

# Convolutional Neural Networks For Semantic Segmentation

Course 3, Module 5, Lesson 2



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# Learning Objectives

- Learn how to use convolutional neural networks to perform the semantic segmentation task
- Learn the different layers required for the good performance of semantic segmentation models

# The Semantic Segmentation Problem

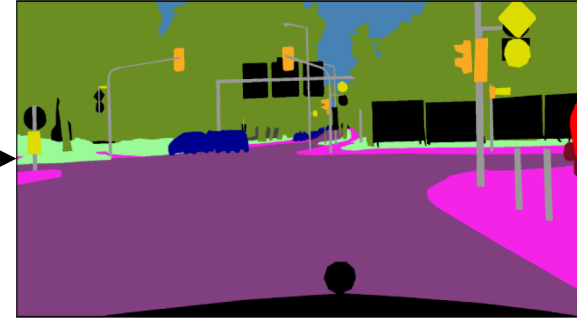


- Road
- Sidewalk
- Pole
- Traffic Light
- Traffic Signs
- Vegetation
- Terrain
- Sky
- Car
- Background

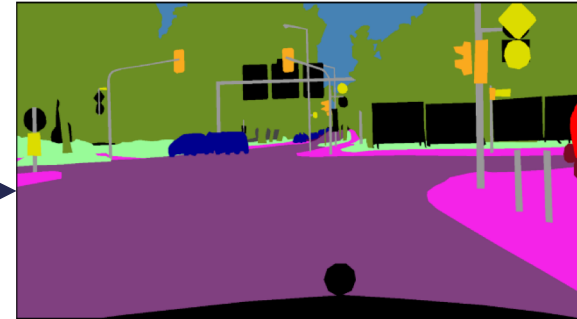
# ConvNets For Semantic Segmentation



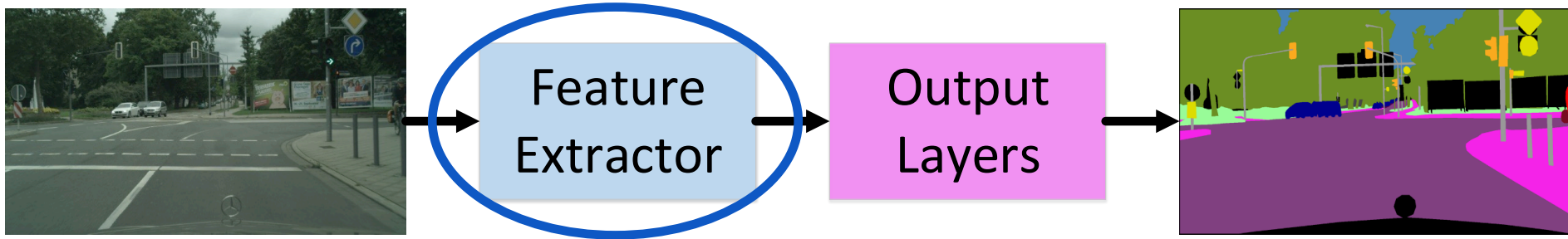
$$f(x; \theta)$$



ConvNet



# ConvNets For Semantic Segmentation



# The Feature Extractor

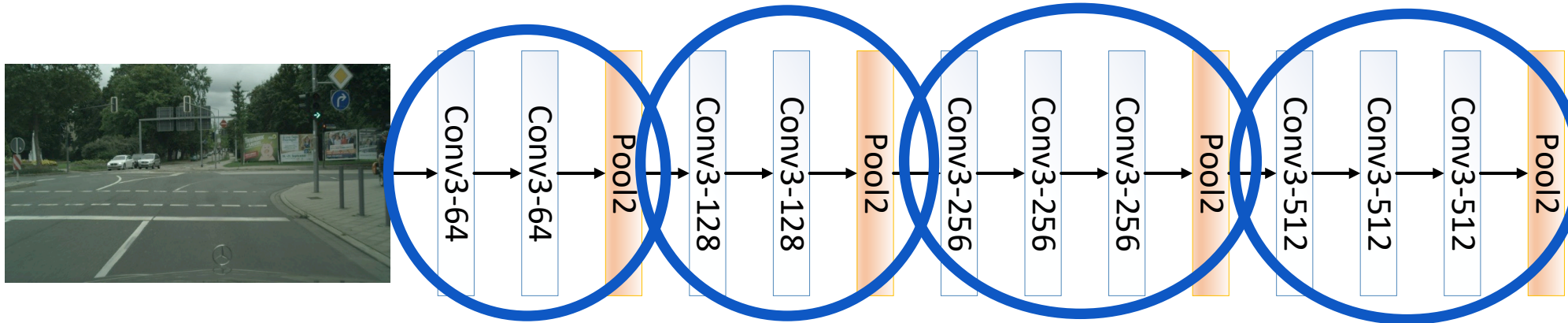
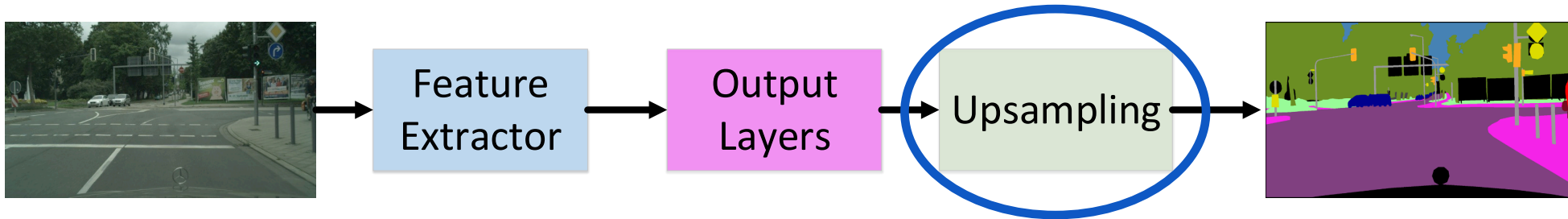


	Image	Conv1	Conv2	Conv3	Conv4
Width	M	M/2	M/4	M/8	M/16
Height	N	N/2	N/4	N/8	N/16
Depth	3	64	128	256	512

