention mechanism into the model. Spatial transformer networks [15] designed a whole new architecture targeting the work. In figure 1 shows that the architecture has three main components: the localization network, the grid generator and the sampler. The localization network inputs feature map directly and outputs predicted transformation parameters to the gird generator, who creates sample grids. Sample grids are set of points marking where the input feature map should be sampled. The sampler takes the two outputs as input and produces the output feature map, a well transformed image.

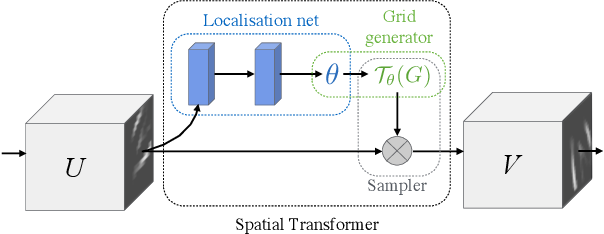


Figure 1: The Architecture of a Spatial Transformer Module. [15]

### b. VGG and Inception Net

The mechanism of the transformer network heavily depends on the localization network, how well the localization network understands the input feature map directly affects the quality of its output, affine transform parameters. The developments in convolution network architectures are highly related to premium localization network designs. After the success of AlexNet, VGG [16] put forward the concept of unified sized convolutional layers, pooling layers and strides, and proved Local Response Normalization useless. The largest VGG structure has 19 layers, with 138 million parameters. Neural network models tend to perform better with deeper or wider architectural design, so Inception Net [17] designed a wider model, with different size of convolutions to extract different features from the feature map. However, such design would lead to explosive increase of parameters, so 1 x 1 kernel are added to reduce the number of channels.

### c. Skip Connections

As when the model’s layers grow, the accuracy soon saturates and then degrades rapidly. Residual neural network (ResNet) [10] popularized the use of skip connections, a direct path for latter layers to access feature maps from previous layers. Identity could easily be learnt from the latter layers to prevent disruption of the former features, albeit learning anything new. Such design opened the door for training neural network over 100 layers without the worry of overfitting. Figure 2 describes a residual learning block Networks like DenseNet [12] is also based on skip connections but with denser interconnect in the convolution block targeting better performance. Some network architectures [18, 19] further incorporates skip connections into their original structure.

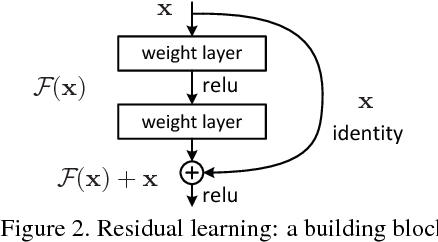


Figure 2: Residual Learning: A Building Block. [10]

### d. Lightweight Models

Some researchers are interested in finding a more efficient convolution model. MobileNet [14] decomposes the convolutional operation into depth-wise and point-wise convolution, greatly reduce the parameters and computational cost. ShuffleNet [20] adopts point wise group convolution and channel shuffle whereas SqueezeNet [21] reduces parameter by designing a fire model, which is somewhat similar to a ResNet structure. Although these models may not reach state-of-the art performance in benchmarks, they endeavor to make concession between performance and computational overhead.

### e. EfficientNet

EfficientNet [22] tries to balance network depth, width and resolution under a certain computational budget. Convolutional models often focus on scaling only one of the three dimensions with an arbitrary scale without further investigation. [22] Suggests a simple but effective compound scaling method which uniformly scales three dimensions. Furthermore, they designed a baseline network through neural architecture search [23] then compound scale to an entire family of network called EfficientNet. The baseline network is based on the inverted bottleneck residual blocks coming from MobileNetV2 [18] in addition to squeeze-and-excitation blocks [24] and Swish activation function [25].

# 3. Localization Net architecture

Affine transformation on 2D space requires 6 parameters and are capable of resizing, rotating, displacing and shearing an image. According to [15] and Figure 1, the localization net inputs the feature map U then output θ, the parameters of the transformation applying to the feature map. θ is a 6-element array carrying the affine transformation specifications. Our work will be further experiment with different localization designs. The localization net is capable being trained through standard back-propagation, so network architectures like convolutions or fully connected layers are fully supported.

