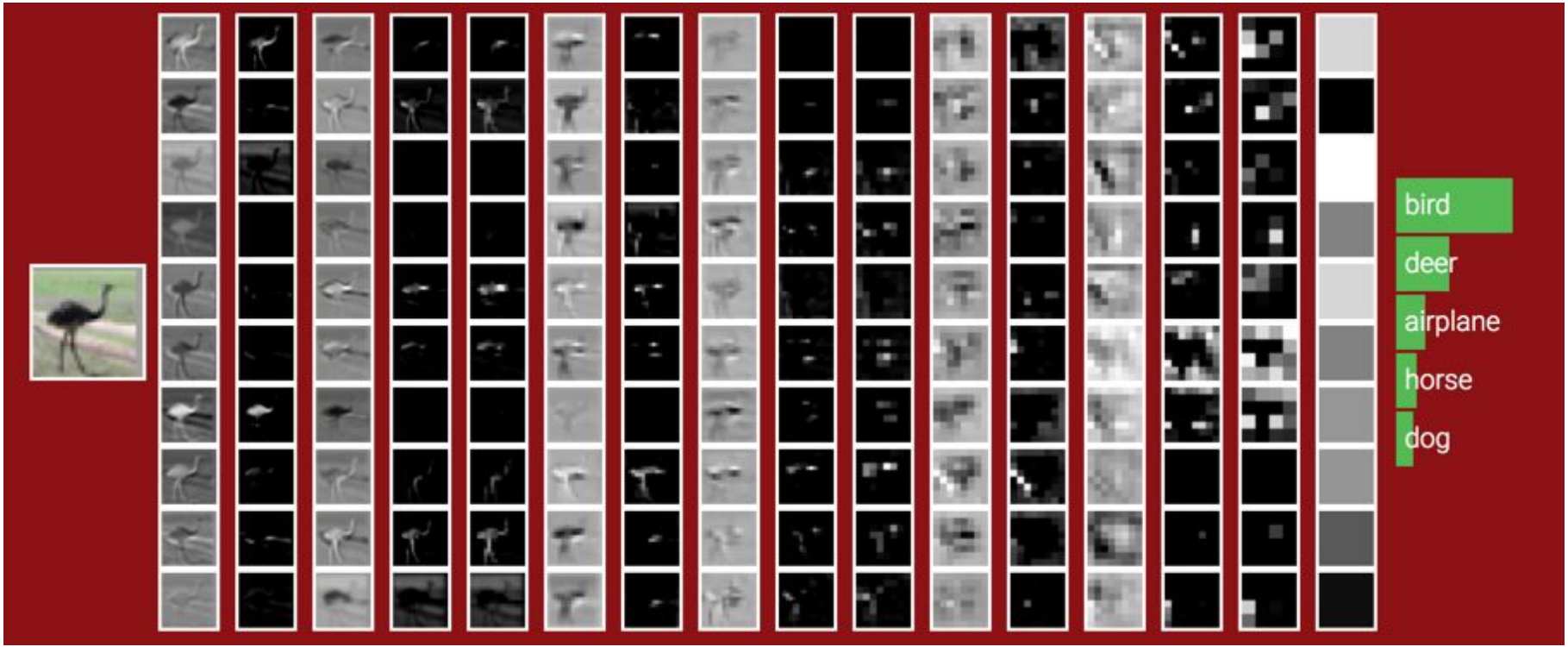
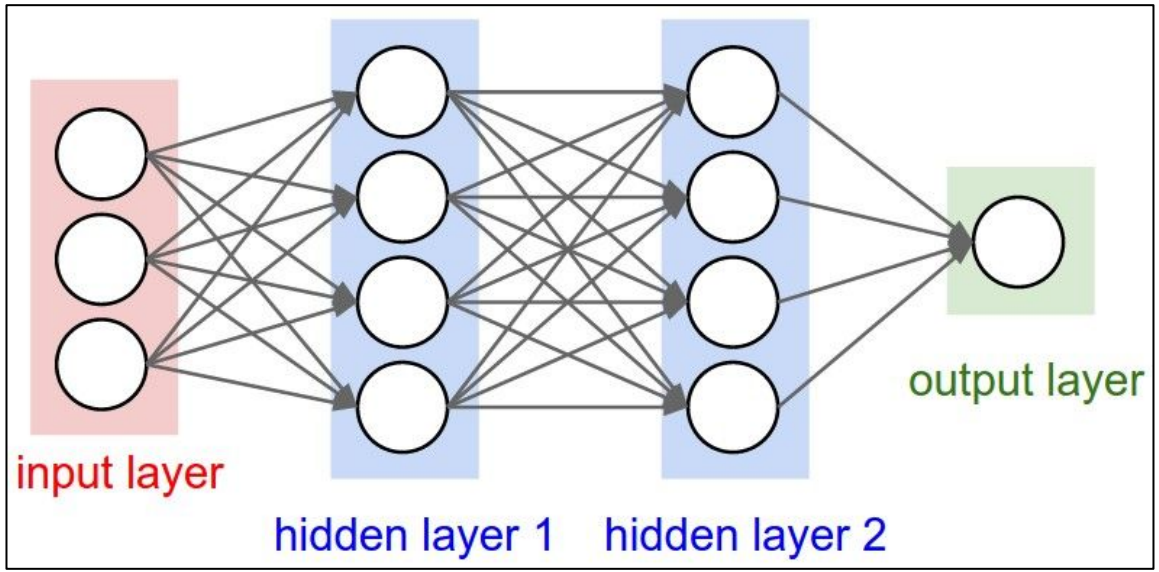
Deep Learning for Computer Vision



Andrej Karpathy

Bay Area Deep Learning School, 2016

So far...



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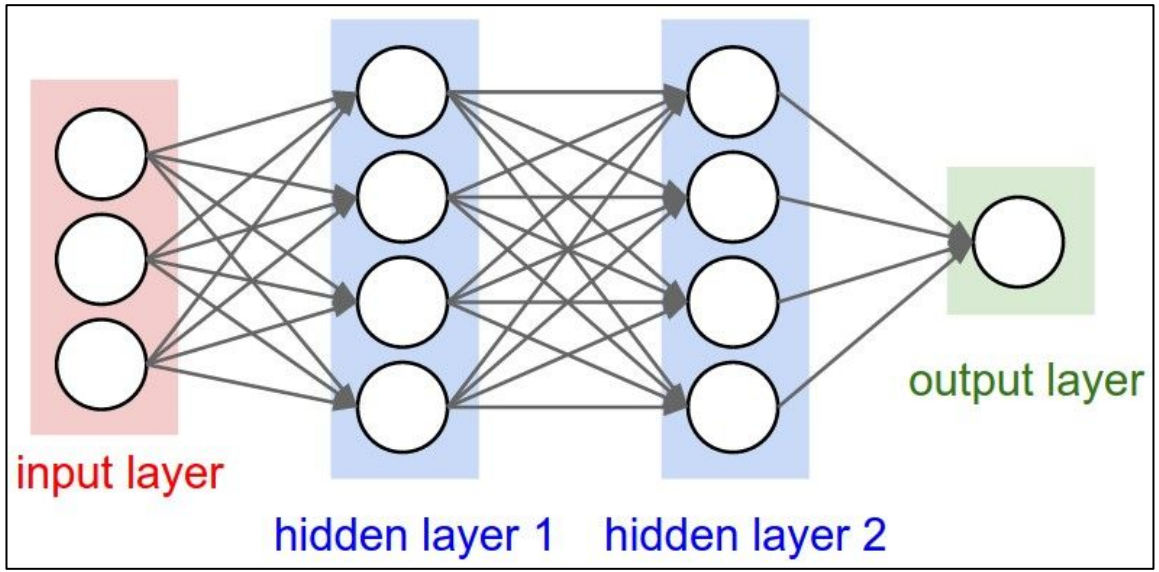
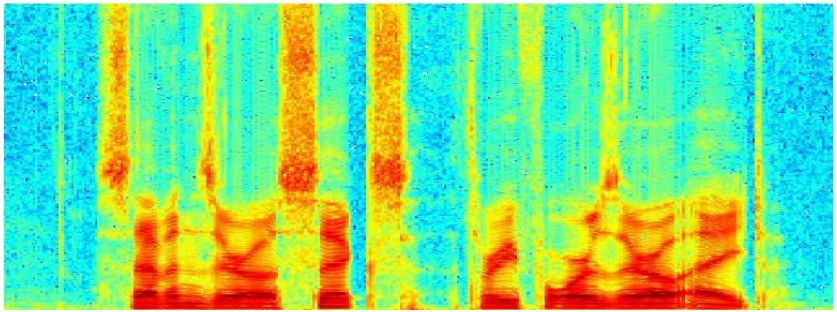


Some input vector (very few assumptions made).

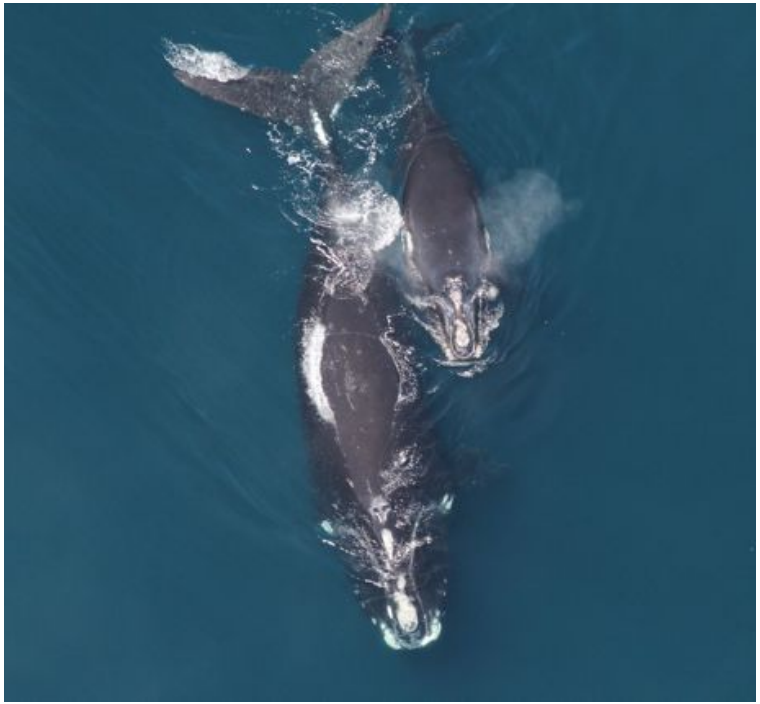
In many real-world applications input vectors have **structure**.



Spectrograms

"Lorem ipsum dolor sit amet, consectetur adipiscing elit, sed do eiusmod tempor incididunt ut labore et dolore magna aliqua. Ut enim ad minim veniam, quis nostrud exercitation ullamco laboris nisi ut aliquip ex ea commodo consequat. Duis aute irure dolor in reprehenderit in voluptate velit esse cillum dolore eu fugiat nulla pariatur. Excepteur sint occaecat cupidatat non proident, sunt in culpa qui officia deserunt mollit anim id est laborum."

Text



Images

Convolutional Neural Networks: A pinch of history

Hubel & Wiesel,

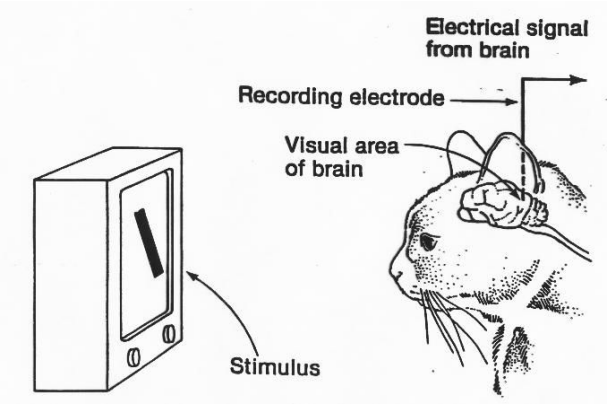
1959

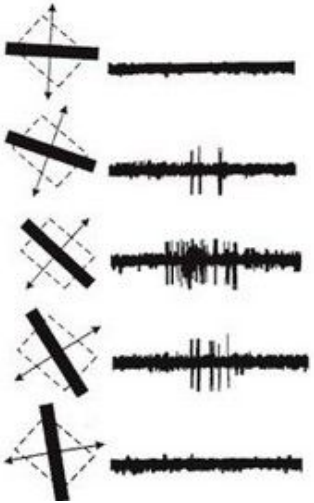
RECEPTIVE FIELDS OF SINGLE NEURONES IN
THE CAT'S STRIATE CORTEX

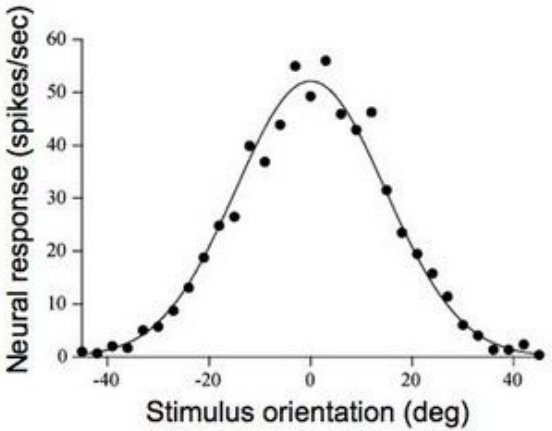
1962

RECEPTIVE FIELDS, BINOCULAR INTERACTION
AND FUNCTIONAL ARCHITECTURE IN
THE CAT'S VISUAL CORTEX

1968...

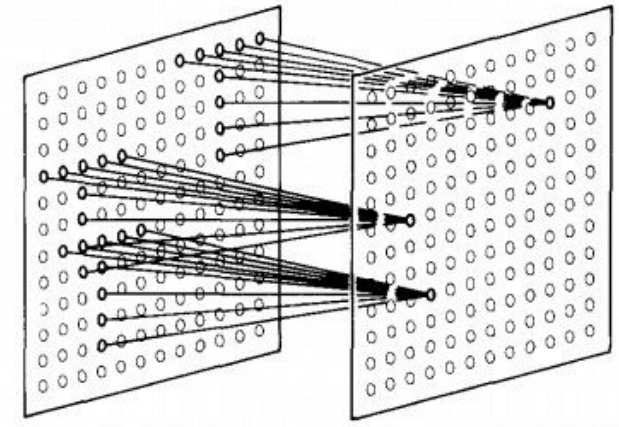




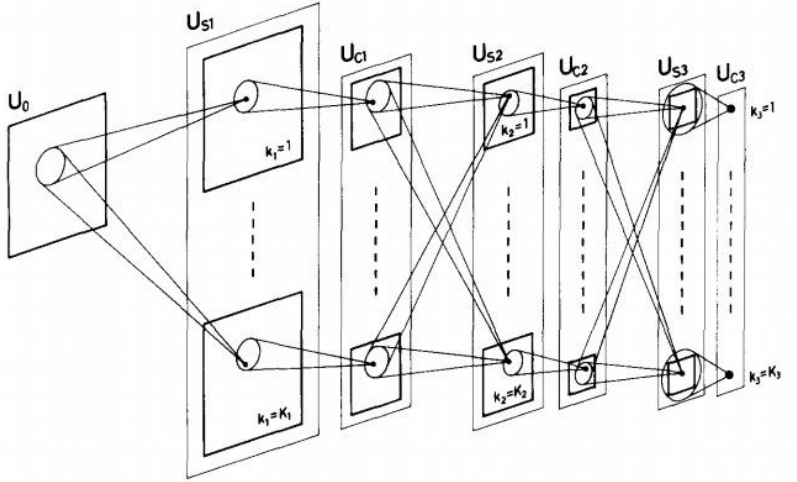


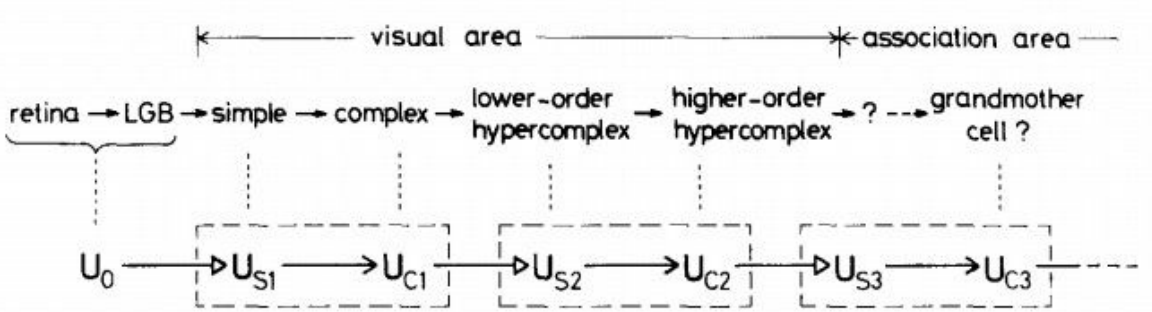
A bit of history:

Neurocognitron
[Fukushima 1980]



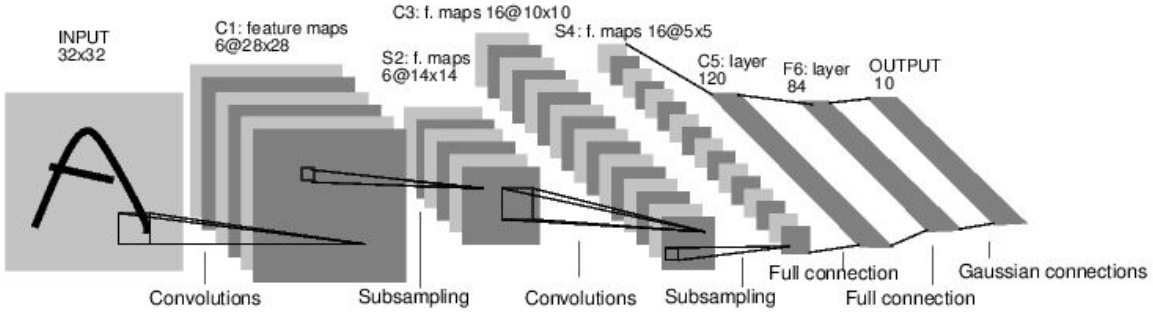
"sandwich" architecture (SCSCSC…)
simple cells: modifiable parameters
complex cells: perform pooling



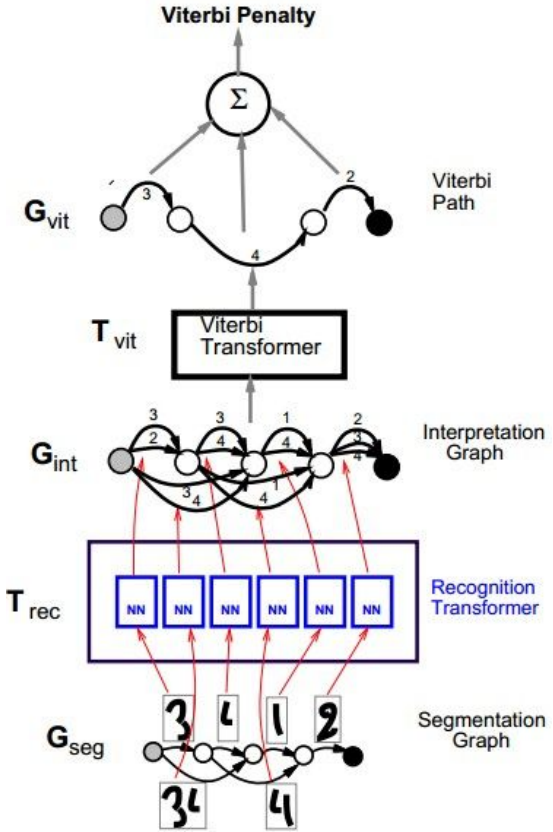


Gradient-based learning applied to document recognition

[LeCun, Bottou, Bengio, Haffner 1998]



LeNet-5



Computer Vision **2011**

Computer Vision **2011**

4.1. Image Features and Kernels

We selected or designed several state-of-art features that are potentially useful for scene classification. GIST features [21] are proposed specifically for scene recognition tasks. Dense SIFT features are also found to perform very well at the 15-category dataset [17]. We also evaluate sparse SIFTs as used in "Video Google" [27]. HOG features provide excellent performance for object and human recognition tasks [4, 9], so it is interesting to examine their utility for scene recognition. While SIFT is known to be very good at finding repeated image content, the self-similarity descriptor (SSIM) [26] relates images using their internal layout of local self-similarities. Unlike GIST, SIFT, and HOG, which are all local gradient-based approaches, SSIM may provide a distinct, complementary measure of scene layout that is somewhat appearance invariant. As a baseline, we also include Tiny Images [28], color histograms and straight line histograms. To make our color and texton histograms more invariant to scene layout, we also build histograms for specific geometric classes as determined by [13]. The geometric classification of a scene is then itself used as a feature, hopefully being invariant to appearance but responsive to layout.

GIST: The GIST descriptor [21] computes the output energy of a bank of 24 filters. The filters are Gabor-like filters tuned to 8 orientations at 4 different scales. The square output of each filter is then averaged on a 4×4 grid.

HOG2x2: First, histogram of oriented edges (HOG) descriptors [4] are densely extracted on a regular grid at steps of 8 pixels. HOG features are computed using the code available online provided by [9], which gives a 31-dimension descriptor for each node of the grid. Then, 2×2 neighboring HOG descriptors are stacked together to form a descriptor with 124 dimensions. The stacked descriptors spatially overlap. This 2×2 neighbor stacking is important because the higher feature dimensionality provides more descriptive power. The descriptors are quantized into 300 visual words by k-means. With this visual word representation, three-level spatial histograms are computed on grids of 1×1, 2×2 and 4×4. Histogram intersection[17] is used to define the similarity of two histograms at the same pyramid level for two images. The kernel matrices at the three levels are normalized by their respective means, and linearly combined together using equal weights.

Dense SIFT: As with HOG2x2, SIFT descriptors are densely extracted [17] using a flat rather than Gaussian window at two scales (4 and 8 pixel radii) on a regular grid at steps of 5 pixels. The three descriptors are stacked together for each HSV color channels, and quantized into 300 visual words by k-means, and spatial pyramid histograms are used as kernels[17].

Computer Vision **2011**

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Tiny Images: The most trivial way to match scenes is to compare them directly in color image space. Reducing the image dimensions drastically makes this approach more computationally feasible and less sensitive to exact alignment. This method of image matching has been examined thoroughly by Torralba et al.[28] for the purpose of object recognition and scene classification.

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Computer
Vision
2011

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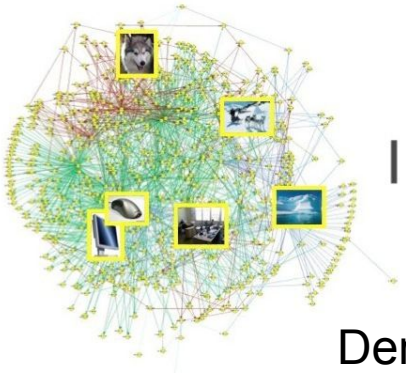
\+ code complexity :(

ImageNet Classification with Deep Convolutional Neural Networks

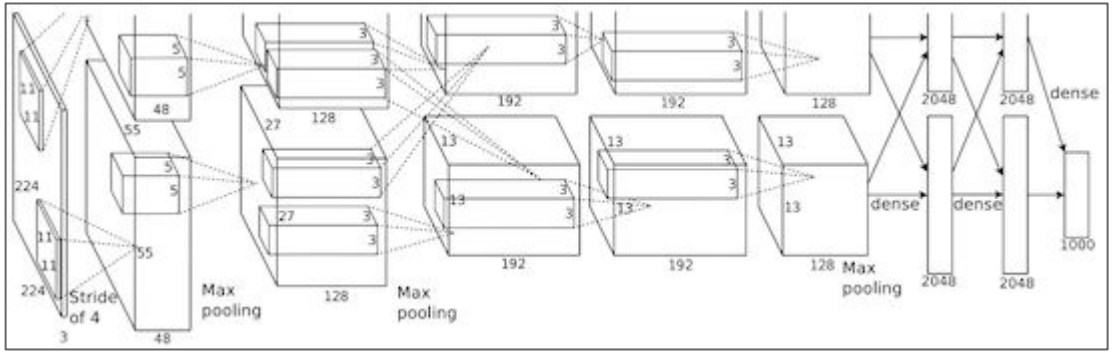
[Krizhevsky, Sutskever, Hinton, 2012]



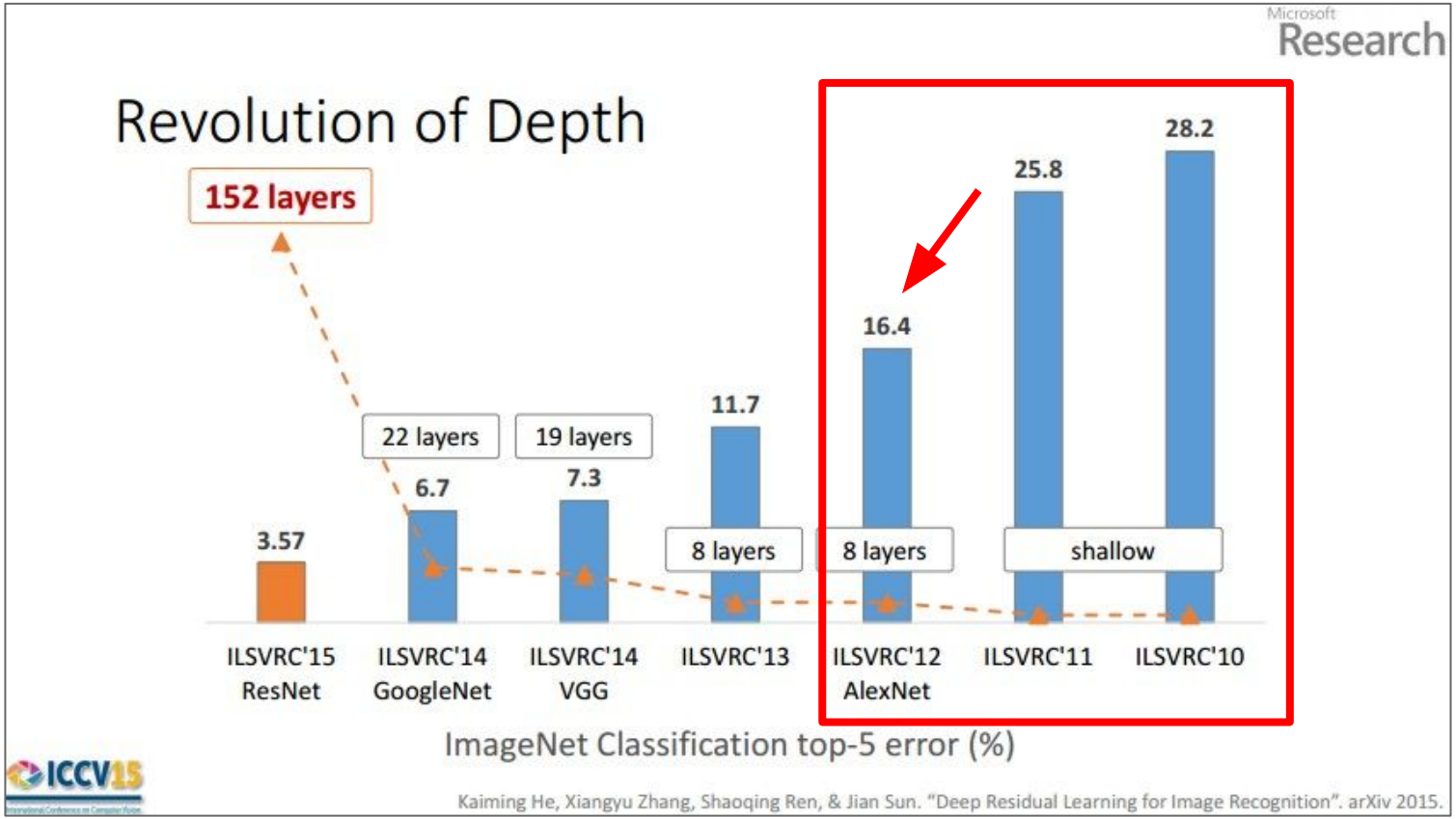
IMAGENET

Deng et al.
Russakovsky et al.