# Upsampling the Output



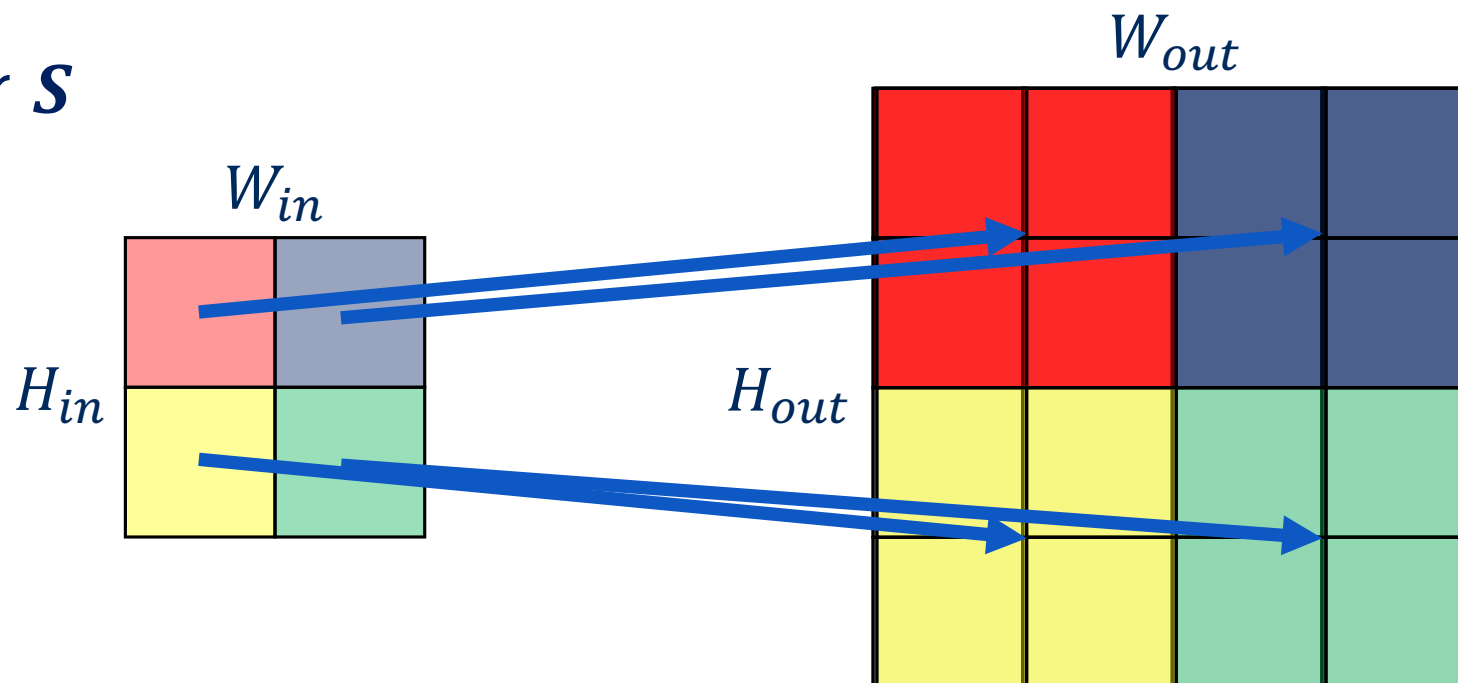
# Upsampling Layer

- Upsampling Multiplier  $S$

