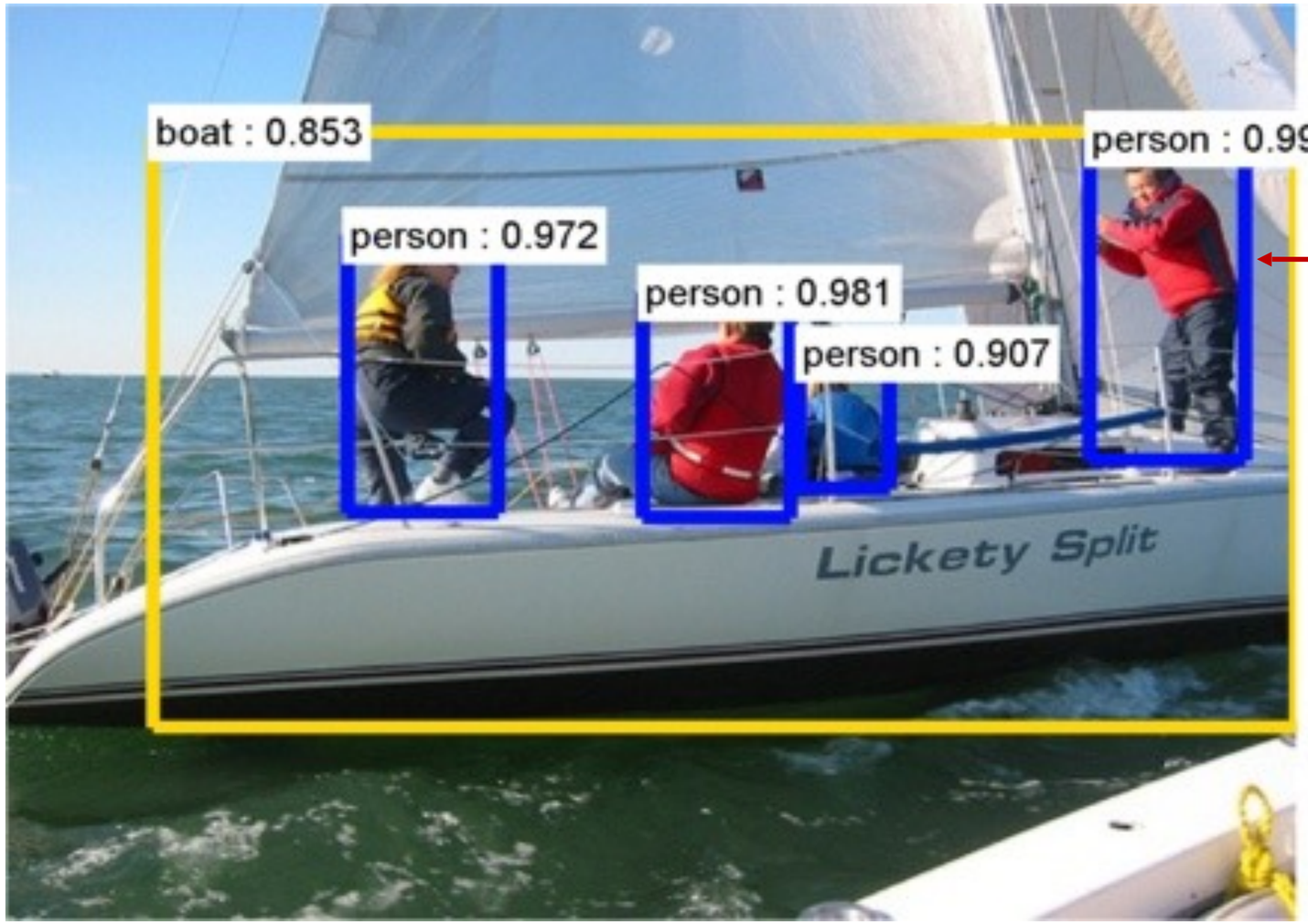
Lecture 10: Object Detection

Contains slides from S. Lazebnik, R. Girshick, B. Hariharan

Object detection with bounding boxes



What?

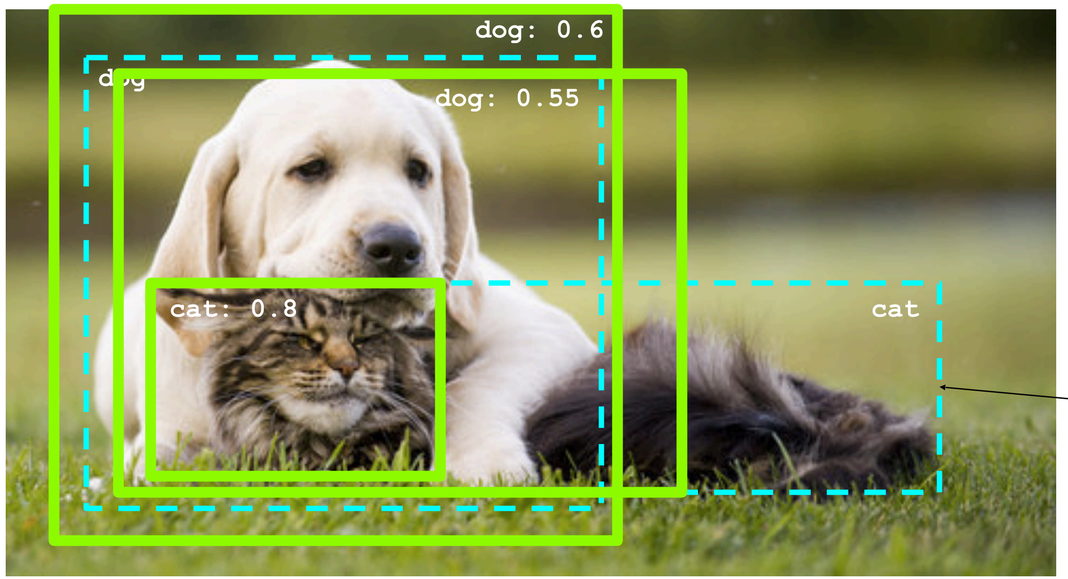
Where?

"Object detection"

Source: R. Girshick

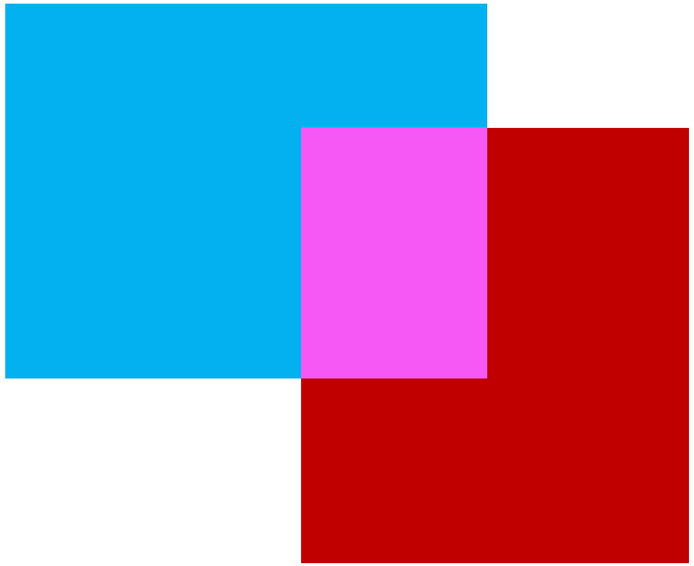
Evaluating an object detector

- At test time, predict bounding boxes, class labels, and confidence scores
- For each detection, determine whether it is a true or false positive
  - **Intersection over union** (IoU): Area(GT ∩ Det) / Area(GT ∪ Det) > 0.5



Source: S. Lazebnik

Evaluating an object detector



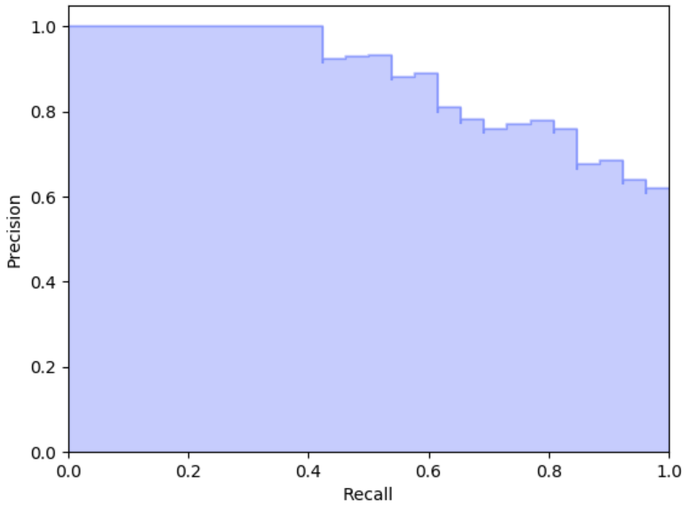
$$IoU(A, B) = \frac{|A \cap B|}{|A \cup B|}$$

Intersection over union (also known as Jaccard similarity)

Source: B. Hariharan

Evaluating an object detector

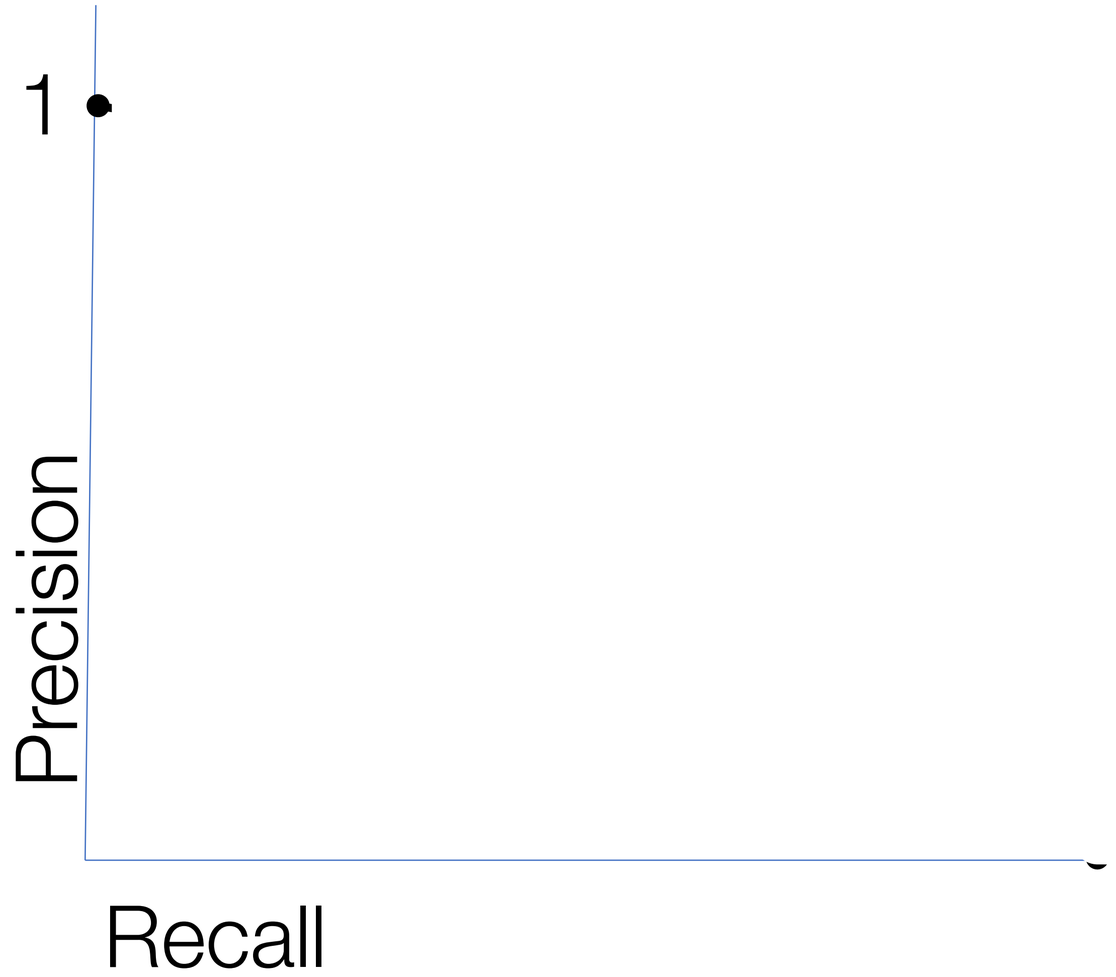
- For each class, plot Recall-Precision curve and compute Average Precision (area under the curve)
- Take mean of AP over classes to get mAP