All classification layers of the localization net would be the same in the experiment. Assume the last hidden layer outputs feature map with height H, width W and Channels C. The feature map shall be flattened to one dimension of length HxWxC in advance and connect with two fully connected layers, One with HxWxC as input and 32 as output, another with 32 as input and 6 (for affine transformation) as output. ReLU [27] is selected as the activation function since it avoids vanishing gradient problem with lightweight cost of computational power. The localization net's classification layers would have HxWxC x 32 + 192 parameters in total.

### a. Regular Structure (STN)

Most commonly used spatial transform network localization architecture is made out of two wide convolution layers, one 7 x 7 in the front followed by a 5 x 5 and with 2 x 2 max pooling layers interleaving between. Pooling layers contains no parameters and are of a certain degree spatial invariant to the position of features, despite the fact that they shrink the input size quickly, dropping gathered information brutally. Such composition resembles the LeNet5 architecture [9]. Table 1 shows the regular localization architecture.

| Table 1: Regular STN Localization Architecture | | | |
| --- | --- | --- | --- |
| **Type** | **Filter Shape** | **Output shape** | **Parameters** |
| Conv | 7 x 7 x 3 x 8 | 218 x 218 x 8 | 1184 |
| Max pool, stride 2 | 2 x 2 x 8 x 8 | 109 x 109 x 8 | 0 |
| Conv | 5 x 5 x 8 x 10 | 105 x 105 x 10 | 2010 |
| Max pool, stride 2 | 2 x 2 x 10 x 10 | 52 x 52 x 10 | 0 |
| Total |  |  | 3194 |

### b. VGG-like Structure (STN1)

Breaking down large size convolution filers into stacked small size convolutions are one of the main contributions of VGG [16]. In theory, two 3 x 3 convolutions would share the same receptive field as one 5 x 5 convolution as well as three stacked 3 x 3 convolutions could replace a wide 7 x 7 convolution layer. Whereas three 3 x 3 convolutions take 27 parameters but a 7 x 7 takes 49, over 40 percent of reduction. Smaller convolutions are also beneficial for increasing model linearity, becoming the mainstream of convolution layer architecture.

Similar changes could be made to the STN localization architecture, by replacing the first 7 x 7 wide convolution layer into three stacked 3 x 3 convolution layers and the second 5 x 5 wide convolution would turn into two 3 x 3 convolution layers at the meantime. Max pooling layers remains unchanged. Table 2 shows the VGG-like localization architecture, it’s called STN1 in this work.

| Table 2: VGG - like Localization Architecture (STN1) | | | |
| --- | --- | --- | --- |
| **Type** | **Filter Shape** | **Output shape** | **Parameters** |
| Conv | 3 x 3 x 3 x 8 | 222 x 222 x 8 | 224 |
| Conv | 3 x 3 x 8 x 8 | 220 x 220 x 8 | 584 |
| Conv | 3 x 3 x 8 x 8 | 218 x 218 x 8 | 584 |
| Max pool, stride 2 | 2 x 2 x 8 x 8 | 109 x 109 x 8 | 0 |
| Conv | 3 x 3 x 8 x 10 | 107 x 107 x 10 | 730 |
| Conv | 3 x 3 x 10 x 10 | 105 x 105 x 10 | 910 |
| Max pool, stride 2 | 2 x 2 x 10 x 10 | 52 x 52 x 10 | 0 |
| Total |  |  | 3032 |

### c. The Proposed Structure (STN2)

Convolution operation comes with heavy overheads, scalar product consumes a large portion of computational resources in the CNN network. According to Amdahl’s law, even by optimizing the convolution operation by an inch would lead to significant improvements. Convolution layers are three dimensional (width x length x height), replacing large convolution with smaller sizes reduces the two dimensions in width and length, which reduces computational cost and parameter counts by the factor of N^2. If there’s a way to further shrink the height dimension, it could also reduce the operation by a factor of N.