$$W_{out} = S \times W_{in}$$

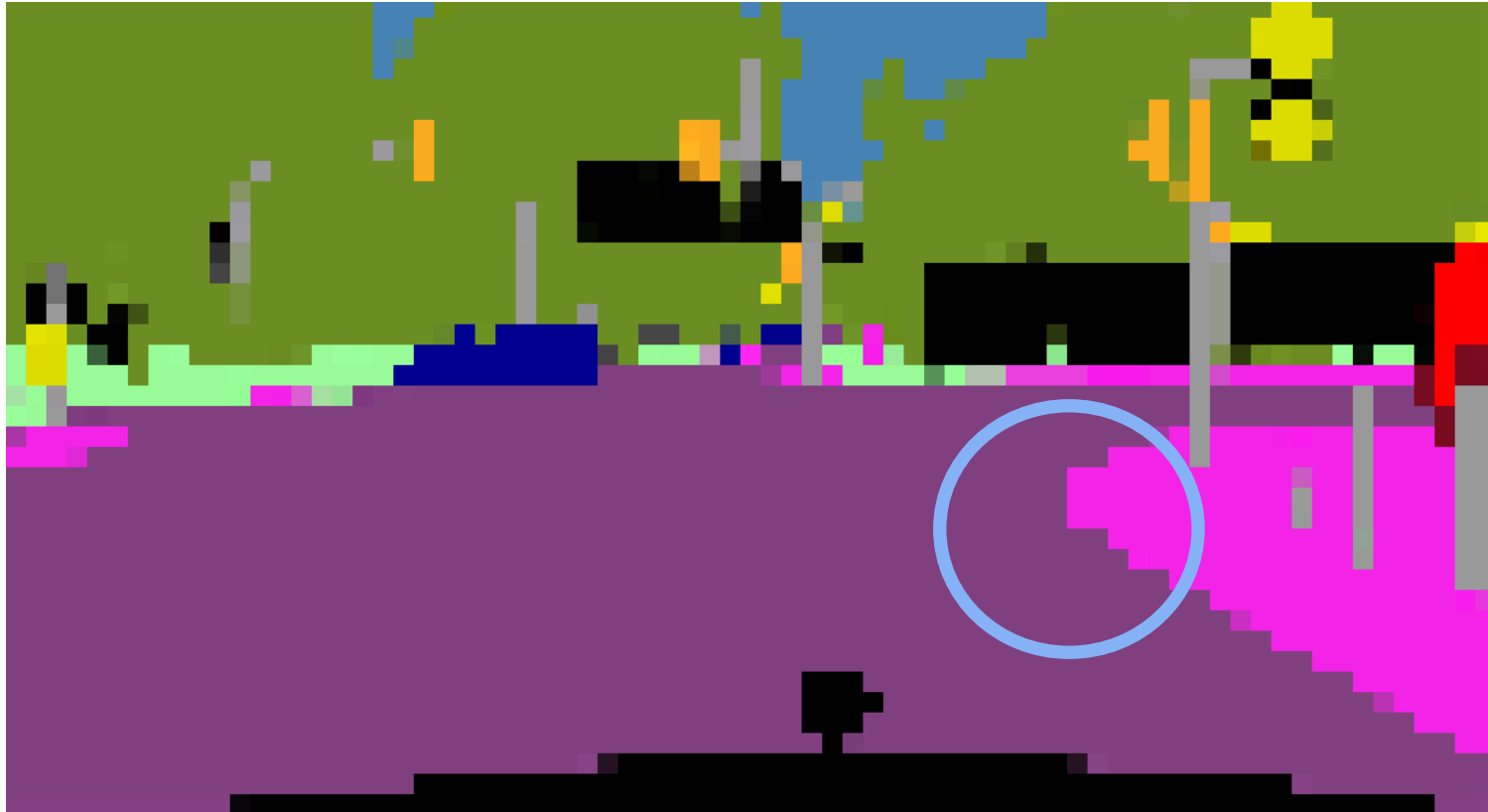
$$H_{out} = S \times H_{in}$$