Precision:
true positive detections / total detections
Recall:
true positive detections / total positive test instances

Source: S. Lazebnik

Average precision



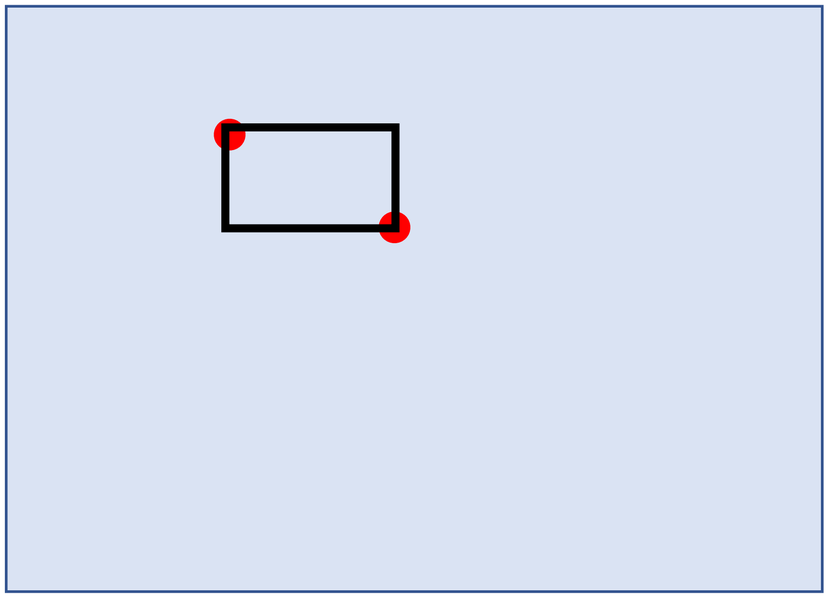
Source: B. Hariharan

Average precision

Source: B. Hariharan

Detection as classification

- Run through every possible box and classify
  - Well-localized object of class k or not?
- How many boxes?
  - Every pair of pixels = 1 box
  - $\begin{pmatrix} N \\ 2 \end{pmatrix}$ = $O(N^2)$
  - For 300 x 500 image, N = 150K
  - 2.25 x 10^{10} boxes!
- Related challenge: almost all boxes are negative!

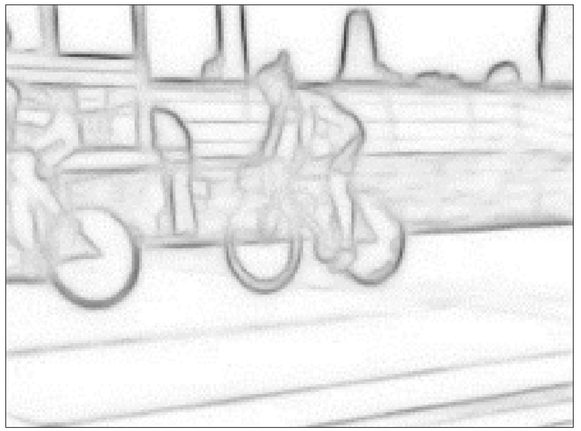


Source: B. Hariharan

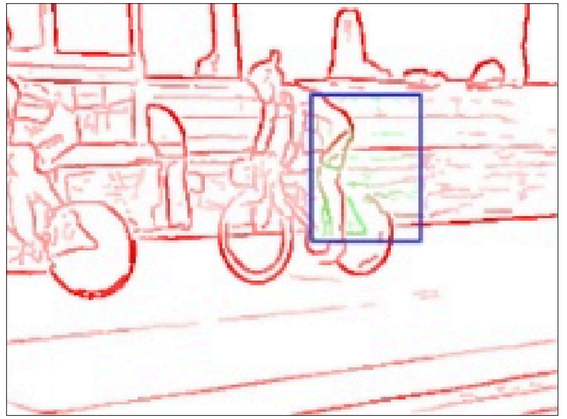
Selective search

Stage 1: generate candidate bounding boxes

Input image



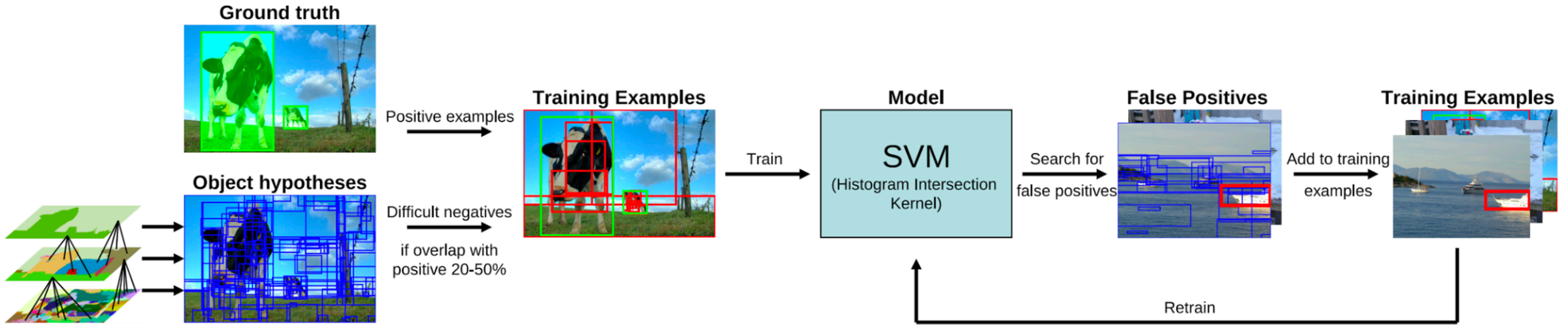
Edge detection



Bounding box proposal

[Zitnick and Dollar, "Edge Boxes…", 2014]

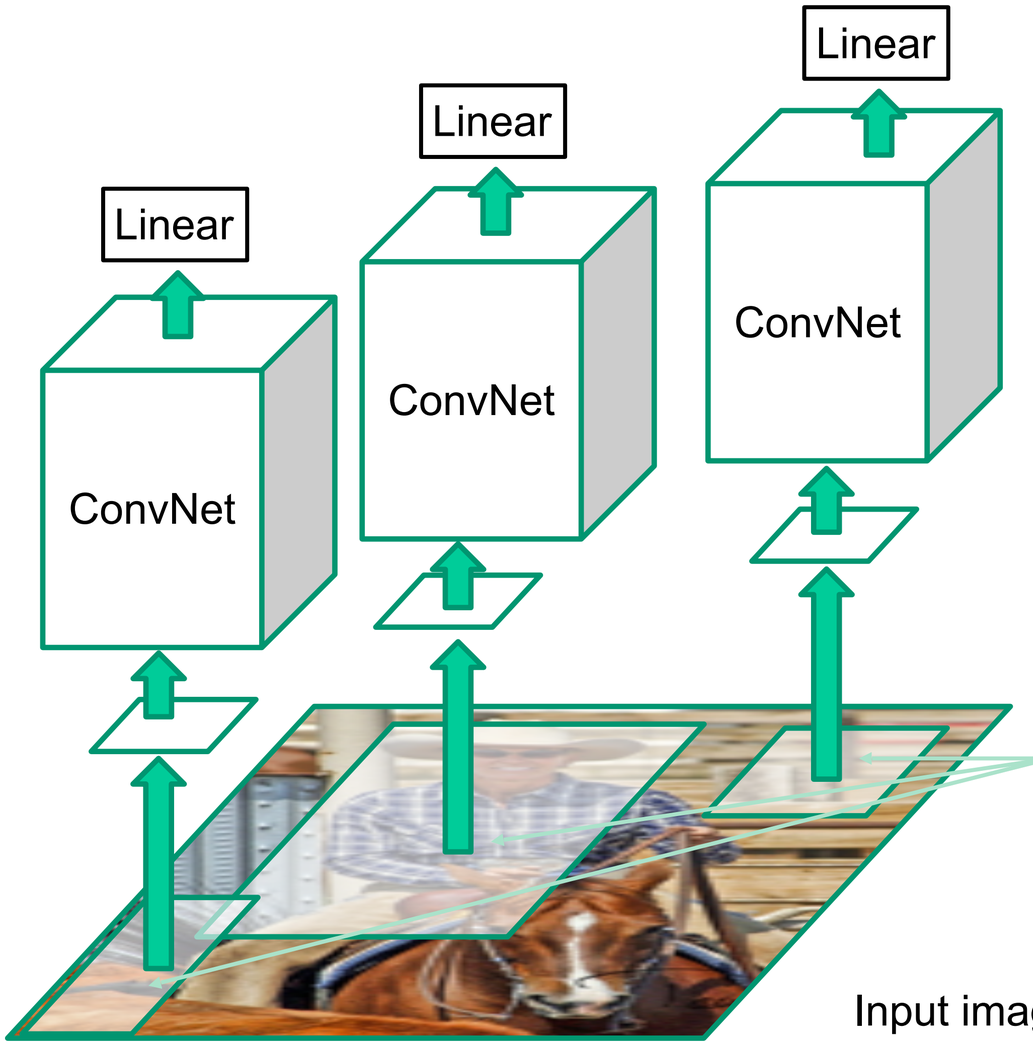
Stage 2: apply classifier only to each candidate bounding box



Source: Torralba, Freeman, Isola

[Uijlings et al., "Selective Search for Object Recognition", 2013]

R-CNN: Region proposals + CNN features



Classify regions with linear classifier

Forward each region through ConvNet

Warped image regions

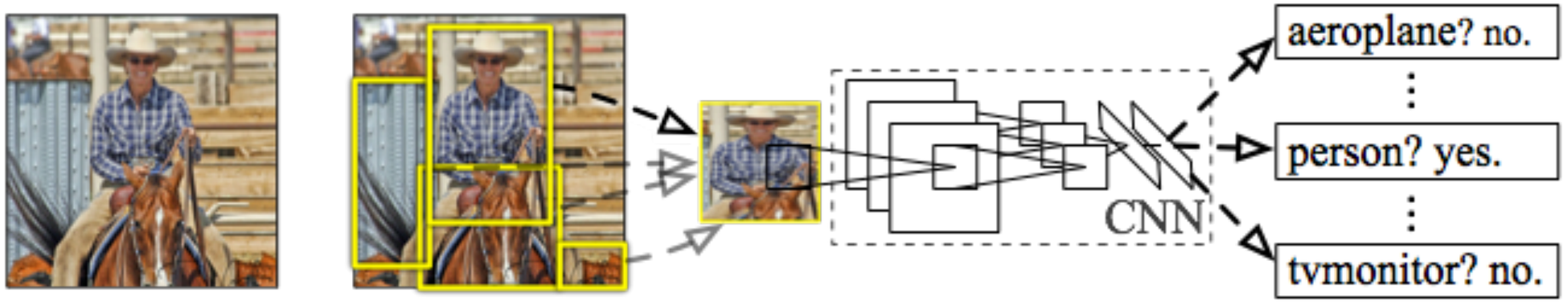
Region proposals from **selective search** (~2K rectangles that are likely to contain objects)

Input image

R. Girshick, J. Donahue, T. Darrell, and J. Malik, [Rich Feature Hierarchies for Accurate Object Detection and Semantic Segmentation](), CVPR 2014.