Inception Net [17] popularizes the use of 1 x 1 kernels between channels to increase or decrease the feature map count, concentrating the useful ones and discard the wastes. There are two types of 1 x 1 kernel that often come in pairs: the encoder and the decoder. The encoder kernel reduces the number of the feature map, in other words cherry pick the informative ones from different feature maps. The decoder kernel expands the compressed information and increases the count of feature maps. With a combination of an encoder and decoder, output channels could be reduced to save computational cost and parameter count.

Batch Normalization [26] is very popular in modern CNN Networks. It reduces the covariate shift so fewer exploding gradients would happen. Furthermore, the training will also be less effected by the initialization process. Batch Normalization are very computational efficient and effective, they could be place right after every convolution layer.

Table 3 shows a localization architecture build by the above-mentioned structures (named STN2). This work applies 1 x 1 kernels to concentrate channels and to reduce parameters. Batch normalizations were added after the convolution and after the activation function. 3 x 3 convolutional kernels with larger strides replacing the pooling layers, which leads to more parameter counts in exchange of versatility. Instead of constantly reducing the size of the feature map, some identity layers were introduced, which includes padding in the convolution operation. Such layers do nothing to shrink the feature into our target size, but focus on extracting spatial information from the feature map.

Although the parameters in this architecture leads to more parameters, the concentration mechanism would lead to better performances and with less computational overhead. The greatest reduction of parameters comes from the stem part of the network. Reducing the parameter by half via adopting a smaller output channel and expand the channel for the next convolutional layer by a decoder. Other layers remain the same I/O size but encoders and decoders were also added in between to concentrate the feature maps.

| Table 3: The Proposed Architecture (STN2) | | | |
| --- | --- | --- | --- |
| **Type** | **Filter Shape** | **Output shape** | **Parameters** |
| Conv, stride 2 + BN | 3 x 3 x 3 x 4 | 112 x 112 x 4 | 112+8 |
| Conv + BN | 1 x 1 x 4 x 8 | 112 x 112 x 8 | 40+16 |
| Conv + BN | 3 x 3 x 8 x 8 | 110 x 110 x 8 | 584+16 |
| Conv + BN | 1 x 1 x 8 x 4 | 110 x 110 x 4 | 36+16 |
| Conv + BN | 1 x 1 x 4 x 8 | 110 x 110 x 8 | 40+16 |
| Conv + BN | 3 x 3 x 8 x 8 | 108 x 108 x 8 | 584+16 |
| Conv + BN | 1 x 1 x 8 x 4 | 108 x 108 x 4 | 36+16 |
| Conv + BN | 1 x 1 x 4 x 8 | 108 x 108 x 8 | 40 + 16 |
| Conv, stride 2 + BN | 3 x 3 x 8 x 8 | 54 x 54 x 8 | 584+16 |
| Conv + BN | 1 x 1 x 8 x 4 | 54 x 54 x 4 | 36+8 |
| Conv + BN | 1 x 1 x 4 x 8 | 54 x 54 x 8 | 40 + 16 |
| Conv, padding 1 | 3 x 3 x 8 x 8 | 54 x 54 x 8 | 584+16 |
| Conv + BN | 1 x 1 x 8 x 4 | 54 x 54 x 4 | 36+8 |
| Conv + BN | 1 x 1 x 4 x 8 | 54 x 54 x 8 | 40 + 16 |
| Conv + BN | 3 x 3 x 8 x 8 | 52 x 52 x 8 | 584+16 |
| Conv + BN | 1 x 1 x 8 x 4 | 52 x 52 x 4 | 36+8 |
| Conv + BN | 1 x 1 x 4 x 10 | 52 x 52 x10 | 50+20 |
| Total |  |  | 3690 |

# 4. Experiments

## 4.1 Datasets

### a. Chinese Traffic Sign Database

The original dataset TSRD includes 6164 traffic sign images with 58 categories, they are collected by National Nature Science Foundation of China (NSFC) to serve as an open traffic sign recognition dataset. A test file containing 4170 images and a test set with 1994 images are open for download. Some duplicated images have been removed and readjustments have been made in this work. 4000 data were kept as training set, 1000 as testing set and the remaining 998 images are left as validation set.

