

PedeScan: A Plug-n-Play Quantized Quality-Aware Modality Balanced Pedestrian Detector

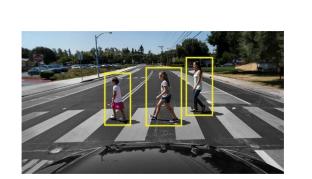
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INTRODUCTION AND MOTIVATION

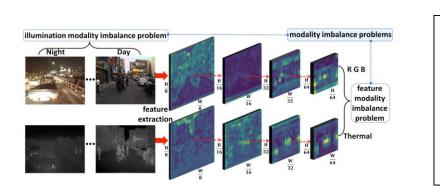


Pedestrian Detection is an task critical to many applications such as autonomous driving and navigation!

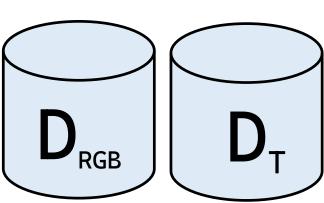


RGB Images works well mainly in the daytime, and fails during the night. This is where thermal imaging comes into importance. However we must now <u>balance both modalities</u> for accurate detection, as they give us same information.

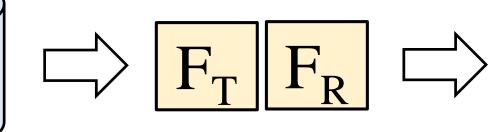


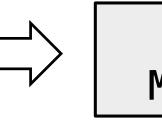


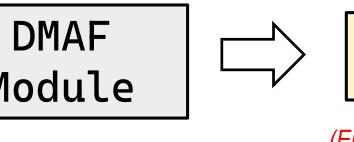
The MBNet Architecture¹ proposed by *Kailai Zhou*, *Linsen Chen*, *Xun Cao* addresses exactly this issue. It uses a two module approach: the DMAF (*Differential Modality Aware Fusion*) Module and the IAFA (Illumination Aware Feature Alignment) Module to address this exact issue.



(RGB + Thermal Datasets)

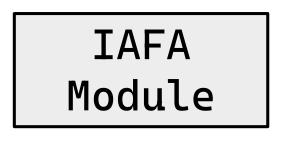






(aligns the feature maps)



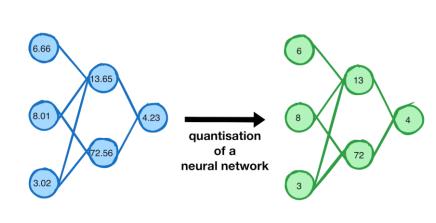




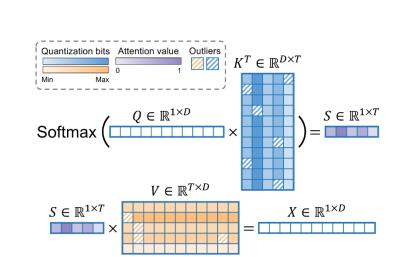


The MBNet Pipeline (shown above) takes a <u>significant amount of time</u>during inference (~10 minutes for 1000 pictures). This can be dangerous for time-sensitive applications such as autonomous driving.

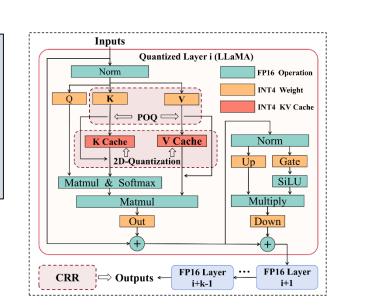
PEDESCAN SYSTEM DETAILS: A QUALITY AWARE QUANTIZATION BASED APPROACH



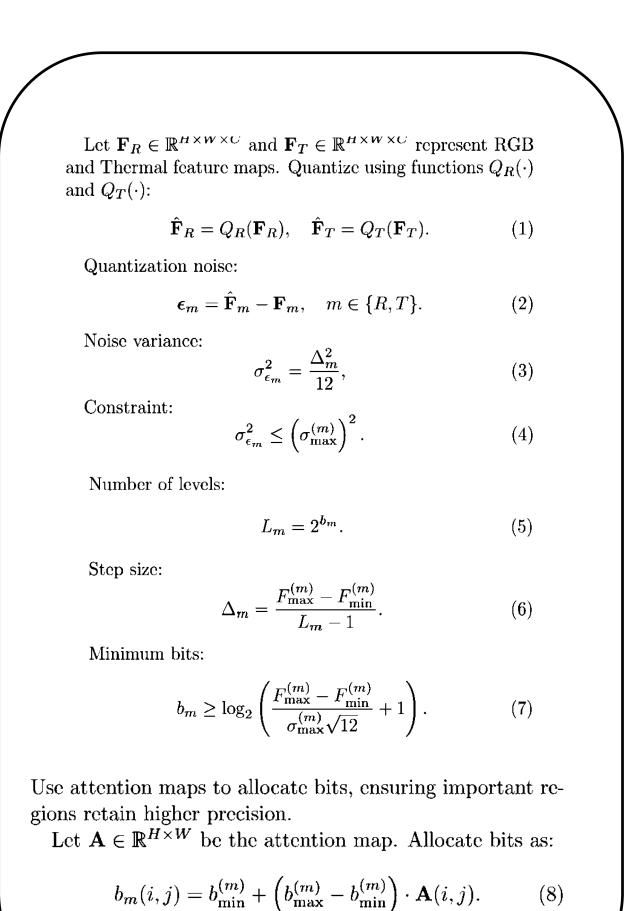
Inspired by works such KVQuant² and QAQ³, we extend the concepts of quality aware quantization our MBNet Framework to reduce latency while maintaining comparable miss rates.