Source: R. Girshick

R-CNN at test time



Input image

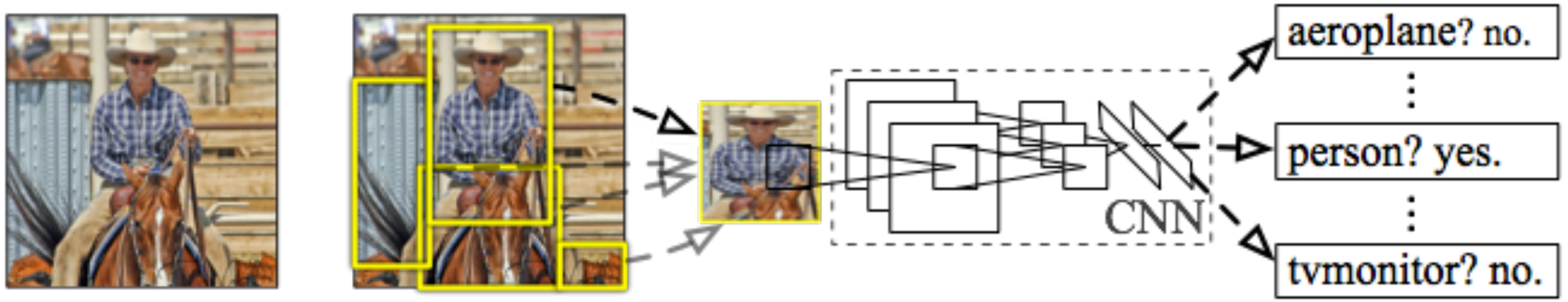
Extract region proposals (~2k / image)

Compute CNN features

a. Crop

Source: R. Girshick

R-CNN at test time



Input image

Extract region proposals (~2k / image)

Compute CNN features

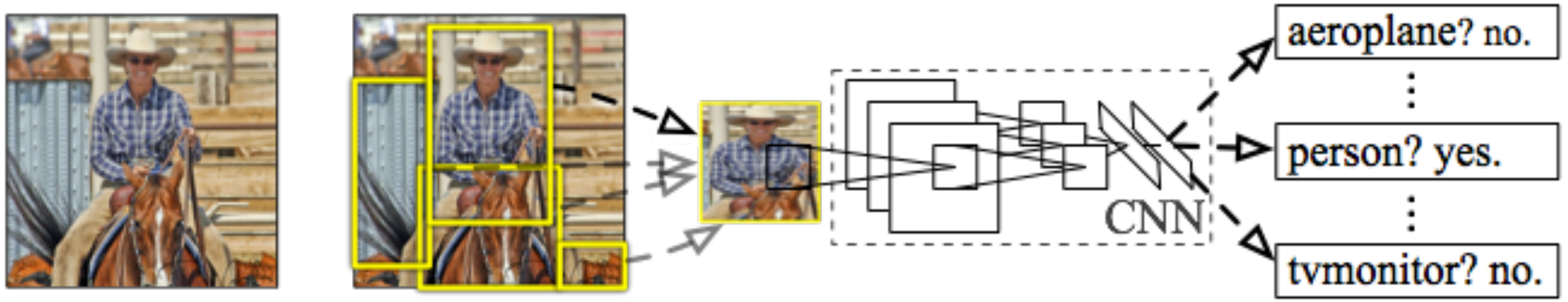
a. Crop

227 x 227

b. Scale (anisotropic)

Source: R. Girshick

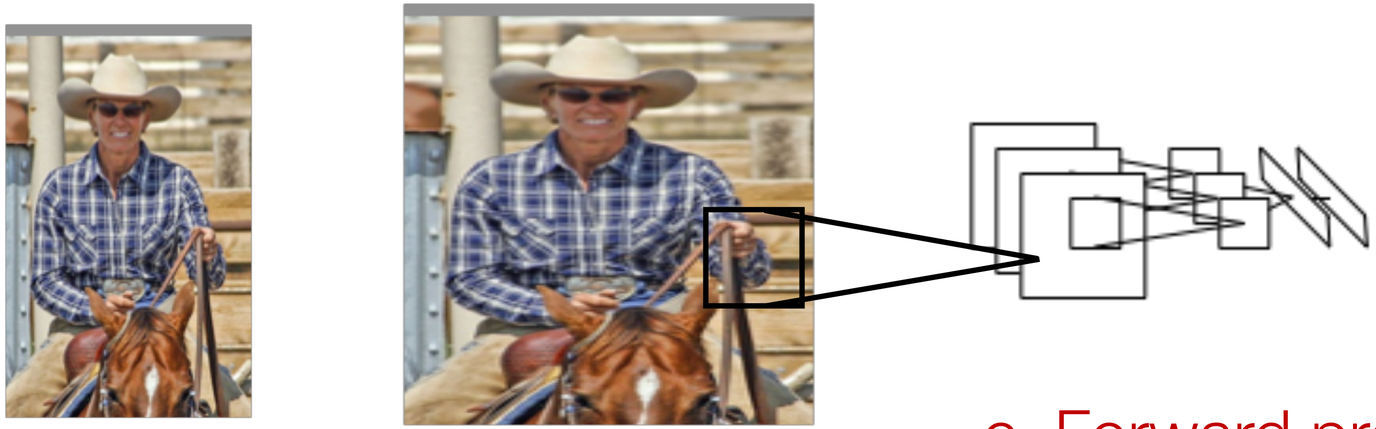
R-CNN at test time



Input image

Extract region proposals (~2k / image)

Compute CNN features



1. Crop

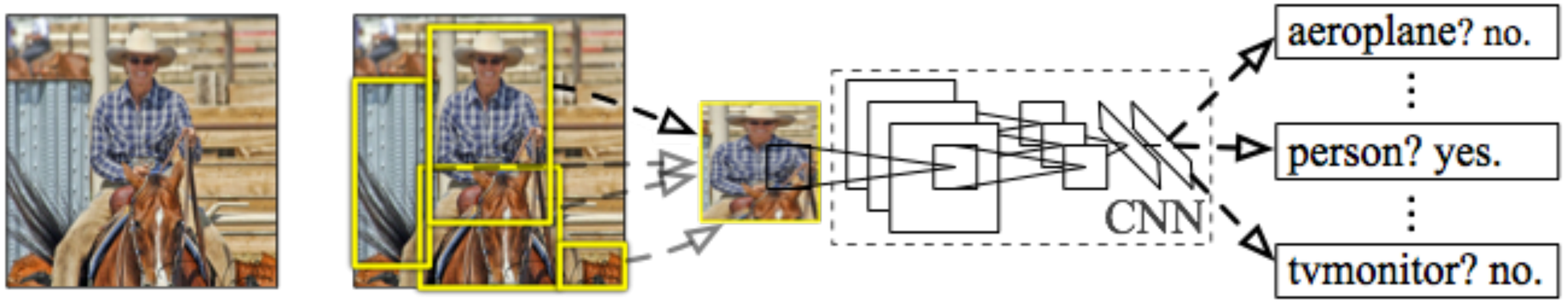
b. Scale (anisotropic)

c. Forward propagate

Output: "fc_7" features

Source: R. Girshick

R-CNN at test time

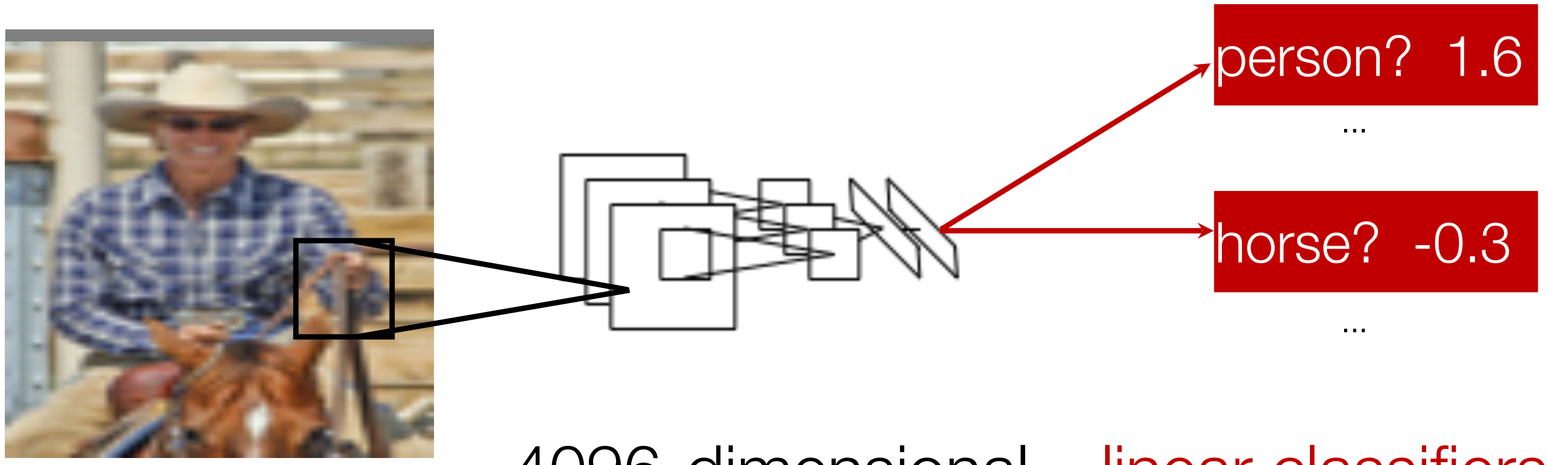


Input image

Extract region proposals (~2k / image)

Compute CNN features

Classify regions



Warped proposal

4096-dimensional fc_7 feature vector

linear classifiers (SVM or softmax)