### b. Caltech 101

The dataset [28] is created by Fei-Fei Li, Marco Andreetto, Marc 'Aurelio Ranzato and Pietro Perona at the California Institute of Technology for computer vision experiments. Pictures of objects are classified into 101 classes, most category has about 50 images with resolution of about 300 x 200. The dataset has in total 8677 images, about 75% (6277) were kept as training set while other images were split evenly as validation (1200) and testing dataset (1200) .

### c. Cifar-10

The dataset [29] was collected by Canadian Institute for Advanced Research and is the subset of the 80 million tiny images dataset. The dataset is a collection of 60000 low resolution images (32x32) classified into 10 classes. Each class has 6000 images. Due to the fact that all classes have a uniform distribution of images, data augmentation may not be critically necessary. 40000 is left as training set and the rest are split evenly as validation set (10000) and testing set (10000) in this work.

## 4.2 Training Procedure

The datasets are first scaled into the input size of the model using bilinear interpolation, then normalized (By assuming each pixel are even distributed between 0 and 1). Other data preprocessing methods like data augmentation are not performed. It is pretty obvious that by performing data preprocessing would lead to better performing models; nevertheless, the main goal is to test different model architectures, it’s fair since the same dataset is used to train and test our models, so techniques alike are omitted.

The batch size is set to 20 for smaller models and 10 or smaller for larger models. Since this work adopt stochastic gradient descent, batch size does affect the model training process but not much to the final result. Setting large batch sizes leads to faster training speed yet smaller batch size saves memory space. (VRAM if hardware acceleration is turned on). In this work, larger training epochs are chosen for models to converge in order to minimize the effect of different batch sizes.

Loss function are set as cross-entropy, with loss averaged over each loss element in the batch and a weighted mean of the output is taken as the reduction to apply to the output. No smoothing measures were taken. Adam [30] is chosen as the optimizer, which is a combination of the adaptive gradient and the momentum optimizer. The learning initial learning rate is 0.001, beta 1 is 0.9 and beta 2 is 0.999. objective and weight decay are set to 0.

Early stopping could reduce unnecessary training resources; furthermore, it helps with overfitting. Stopping conditions should be carefully set, not to stop the training before the model has converged thus a tolerance parameter is set up to judge whether the early stopping should take place. If the oscillation of the variation accuracy of a continuous 10 epochs does not exceed the tolerance parameter plus the accuracy is no longer raising, suggesting the model has already diverged, may then stop the training procedure. Note that a training epoch floor could be set in order to avoid the model from stop training at the start up stage.

All experiments are conducted on a workstation equipped with 8 cores 16 threads Intel Core i9-9900KF CPU with 3.6 GHz clock rate and could reach 5 GHz with Intel Turbo Boost Technology 2.0. Along with 32 GB DDR4 memory running at 2400 MHz A graphics card is installed for hardware acceleration: Nvidia TITAN RTX, built with Nvidia Turing architecture. It has 4608 CUDA cores running 1350 MHz base clock, 1770 MHz boost clock, also equipped with 24 GB GDDR6 memory running 14 Gbps memory data rate.