We extend the key concepts of quality aware KV Cache quantization — including non uniform channel quantization, and the statistical allocation of non uniform number of bits for each channel.



We use a three-stage pipeline for our system as shown below:



Multimodal QAQ Stage

Assign bits based on channel variance to preserve important features. Quantization noise: $\sigma_{\epsilon_c^{(m)}}^2 = \frac{\left(F_{\max}^{(c,m)} - F_{\min}^{(c,m)}\right)^2}{12 \cdot 2^{2b_c^{(m)}}}. \qquad (9)$ Constraint: $\sigma_{\epsilon_c^{(m)}}^2 \leq \left(\sigma_{\max}^{(c,m)}\right)^2. \qquad (10)$ Minimum bits: $b_c^{(m)} \geq \frac{1}{2}\log_2\left(\frac{F_{\max}^{(c,m)} - F_{\min}^{(c,m)}}{\sigma_{\max}^{(c,m)}\sqrt{12}}\right). \qquad (11)$ Identify and handle outliers to prevent distortion in quantization. Kurtosis: $\kappa_c^{(m)} = \frac{\mathbb{E}\left[\left(F_c^{(m)} - \mu_c^{(m)}\right)^4\right]}{\left(\sigma_c^{(m)}\right)^4}. \qquad (12)$ Optimize bit allocation to minimize total bits while controlling quantization noise. $\min_{b_m,b_c^{(m)}(i,j)} \sum_m \sum_c \sum_{i,j} b_c^{(m)}(i,j) \qquad (13)$ subject to $\sigma_{\epsilon_c^{(m)}}^2(i,j) \leq \left(\sigma_{\max}^{(c,m)}\right)^2, \quad \forall m,c,i,j. \qquad (14)$

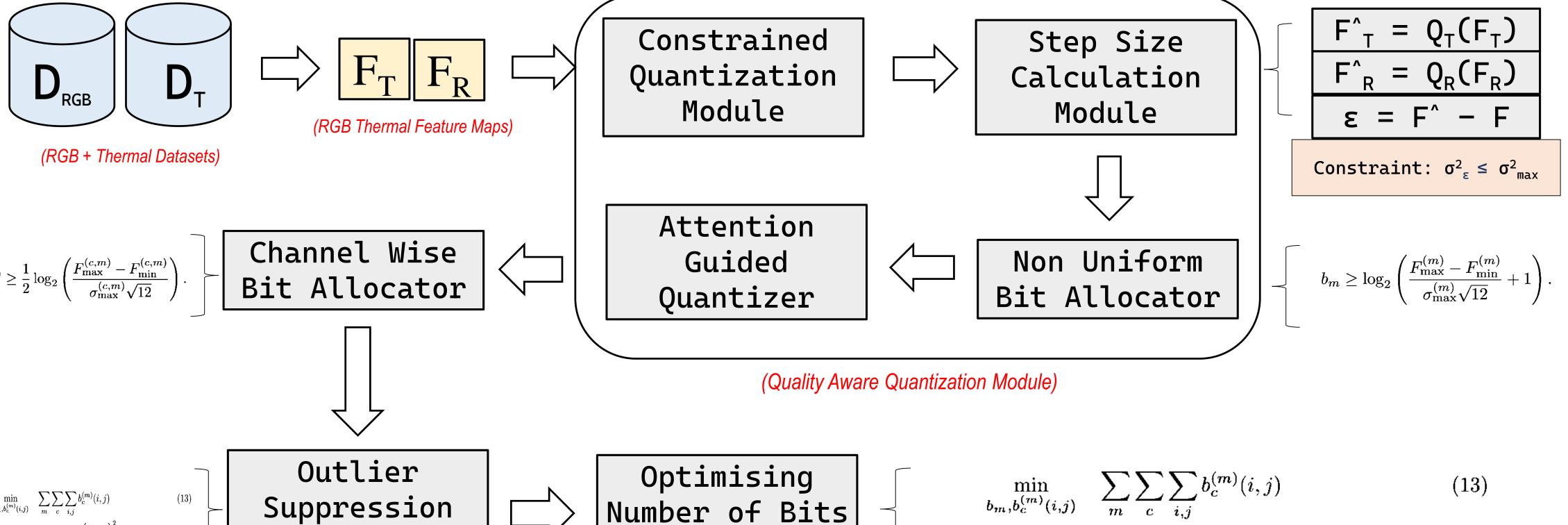
Combine quantized features with DMAF and IAFA for enhanced fusion and alignment.