"AlexNet"



NVIDIA et al.



(slide from Kaiming He's recent presentation)

“What I learned from competing against a ConvNet on ImageNet” [(karpathy.github.io)](karpathy.github.io)

“What I learned from competing against a ConvNet on ImageNet” (karpathy.github.io)

TLDR: Human accuracy is **somewhere 2-5%.**
(depending on how much training or how little life you have)

vector describing
various image statistics

[224x224x3]

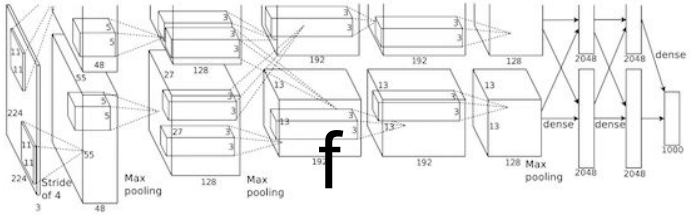
Feature Extraction

f

training

1000 numbers,
indicating class scores

[224x224x3]



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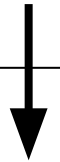


"Run the image through 20 layers of 3x3 convolutions and train the filters with SGD."*

* to the first order

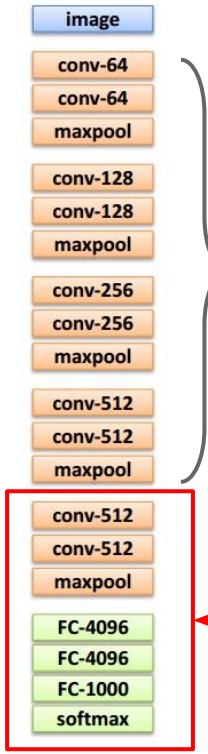
Transfer Learning

1. Train on Imagenet

2. Small dataset: **feature extractor**

Freeze these

Train this



3. Medium dataset: **finetuning**

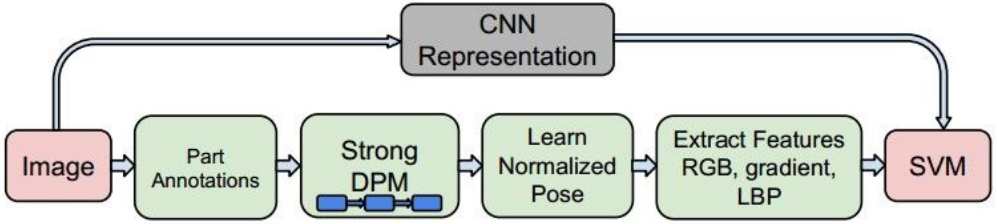
more data = retrain more of the network (or all of it)

Freeze these

Train this

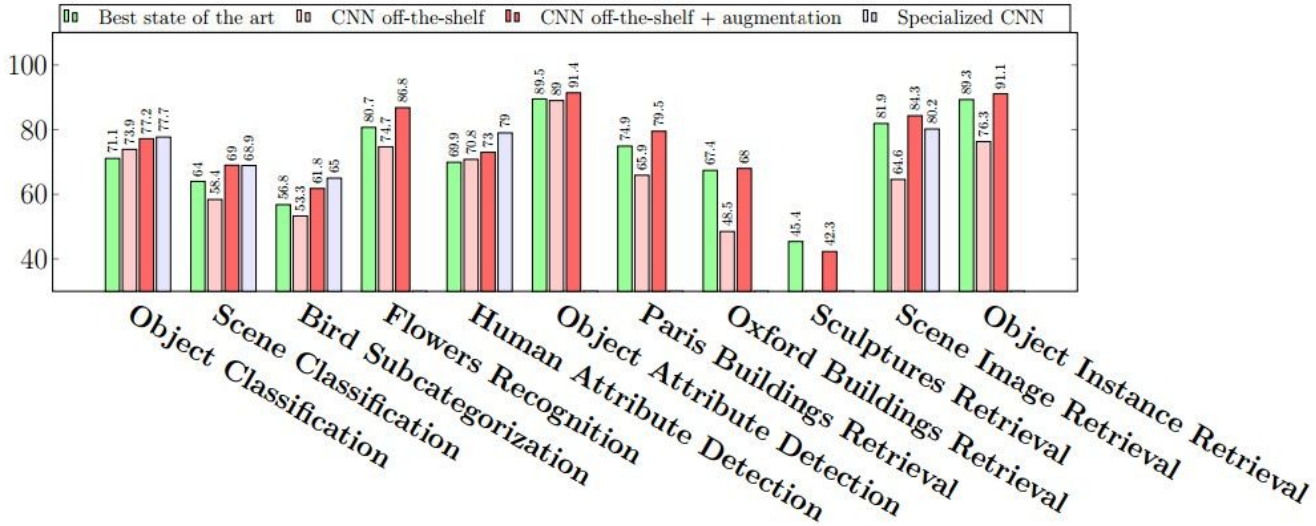
Transfer Learning

CNN Features off-the-shelf: an Astounding Baseline for Recognition [Razavian et al, 2014]



DeCAF: A Deep Convolutional Activation Feature for Generic Visual Recognition [Donahue, Jia*, et al., 2013]*

	$DeCAF_6$	$DeCAF_7$
LogReg	**40.94 ± 0.3**	40.84 ± 0.3
SVM	39.36 ± 0.3	40.66 ± 0.3
Xiao et al. (2010)	38.0	



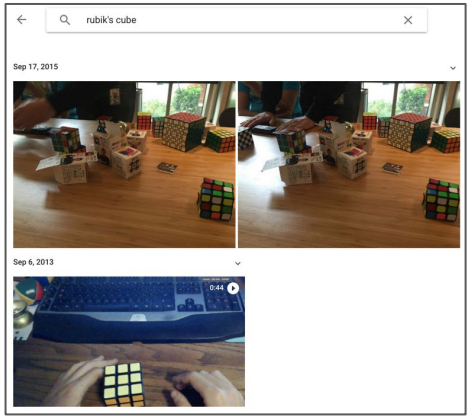
The power is easily accessible.

e.g. with keras.io

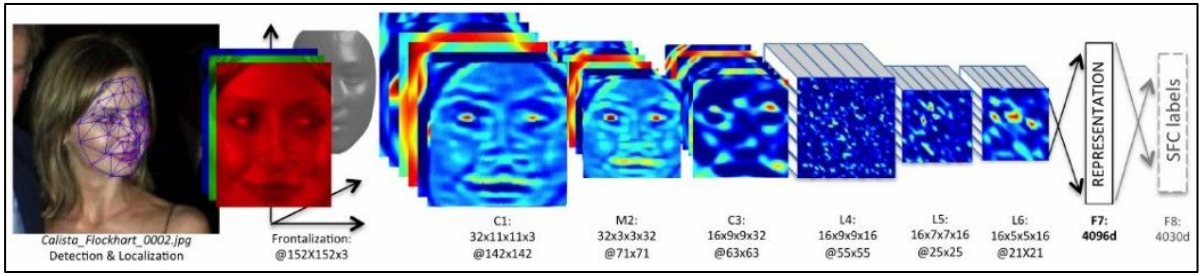
```
sudo pip install keras
```

```
from keras.applications.resnet50 import ResNet50
from keras.preprocessing import image
from keras.applications.resnet50 import preprocess_input, decode_predictions

model = ResNet50(weights='imagenet')

img_path = 'elephant.jpg'
img = image.load_img(img_path, target_size=(224, 224))
x = image.img_to_array(img)
x = np.expand_dims(x, axis=0)
x = preprocess_input(x)

preds = model.predict(x)
print('Predicted:', decode_predictions(preds))
# print: [[u'n02504458', u'African_elephant']]
```

ConvNets are everywhere…



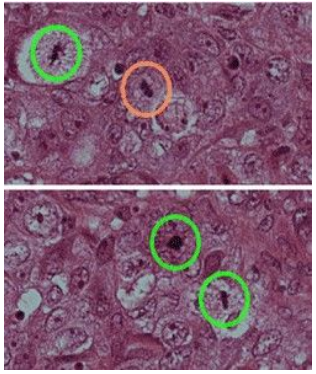
e.g. Google Photos search



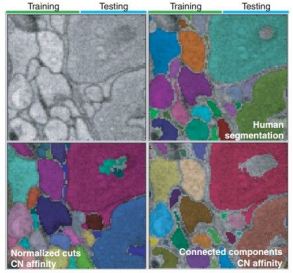
Face Verification, Taigman et al. 2014 (FAIR)

[Goodfellow et al. 2014]

Self-driving cars

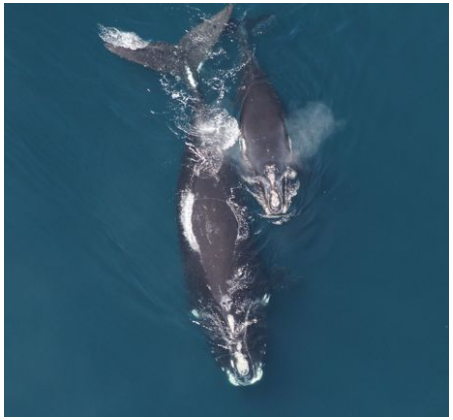


Ciresan et al. 2013



Turaga et al 2010

ConvNets are everywhere…



Whale recognition, Kaggle Challenge

Satellite image analysis
Mnih and Hinton, 2010

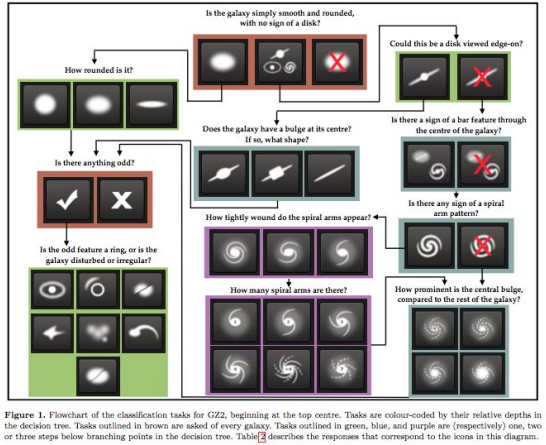
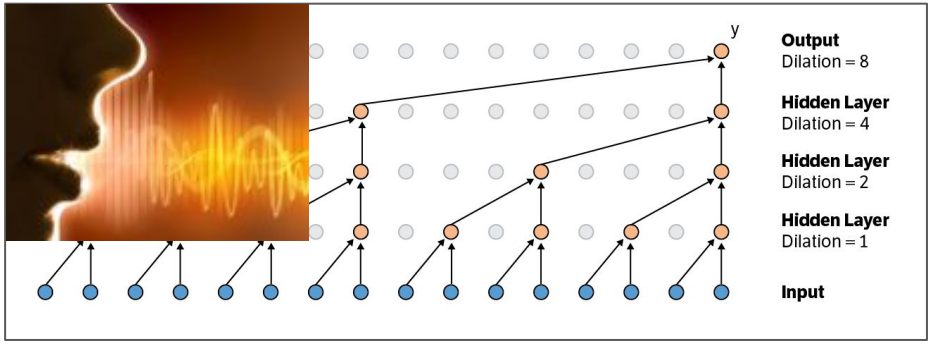


Figure 1. Flowchart of the classification tasks for GZ2, beginning at the top centre. Tasks are colour-coded by their relative depths in the decision tree. Tasks outlined in brown are asked of every galaxy. Tasks outlined in green, blue, and purple are (respectively) one, two or three steps below branching points in the decision tree. Table 2 describes the responses that correspond to the icons in this diagram.

Galaxy Challenge Dielman et al. 2015



WaveNet, van den Oord et al. 2016

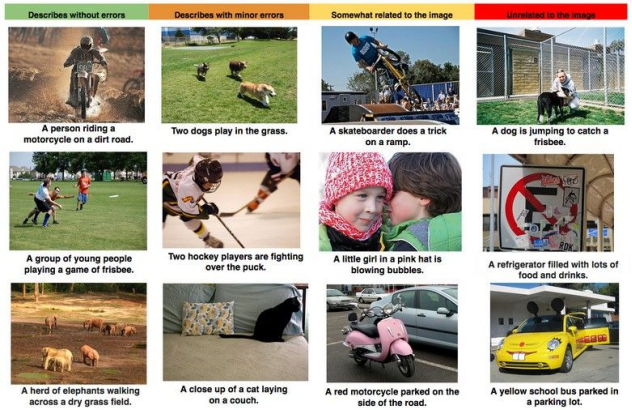
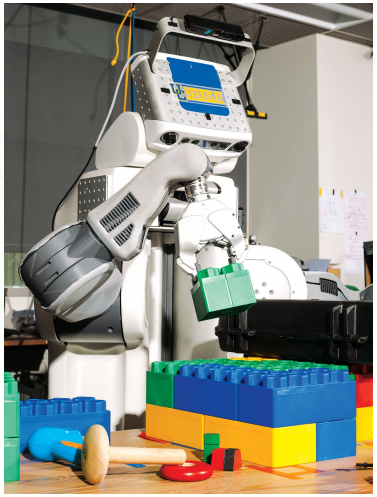
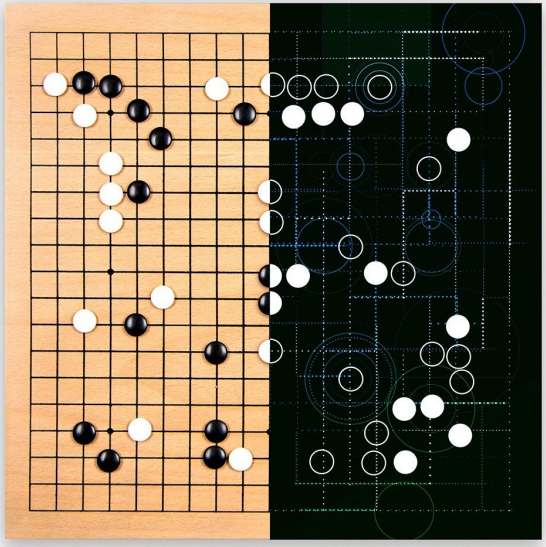


Image captioning, Vinyals et al. 2015

ConvNets are everywhere…

ATARI game playing, Mnih 2013





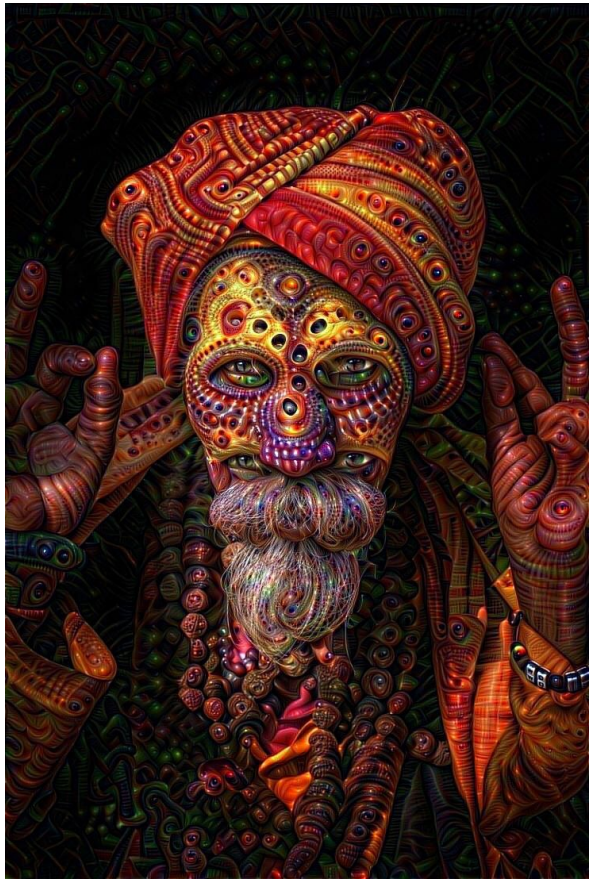
AlphaGo, Silver et al 2016

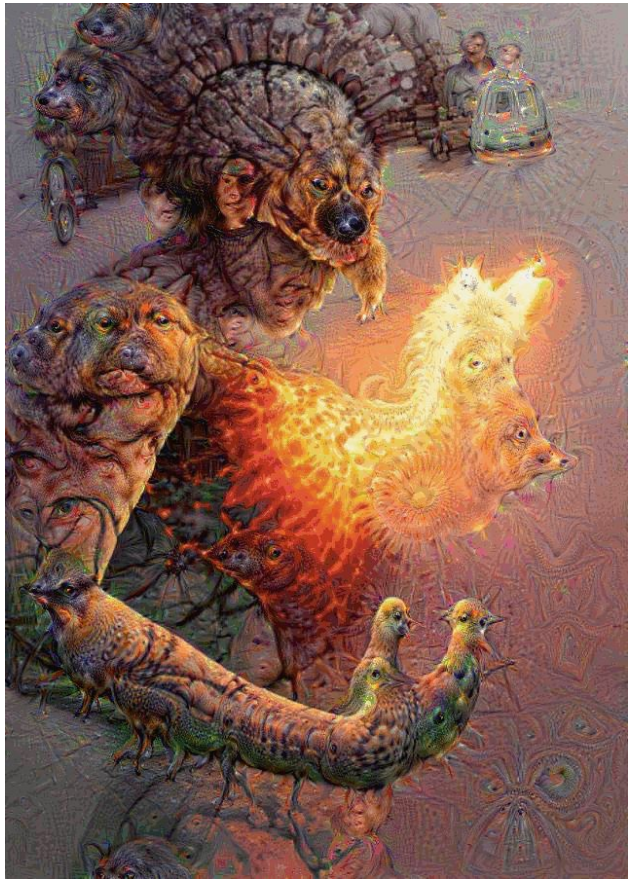
VizDoom

StarCraft

….

ConvNets are everywhere…

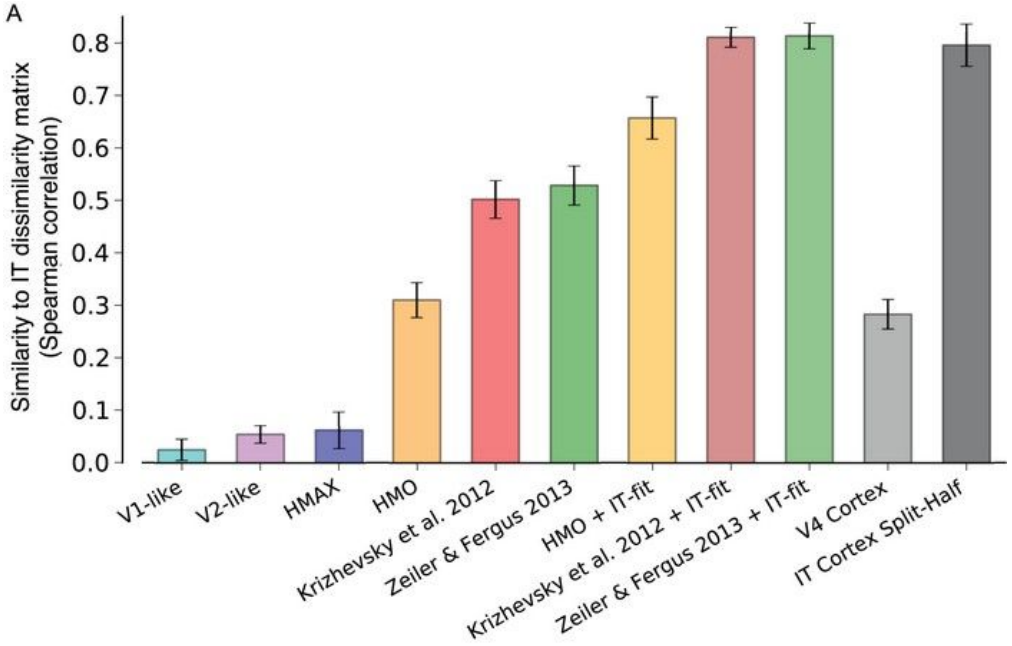


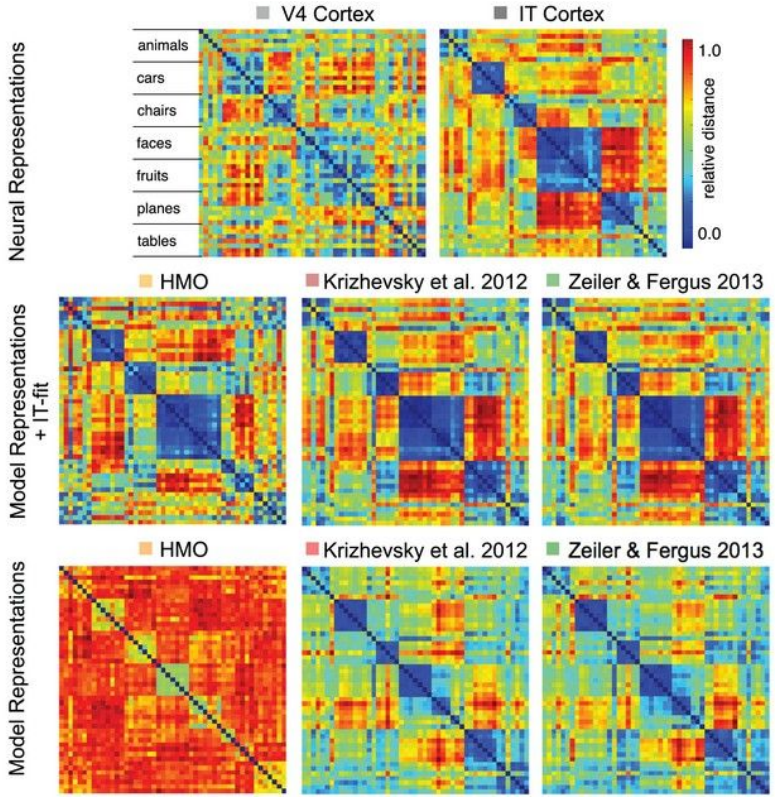


DeepDream *reddit.com/r/deepdream*

NeuralStyle, Gatys et al. 2015
deepart.io, Prisma, etc.