## 4.3 Classification Results

### Chinese Traffic Sign Database

Chinese traffic sign dataset is modest in size. Due to the fact that most of the traffic signs are installed according to local regulations, a large number of images are of the same shape with slight rotations. Hence, the usage of spatial transform network might be as effective. From Table 4, the accuracy of all models is well above 98%, showing how well modern CNN architecture could deal with such real time tasks.

| Table 4: TSRD Classification Cost and Results | | | | |
| --- | --- | --- | --- | --- |
| Model | Parameters | GFLOPS | Training Error | Validation Error |
| AlexNet | 57,044,810 | 0.7106 | 96.69 | 98.10 |
| EfficientNet-b0 | 14,047,366 | 1.7299 | 99.50 | 99.40 |
| EfficientNet-b1 | 27,235,236 | 3.5579 | 100.00 | 100.00 |
| EfficientNet-b2 | 29,487,358 | 4.8370 | 99.90 | 99.30 |
| EfficientNet-b3 | 40,648,506 | 8.2597 | 99.70 | 99.70 |
| ResNet-18 | 11,181,642 | 1.8185 | 99.20 | 99.20 |
| ResNet-34 | 21,289,802 | 3.6707 | 99.70 | 99.80 |
| ResNet-50 | 23,528,522 | 4.1094 | 99.30 | 99.40 |
| ResNet-101 | 42,520,650 | 7.8320 | 99.70 | 99.80 |
| ResNet-150 | 58,164,298 | 11.5567 | 99.70 | 99.80 |
| DenseNet-121 | 6,964,106 | 2.8647 | 99.90 | 99.90 |
| DenseNet-120 | 12,501,130 | 3.3964 | 99.90 | 99.90 |
| DenseNet-119 | 18,112,138 | 4.3391 | 99.80 | 99.90 |
| DenseNet-118 | 30,675,594 | 5.8172 | 99.80 | 99.90 |

It is also noticeable that not model with the most parameters perform the best. The excessive parameters may cause overfitting to the training thus further harm the accuracy. That’s when the residual structure comes in handy, by introducing feature maps form the previous layers, identity layers could be learnt by the layer that are close to the output layers to prevent model accuracy from falling when the overall parameters become large.

In reality, models with appropriate size shall be chosen even if residual layers were added. If identity matrix were learnt at the last few layers, it will be better to remove them to levy the computational burden. And identify might not be learnt properly at the layers that are excessive. The chart also shows that some smaller model even have higher accuracy, due to the noise coming from redundant layers of a larger size model.

The TSRD could be dealt with most of the modern CNN architectures pretty well, even with the obsolescent AlexNet could reach a high accuracy of 98.1%. If the CNN models could already deal with the datasets very well, it would be nice if the STN structure was kept from the model to save parameters and computational overhead.

### b. Caltech 101

Caltech 101 with 101 classes of objects another class if compared to TSRD. The objects with distinct shapes in all types of angels are nothing like traffic signs that approximately share a unified contour. That’s when the spatial transformer network could take advantage to readjust the input image size further perform automatic rotations to the input image. This work would put more emphasis on the EfficientNet structure and add different spatial transform networks on top of them.

| Table 5: Parameters & GFLOPS of Different Models on Caltech 101 | | | | | | | | |
| --- | --- | --- | --- | --- | --- | --- | --- | --- |
| Model | Original | | STN | | STN 1 | | The proposed structure - STN 2 | |
|  | **Parameters** | **GFLOPS** | **Parameters** | **GFLOPS** | **Parameters** | **GFLOPS** | **Parameters** | **GFLOPS** |
| EfficientNet-b0 | 14,163,937 | 1.730 | 15,032,641 | 1.809 | 15,032,479 | 1.816 | 15,033,137 | 1.756 |
| EfficientNet-b1 | 27,357,540 | 3.558 | 28,364,484 | 3.650 | 28,364,322 | 3.658 | 28,364,980 | 3.588 |
| EfficientNet-b2 | 29,615,577 | 4.837 | 30,809,721 | 4.945 | 30,809,559 | 4.954 | 30,810,217 | 4.872 |
| EfficientNet-b3 | 40,789,556 | 8.260 | 42,406,100 | 8.405 | 42,405,938 | 8.417 | 42,406,596 | 8.307 |
| EfficientNet-b4 | 56,613,262 | 18.432 | 59,266,606 | 18.668 | 59,266,444 | 18.687 | 59,267,102 | 18.508 |
| EfficientNet-b5 | 95,571,391 | 41.653 | 99,446,815 | 41.994 | 99,446,653 | 42.021 | 99,447,311 | 41.763 |
| ResNet-50 | 23,714,981 | 4.110 | 24,583,685 | 4.189 | 24,583,523 | 4.196 | 24,584,181 | 4.135 |