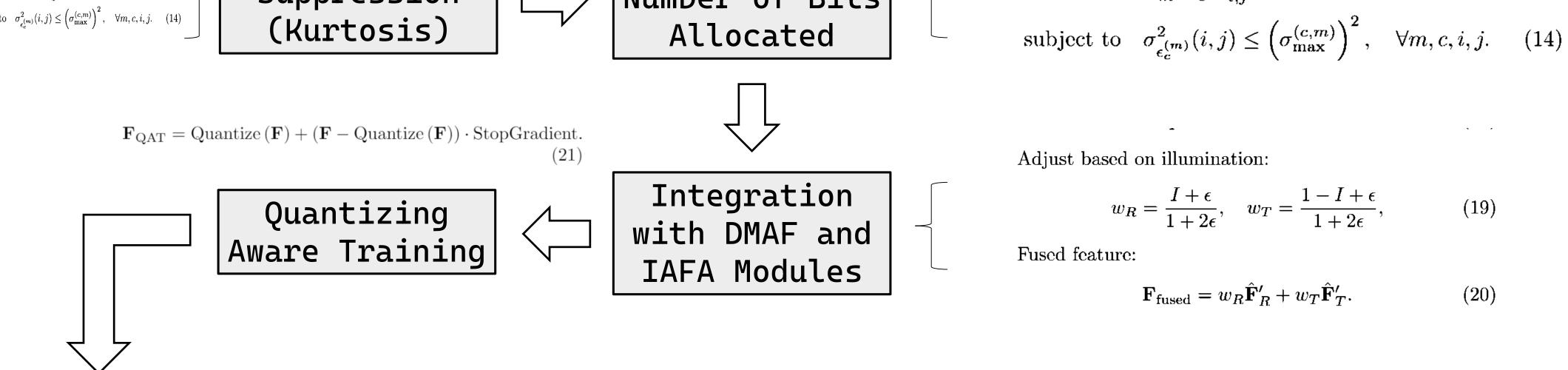
Compute differential feature: $\hat{\mathbf{F}}_D = \hat{\mathbf{F}}_R - \hat{\mathbf{F}}_T. \qquad (15)$ Fusion weights: $\mathbf{V}_w = \tanh\left(\mathrm{GAP}\left(\hat{\mathbf{F}}_D\right)\right). \qquad (16)$ Recalibrate features: $\hat{\mathbf{F}}_R' = \hat{\mathbf{F}}_R + \mathbf{V}_w \odot \hat{\mathbf{F}}_T, \qquad (17)$ $\hat{\mathbf{F}}_T' = \hat{\mathbf{F}}_T + \mathbf{V}_w \odot \hat{\mathbf{F}}_R. \qquad (18)$ Adjust based on illumination: $w_R = \frac{I+\epsilon}{1+2\epsilon}, \quad w_T = \frac{1-I+\epsilon}{1+2\epsilon}, \qquad (19)$ Fused feature: $\mathbf{F}_{\text{fused}} = w_R \hat{\mathbf{F}}_R' + w_T \hat{\mathbf{F}}_T'. \qquad (20)$ Train the network to handle quantization effects using fake quantization during training. $\mathbf{F}_{\text{QAT}} = \text{Quantize}\left(\mathbf{F}\right) + (\mathbf{F} - \text{Quantize}\left(\mathbf{F}\right)) \cdot \text{StopGradient}. \qquad (21)$ Evaluate memory and computational savings from the quantization scheme. $\text{Compression Ratio} = \frac{\sum_m HWCb_{\text{float}}}{\sum_m \sum_c \sum_{i,j} b_c^{(m)}(i,j)}, \qquad (22)$