ConvNets ←→ Visual Cortex





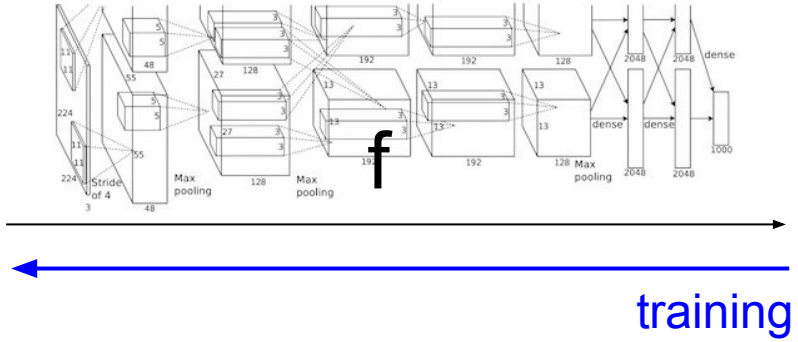
Deep Neural Networks Rival the Representation of Primate IT Cortex for Core Visual Object Recognition [Cadieu et al., 2014]

</history>
</context>

Convolutional Neural Networks

<explanation>

[224x224x3]

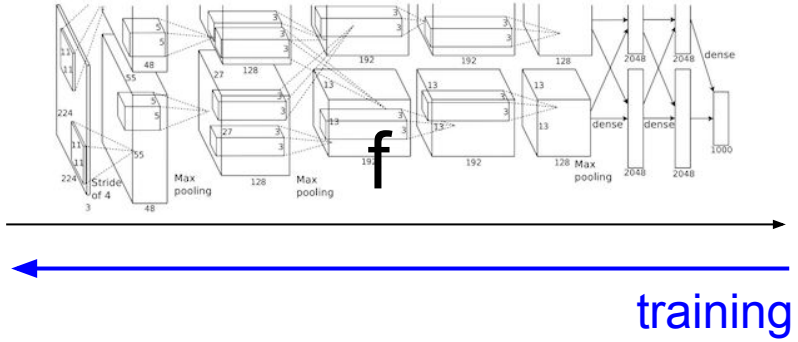


1000 numbers, indicating class scores

Only two basic operations are involved throughout:

1. Dot products w^Tx
2. Max operations max(.)

[224x224x3]



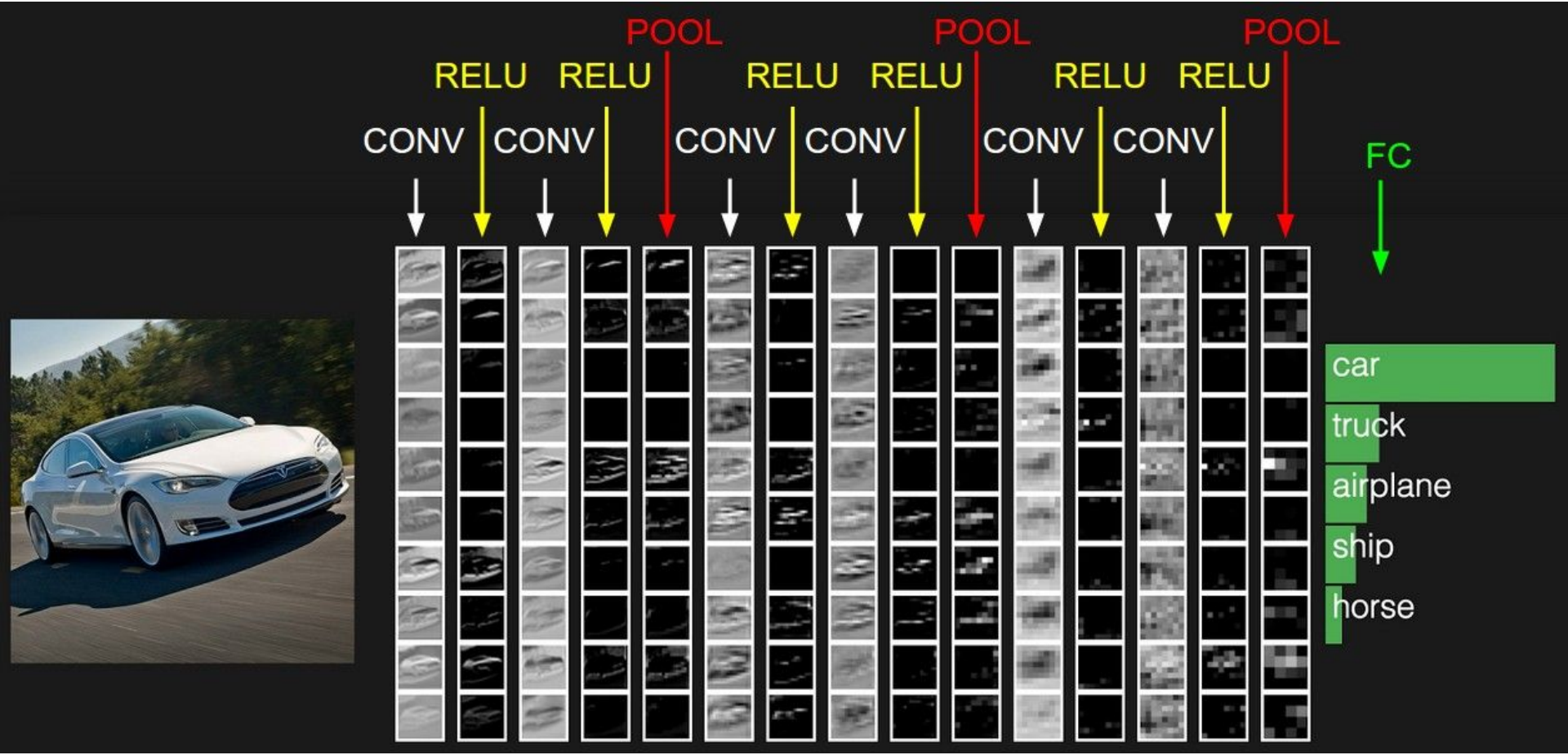
1000 numbers,
indicating class scores

Only two basic operations are involved throughout:

1. Dot products **w**^Tx
2. Max operations max(.)

parameters
(~10M of them)

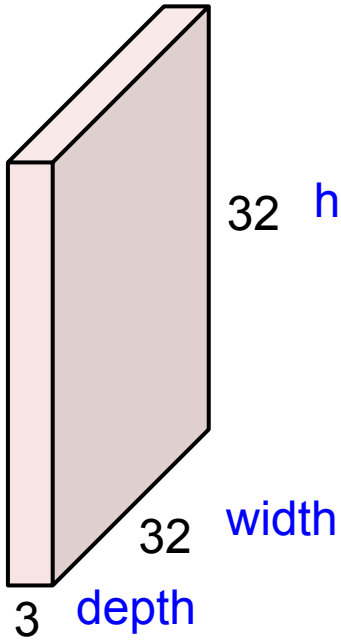
preview:



e.g. 200K numbers → e.g. 10 numbers

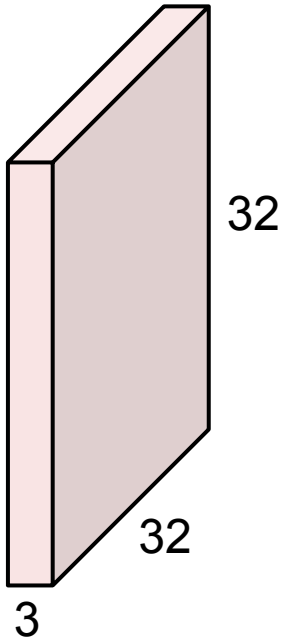
Convolution Layer

32x32x3 image

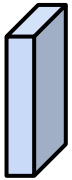


Convolution Layer

32x32x3 image



5x5x3 filter

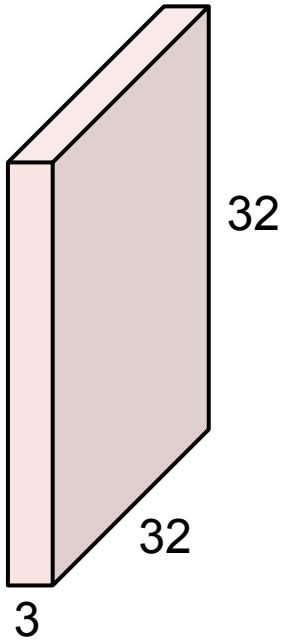


Convolve the filter with the image i.e. “slide over the image spatially, computing dot products”

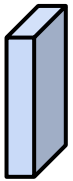
Convolution Layer

Filters always extend the full depth of the input volume

32x32x3 image

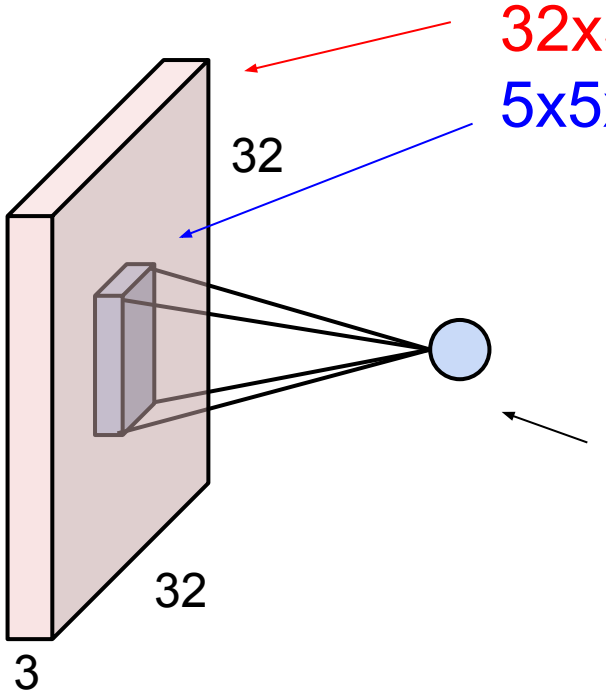


5x5x3 filter



Convolve the filter with the image i.e. “slide over the image spatially, computing dot products”

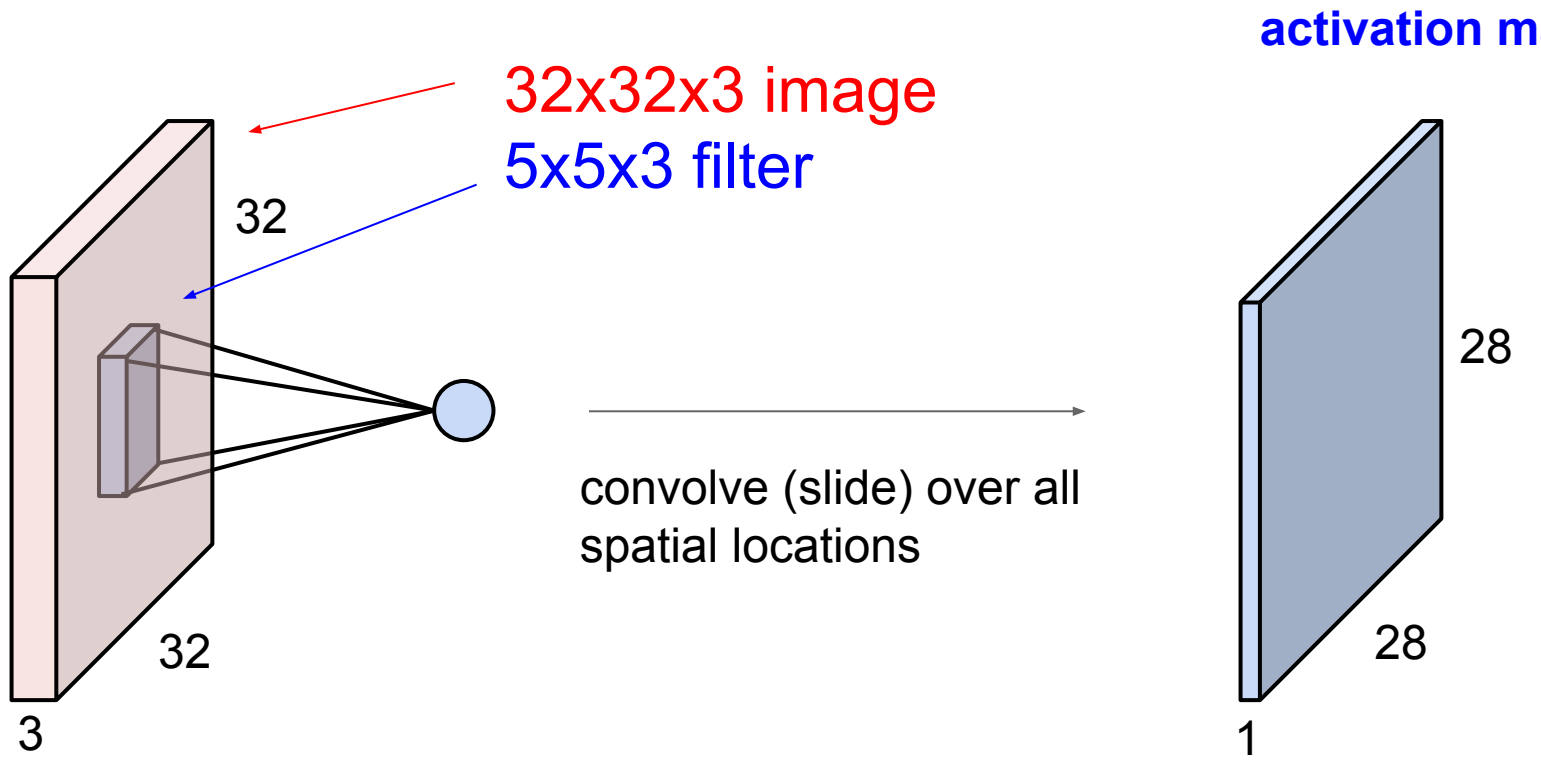
Convolution Layer



1 number:
the result of taking a dot product between the filter and a small 5x5x3 chunk of the image (i.e. 5*5*3 = 75-dimensional dot product + bias)

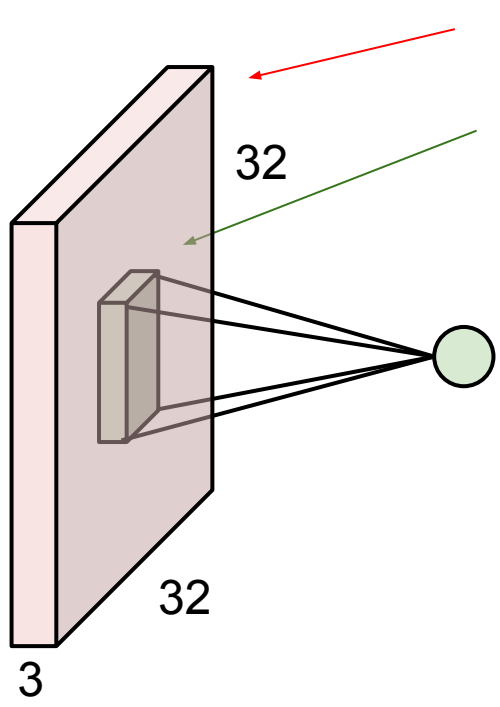
$$w^T x + b$$

Convolution Layer

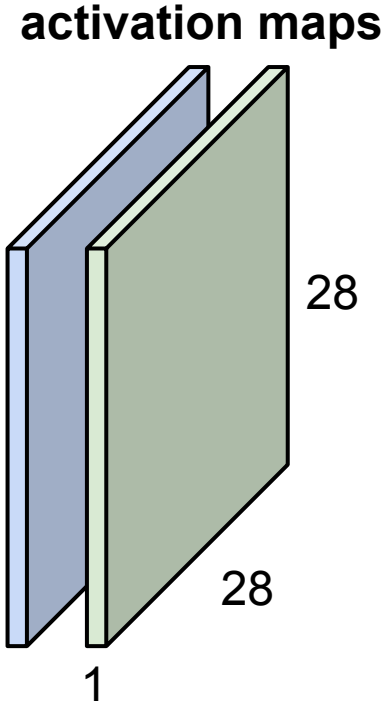


Convolution Layer

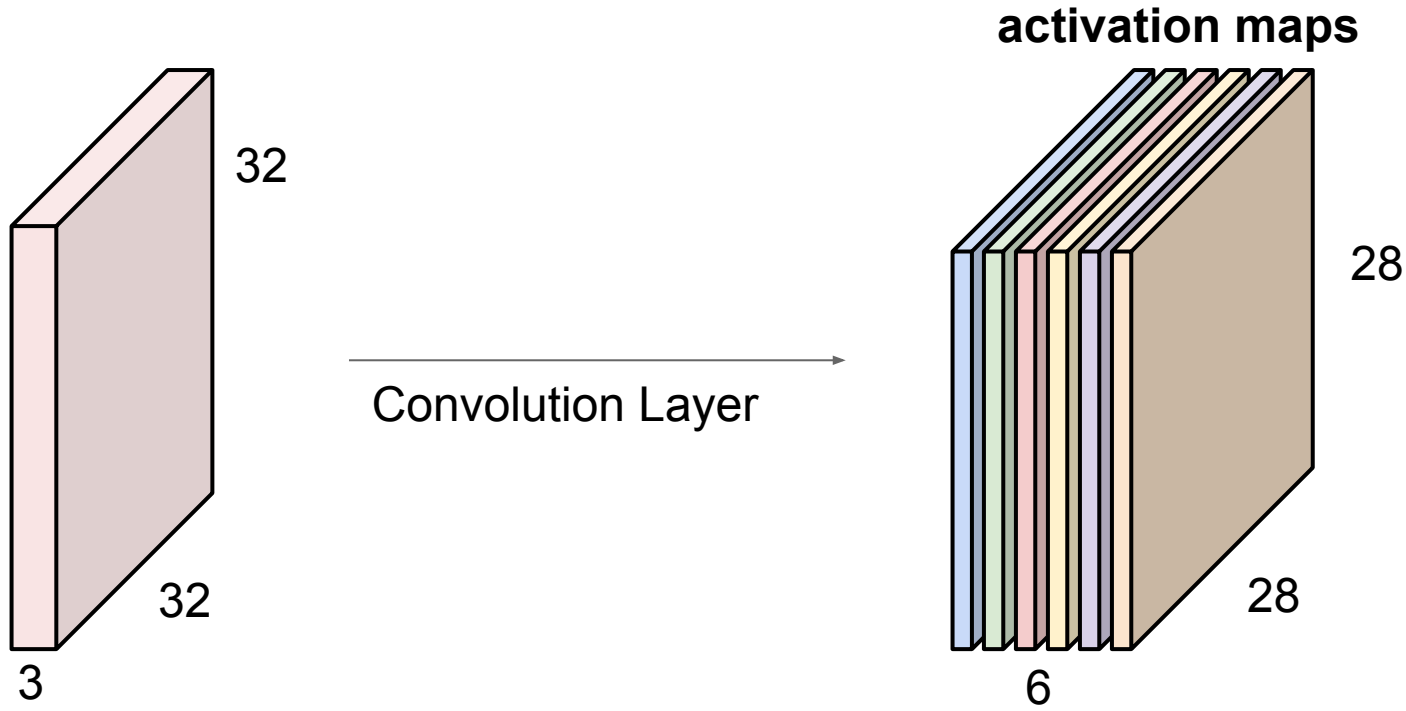
consider a second, green filter



convolve (slide) over all spatial locations

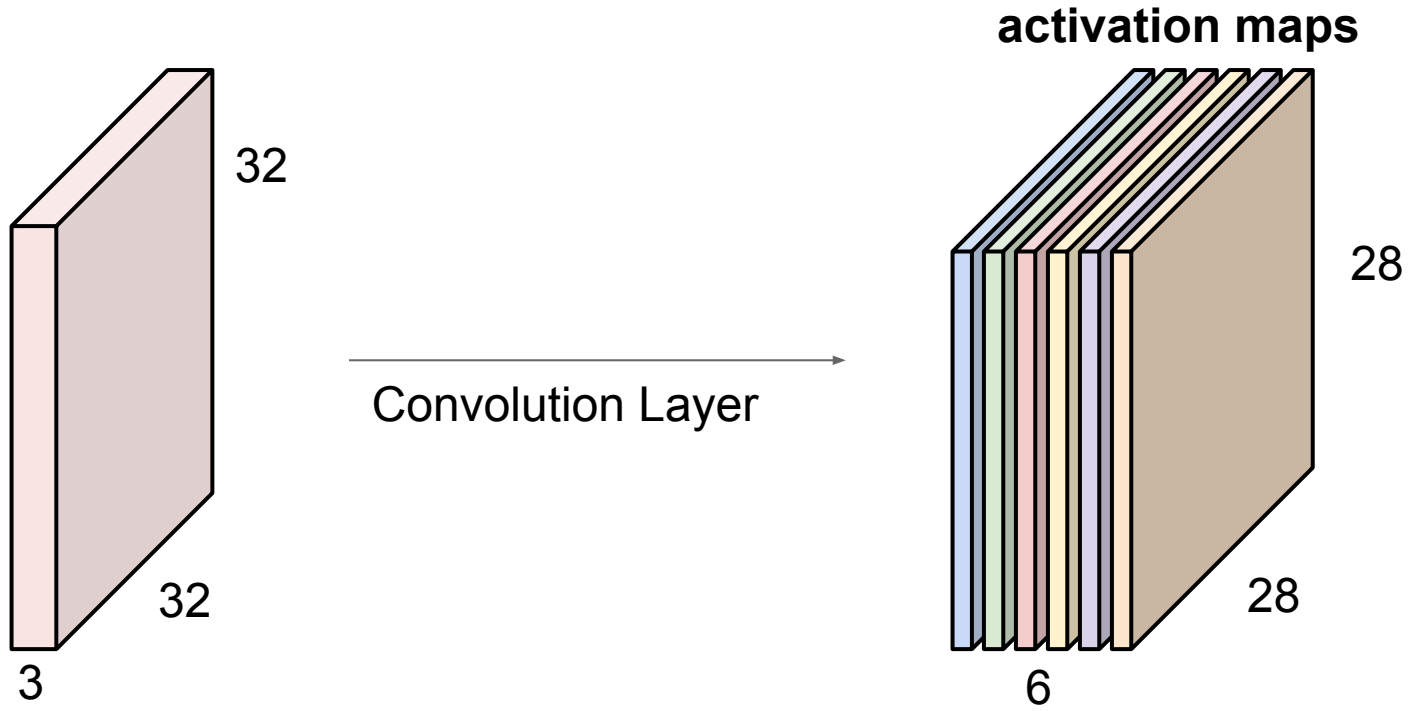


For example, if we had 6 5x5 filters, we'll get 6 separate activation maps:



We stack these up to get a "new image" of size 28x28x6!

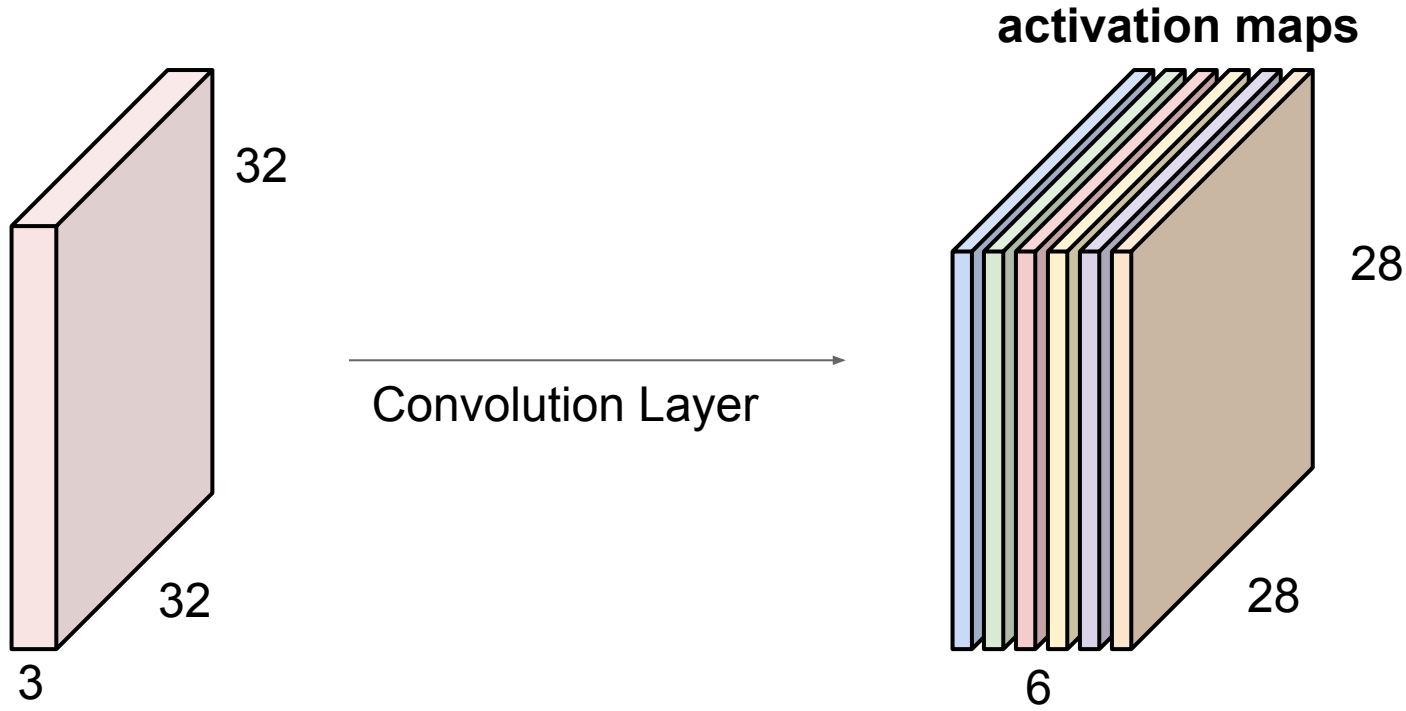
For example, if we had 6 5x5 filters, we'll get 6 separate activation maps:



We processed [32x32x3] volume into [28x28x6] volume.

Q: how many parameters would this be if we used a fully connected layer instead?