| Table 6: Validation and Test Accuracy of Different Models on Caltech 101 | | | | | | | | |
| --- | --- | --- | --- | --- | --- | --- | --- | --- |
| Model | Original | | STN | | STN 1 | | The proposed structure - STN 2 | |
|  | **Top-5 val.** | **Top-5 test** | **Top-5**  **val.** | **Top-5**  **test** | **Top-5**  **val.** | **Top-5**  **test** | **Top-5**  **val.** | **Top-5**  **test** |
| EfficientNet-b0 | 73.33 | 72.33 | 75.67 | 73.92 | 71.83 | 74.25 | 74.00 | 74.83 |
| EfficientNet-b1 | 72.83 | 71.58 | 73.33 | 71.92 | 71.42 | 72.25 | 72.00 | 73.00 |
| EfficientNet-b2 | 66.83 | 66.83 | 68.50 | 68.42 | 69.58 | 68.50 | 73.17 | 75.00 |
| EfficientNet-b3 | 63.33 | 60.83 | 69.83 | 69.83 | 74.00 | 73.67 | 75.58 | 75.42 |
| EfficientNet-b4 | 68.67 | 69.25 | 69.42 | 71.83 | 73.25 | 72.08 | 73.92 | 74.83 |
| EfficientNet-b5 | 70.00 | 68.75 | 72.75 | 71.83 | 73.25 | 72.08 | 79.83 | 78.33 |
| ResNet-50 | 75.17 | 73.58 | 76.42 | 76.92 | 78.75 | 77.00 | 77.42 | 77.33 |

From Table 5, ResNet-50 has parameters and FLOPS close to EfficientNet-b1 and EfficientNet-b2. Without the spatial transform networks, the accuracy of the EfficientNet models are inferior to ResNet. EfficientNet takes the measure of compound scaling to enlarge the entire model thus leading to large input size when the model expands. FLOPS expand quickly as when the input resolution increases. The EfficientNet-b5 has an input size of 456x456, 4 times the size of the ordinary 224 x 224 resolution, which leads to a scale of times FLOPS to the model. Even with such an expensive overhead, it performs even worse compared to the cheap ResNet-50 model.

After adding STN network to the stem network, ahead of all model structures. From Table 6, the accuracy of the models increases. No single model performs worse after adding the spatial transformer network. Most models have 1 to 3 percent accuracy growth and the EfficientNet-b3 model increased its accuracy over 8 percent, from 60.83% to 69.25 %. The experiment demonstrates that models do benefit from rotating and resizing the input image in advance. By adjusting the input images to unify what is fed into the network, the hidden layers could do a better job discovering the features in the images and extracting them using the convolution operation. In other words, the network could focus on extracting features to do the classification, thus increases the test accuracy. Examples like EfficientNet-b3 may result from the original model has difficulties recognizing target images with diverge resolutions and spatial information.

By replacing the Spatial transformer Network structure by STN1, the VGG-like structure. All models decrease parameter counts but increase in FLOPS operations. Thanks to splitting multiple large convolutional layers to smaller ones, some parameters could be saved. The overall structure and overhead are very similar to the original structure, in spite that accuracy further improved. All models performed better with the STN1 structure than the original STN structure. EfficientNet-b3 even has a 4.42% increase in performance. Other models increase by a bit, but not as much, this is because from changing from STN to STN1, the overall architecture did not change much, which leads to only slight performance leap.

It is a completely different story when models are equipped with STN2 structure. Owing the fact that STN2 is imitating an entire CNN architecture at the localization architecture, seems to provide more accurate information about how to perform the affine transform. The accuracy of all models was boosted even more switching to STN1. models like EfficientNet-b3 and EfficientNet-b5 even boosted their accuracy over 6%. After adding STN2 in prior to the main CNN structure, EfficientNet-b5 finally outperforms the ResNet-50 model to become the best performing model.