Source: R. Girshick

R-CNN at test time: proposal refinement

Linear regression

on CNN features

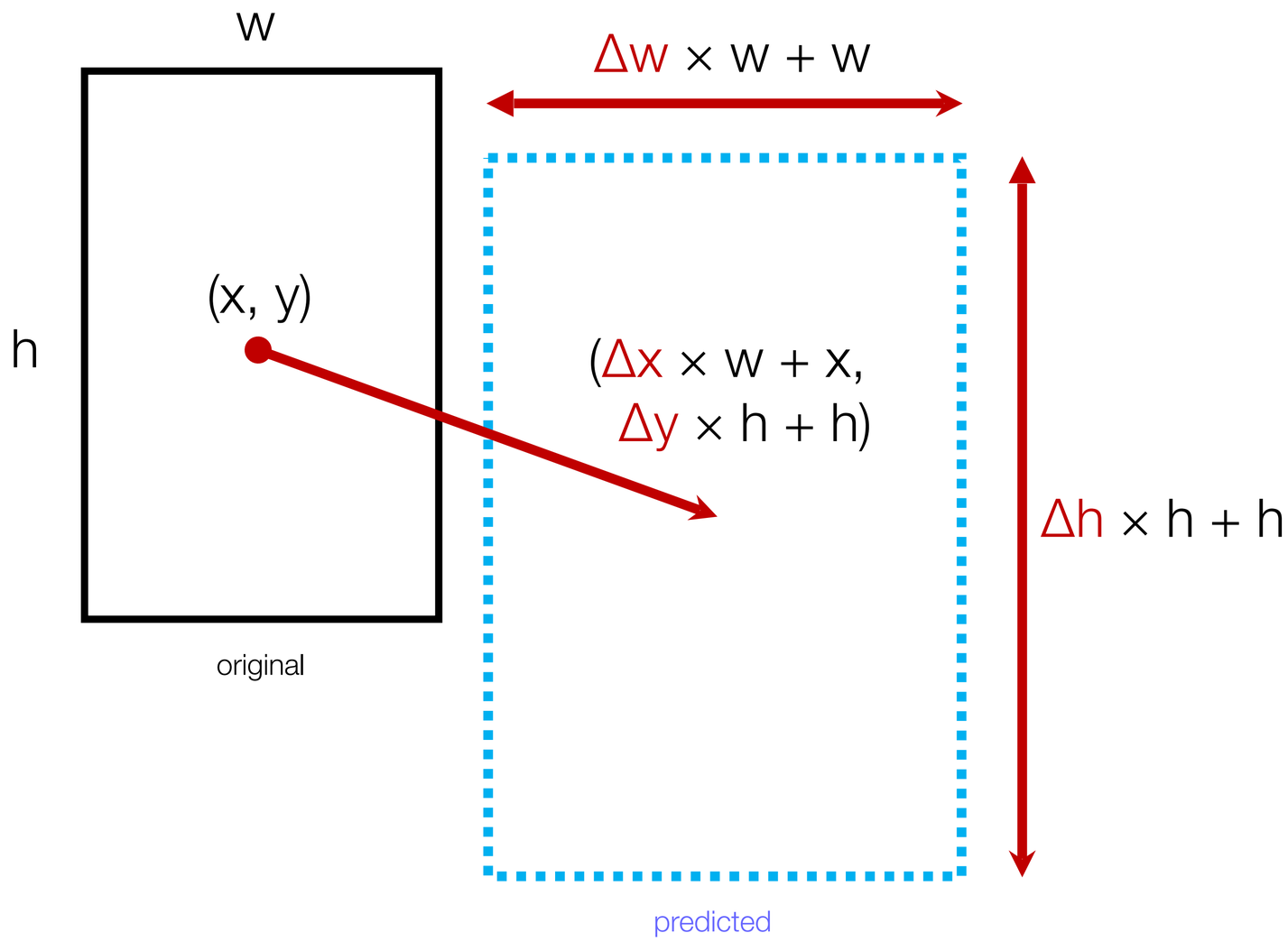
Original proposal

Predicted object bounding box

Bounding-box regression

Source: R. Girshick

Bounding-box regression



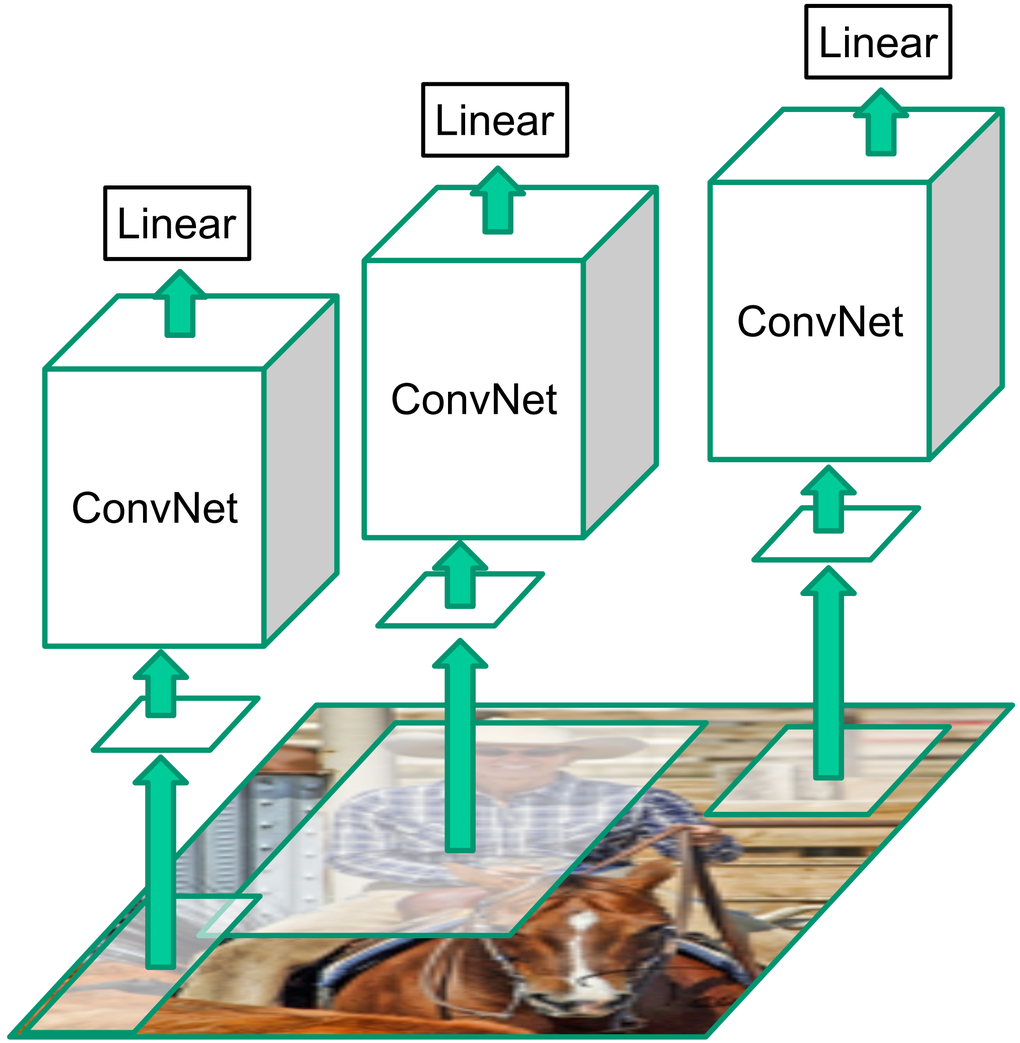
Source: R. Girshick

Non-maximum suppression

If two boxes overlap significantly (e.g. > 50% IoU), drop the one with the lower score. Usually use greedy algorithm.

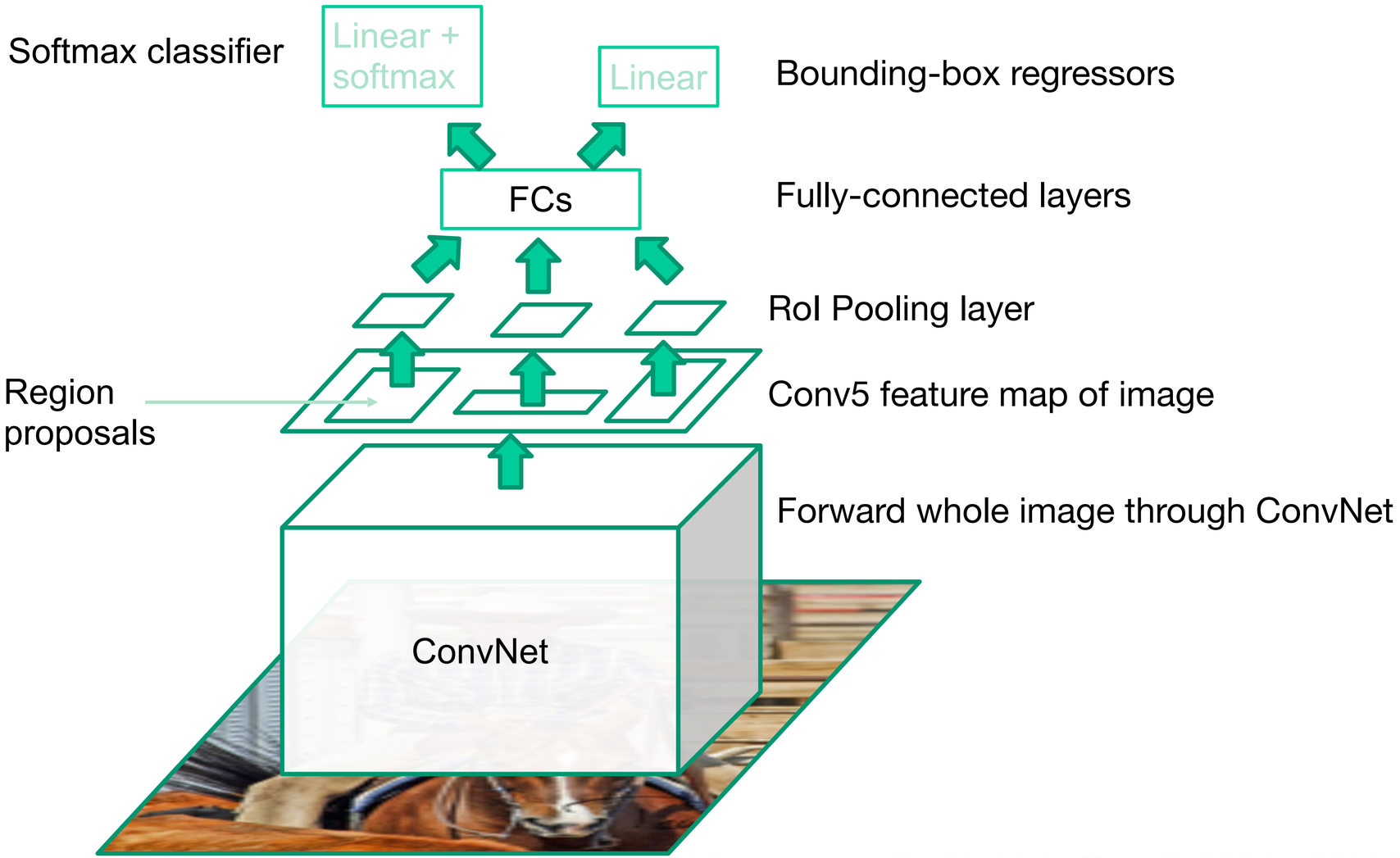
Source: B. Hariharan

Problems with R-CNN



1. Slow! Have to run CNN per window
2. Hand-crafted mechanism for region proposal might be suboptimal.

“Fast” R-CNN: reuse features between proposals

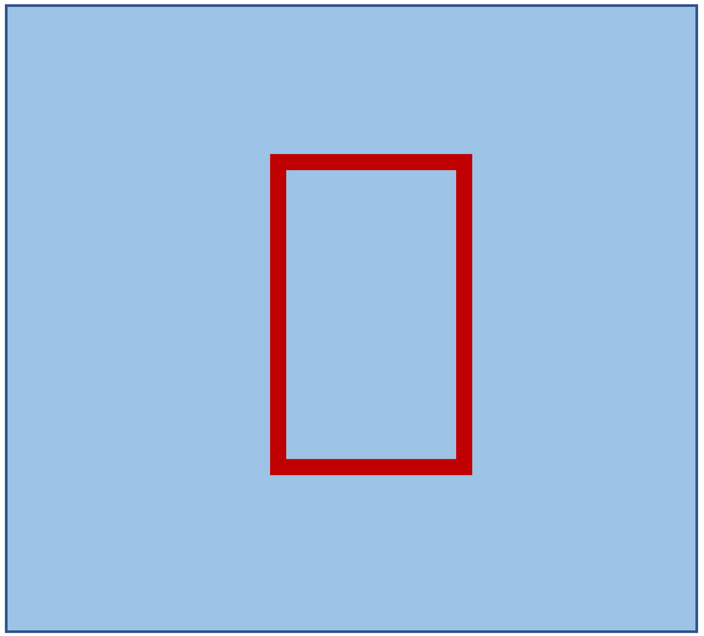


Source: R. Girshick

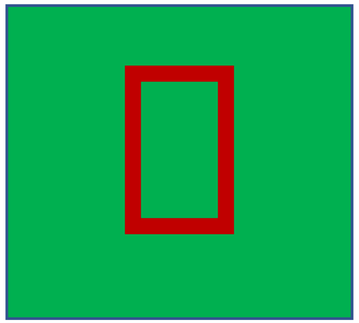
R. Girshick, Fast R-CNN, ICCV 2015

ROI Pooling

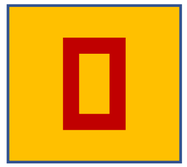
- How do we crop from a feature map?
- Step 1: Resize boxes to account for subsampling



Layer 1



Layer 2

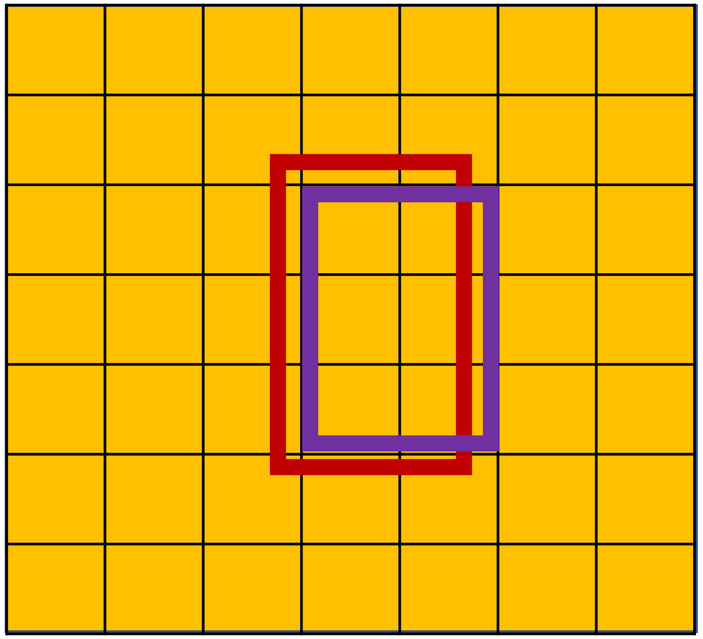


Layer 3

Source: B. Hariharan

ROI Pooling

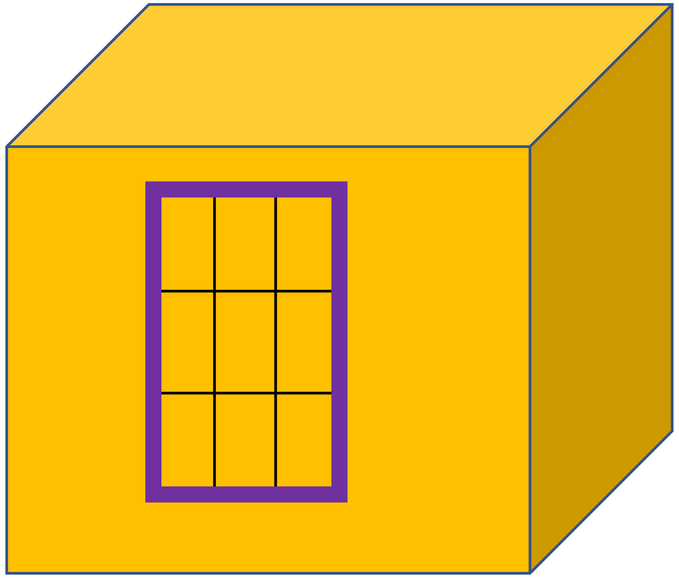
- How do we crop from a feature map?
- Step 2: Snap to feature map grid