$$D_{out} = D_{in}$$

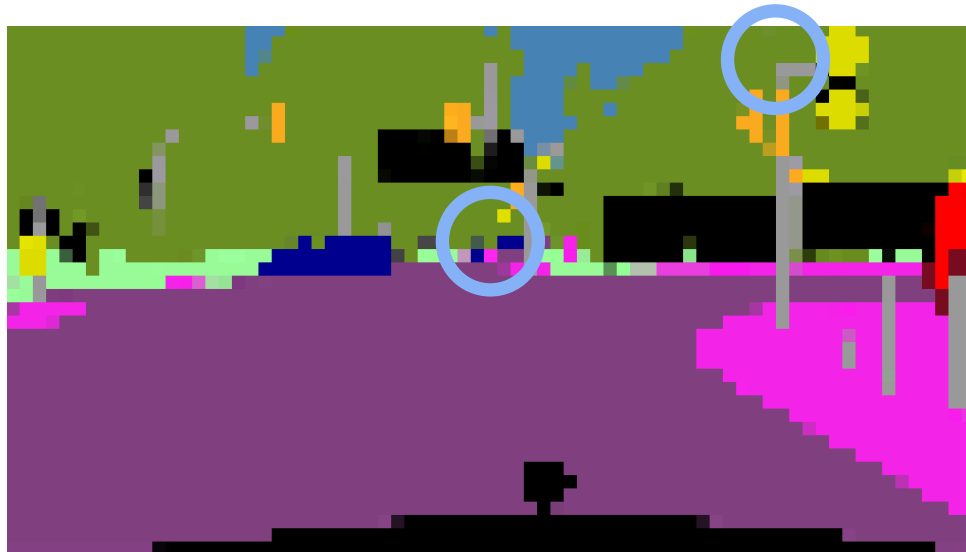
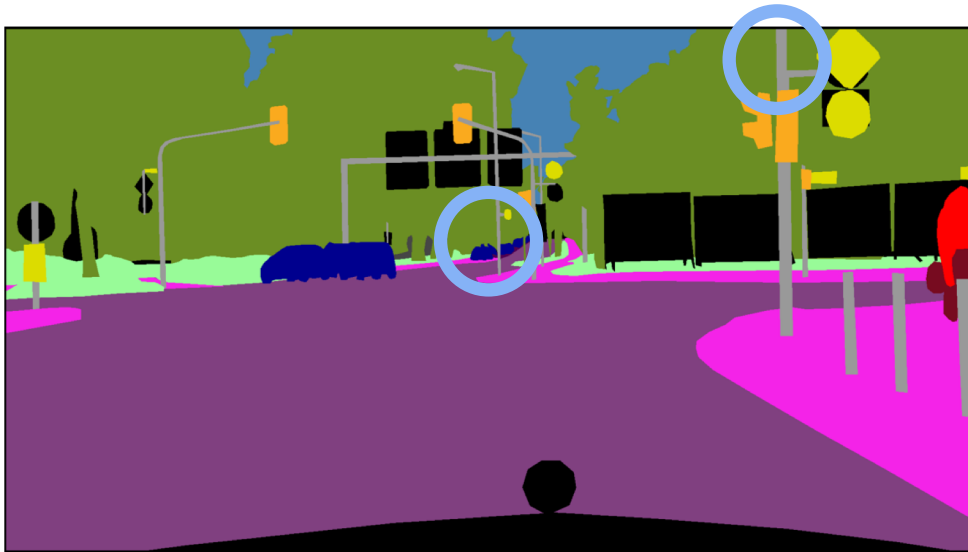