For example, if we had 6 5x5 filters, we'll get 6 separate activation maps:

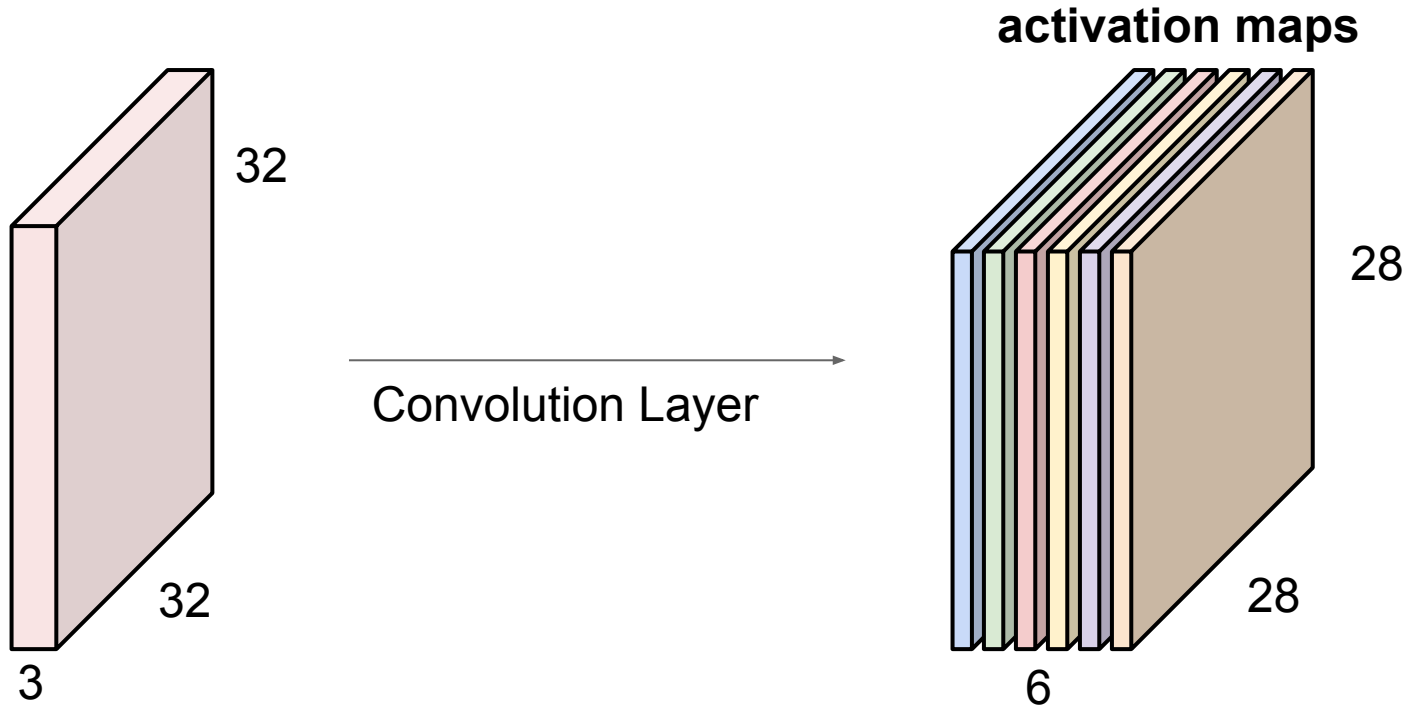


We processed [32x32x3] volume into [28x28x6] volume.

Q: how many parameters would this be if we used a fully connected layer instead?

A: (32*32*3)*(28*28*6) = **14.5M parameters**, **~14.5M multiplies**

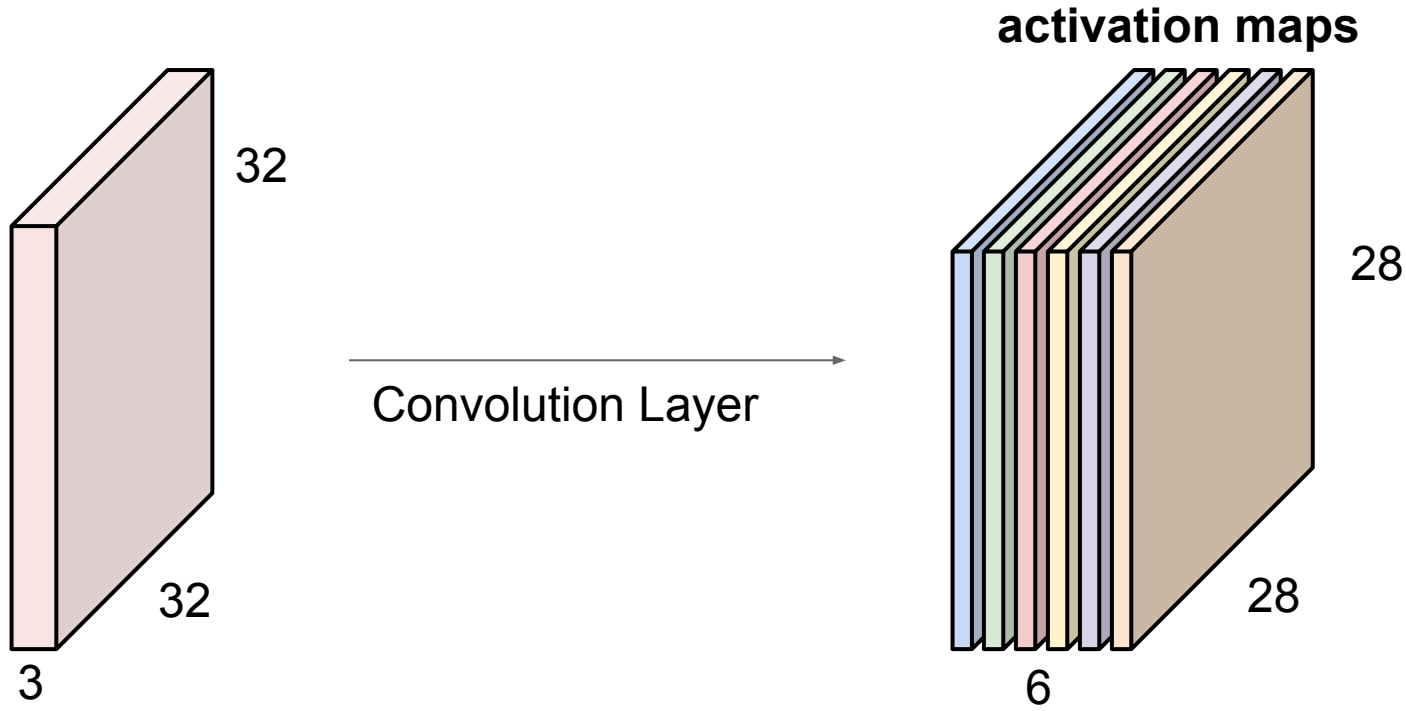
For example, if we had 6 5x5 filters, we'll get 6 separate activation maps:



We processed [32x32x3] volume into [28x28x6] volume.

Q: how many parameters are used instead?

For example, if we had 6 5x5 filters, we'll get 6 separate activation maps:

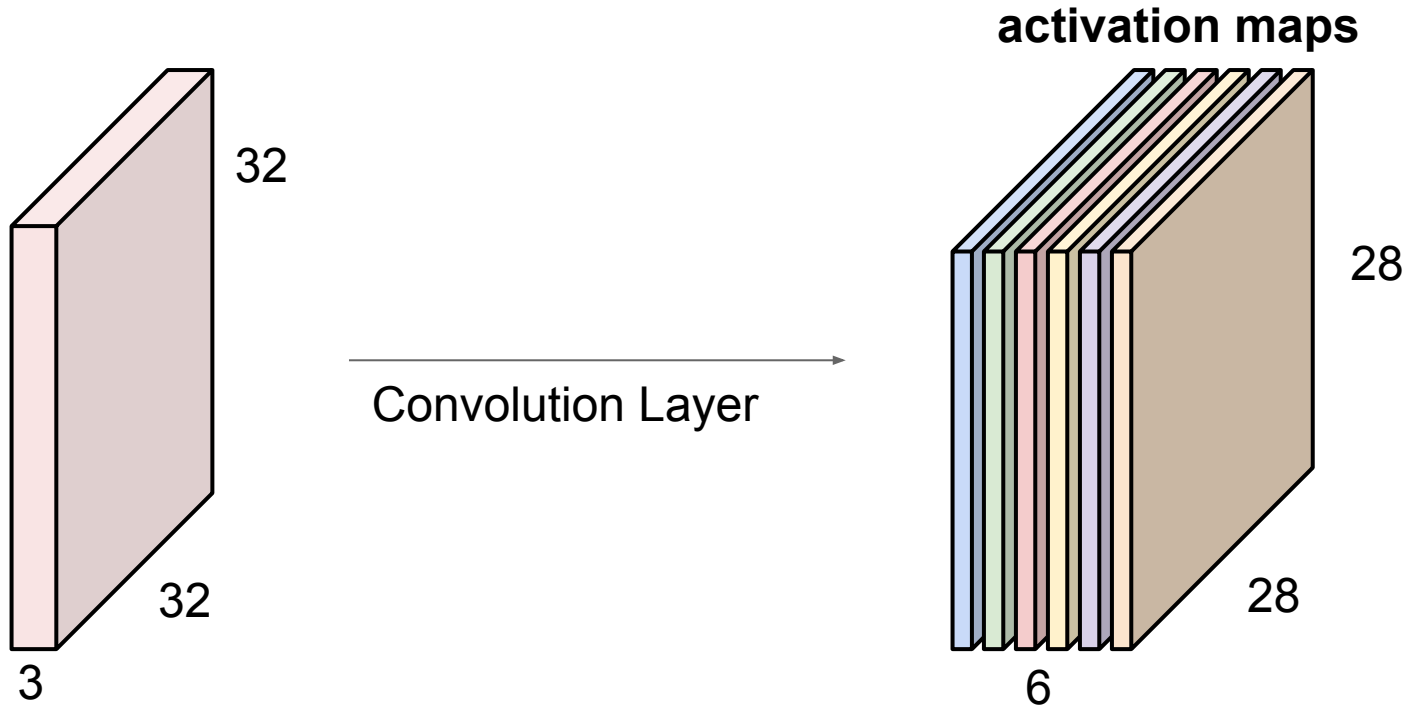


We processed [32x32x3] volume into [28x28x6] volume.

Q: how many parameters are used instead? --- And how many multiplies?

A: (5*5*3)*6 = **450 parameters**

For example, if we had 6 5x5 filters, we'll get 6 separate activation maps:



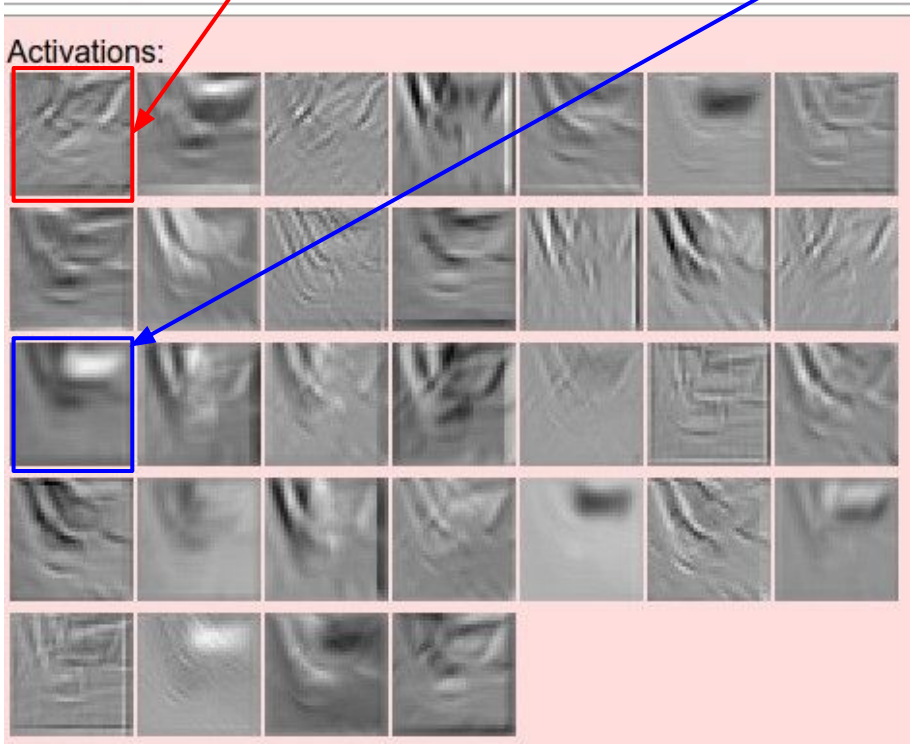
We processed [32x32x3] volume into [28x28x6] volume.

Q: how many parameters are used instead?

A: (5*5*3)*6 = **450 parameters**, (5*5*3)*(28*28*6) = **~350K multiplies**

one filter =>
one activation map

example 5x5 filters
(32 total)

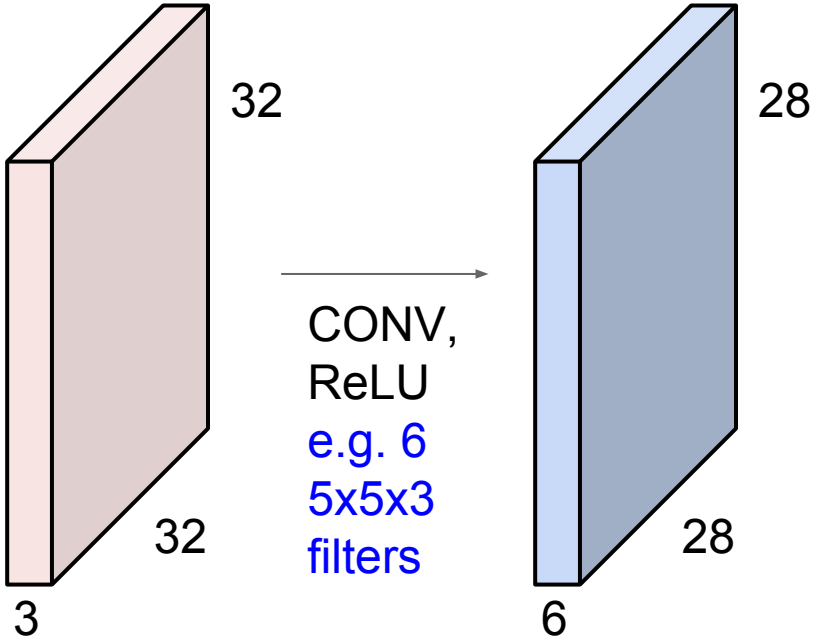


We call the layer convolutional because it is related to convolution of two signals:

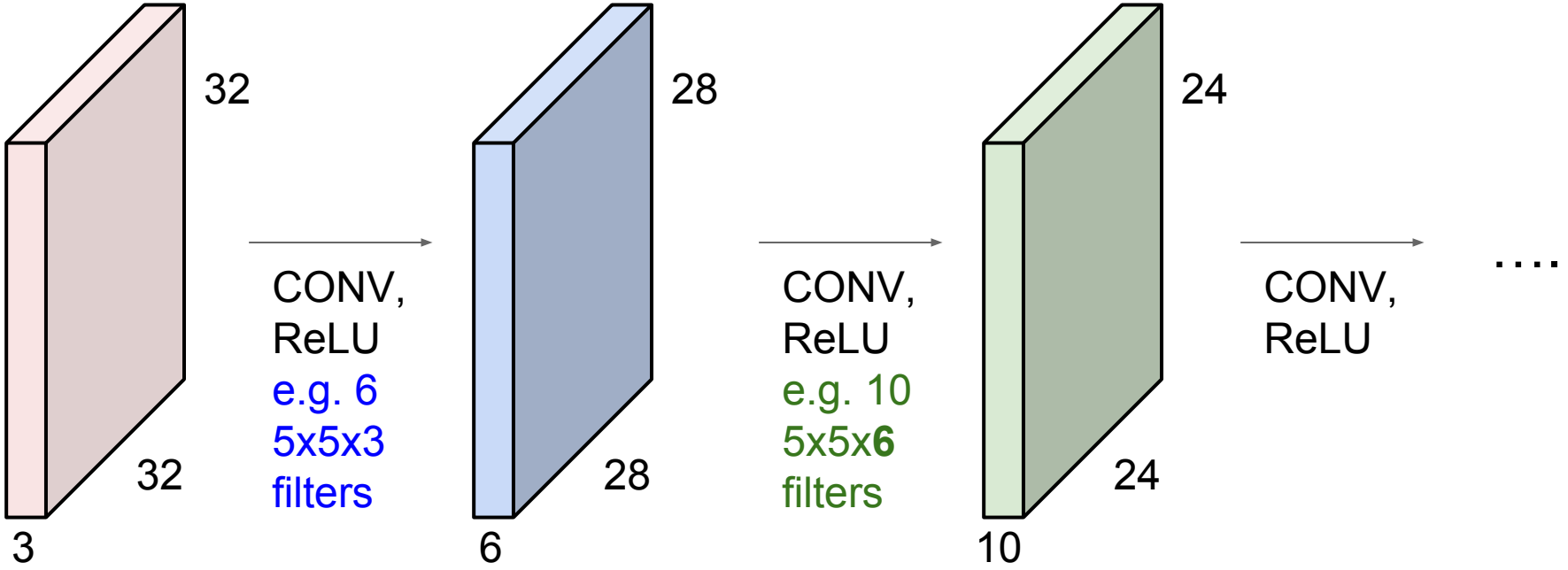
$$f[x,y] * g[x,y] = \sum_{n_1=-\infty}^{\infty} \sum_{n_2=-\infty}^{\infty} f[n_1,n_2] \cdot g[x-n_1, y-n_2]$$

elementwise multiplication and sum of a filter and the signal (image)

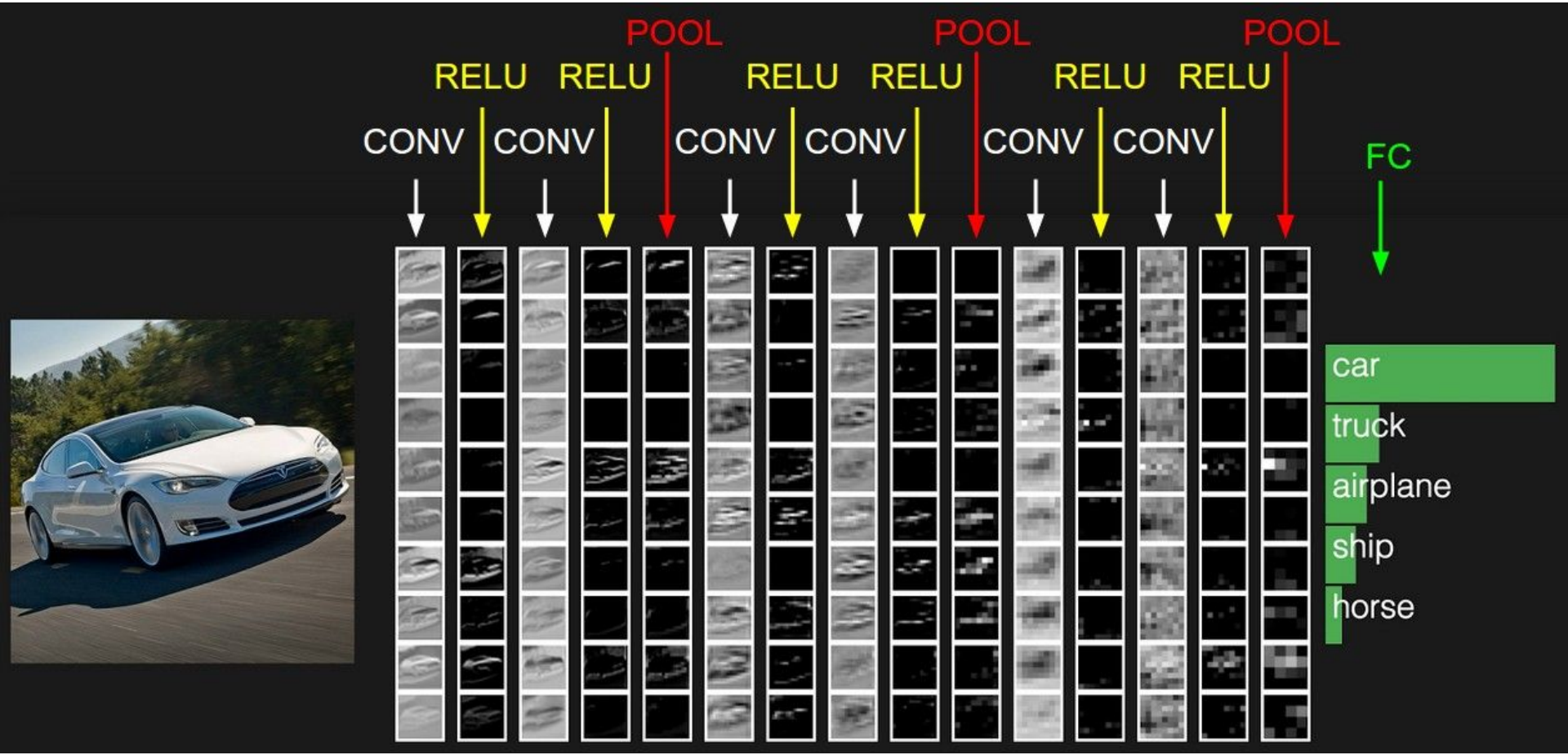
Preview: ConvNet is a sequence of Convolution Layers, interspersed with activation functions



Preview: ConvNet is a sequence of Convolutional Layers, interspersed with activation functions

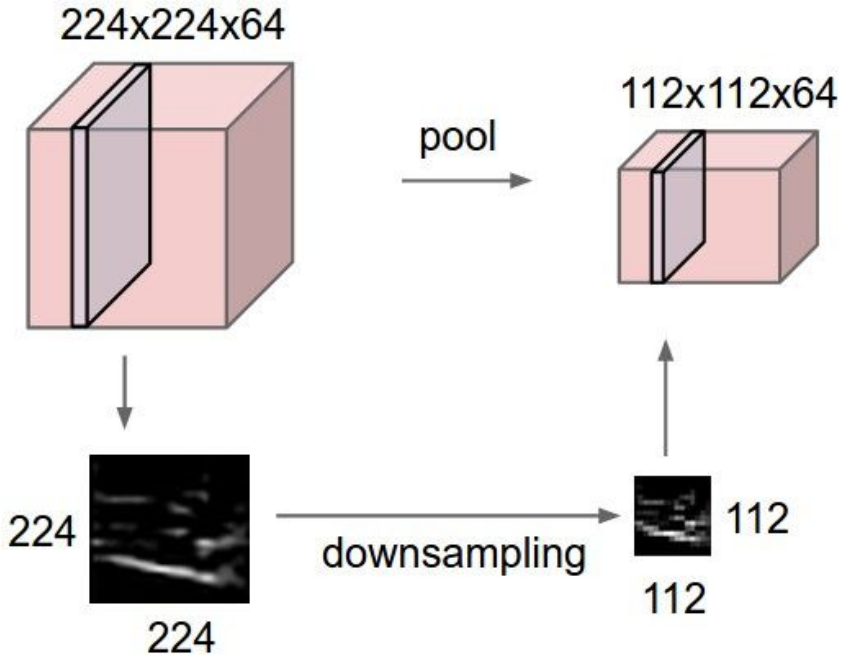


two more layers to go: POOL/FC

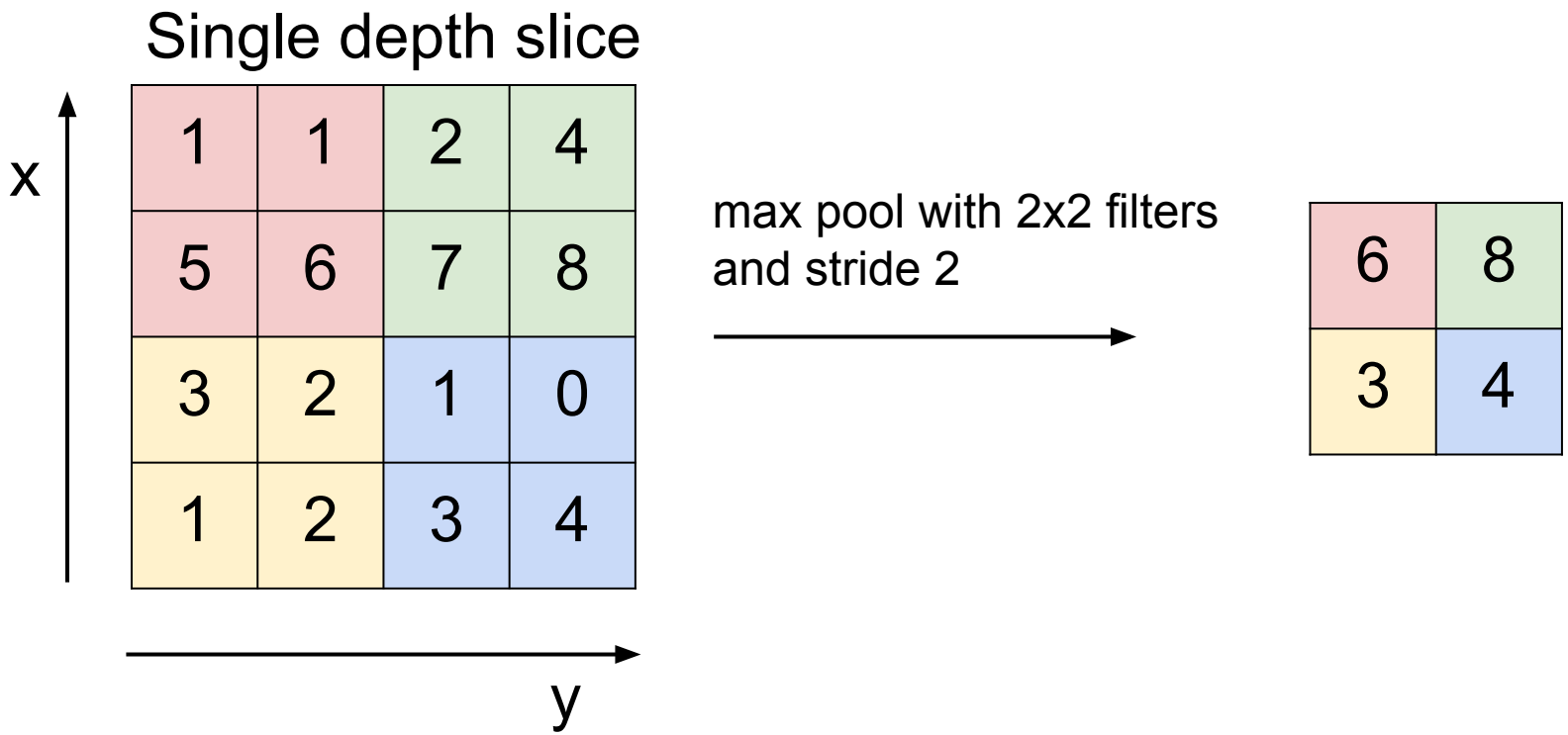


Pooling layer

- makes the representations smaller and more manageable
- operates over each activation map independently:

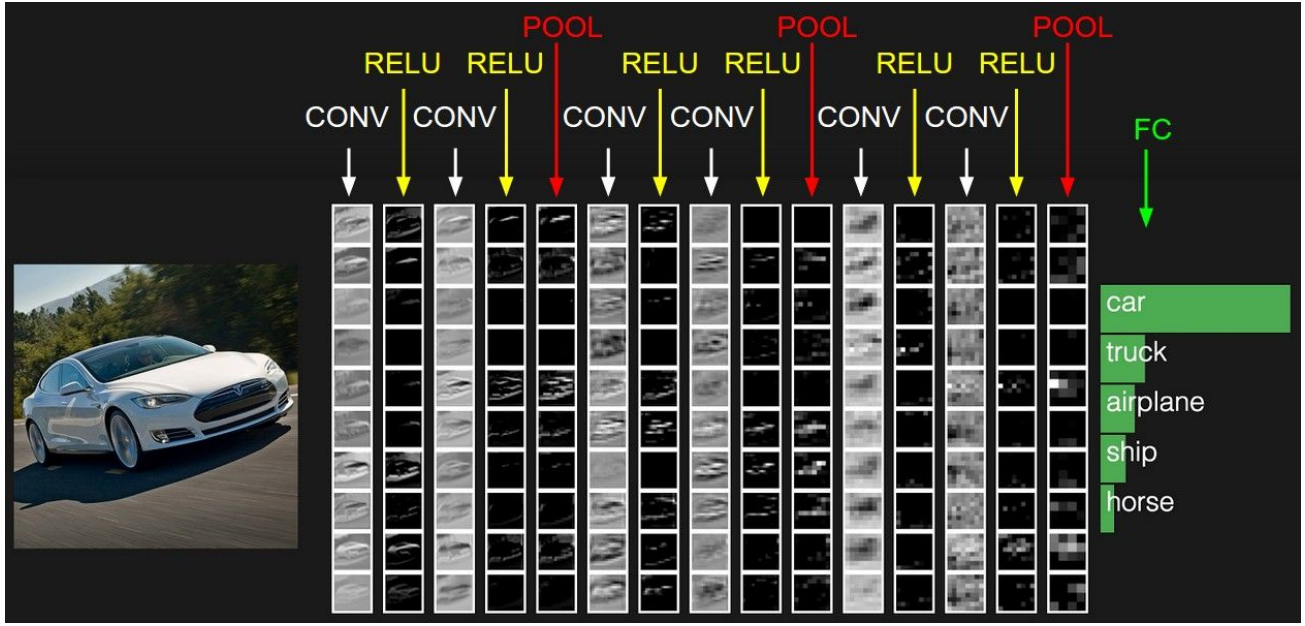


MAX POOLING


Single depth slice
x
y
1 1 2 4
5 6 7 8
3 2 1 0
1 2 3 4
max pool with 2x2 filters
and stride 2
6 8
3 4

Fully Connected Layer (FC layer)

- Contains neurons that connect to the entire input volume, as in ordinary Neural Networks



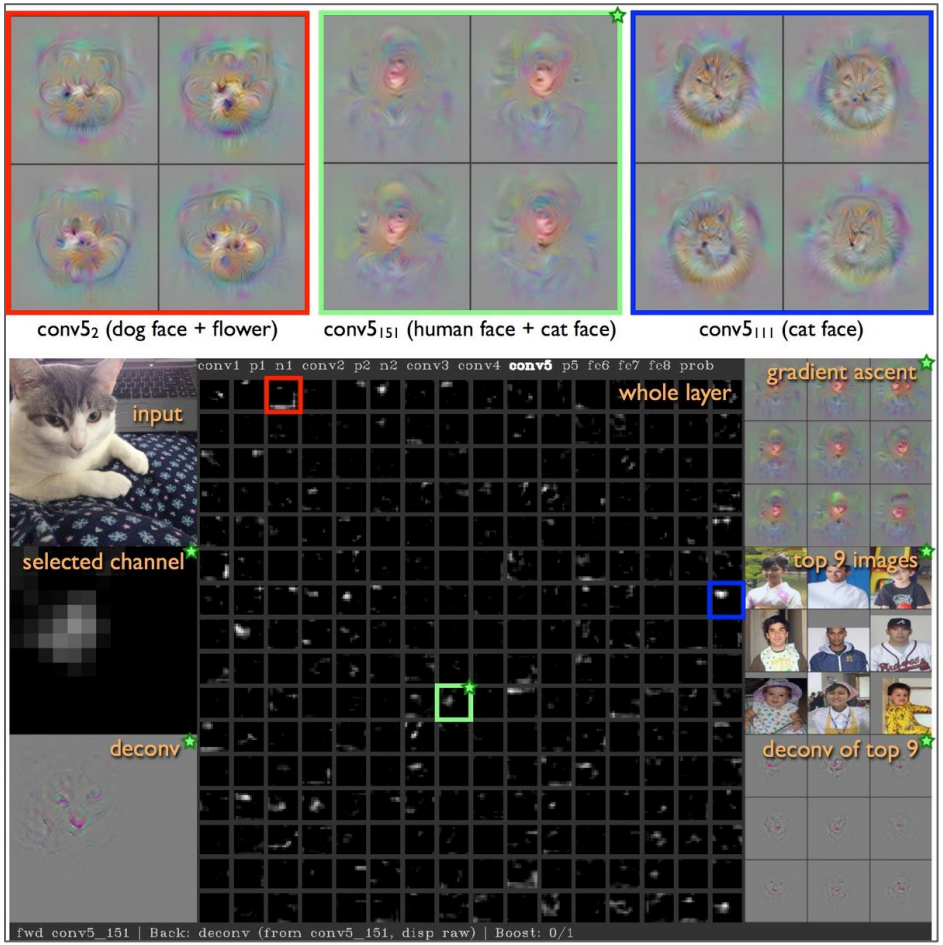
[ConvNetJS demo: training on CIFAR-10]

http://cs.stanford.edu/people/karpathy/convnetjs/demo/cifar10.html

Visualizing Activations

http://yosinski.com/deepvis

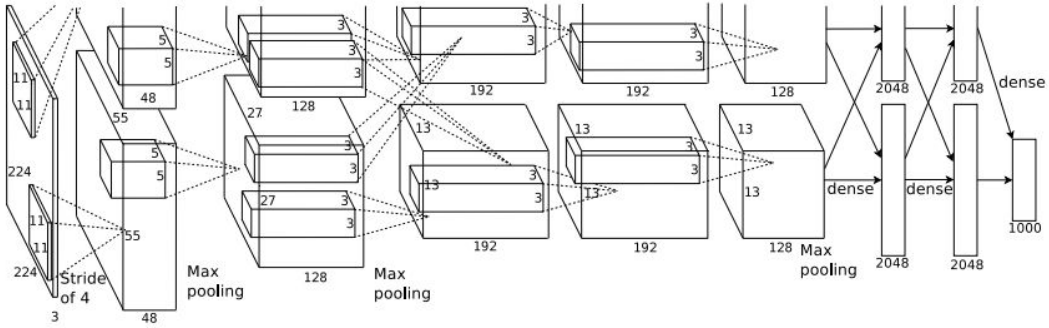
YouTube video
https://www.youtube.com/watch?v=AgkfIQ4IGaM
(4min)



Convolutional Neural Networks: Case Study

Case Study: AlexNet

[Krizhevsky et al. 2012]



Input: 227x227x3 images

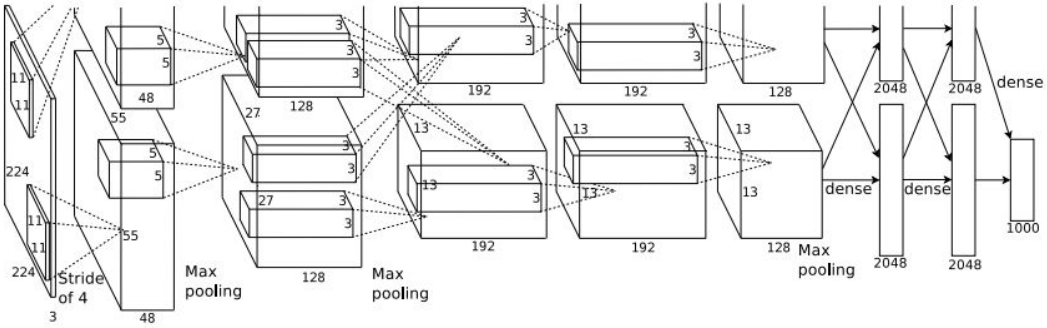
First layer (CONV1): 96 11x11 filters applied at stride 4

=>

Q: what is the output volume size? Hint: (227-11)/4+1 = 55

Case Study: AlexNet

[Krizhevsky et al. 2012]



Input: 227x227x3 images

First layer (CONV1): 96 11x11 filters applied at stride 4
=>
Output volume **[55x55x96]**

Q: What is the total number of parameters in this layer?

Case Study: AlexNet

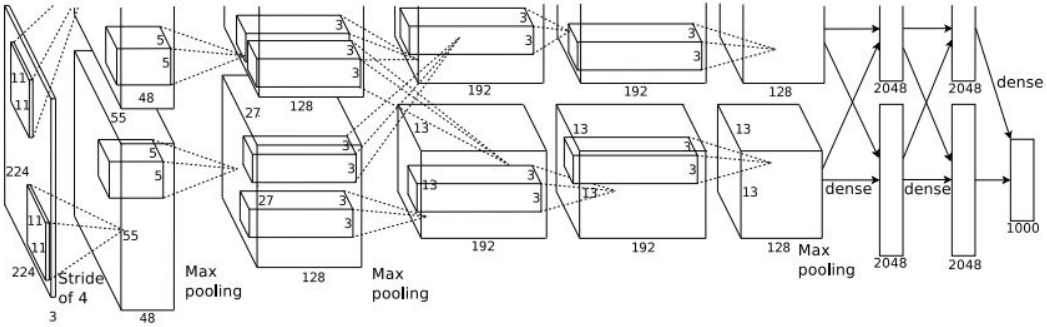
[Krizhevsky et al. 2012]

Input: 227x227x3 images

First layer (CONV1): 96 11x11 filters applied at stride 4
=>
Output volume **[55x55x96]**
Parameters: (11*11*3)*96 = **35K**

Case Study: AlexNet

[Krizhevsky et al. 2012]



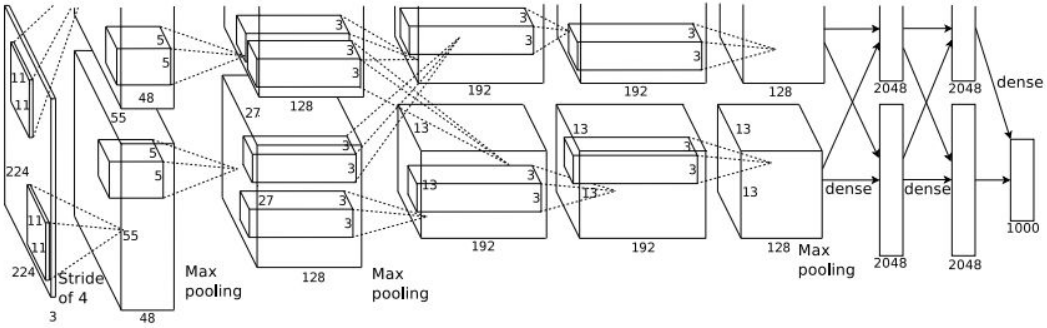
Input: 227x227x3 images
After CONV1: 55x55x96

Second layer (POOL1): 3x3 filters applied at stride 2

Q: what is the output volume size? Hint: (55-3)/2+1 = 27

Case Study: AlexNet

[Krizhevsky et al. 2012]



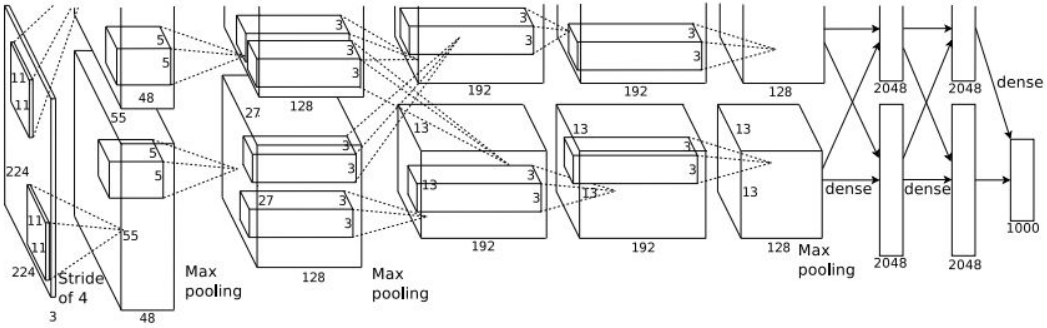
Input: 227x227x3 images
After CONV1: 55x55x96

Second layer (POOL1): 3x3 filters applied at stride 2
Output volume: 27x27x96

Q: what is the number of parameters in this layer?

Case Study: AlexNet

[Krizhevsky et al. 2012]

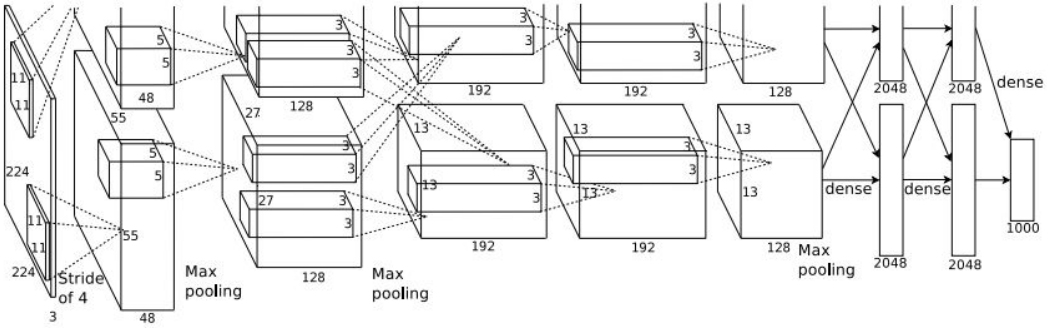


Input: 227x227x3 images
After CONV1: 55x55x96

Second layer (POOL1): 3x3 filters applied at stride 2
Output volume: 27x27x96
Parameters: 0!

Case Study: AlexNet

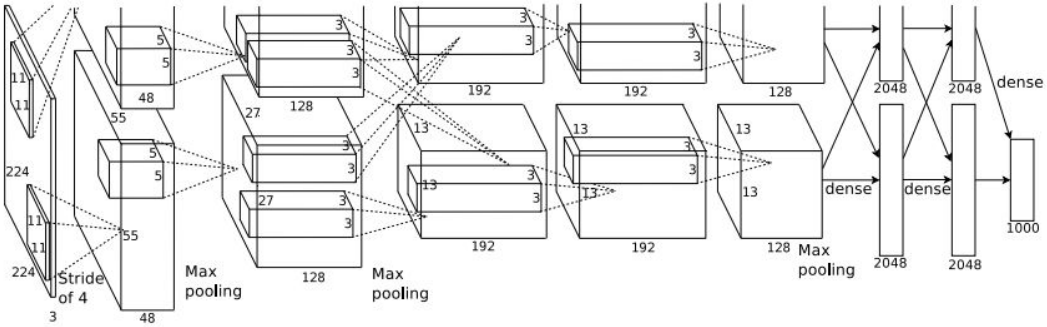
[Krizhevsky et al. 2012]



Input: 227x227x3 images
After CONV1: 55x55x96
After POOL1: 27x27x96
...

Case Study: AlexNet

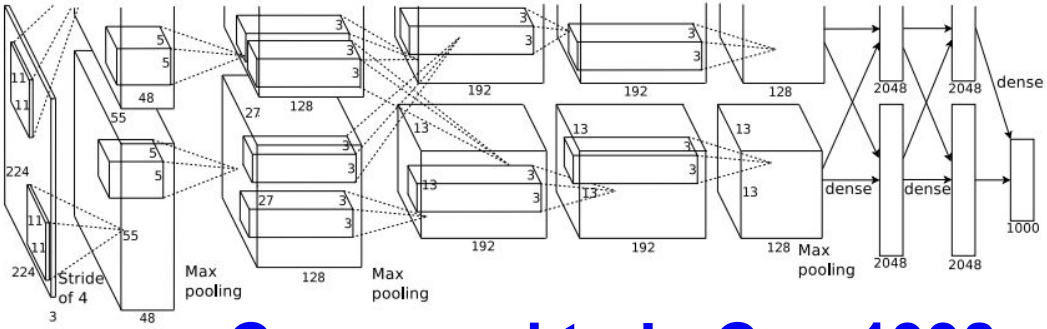
[Krizhevsky et al. 2012]



Full (simplified) AlexNet architecture:
[227x227x3] INPUT
[55x55x96] CONV1: 96 11x11 filters at stride 4, pad 0
[27x27x96] MAX POOL1: 3x3 filters at stride 2
[27x27x96] NORM1: Normalization layer
[27x27x256] CONV2: 256 5x5 filters at stride 1, pad 2
[13x13x256] MAX POOL2: 3x3 filters at stride 2
[13x13x256] NORM2: Normalization layer
[13x13x384] CONV3: 384 3x3 filters at stride 1, pad 1
[13x13x384] CONV4: 384 3x3 filters at stride 1, pad 1
[13x13x256] CONV5: 256 3x3 filters at stride 1, pad 1
[6x6x256] MAX POOL3: 3x3 filters at stride 2
[4096] FC6: 4096 neurons
[4096] FC7: 4096 neurons
[1000] FC8: 1000 neurons (class scores)

Case Study: AlexNet

[Krizhevsky et al. 2012]



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[6x6x256] MAX POOL3: 3x3 filters at stride 2
[4096] FC6: 4096 neurons
[4096] FC7: 4096 neurons
[1000] FC8: 1000 neurons (class scores)

Compared to LeCun 1998:

1 DATA:
- More data: 10^6 vs. 10^3

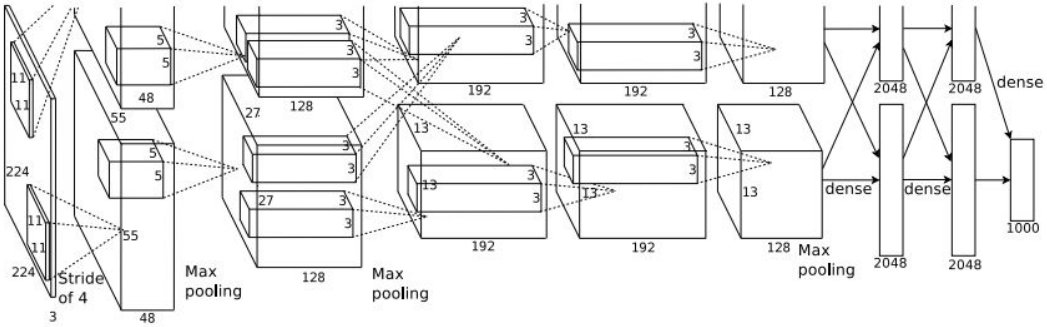
2 COMPUTE:
- GPU (~20x speedup)

3 ALGORITHM:
- Deeper: More layers (8 weight layers)
- Fancy regularization (dropout)
- Fancy non-linearity (ReLU)

4 INFRASTRUCTURE:
- CUDA

Case Study: AlexNet

[Krizhevsky et al. 2012]



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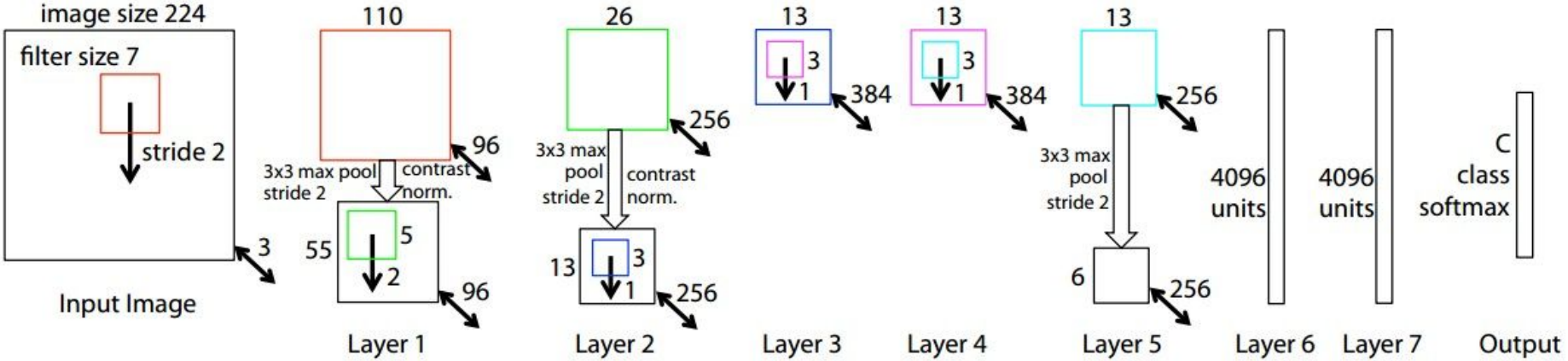
[6x6x256] MAX POOL3: 3x3 filters at stride 2
[4096] FC6: 4096 neurons
[4096] FC7: 4096 neurons
[1000] FC8: 1000 neurons (class scores)

Details/Retrospectives:
- first use of ReLU
- used Norm layers (not common anymore)
- heavy data augmentation
- dropout 0.5
- batch size 128
- SGD Momentum 0.9
- Learning rate 1e-2, reduced by 10 manually when val accuracy plateaus
- L2 weight decay 5e-4
- 7 CNN ensemble: 18.2% -> 15.4%

Case Study: ZFNet *[Zeiler and Fergus, 2013]*



AlexNet but:
CONV1: change from (11x11 stride 4) to (7x7 stride 2)
CONV3,4,5: instead of 384, 384, 256 filters use 512, 1024, 512

ImageNet top 5 error: 15.4% -> 14.8%

Case Study: VGGNet

[Simonyan and Zisserman, 2014]

Only 3x3 CONV stride 1, pad 1
and 2x2 MAX POOL stride 2

best model

11.2% top 5 error in ILSVRC 2013
->
7.3% top 5 error

ConvNet Configuration					
A	A-LRN	B	C	D	E
11 weight layers	11 weight layers	13 weight layers	16 weight layers	16 weight layers	19 weight layers
input (224 × 224 RGB image)					
conv3-64	conv3-64 **LRN**	conv3-64 **conv3-64**	conv3-64 conv3-64	conv3-64 conv3-64	conv3-64 conv3-64
maxpool					
conv3-128	conv3-128	conv3-128 **conv3-128**	conv3-128 conv3-128	conv3-128 conv3-128	conv3-128 conv3-128
maxpool					
conv3-256 conv3-256	conv3-256 conv3-256	conv3-256 conv3-256	conv3-256 **conv1-256**	conv3-256 conv3-256 **conv3-256**	conv3-256 conv3-256 conv3-256 **conv3-256**
maxpool					
conv3-512 conv3-512	conv3-512 conv3-512	conv3-512 conv3-512	conv3-512 conv3-512 **conv1-512**	conv3-512 conv3-512 **conv3-512**	conv3-512 conv3-512 conv3-512 **conv3-512**
maxpool					
conv3-512 conv3-512	conv3-512 conv3-512	conv3-512 conv3-512	conv3-512 conv3-512 **conv1-512**	conv3-512 conv3-512 **conv3-512**	conv3-512 conv3-512 conv3-512 **conv3-512**
maxpool					
FC-4096					
FC-4096					
FC-1000					
soft-max					

Table 2: **Number of parameters** (in millions).