Source: B. Hariharan

ROI Pooling

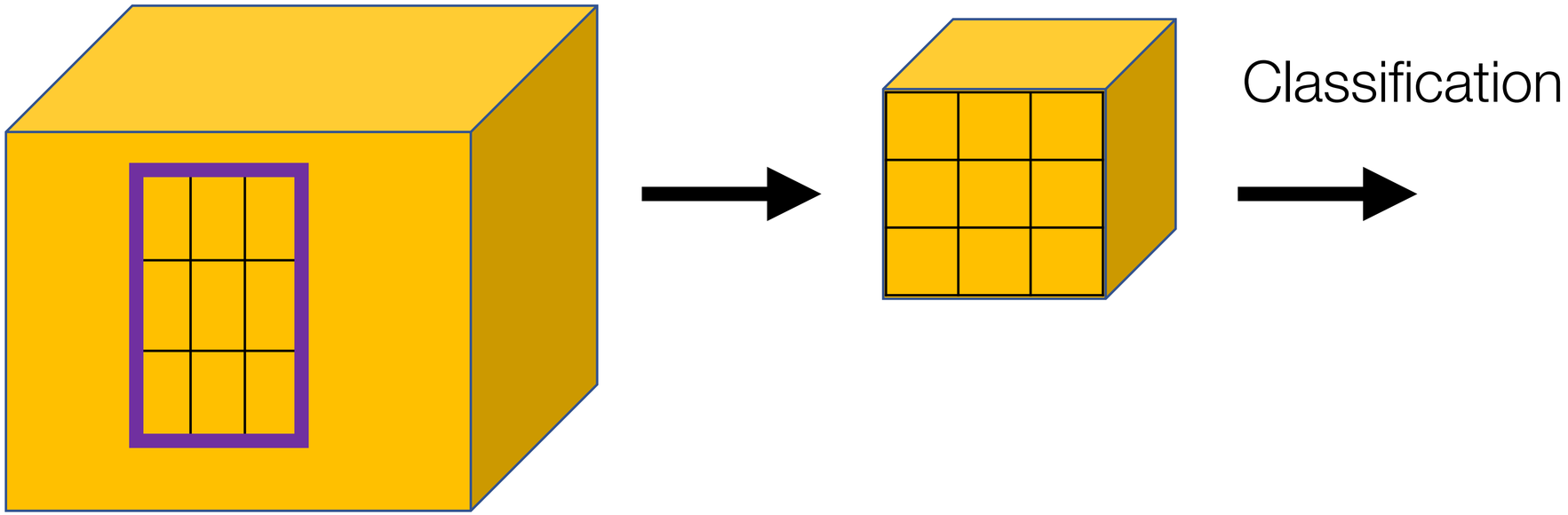
- How do we crop from a feature map?
- Step 3: Overlay a new grid of fixed size



Source: B. Hariharan

ROI Pooling

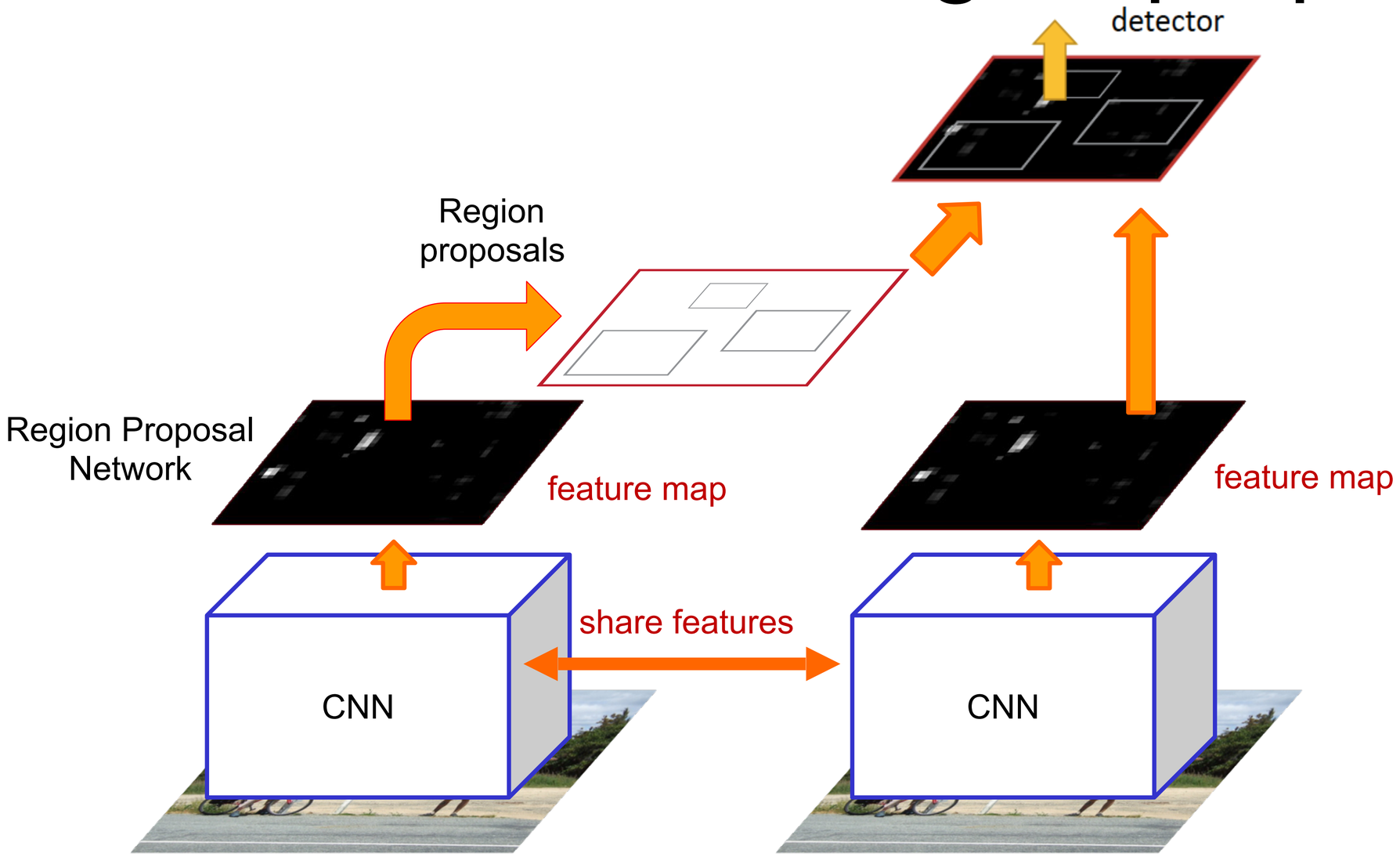
- How do we crop from a feature map?
- Step 4: Take max in each cell



See more here: https://deepsense.ai/region-of-interest-pooling-explained/

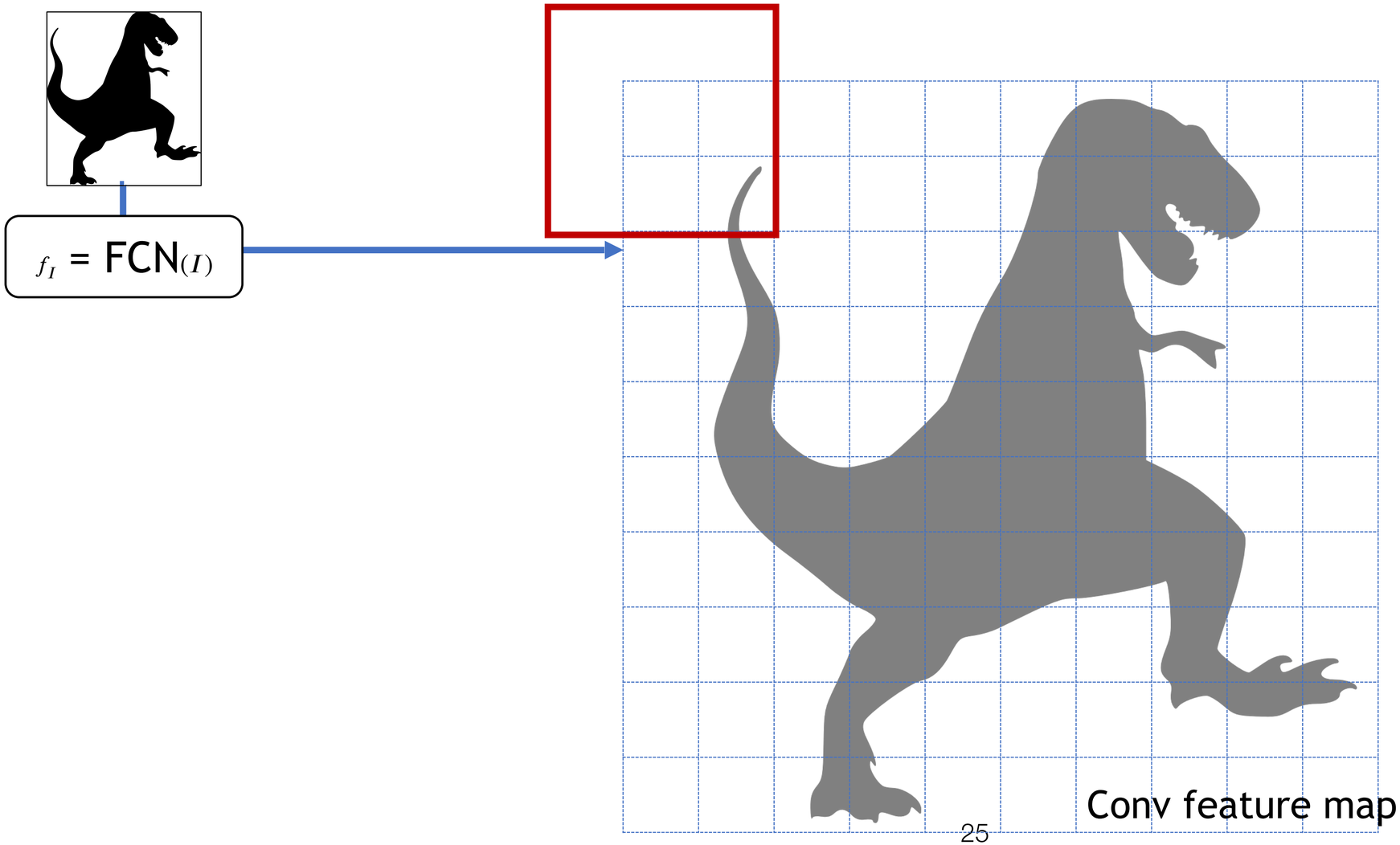
Source: B. Hariharan

“Faster” R-CNN: learn region proposals



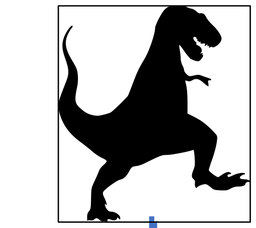
S. Ren, K. He, R. Girshick, and J. Sun, Faster R-CNN: Towards Real-Time Object Detection with Region Proposal Networks, NIPS 2015