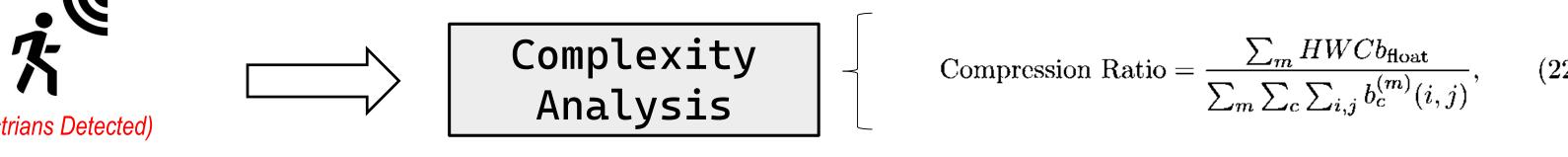
Non Uniform Bit Allocation Stage

Integration Stage

PEDESCAN SYSTEM FLOWCHART







(used for calculating the quantization rate – an important hyper parameter)

RESULTS ON CVC14 AND KAIST DATASETS

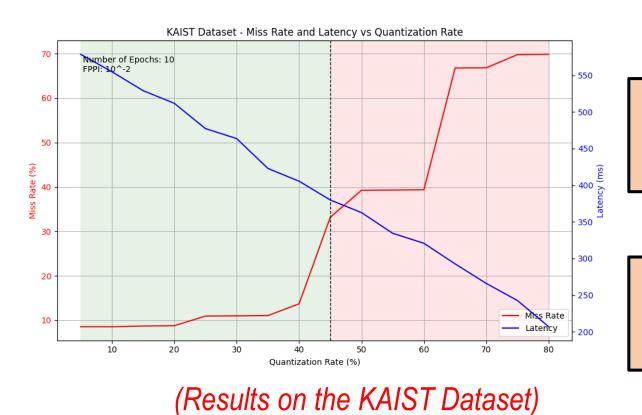


Table 2: KAIST Dataset

Quantization Noise (%) | Miss Rate (%) | Latency (ms)

22.95

37.24*

38.57

258.59 222.67 222.29

222.56

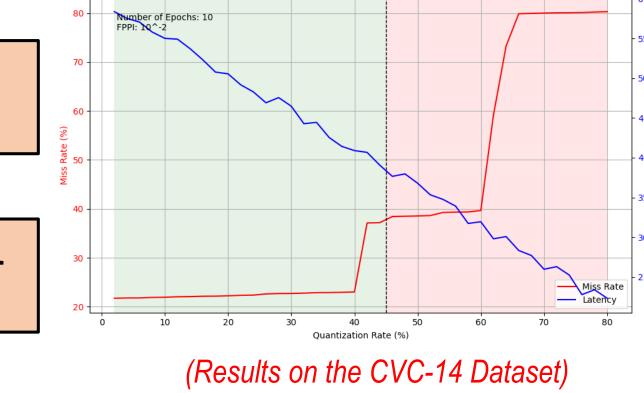
222.60

222.17

222.49

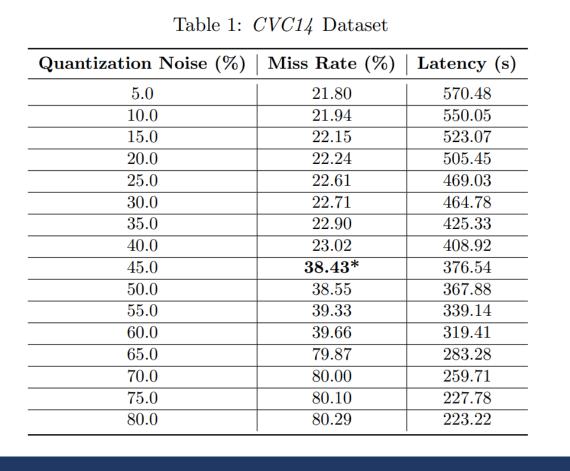
~50% latency reduction achieved with just a ~1% increase in MR⁻² %

Latency reduction is achieved up to a peak quantization noise of ~45% ($\theta_{\rm 0}$)



We define the green region where $\sigma^2_{\epsilon} \le \theta_0$ as the "viable" region where quality aware latency reduction is possible.

We define the red region where $\sigma^2_{\epsilon} \geq \theta_0$ as the "un-viable" region where latency reduction is not possible.



REFERENCES

- [1] Kailai Zhou, Linsen Chen, Xun Cao. Improving Multispectral Pedestrian Detection by Addressing Modality Imbalance Problems. ECCV 2020.
- [2] Coleman Hooper, Sehoon et al.. KVQuant: Towards 10 Million Context Length LLM Inference with KV Cache Quantization. arXiv preprint. 2024.
- [3] Shichen Dong, Wen Cheng, Jiayu Qin, Wei Wang. QAQ: Quality Adaptive Quantization for LLM KV Cache. arXiv preprint. 2024



Scan this QR code to access the GitHub Repository and learn about the code behind PedeScan!