Network	A,A-LRN	B	C	D	E
Number of parameters	133	133	134	138	144

(not counting biases)

INPUT: [224x224x3] memory: 224*224*3=150K params: 0
CONV3-64: [224x224x64] memory: 224*224*64=3.2M params: (3*3*3)*64 = 1,728
CONV3-64: [224x224x64] memory: 224*224*64=3.2M params: (3*3*64)*64 = 36,864
POOL2: [112x112x64] memory: 112*112*64=800K params: 0
CONV3-128: [112x112x128] memory: 112*112*128=1.6M params: (3*3*64)*128 = 73,728
CONV3-128: [112x112x128] memory: 112*112*128=1.6M params: (3*3*128)*128 = 147,456
POOL2: [56x56x128] memory: 56*56*128=400K params: 0
CONV3-256: [56x56x256] memory: 56*56*256=800K params: (3*3*128)*256 = 294,912
CONV3-256: [56x56x256] memory: 56*56*256=800K params: (3*3*256)*256 = 589,824
CONV3-256: [56x56x256] memory: 56*56*256=800K params: (3*3*256)*256 = 589,824
POOL2: [28x28x256] memory: 28*28*256=200K params: 0
CONV3-512: [28x28x512] memory: 28*28*512=400K params: (3*3*256)*512 = 1,179,648
CONV3-512: [28x28x512] memory: 28*28*512=400K params: (3*3*512)*512 = 2,359,296
CONV3-512: [28x28x512] memory: 28*28*512=400K params: (3*3*512)*512 = 2,359,296
POOL2: [14x14x512] memory: 14*14*512=100K params: 0
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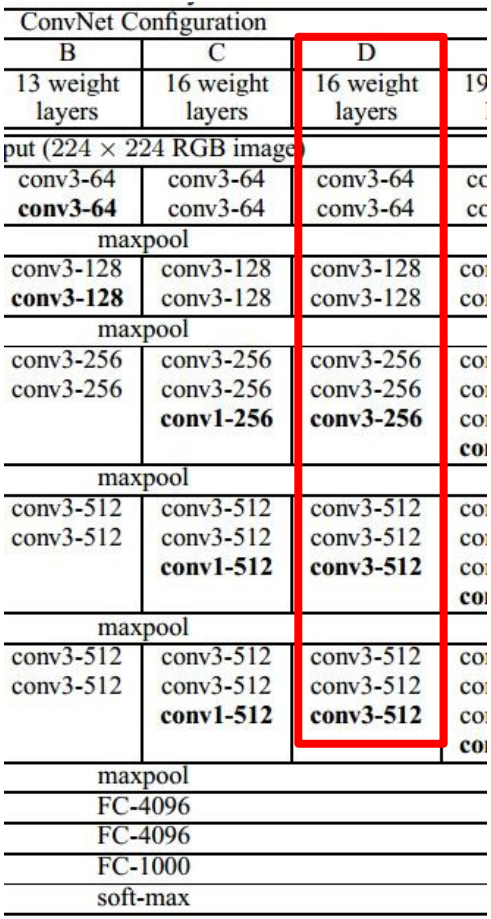
CONV3-512: [14x14x512] memory: 14*14*512=100K params: (3*3*512)*512 = 2,359,296
POOL2: [7x7x512] memory: 7*7*512=25K params: 0
FC: [1x1x4096] memory: 4096 params: 7*7*512*4096 = 102,760,448
FC: [1x1x4096] memory: 4096 params: 4096*4096 = 16,777,216
FC: [1x1x1000] memory: 1000 params: 4096*1000 = 4,096,000



ConvNet Configuration			
B	C	D	
13 weight layers	16 weight layers	16 weight layers	19
put (224 × 224 RGB image)			
conv3-64	conv3-64	conv3-64	co
conv3-64	conv3-64	conv3-64	co
maxpool			
conv3-128	conv3-128	conv3-128	co
conv3-128	conv3-128	conv3-128	co
maxpool			
conv3-256	conv3-256	conv3-256	co
conv3-256	conv3-256	conv3-256	co
	conv1-256	**conv3-256**	co
			co
maxpool			
conv3-512	conv3-512	conv3-512	co
conv3-512	conv3-512	conv3-512	co
	conv1-512	**conv3-512**	co
			co
maxpool			
conv3-512	conv3-512	conv3-512	co
conv3-512	conv3-512	conv3-512	co
	conv1-512	**conv3-512**	co
			co
maxpool			
FC-4096			
FC-4096			
FC-1000			
soft-max			

(not counting biases)

INPUT: [224x224x3] memory: 224*224*3=150K params: 0
CONV3-64: [224x224x64] memory: 224*224*64=3.2M params: (3*3*3)*64 = 1,728
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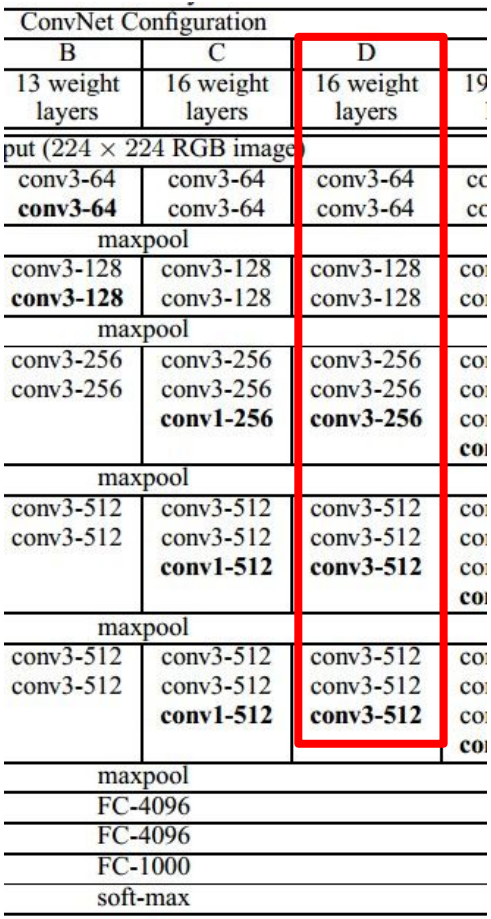
FC: [1x1x4096] memory: 4096 params: 4096*4096 = 16,777,216
FC: [1x1x1000] memory: 1000 params: 4096*1000 = 4,096,000

TOTAL memory: 24M * 4 bytes ~= 93MB / image (only forward! ~*2 for bwd)
TOTAL params: 138M parameters



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conv3-128	conv3-128	conv3-128	co
maxpool			
conv3-256	conv3-256	conv3-256	co
conv3-256	conv3-256	conv3-256	co
	conv1-256	**conv3-256**	co
			co
maxpool			
conv3-512	conv3-512	conv3-512	co
conv3-512	conv3-512	conv3-512	co
	conv1-512	**conv3-512**	co
			co
maxpool			
conv3-512	conv3-512	conv3-512	co
conv3-512	conv3-512	conv3-512	co
	conv1-512	**conv3-512**	co
			co
maxpool			
FC-4096			
FC-4096			
FC-1000			
soft-max			

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FC: [1x1x1000] memory: 1000 params: 4096*1000 = 4,096,000

Note:

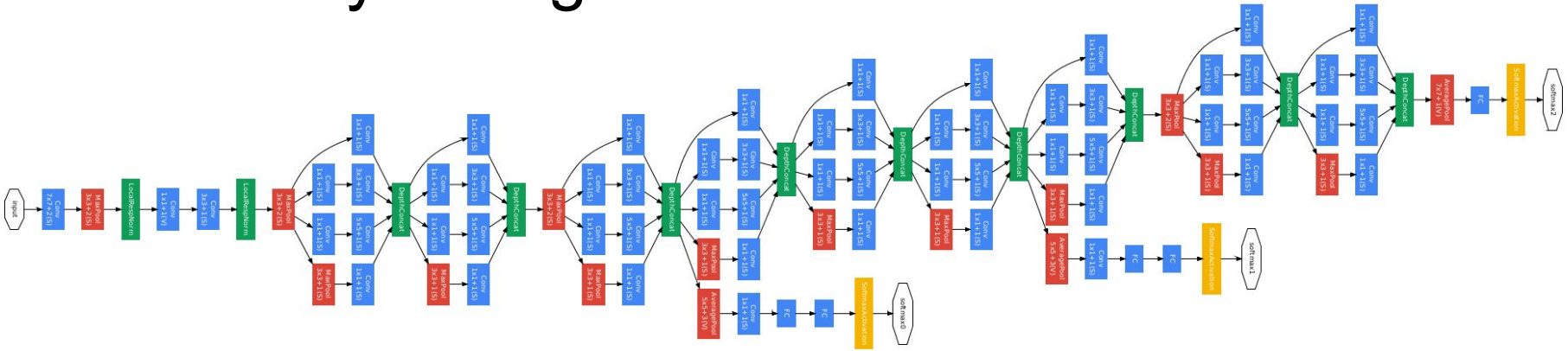
Most memory is in early CONV

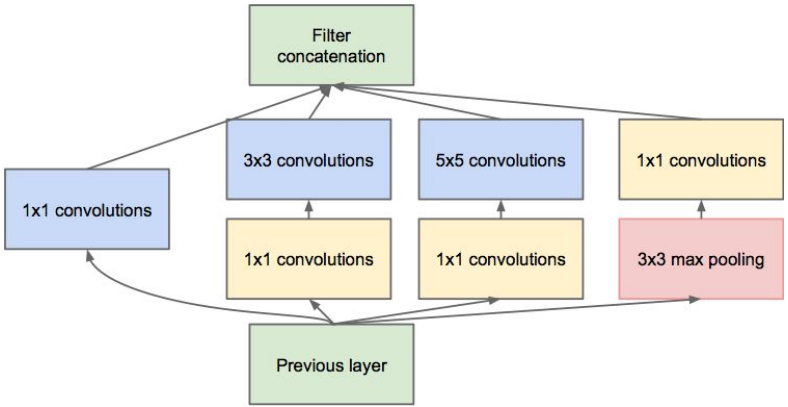
Most params are in late FC

TOTAL memory: 24M * 4 bytes ~= 93MB / image (only forward! ~*2 for bwd)
TOTAL params: 138M parameters

Case Study: GoogLeNet

[Szegedy et al., 2014]





Inception module

ILSVRC 2014 winner (6.7% top 5 error)

Case Study: GoogLeNet

type	patch size/ stride	output size	depth	#1×1	#3×3 reduce	#3×3	#5×5 reduce	#5×5	pool proj	params	ops
convolution	7×7/2	112×112×64	1							2.7K	34M
max pool	3×3/2	56×56×64	0								
convolution	3×3/1	56×56×192	2		64	192				112K	360M
max pool	3×3/2	28×28×192	0								
inception (3a)		28×28×256	2	64	96	128	16	32	32	159K	128M
inception (3b)		28×28×480	2	128	128	192	32	96	64	380K	304M
max pool	3×3/2	14×14×480	0								
inception (4a)		14×14×512	2	192	96	208	16	48	64	364K	73M
inception (4b)		14×14×512	2	160	112	224	24	64	64	437K	88M
inception (4c)		14×14×512	2	128	128	256	24	64	64	463K	100M
inception (4d)		14×14×528	2	112	144	288	32	64	64	580K	119M
inception (4e)		14×14×832	2	256	160	320	32	128	128	840K	170M
max pool	3×3/2	7×7×832	0								
inception (5a)		7×7×832	2	256	160	320	32	128	128	1072K	54M
inception (5b)		7×7×1024	2	384	192	384	48	128	128	1388K	71M
avg pool	7×7/1	1×1×1024	0								
dropout (40%)		1×1×1024	0								
linear		1×1×1000	1							1000K	1M
softmax		1×1×1000	0								

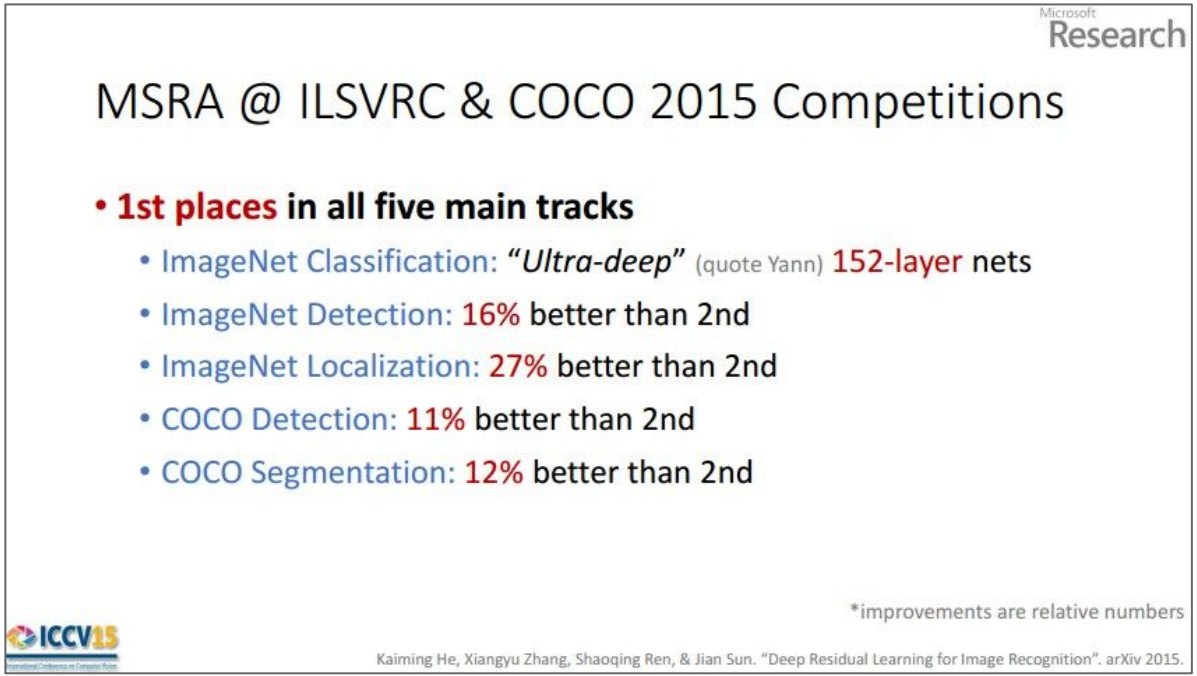
Fun features:

- Only 5 million params! (Removes FC layers completely)

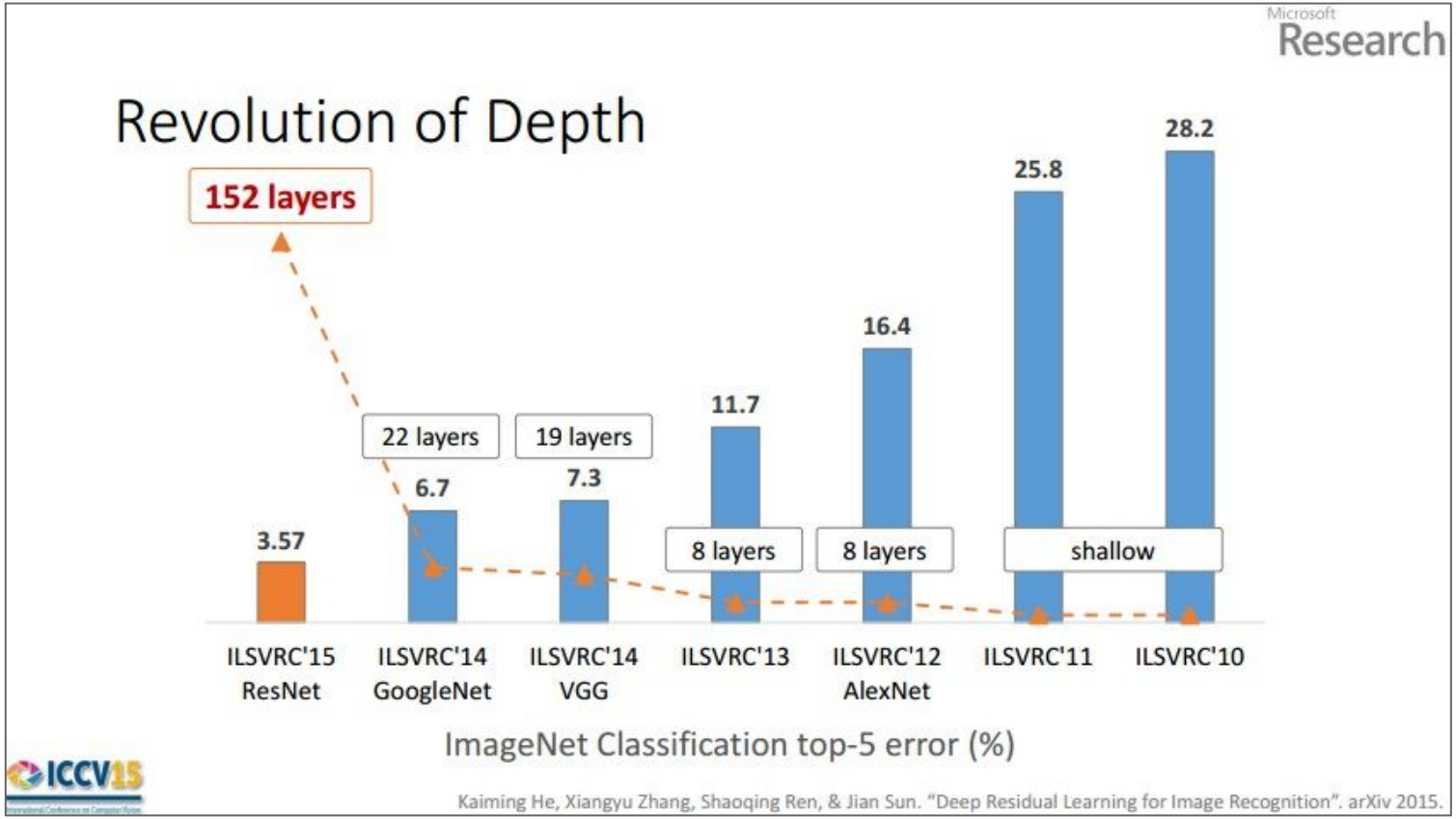
Compared to AlexNet:
- 12X less params
- 2x more compute
- 6.67% (vs. 16.4%)

Case Study: ResNet *[He et al., 2015]*

ILSVRC 2015 winner (3.6% top 5 error)

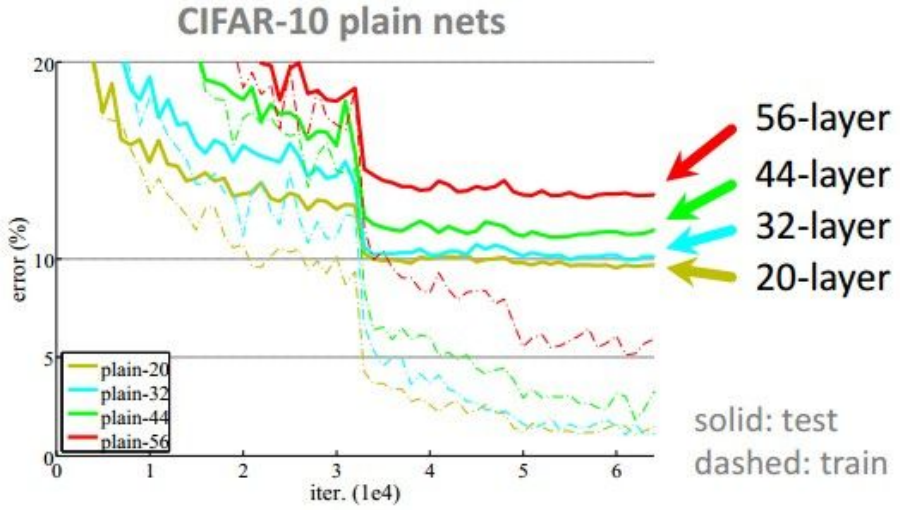


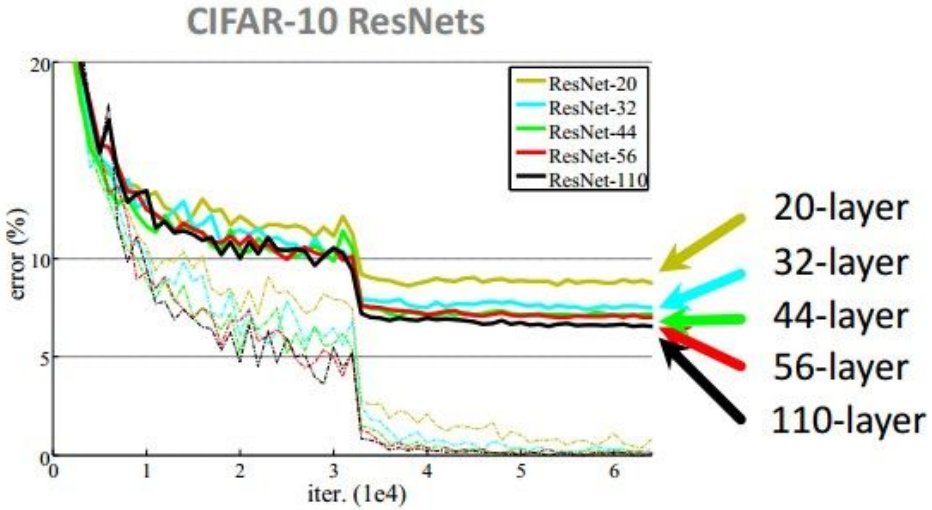
Slide from Kaiming He's recent presentation https://www.youtube.com/watch?v=1PGLj-uKT1w



(slide from Kaiming He's recent presentation)

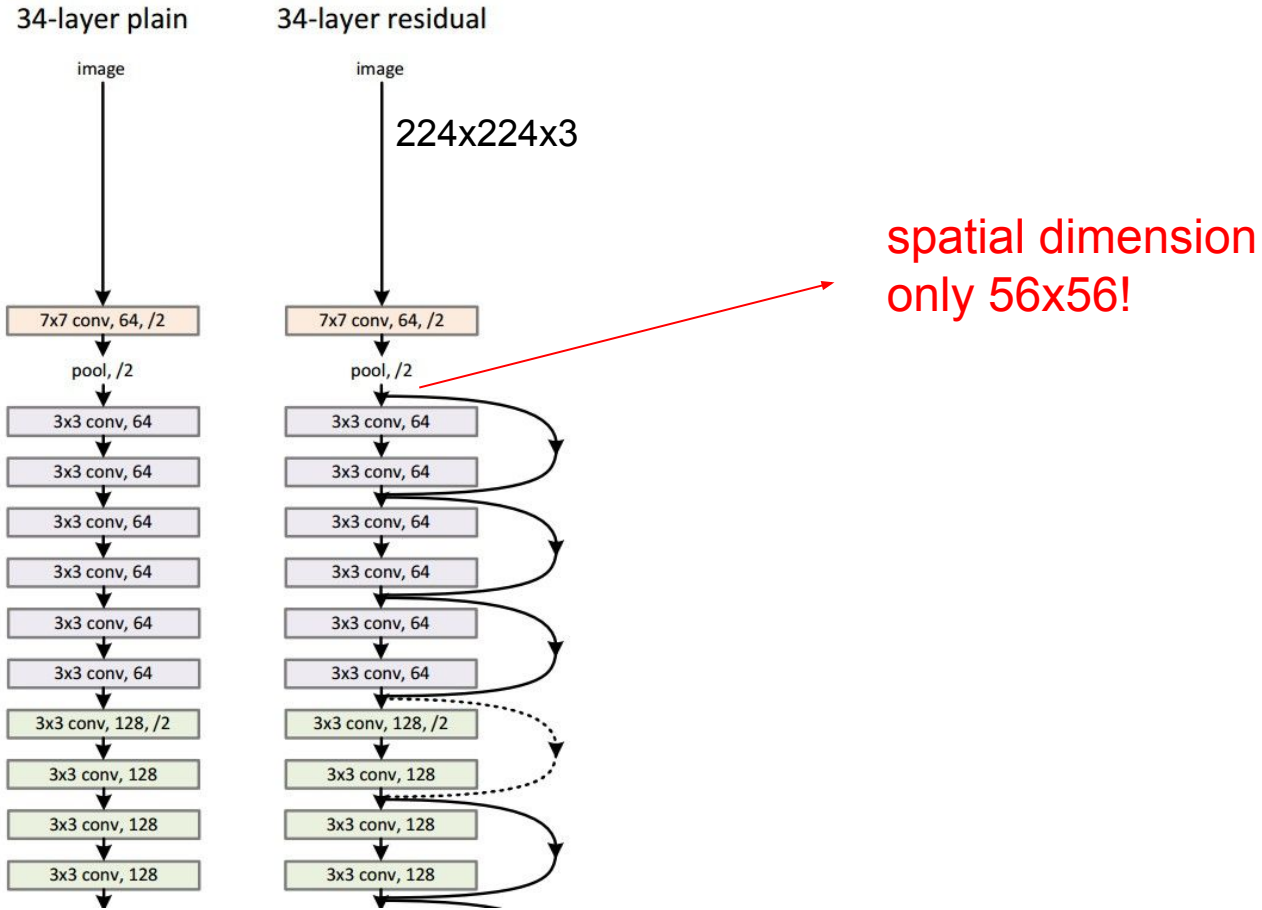
CIFAR-10 experiments



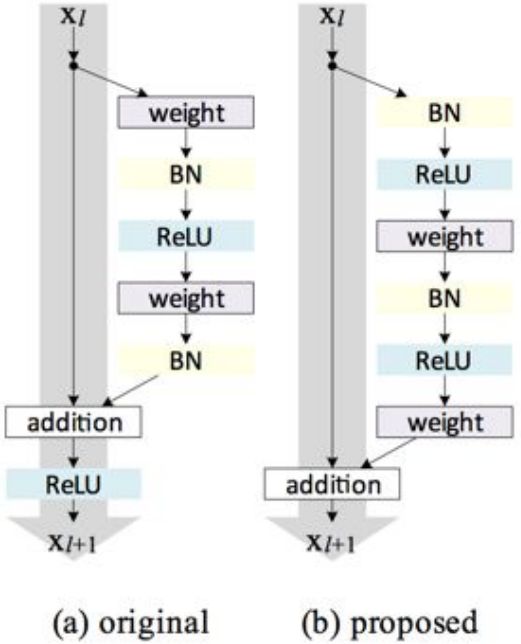


Case Study: ResNet

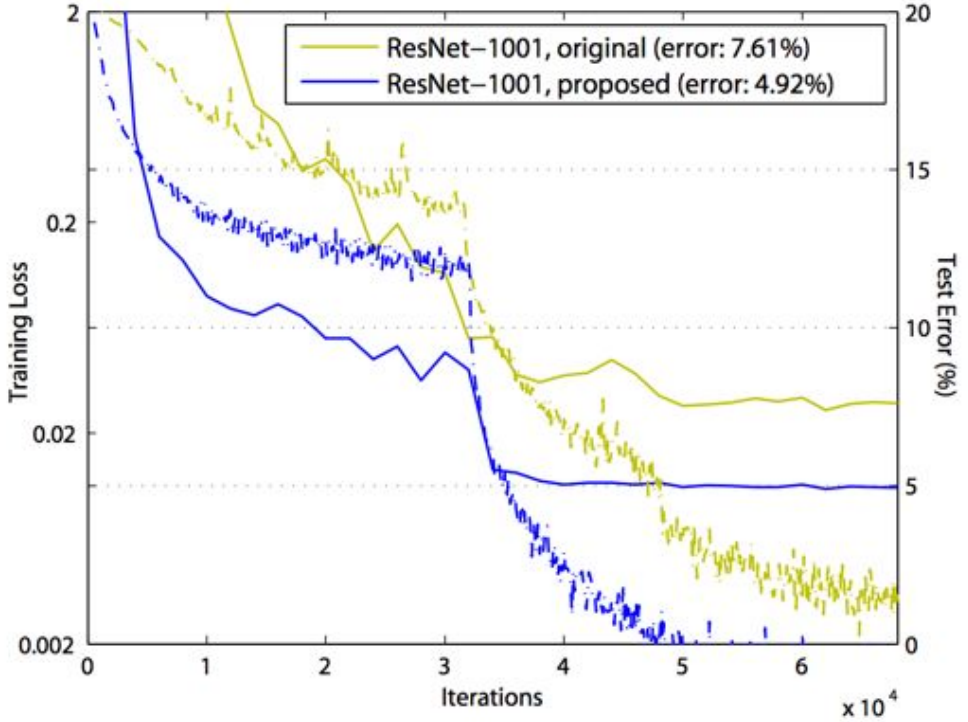
[He et al., 2015]



Identity Mappings in Deep Residual Networks, He et al. 2016

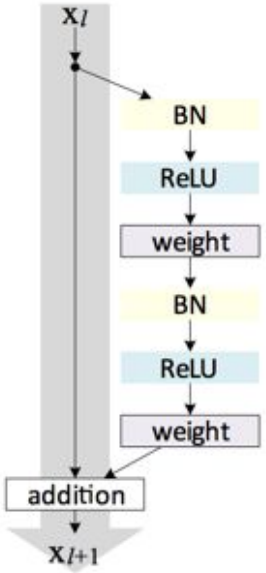


(a) original (b) proposed

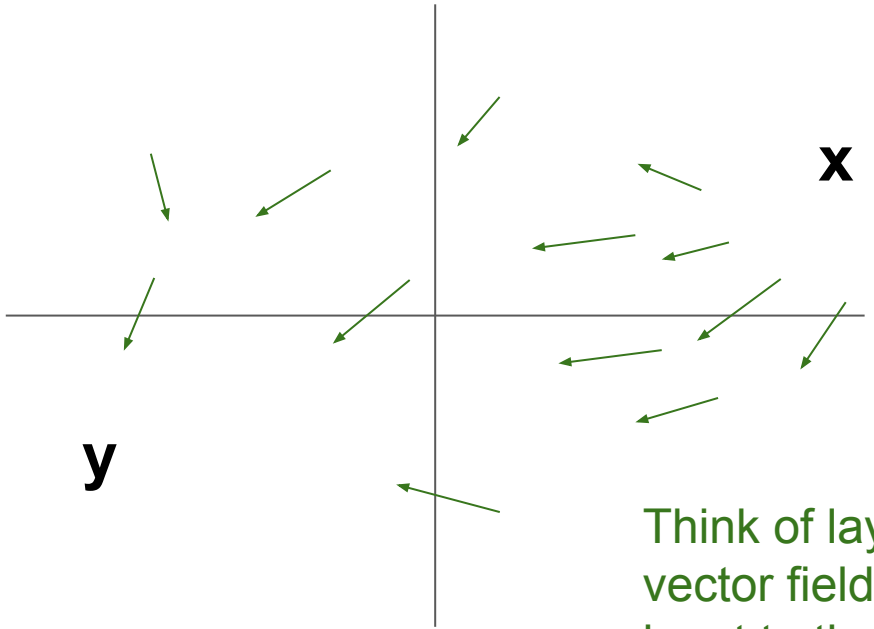


Deep Networks with Stochastic Depth, Huang et al., 2016

"We start with very deep networks but during training, for each mini-batch, randomly drop a subset of layers and bypass them with the identity function."