### c. Cifar-10

Will the improvements via adding spatial transformer network on a larger scale dataset still remain? This work applies similar setups on Cifar-10 and from Table 8 could illustrate that all of the models has higher accuracy when spatial transform layers were added. The greatest performance boost comes from EfficientNet-b2, a 0.92% accuracy advance. However, the accuracy scores are so close that does not make much of a difference.

By replacing STN1 with STN layers, similar results were also observed. All model once again outperforms STN but only with minor performance boosts. 3 out of 7 models increased their performance lower than 0.1% and no model has a performance leap over 0.5%. When the localization architecture switched to STN2, a much greater performance leap could be observed. Some models even performed 1% better overall on the testing set. The improvements of models equipped with STN2 could be 1 to 1.5 % higher than model without such architecture, which is a noticeable difference.

From the tables below strongly suggests that the model’s accuracy before and after adding the spatial transformer layer are strongly related. For example, DenseNet-121 model performs the best among all models without STN layers. With STN layers added, the model still tops all performances. Some models have powerful classification capabilities but perform poorly without the spatial transformer layers, this is due to the input images are difficult for the model to learn. By transforming each image by a specialized network could it standardize the shape of the input figure, allowing the neural network to learn more effortlessly, reaching its full potential.

| Table7: Parameters & GFLOPS of Different models on Cifar-10 | | | | | | | | |
| --- | --- | --- | --- | --- | --- | --- | --- | --- |
| Model | Original | | STN | | STN 1 | | The proposed structure - STN 2 | |
|  | **Parameters** | **GFLOPS** | **Parameters** | **GFLOPS** | **Parameters** | **GFLOPS** | **Parameters** | **GFLOPS** |
| EfficientNet-b0 | 14,047,366 | 1.7299 | 14,916,070 | 1.8092 | 14,915,908 | 1.8162 | 14,916,566 | 1.7556 |
| EfficientNet-b1 | 27,235,236 | 3.5579 | 28,242,180 | 3.6494 | 28,242,018 | 3.6574 | 28,242,676 | 3.5876 |
| EfficientNet-b2 | 29,487,358 | 4.8370 | 30,681,502 | 4.9450 | 30,681,340 | 4.9542 | 30,681,998 | 4.8720 |
| EfficientNet-b3 | 40,648,506 | 8.2597 | 42,265,050 | 8.4046 | 42,264,888 | 8.4167 | 42,265,546 | 8.3064 |
| ResNet-18 | 11,181,642 | 1.8185 | 12,050,346 | 1.8979 | 12,050,184 | 1.9049 | 12,050,842 | 1.8443 |
| ResNet-50 | 23,528,522 | 4.1094 | 24,397,226 | 4.1888 | 24,397,064 | 4.1958 | 24,397,722 | 4.1352 |
| ResNet-152 | 58,164,298 | 11.5567 | 59,033,002 | 11.6361 | 59,032,840 | 11.6431 | 59,033,498 | 11.5825 |
| DenseNet-121 | 6,964,106 | 2.8647 | 7,832,810 | 2.9440 | 7,832,648 | 2.9510 | 7,833,306 | 2.8904 |