RPN: Region Proposal Network

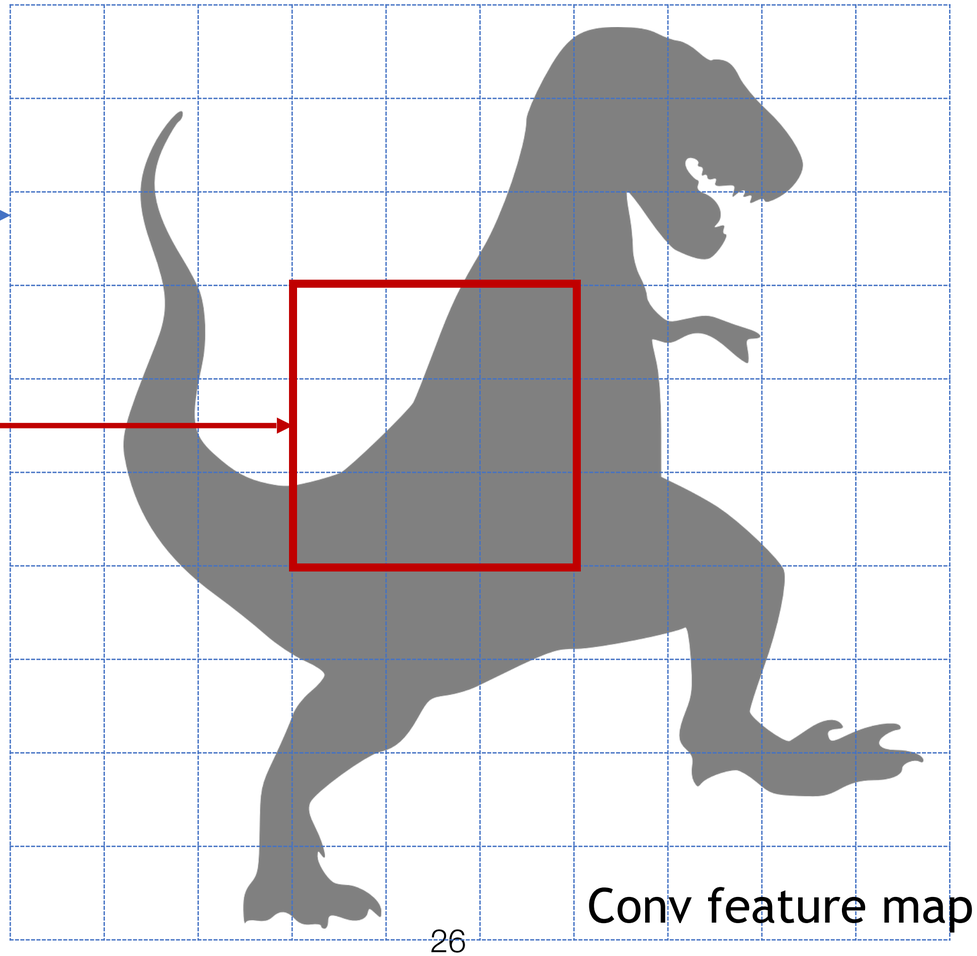


Source: R. Girshick

RPN: Region Proposal Network



f_I = FCN(I)



3x3 “sliding window”

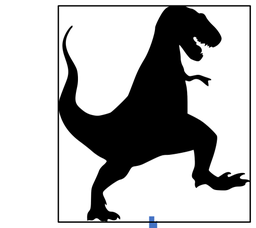
Scans the feature map looking for objects

Conv feature map

Source: R. Girshick

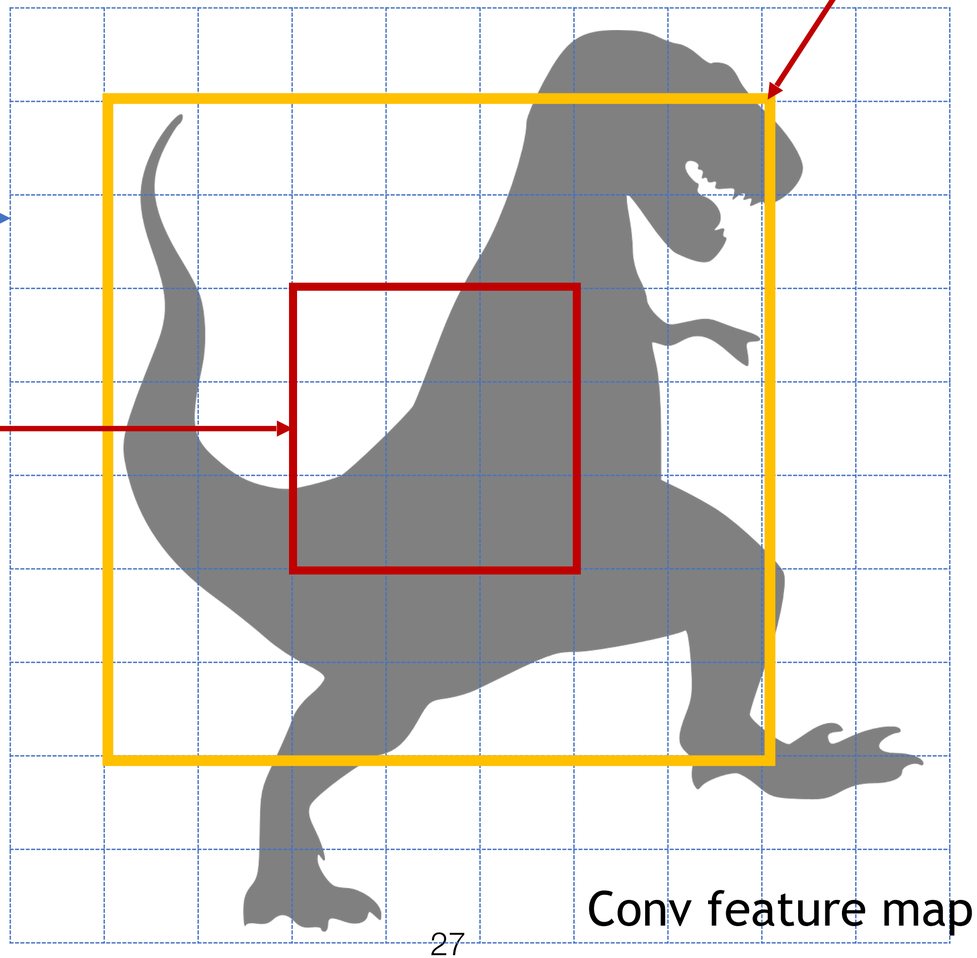
RPN: Anchor Box

Anchor box: predictions are w.r.t. this box, *not the 3x3 sliding window*



f_I = FCN(I)

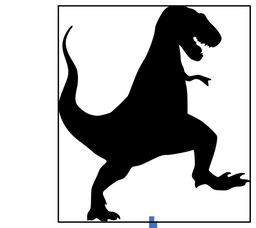
3x3 “sliding window”
Scans the feature map looking for objects



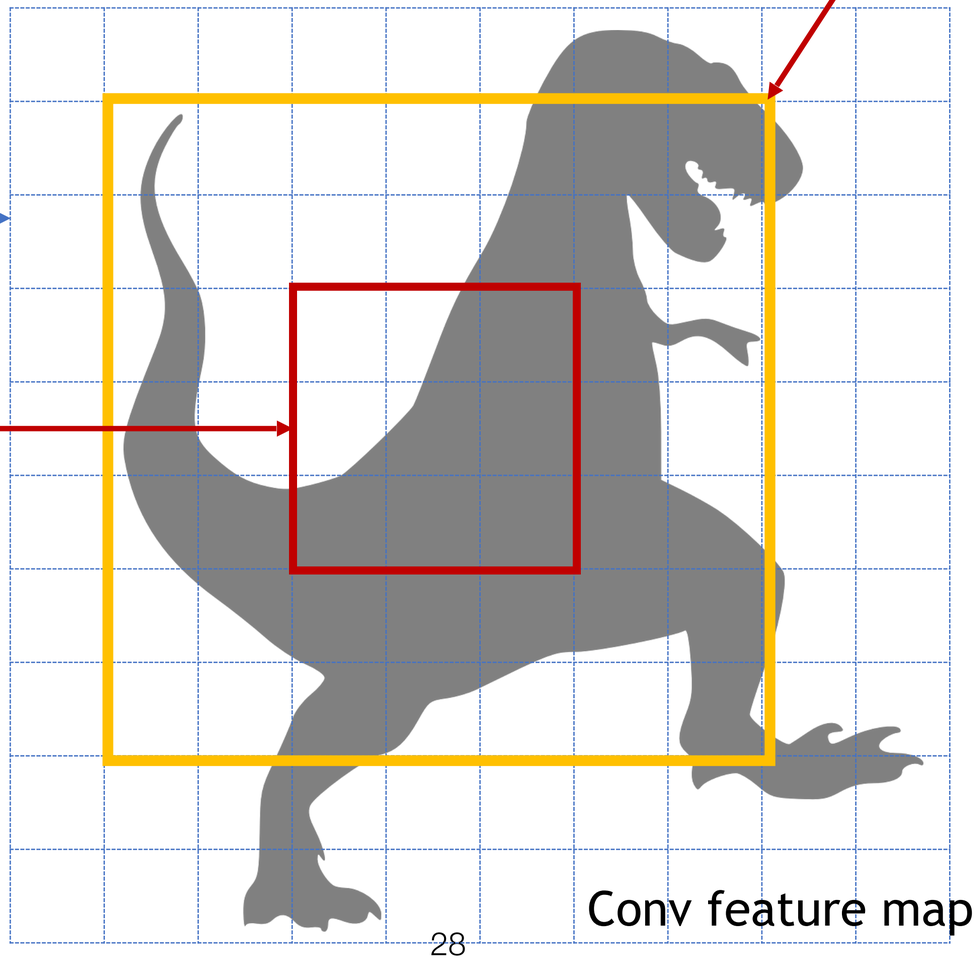
Conv feature map

Source: R. Girshick

RPN: Anchor Box



f_I = FCN(I)



Conv feature map

Anchor box: predictions are w.r.t. this box, *not the 3x3 sliding window*

3x3 “sliding window”

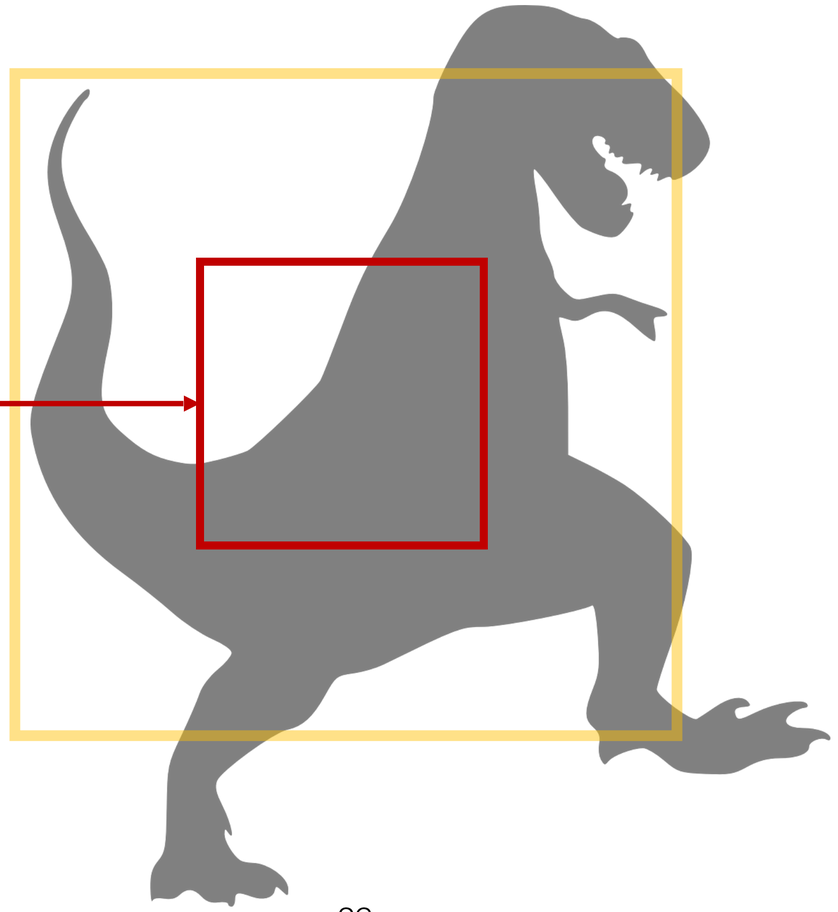
- Objectness classifier [0, 1]
- Box regressor predicting (dx, dy, dh, dw)