(b) proposed



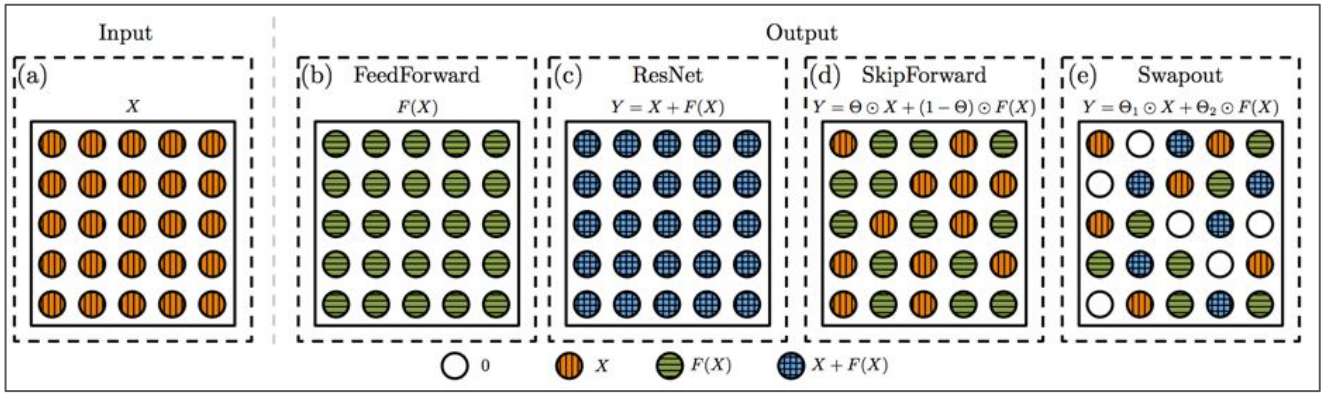
Think of layers more like vector fields, nudging the input to the label

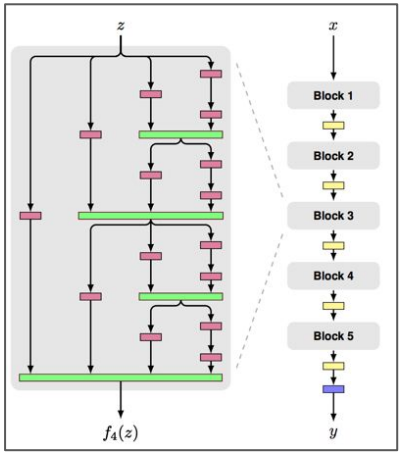
Wide Residual Networks, Zagoruyko and Komodakis, 2016

- wide networks with only 16 layers can significantly outperform 1000-layer deep networks
- main power of residual networks is in residual blocks, and not in extreme depth
- wide residual networks are several times faster to train

Swapout: Learning an ensemble of deep architectures, Singh et al., 2016

- 32 layer wider model performs similar to a 1001 layer ResNet model





FractalNet: Ultra-Deep Neural Networks without Residuals, Larsson et al. 2016

Still an active area of research...

Densely Connected Convolutional Networks, Huang et al.

ResNet in ResNet, Targ et al.

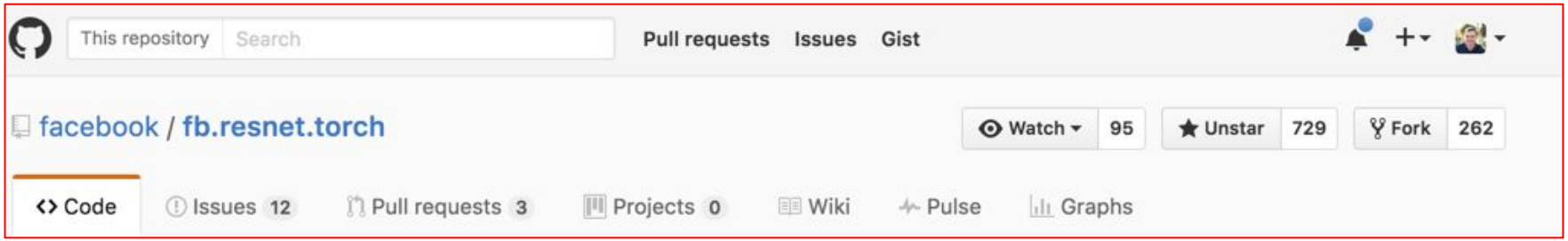
Deeply-Fused Nets, Wang et al.

Weighted Residuals for Very Deep Networks, Shen et al.

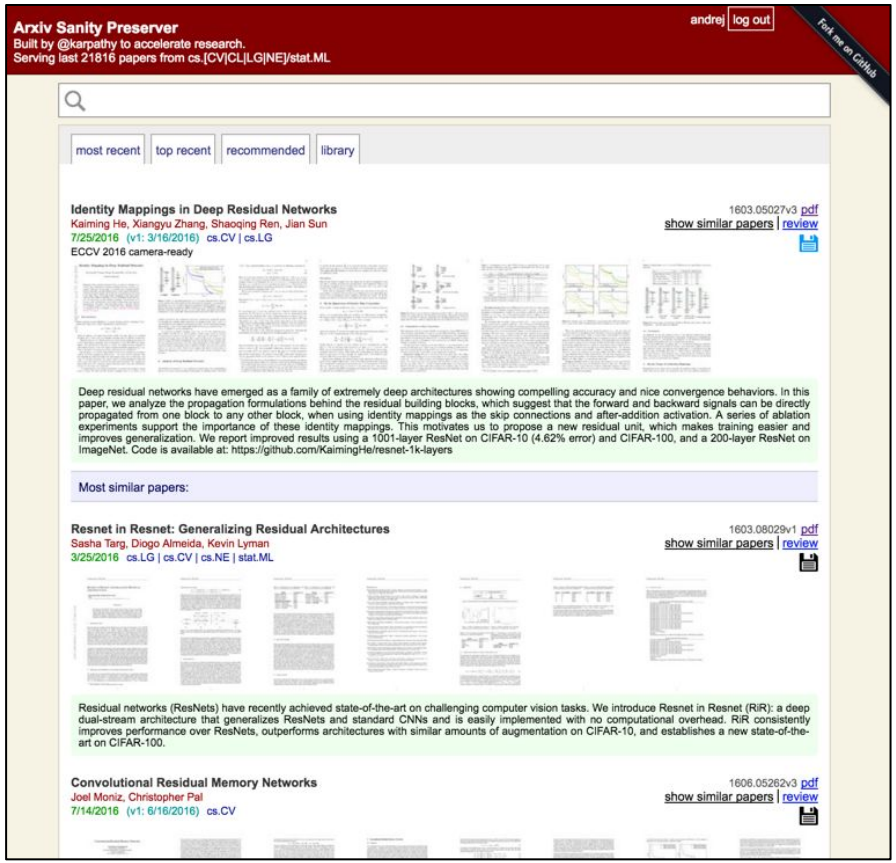
Residual Networks of Residual Networks: Multilevel Residual Networks, Zhang et al.

...

In large part likely due to open source code available, e.g.:



ASIDE: arxiv-sanity.com plug



Addressing other tasks...

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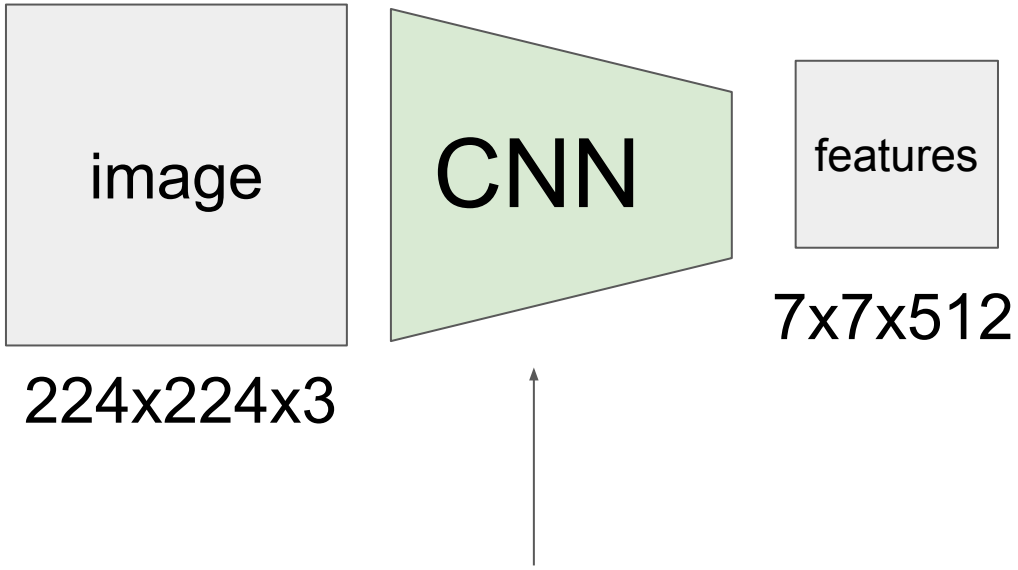
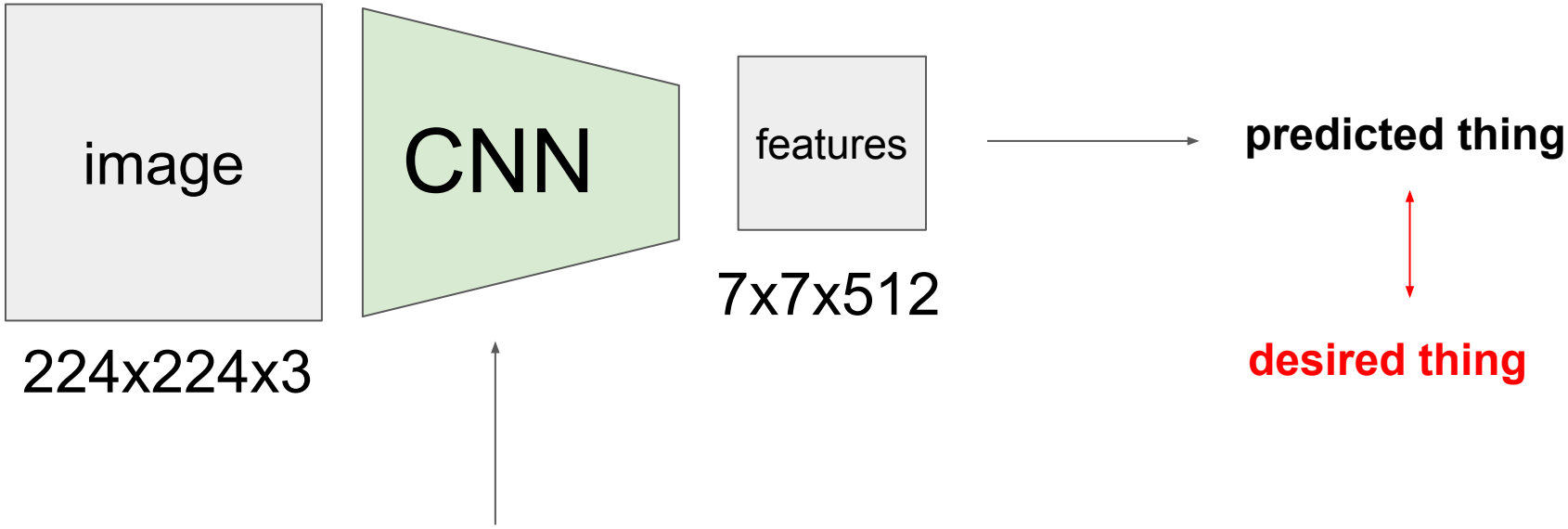


Addressing other tasks...



Addressing other tasks...

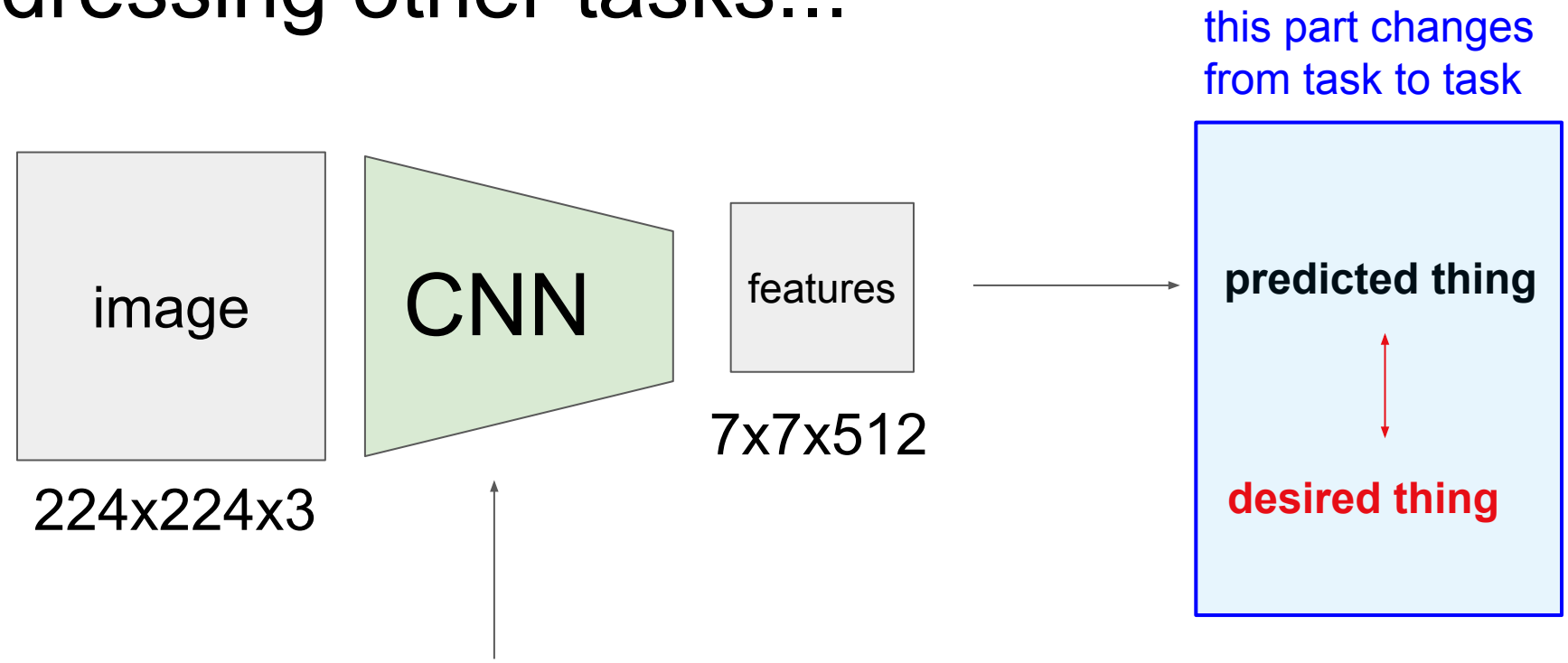
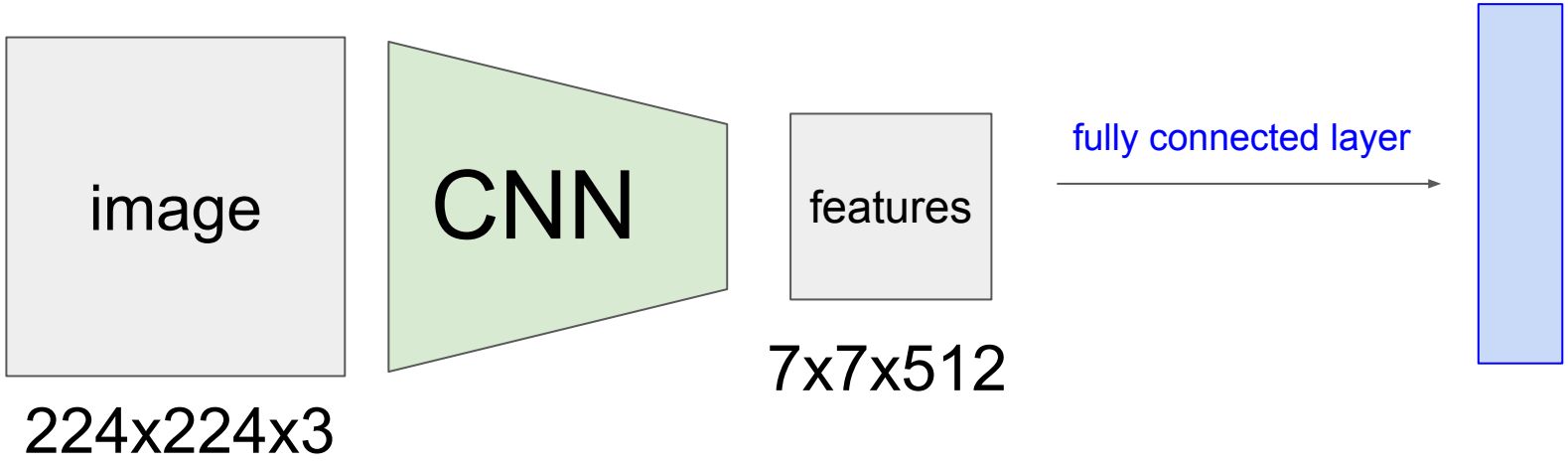


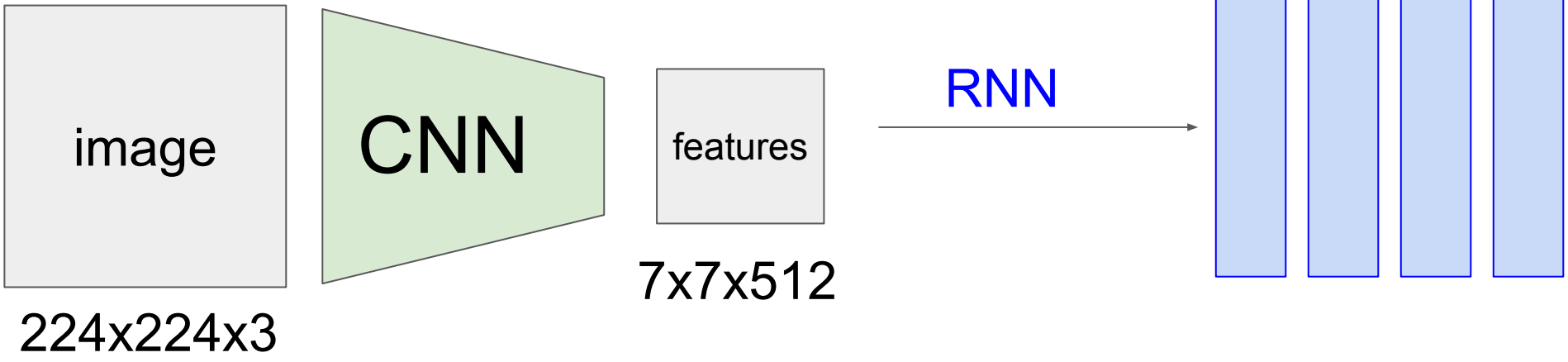
Image Classification

thing = a vector of probabilities for different classes



e.g. vector of 1000 numbers giving probabilities for different classes.

Image Captioning



A sequence of 10,000-dimensional vectors giving probabilities of different words in the caption.

Localization

image

224x224x3

CNN

features

7x7x512

fully connected layer

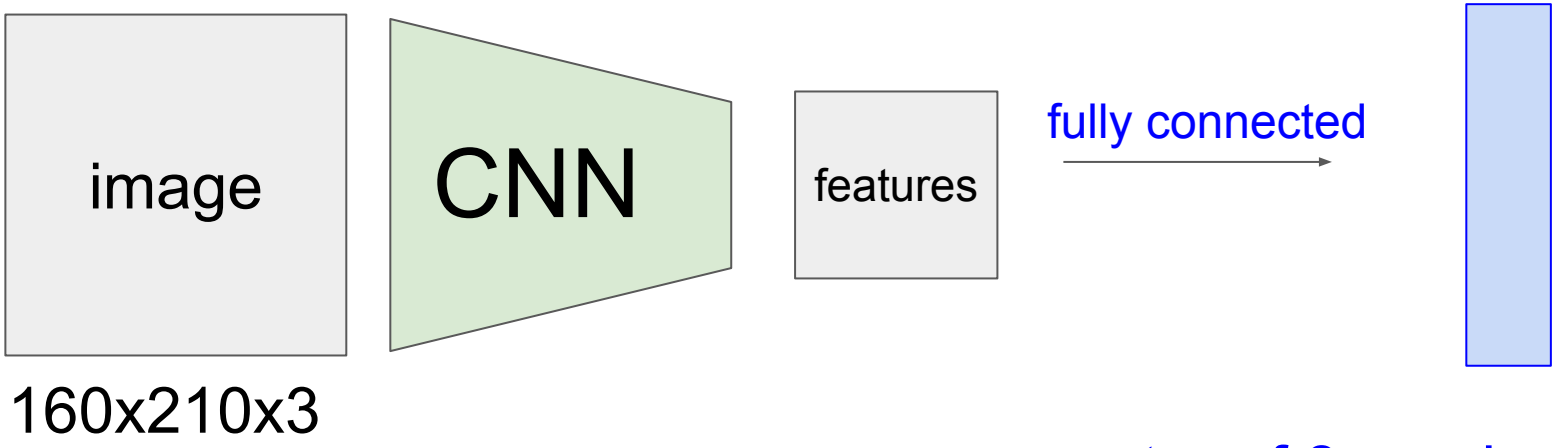
Class probabilities (as before)

4 numbers:

- X coord
- Y coord
- Width
- Height

Reinforcement Learning

Mnih et al. 2015



160x210x3

e.g. vector of 8 numbers giving probability of wanting to take any of the 8 possible ATARI actions.