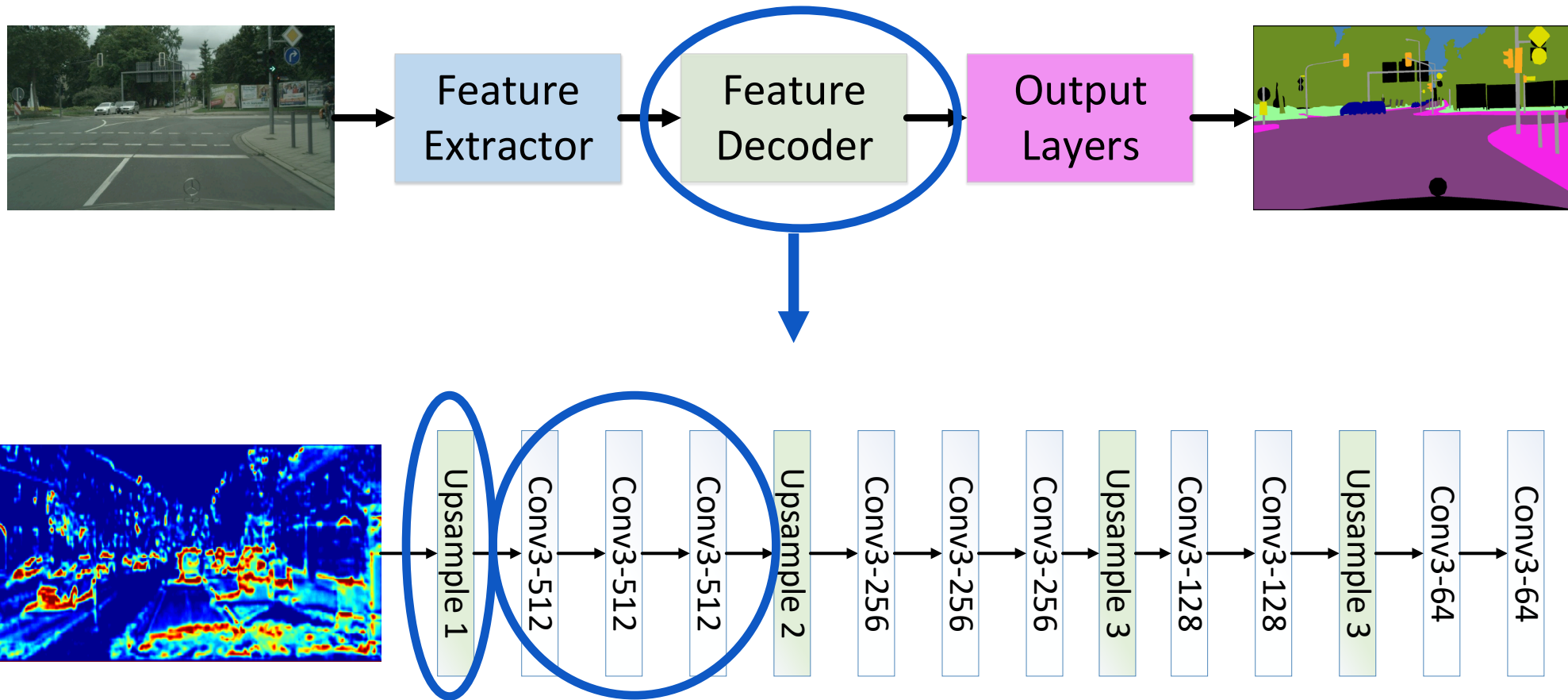
# Upsampling The Output



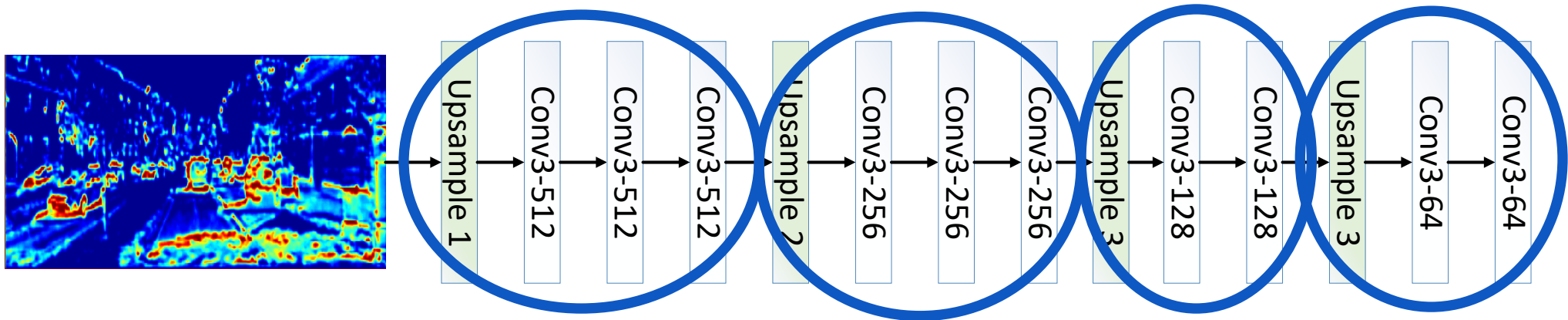
# Upsampling The Output



# Learning Same Resolution Feature Maps

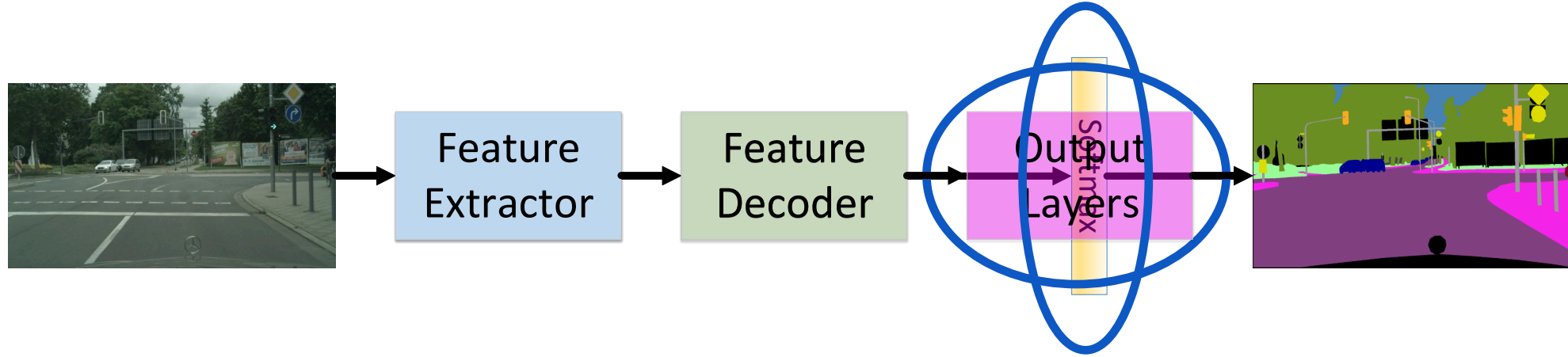


# The Feature Decoder



	Feature Map	Deconv1	Deconv2	Deconv3	Deconv4
Width	M/16	M/8	M/4	M/2	M
Height	N/16	N/8	N/4	N/2	N
Depth	512	512	256	128	64