Source: R. Girshick

RPN: Prediction (on object)

Objectness score

P(object) = 0.94



3x3 “sliding window”

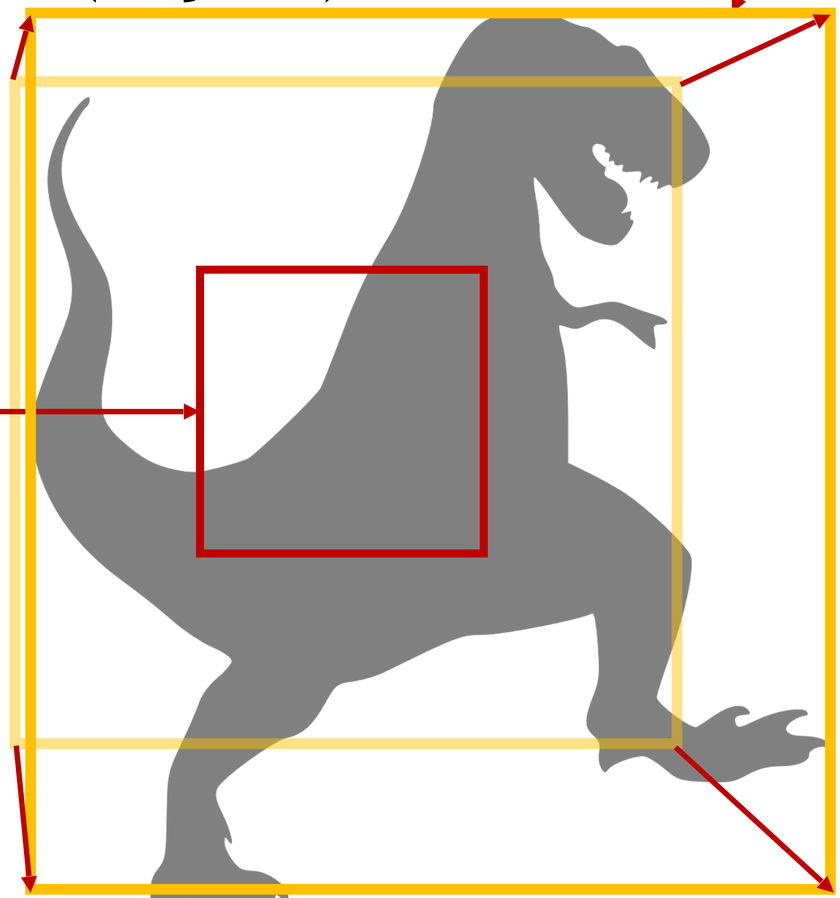
- Objectness classifier [0, 1]
- Box regressor predicting (dx, dy, dh, dw)

Source: R. Girshick

RPN: Prediction (on object)

Anchor box: transformed by box regressor

P(object) = 0.94



3x3 “sliding window”

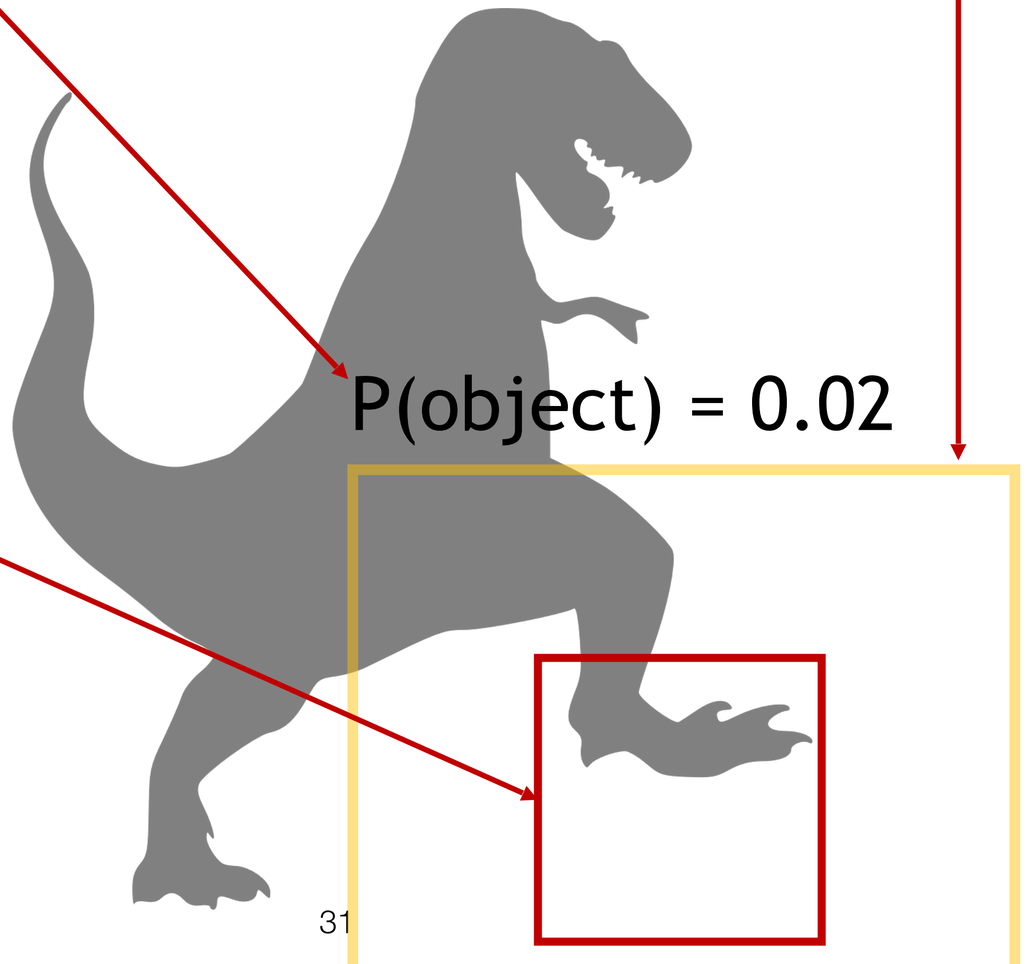
- Objectness classifier [0, 1]
- Box regressor predicting (dx, dy, dh, dw)

Source: R. Girshick

RPN: Prediction (off object)

Anchor box: transformed by box regressor

Objectness score

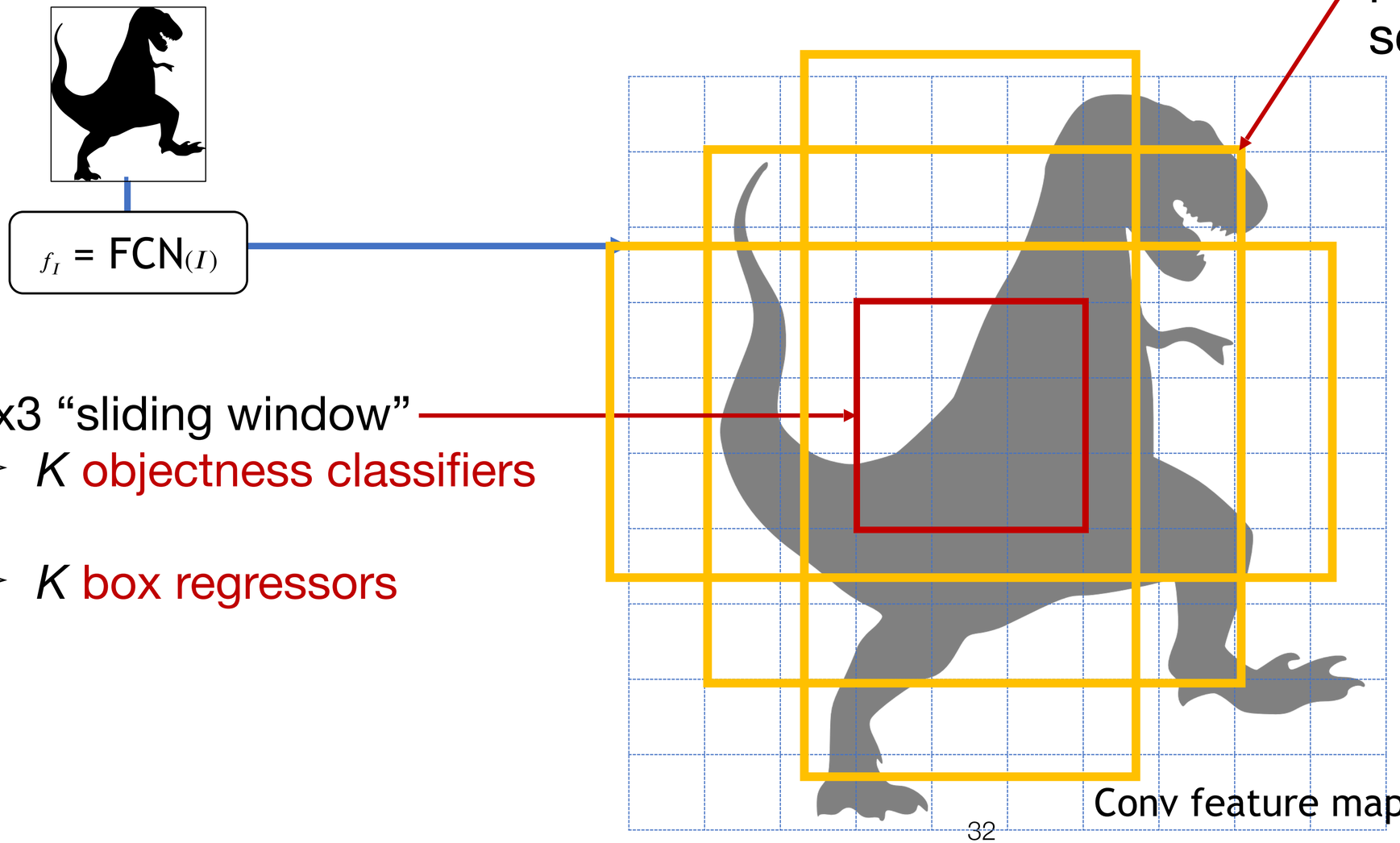


3x3 “sliding window”

- Objectness classifier
- Box regressor predicting (dx, dy, dh, dw)