Segmentation

image

class “map”

image

224x224x3

CNN

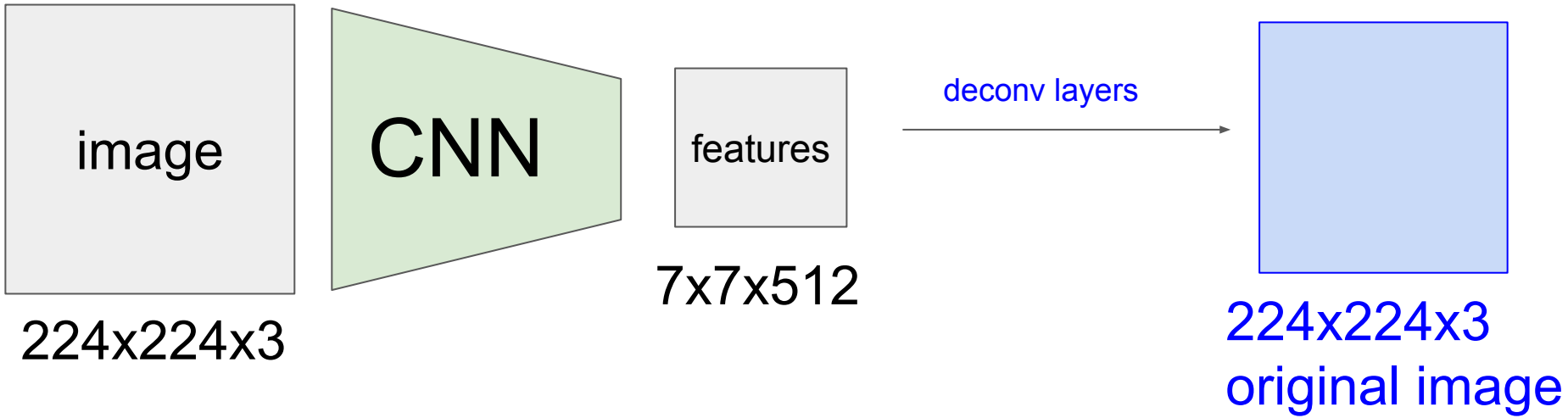
features

7x7x512

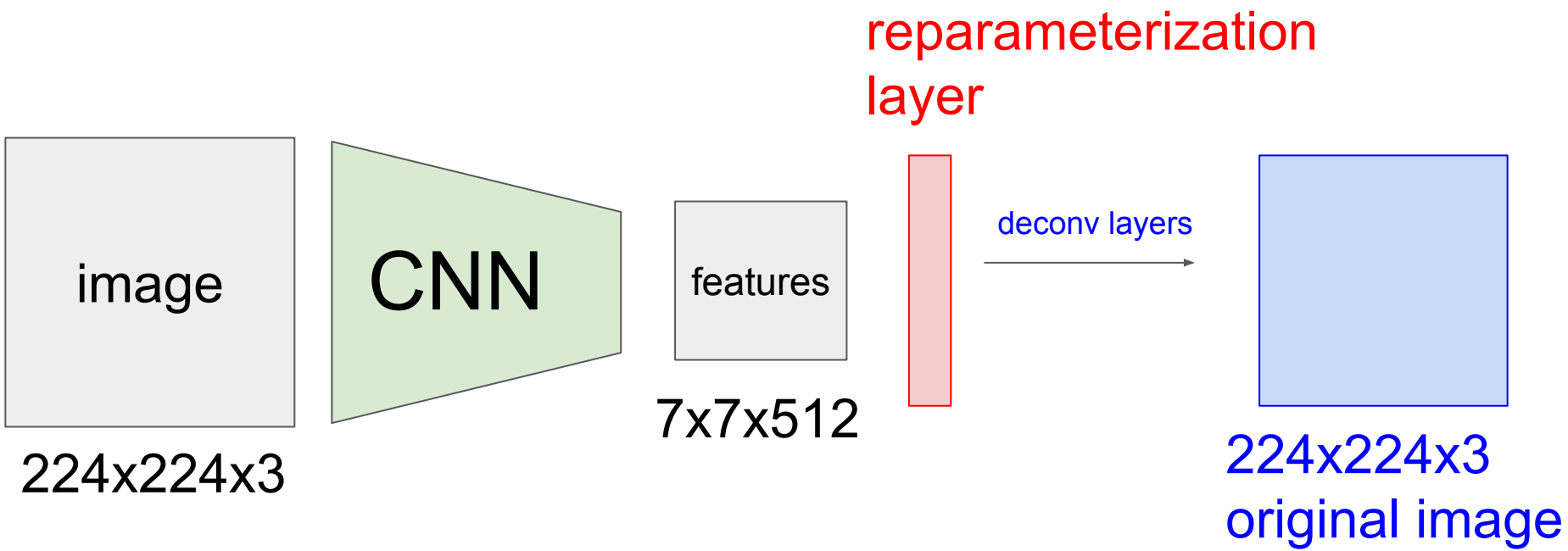
deconv layers

224x224x20 array of class probabilities at each pixel.

Autoencoders

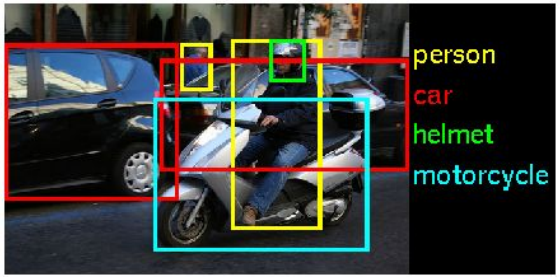


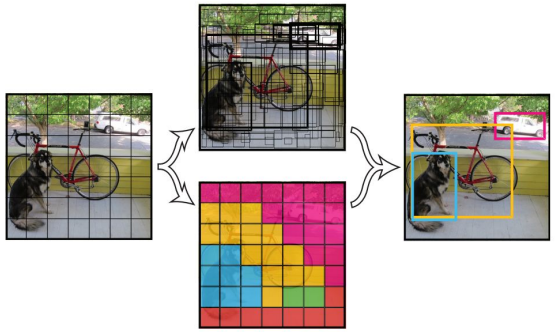
Variational Autoencoders

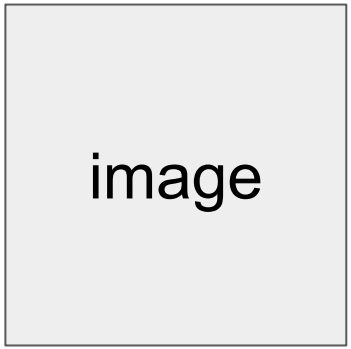


[Kingma et al.], [Rezende et al.], [Salimans et al.]

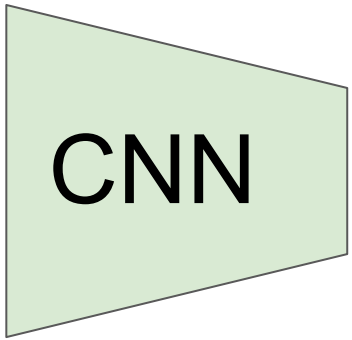
Detection





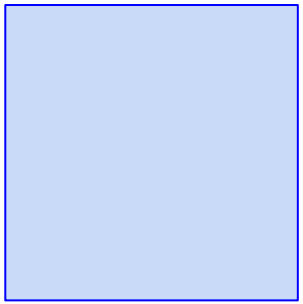


224x224x3



7x7x512

1x1 CONV



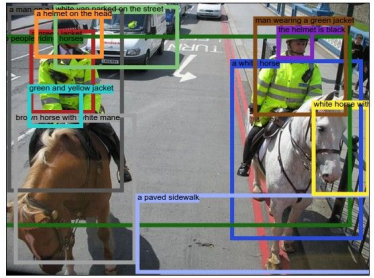
7x7x(5*B+C)

For each of 7x7 locations:

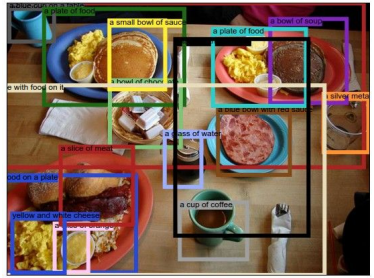
- [x,y,width,height,confidence]*B
- class

E.g. YOLO: You Only Look Once (Demo: http://pjreddie.com/darknet/yolo/)

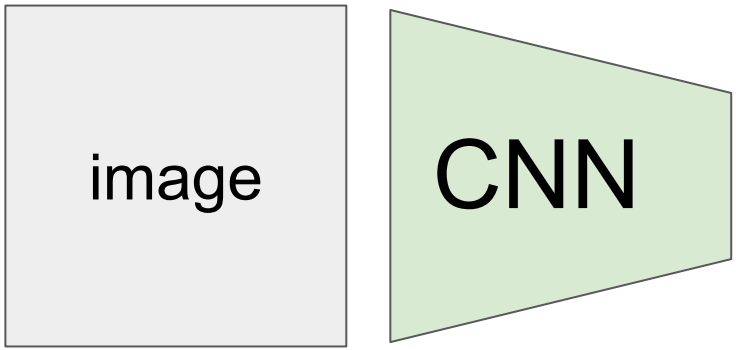
Dense Image Captioning



a green jacket. a white horse. a man on a horse. two people riding horses. man wearing a green jacket. the helmet is black. brown horse with white mane. white van parked on the street. a paved sidewalk. green and yellow jacket. a helmet on the head. white horse with white face.



a plate of food. food on a plate. a blue cup on a table. a plate of food. a blue bowl with red sauce. a bowl of soup. a cup of coffee. a bowl of chocolate. a glass of water. a plate of food. a silver metal container. a small bowl of sauce. table with food on it. a slice of orange. a table with food on it. a slice of meat. yellow and white cheese.



224x224x3

7x7x512

7x7x(5*B+[C,..])

For each of 7x7 locations:

- x,y,width,height,confidence
- sequence of words

DenseCap: Fully Convolutional Localization Networks for Dense Captioning, Johnson et al. 2016

Practical considerations when applying ConvNets

What hardware do I use?

Buy your own machine:

- NVIDIA DIGITS DevBox (TITAN X GPUs)
- NVIDIA DGX-1 (P100 GPUs)

Build your own machine:

https://graphific.github.io/posts/building-a-deep-learning-dream-machine/

GPUs in the cloud:

- Amazon AWS (GRID K520 :( )
- Microsoft Azure (soon); 4x K80 GPUs
- Cirrascale (“rent-a-box”)

What framework do I use?

Caffe

No need to write code!

1. Convert data (run a script)
2. Define net (edit prototxt)
3. Define solver (edit prototxt)
4. Train (with pretrained weights)

Torch

```
require 'torch'
require 'nn'
require 'optim'

-- Batch size, input dim, hidden dim, num classes
local N, D, H, C = 100, 1000, 100, 10

-- Build a one-layer ReLU network
local net = nn.Sequential()
net:add(nn.Linear(D, H))
net:add(nn.ReLU())
net:add(nn.Linear(H, C))

-- Collect all weights and gradients in a single Tensor
local weights, grad_weights = net:getParameters()

-- Loss functions are called "criterions"
local crit = nn.CrossEntropyCriterion()  -- Softmax loss

-- Calback to interface with optim methods
local function f(w)
  assert(w == weights)

  -- Generate some random input data
  local x = torch.randn(N, D)
  local y = torch.Tensor(N):random(C)

  -- Forward pass: Compute scores and loss
  local scores = net:forward(x)
  local loss = crit:forward(scores, y)

  -- Backward pass: compute gradients
  grad_weights:zero()
  local dscores = crit:backward(scores, y)
  local dx = net:backward(x, dscores)

  return loss, grad_weights
end

-- Make a step using Adam
local state = {learningRate=1e-3}
optim.adam(f, weights, state)
```

TensorFlow

```
import tensorflow as tf
import numpy as np

N, D, H, C = 64, 1000, 100, 10

x = tf.placeholder(tf.float32, shape=[None, D])
y = tf.placeholder(tf.float32, shape=[None, C])

w1 = tf.Variable(1e-3 * np.random.randn(D, H).astype(np.float32))
w2 = tf.Variable(1e-3 * np.random.randn(H, C).astype(np.float32))

a = tf.matmul(x, w1)
a_relu = tf.nn.relu(a)
scores = tf.matmul(a_relu, w2)
probs = tf.nn.softmax(scores)
loss = -tf.reduce_sum(y * tf.log(probs))

learning_rate = 1e-2
train_step = tf.train.GradientDescentOptimizer(learning_rate).minimize(loss)

xx = np.random.randn(N, D).astype(np.float32)
yy = np.zeros((N, C)).astype(np.float32)
yy[np.arange(N), np.random.randint(C, size=N)] = 1

with tf.Session() as sess:
  sess.run(tf.initialize_all_variables())

  for t in xrange(100):
    _, loss_value = sess.run([train_step, loss],
                             feed_dict={x: xx, y: yy})
    print loss_value
```

Theano

```
import theano
import theano.tensor as T

# Batch size, input dim, hidden dim, num classes
N, D, H, C = 64, 1000, 100, 10

x = T.matrix('x')
y = T.vector('y', dtype='int64')
w1 = T.matrix('w1')
w2 = T.matrix('w2')

# Forward pass: Compute scores
a = x.dot(w1)
a_relu = T.nnet.relu(a)
scores = a_relu.dot(w2)

# Forward pass: compute softmax loss
probs = T.nnet.softmax(scores)
loss = T.nnet.categorical_crossentropy(probs, y).mean()

# Backward pass: compute gradients
dw1, dw2 = T.grad(loss, [w1, w2])

f = theano.function(
      inputs=[x, y, w1, w2],
      outputs=[loss, scores, dw1, dw2],
    )
```

Mxnet
chainer
Nervana's Neon
Microsoft's CNTK
Deeplearning4j
...

Lasagne

```
import numpy as np
import theano
import theano.tensor as T
import lasagne

N, D, H, C = 64, 1000, 100, 10

x = T.matrix('x')
y = T.vector('y', dtype='int64')

relu = lasagne.nonlinearities.rectify
softmax = lasagne.nonlinearities.softmax
net = lasagne.layers.InputLayer(shape=(None, D), input_var=x)
net = lasagne.layers.DenseLayer(net, H, nonlinearity=relu)
net = lasagne.layers.DenseLayer(net, C, nonlinearity=softmax)

probs = lasagne.layers.get_output(net)
loss = lasagne.objectives.categorical_crossentropy(probs, y).mean()

params = lasagne.layers.get_all_params(net, trainable=True)
updates = lasagne.updates.nesterov_momentum(loss, params,
                                            learning_rate=1e-2, momentum=0.0)

train_fn = theano.function([x, y], loss, updates=updates)

xx = np.random.randn(N, D)
yy = np.random.randint(C, size=N).astype(np.int64)

for t in xrange(100):
  loss_val = train_fn(xx, yy)
  print loss_val
```

Keras

```
from keras.models import Sequential
from keras.layers.core import Dense, Activation
from keras.optimizers import SGD
from keras.utils import np_utils

D, H, C = 1000, 100, 10

model = Sequential()
model.add(Dense(input_dim=D, output_dim=H))
model.add(Activation('relu'))
model.add(Dense(input_dim=H, output_dim=C))
model.add(Activation('softmax'))

sgd = SGD(lr=1e-3, momentum=0.9, nesterov=True)
model.compile(loss='categorical_crossentropy', optimizer=sgd)

N, N_batch = 1000, 32
X = np.random.randn(N, D)
y = np.random.randint(C, size=N)
y = np_utils.to_categorical(y)

model.fit(X, y, nb_epoch=5, batch_size=N_batch, verbose=2)
```

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  grad_weights:zero()
  local dscores = crit:backward(scores, y)
  local dx = net:backward(x, dscores)

  return loss, grad_weights
end

-- Make a step using Adam
local state = {learningRate=1e-3}
optim.adam(f, weights, state)
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2,3

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y = tf.placeholder(tf.float32, shape=[None, C])

w1 = tf.Variable(1e-3 * np.random.randn(D, H).astype(np.float32))
w2 = tf.Variable(1e-3 * np.random.randn(H, C).astype(np.float32))

a = tf.matmul(x, w1)
a_relu = tf.nn.relu(a)
scores = tf.matmul(a_relu, w2)
probs = tf.nn.softmax(scores)
loss = -tf.reduce_sum(y * tf.log(probs))

learning_rate = 1e-2
train_step = tf.train.GradientDescentOptimizer(learning_rate).minimize(loss)

xx = np.random.randn(N, D).astype(np.float32)
yy = np.zeros((N, C)).astype(np.float32)
yy[np.arange(N), np.random.randint(C, size=N)] = 1

with tf.Session() as sess:
  sess.run(tf.initialize_all_variables())

  for t in xrange(100):
    _, loss_value = sess.run([train_step, loss],
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w1 = T.matrix('w1')
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scores = a_relu.dot(w2)

# Forward pass: compute softmax loss
probs = T.nnet.softmax(scores)
loss = T.nnet.categorical_crossentropy(probs, y).mean()

# Backward pass: compute gradients
dw1, dw2 = T.grad(loss, [w1, w2])

f = theano.function(
      inputs=[x, y, w1, w2],
      outputs=[loss, scores, dw1, dw2],
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```

1

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relu = lasagne.nonlinearities.rectify
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net = lasagne.layers.DenseLayer(net, H, nonlinearity=relu)
net = lasagne.layers.DenseLayer(net, C, nonlinearity=softmax)

probs = lasagne.layers.get_output(net)
loss = lasagne.objectives.categorical_crossentropy(probs, y).mean()

params = lasagne.layers.get_all_params(net, trainable=True)
updates = lasagne.updates.nesterov_momentum(loss, params,
                                            learning_rate=1e-2, momentum=0.8)

train_fn = theano.function([x, y], loss, updates=updates)

xx = np.random.randn(N, D)
yy = np.random.randint(C, size=N).astype(np.int64)

for t in xrange(100):
  loss_val = train_fn(xx, yy)
  print loss_val
```

Keras

```
from keras.models import Sequential
from keras.layers.core import Dense, Activation
from keras.optimizers import SGD
from keras.utils import np_utils

D, H, C = 1000, 100, 10

model = Sequential()
model.add(Dense(input_dim=D, output_dim=H))
model.add(Activation('relu'))
model.add(Dense(input_dim=H, output_dim=C))
model.add(Activation('softmax'))

sgd = SGD(lr=1e-3, momentum=0.9, nesterov=True)
model.compile(loss='categorical_crossentropy', optimizer=sgd)

N, N_batch = 1000, 32
X = np.random.randn(N, D)
y = np.random.randint(C, size=N)
y = np_utils.to_categorical(y)

model.fit(X, y, nb_epoch=5, batch_size=N_batch, verbose=2)
```

Q: How do I know what architecture to use?

Q: How do I know what architecture to use?

A: don’t be a hero.

1. Take whatever works best on ILSVRC (latest ResNet)
2. Download a pretrained model
3. Potentially add/delete some parts of it
4. Finetune it on your application.

Q: How do I know what hyperparameters to use?

Q: How do I know what hyperparameters to use?

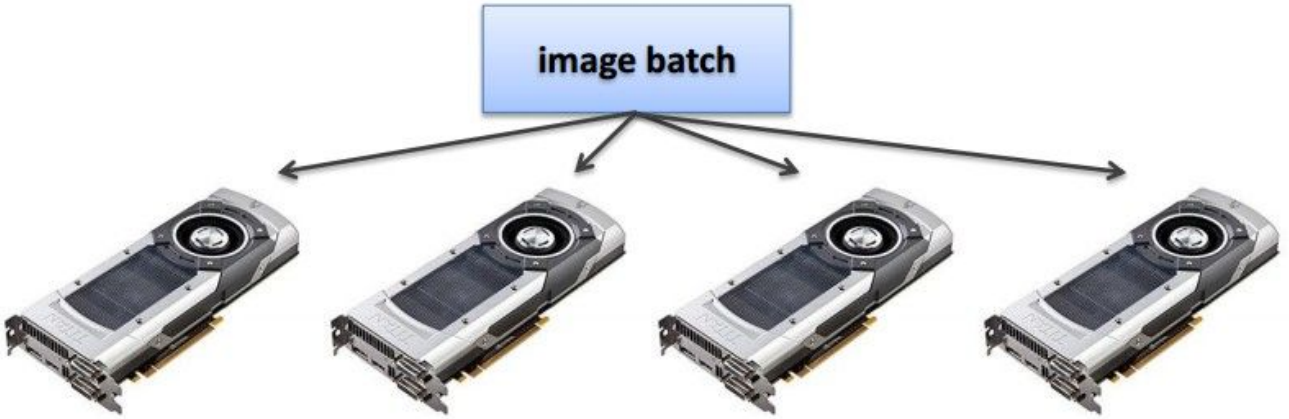
A: don’t be a hero.

- Use whatever is reported to work best on ILSVRC.
- Play with the regularization strength (dropout rates)

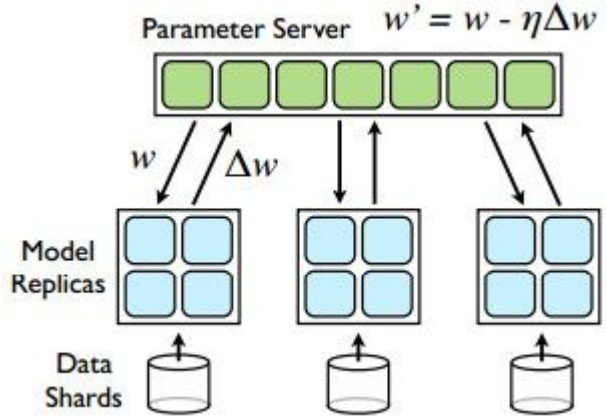
ConvNets in practice: Distributed training

VGG: ~2-3 weeks training with 4 GPUs
ResNet 101: 2-3 weeks with 4 GPUs

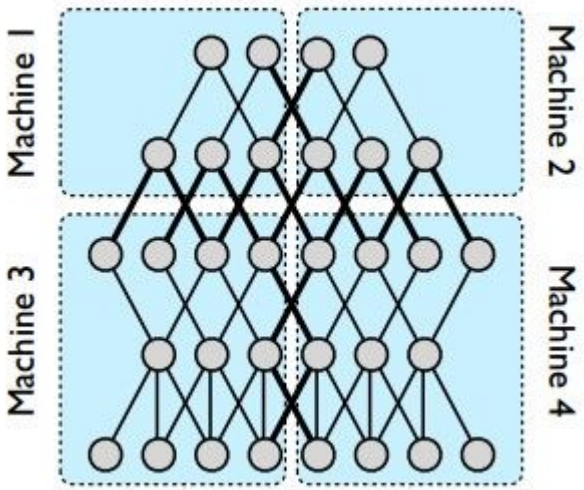
~$1K each



ConvNets in practice: Distributed training



Data parallelism



Model parallelism

[Large Scale Distributed Deep Networks, Jeff Dean et al., 2013]

ConvNets in practice: pre-fetching threads

Moving parts lol

CPU-disk bottleneck

Hard disk is slow to read from
=> Pre-processed images
stored contiguously in files, read as raw byte stream from SSD disk

CPU-GPU bottleneck

CPU data prefetch+augment thread running while
GPU performs forward/backward pass

Learn more!
CS231n

- lecture videos on YouTube
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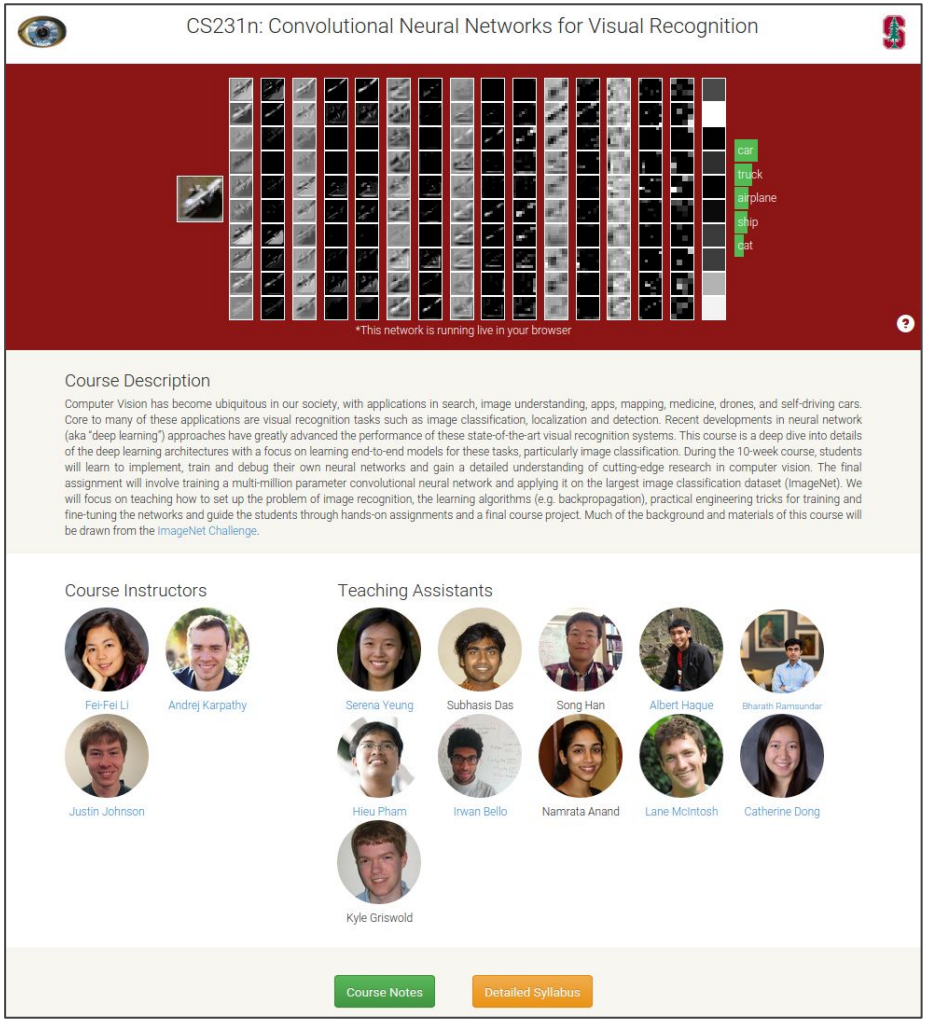
- notes
- assignments

cs231n.stanford.edu



Thank you!