# Learning Same Resolution Feature Maps



# Output Representation

Ground Truth



Class

R	R	R
R	R	S
S	S	S

Output

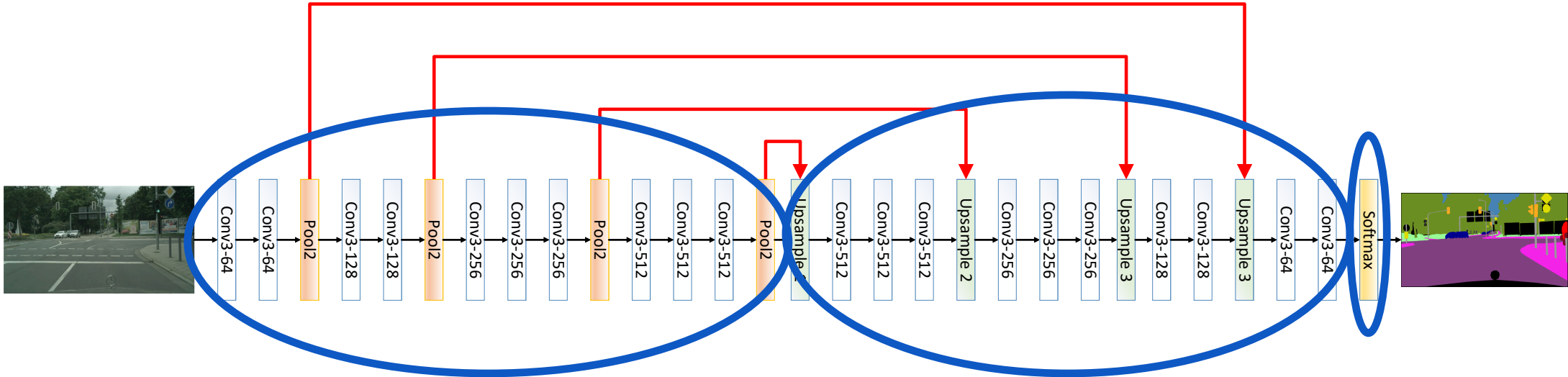
019	1
001	0
0	0

# Classification Loss

$$L_{cls} = \frac{1}{N_{total}} \sum_i CrossEntropy(s_i^*, s_i)$$

- $N_{total}$  is the number of pixels in all images of our **minibatch**
- $s_i$  is the output of the neural network
- $s_i^*$  is the ground truth classification

# ConvNets For Semantic Segmentation





# Summary

- Convolutional Neural Networks can be used to solve the semantic segmentation problem
- In a feature extractor and a feature decoder are required to provide the final output of semantic segmentation models
- **Next: Semantic Segmentation For Autonomous Driving**