| Table 8: Validation and Test Accuracy of Different models on Cifar-10 | | | | | | | | |
| --- | --- | --- | --- | --- | --- | --- | --- | --- |
| Model | Original | | STN | | STN 1 | | The proposed structure - STN 2 | |
|  | **Top-5 val.** | **Top-5 test** | **Top-5**  **val.** | **Top-5**  **test** | **Top-5**  **val.** | **Top-5**  **test** | **Top-5**  **val.** | **Top-5**  **test** |
| EfficientNet-b0 | 86.83 | 86.05 | 87.48 | 86.40 | 87.88 | 86.81 | 87.71 | 87.45 |
| EfficientNet-b1 | 86.90 | 86.89 | 87.01 | 86.95 | 87.62 | 86.98 | 87.71 | 87.03 |
| EfficientNet-b2 | 86.65 | 86.38 | 87.81 | 87.30 | 87.57 | 87.36 | 87.77 | 87.52 |
| EfficientNet-b3 | 87.11 | 86.79 | 87.12 | 86.96 | 87.19 | 87.02 | 87.64 | 87.22 |
| ResNet-18 | 85.60 | 84.96 | 85.44 | 85.53 | 85.79 | 85.83 | 86.37 | 86.41 |
| ResNet-50 | 85.07 | 84.84 | 85.43 | 85.01 | 85.63 | 85.02 | 86.69 | 86.19 |
| ResNet-152 | 85.15 | 84.65 | 85.09 | 84.81 | 85.40 | 85.16 | 86.86 | 85.17 |
| DenseNet-121 | 88.91 | 88.61 | 89.42 | 89.29 | 89.88 | 89.51 | 86.17 | 90.28 |

### d. Computational Cost of STN Architectures

This work is also interested in how much resource it takes for the spatial transformer network to apply. The number of parameters and the FLOPS takes to compute them are in Table 9. The size of the layer is proportional to the input resolution, thus models with identical input resolution would share the same spatial transformer structure. It is apparent that STN1 brings lower parameter counts but with slightly more FLOPS than the original STN architecture. STN2 has slightly more parameters but the FLOPS it takes to compute is almost one third. This resulted from the widely use of decoder and encoder structure. EfficientNet adopts compound scaling method, so the input resolution as well as the spatial transformer structure grows as the model scales.

| Table 9: Parameters of GFLOPS of Different Spatial Transformer Architecture | | | | | | |
| --- | --- | --- | --- | --- | --- | --- |
| Model | STN | | STN 1 | | The proposed structure - STN 2 | |
|  | **Parameters** | **GFLOPS** | **Parameters** | **GFLOPS** | **GFLOPS** | **Parameters** |
| EfficientNet-b0 | 868,704 | 0.0793 | 868,542 | 0.0863 | 869,200 | 0.0257 |
| EfficientNet-b1 | 1,006,944 | 0.0915 | 1,006,782 | 0.0995 | 1,007,440 | 0.0297 |
| EfficientNet-b2 | 1,194,144 | 0.1080 | 1,193,982 | 0.1172 | 1,194,640 | 0.0350 |
| EfficientNet-b3 | 1,616,544 | 0.1449 | 1,616,382 | 0.1570 | 1,617,040 | 0.0469 |
| EfficientNet-b4 | 2,653,344 | 0.2356 | 2,653,182 | 0.2544 | 2,653,840 | 0.0760 |
| EfficientNet-b5 | 3,875,424 | 0.3418 | 3,875,262 | 0.3683 | 3,875,920 | 0.1101 |
| ResNet-18 | 868,704 | 0.0793 | 868,542 | 0.0863 | 869,200 | 0.0257 |
| ResNet-50 | 868,704 | 0.0793 | 868,542 | 0.0863 | 869,200 | 0.0257 |
| ResNet-152 | 868,704 | 0.0793 | 868,542 | 0.0863 | 869,200 | 0.0257 |
| DenseNet-121 | 868,704 | 0.0793 | 868,542 | 0.0863 | 869,200 | 0.0257 |

# 5. Conclusions

Experiments with different spatial transformer network architecture on separate models has been made in this paper. This work has ventured with three different localization network design: a default setting, a VGG like design and a redesigned structure. Experiments show the performance of the model increased even if the default setting was selected. The redesigned structure performed the best with one third of the FLOPS with the cost of slightly more parameters. The localization design could seamlessly replace the old structure with instant performance boost. The structure of convolutional neural networks is rapidly developing by researchers all around the world, any breakthrough architecture design would push the limit one step ahead. We plan to keep investigating the perfect localization architecture design to achieve the goal: Bring neural network the ability to be spatially invariant to input data with a focus to reach better performance.

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