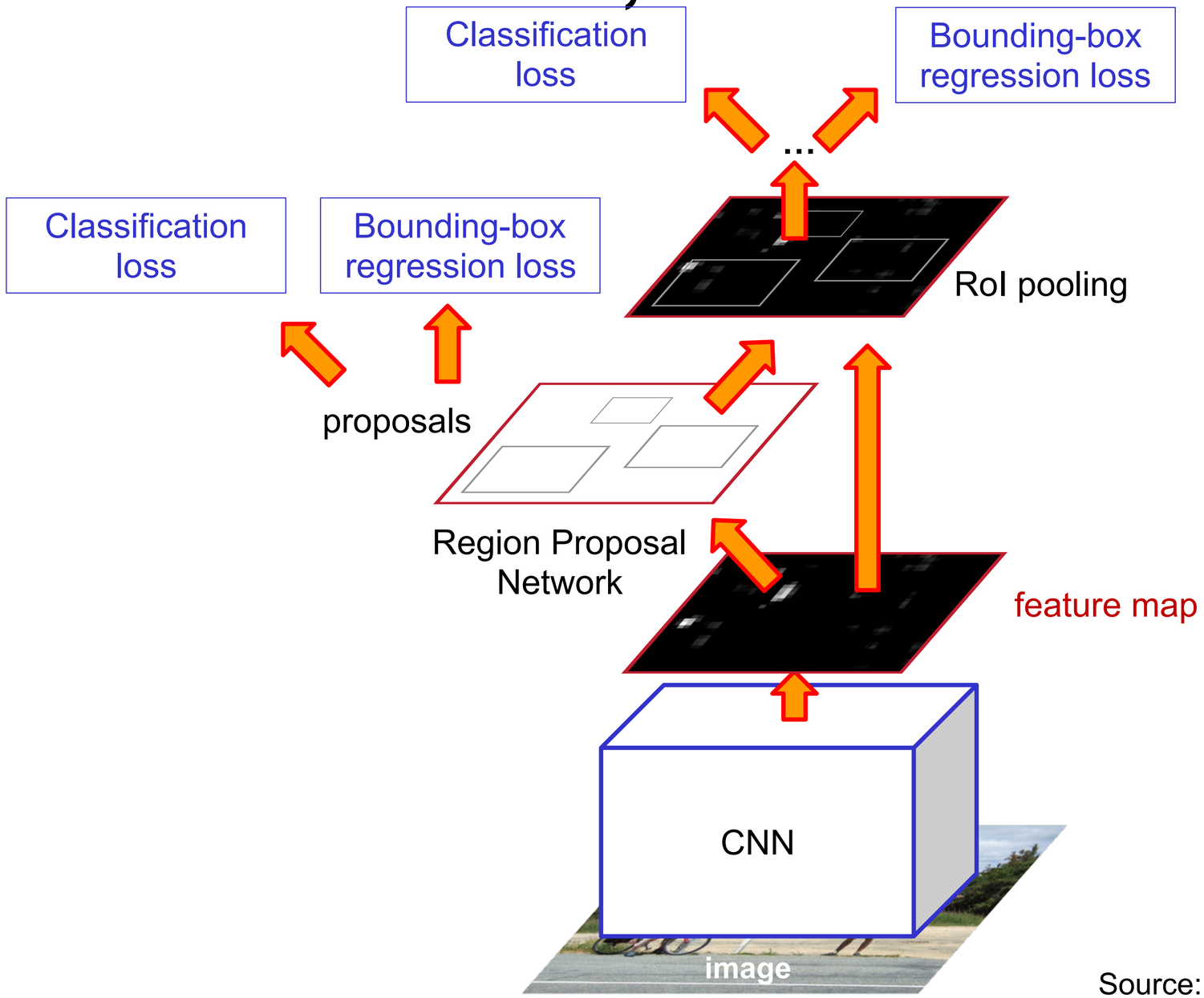
Source: R. Girshick

RPN: Multiple Anchors



Source: R. Girshick

One network, four losses



Source: R. Girshick, K. He, S. Lazebnik

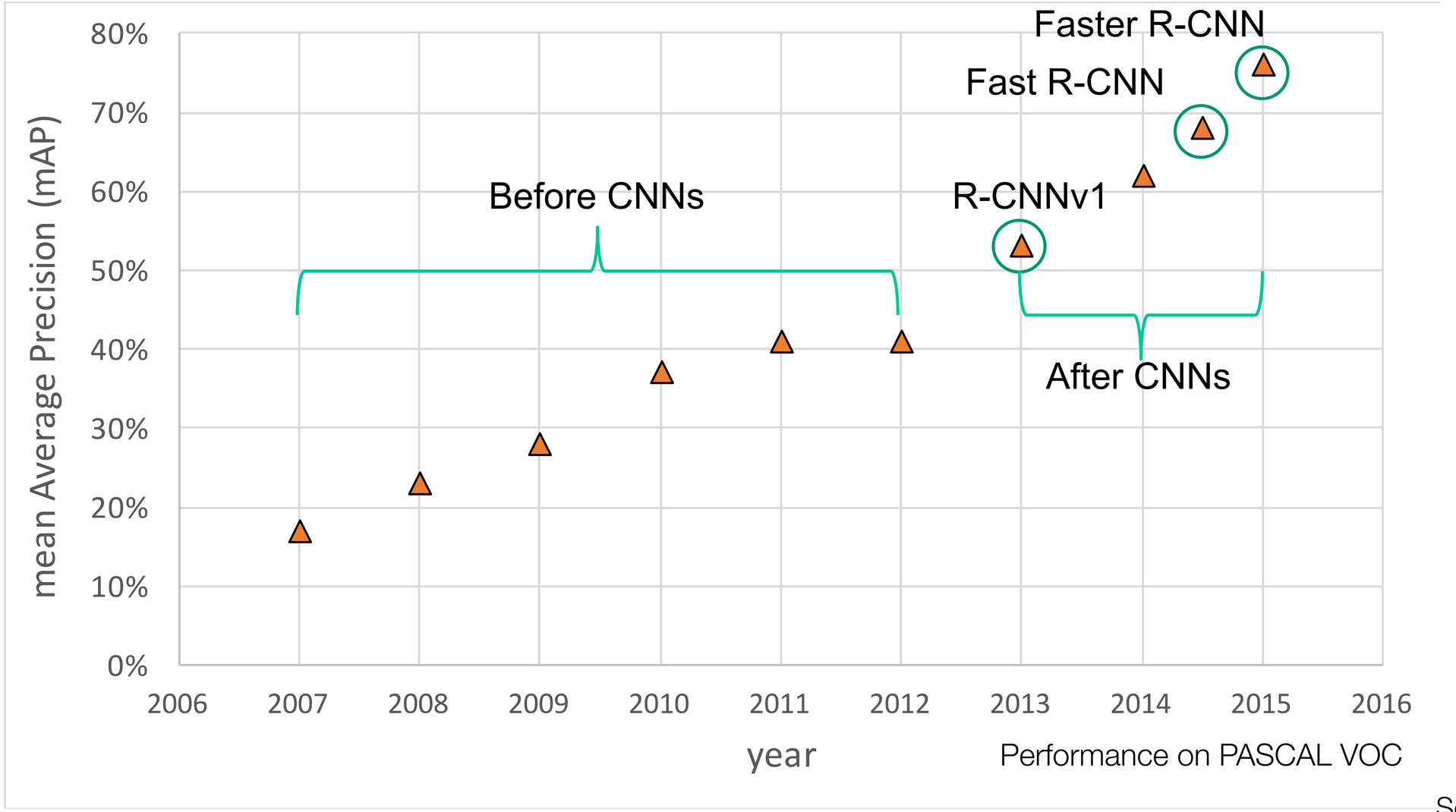
Faster R-CNN results

system	time	07 data	07+12 data
R-CNN	~50s	66.0	-
Fast R-CNN	~2s	66.9	70.0
Faster R-CNN	198ms	**69.9**	**73.2**

detection mAP on PASCAL VOC 2007, with VGG-16 pre-trained on ImageNet

Source: S. Lazebnik

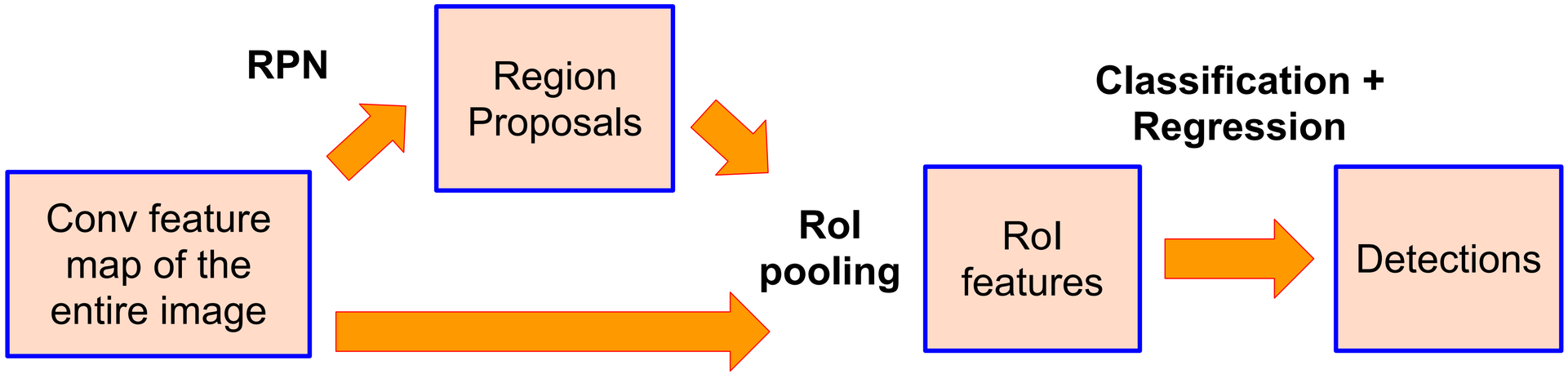
Object detection progress



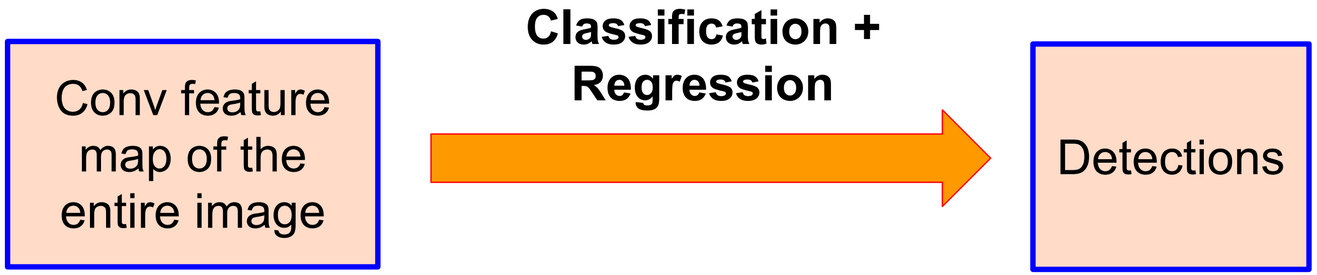
Source: S. Lazebnik

Streamlined detection architectures

- The Faster R-CNN pipeline separates proposal generation and region classification:



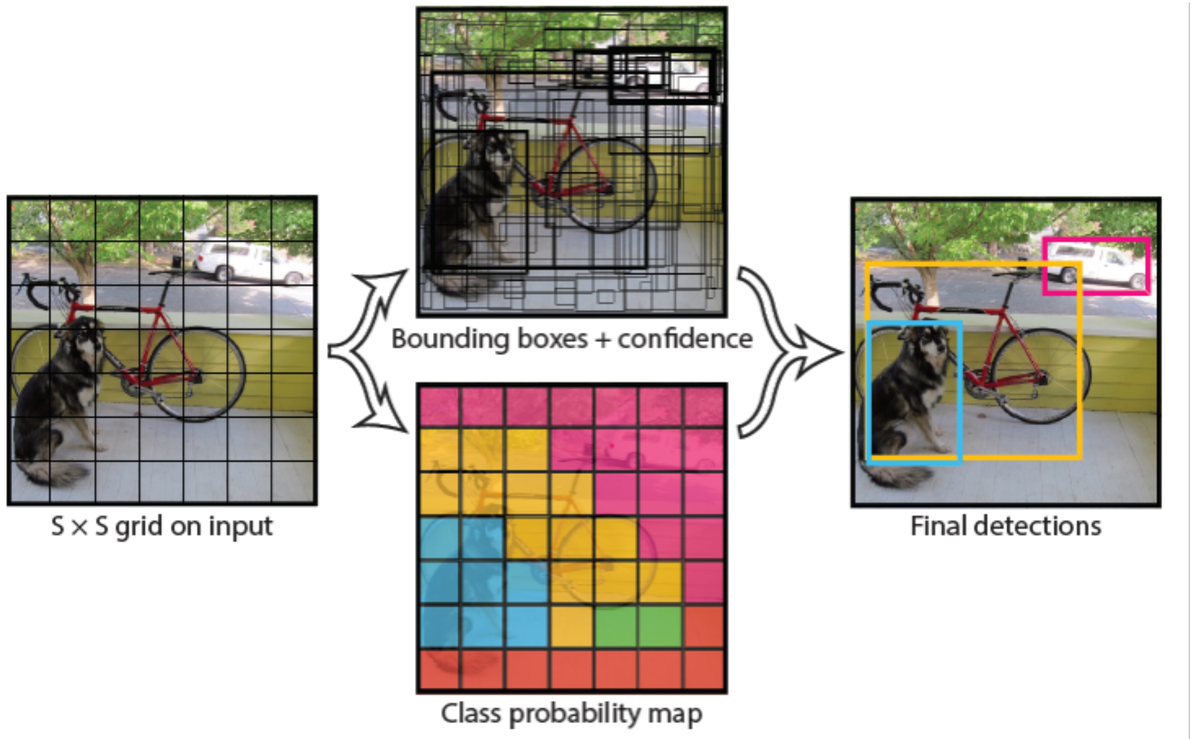
- Is it possible do detection in one shot?



Source: S. Lazebnik

Single-stage object detector

- Divide the image into a coarse grid and directly predict class label and a few candidate boxes for each grid cell



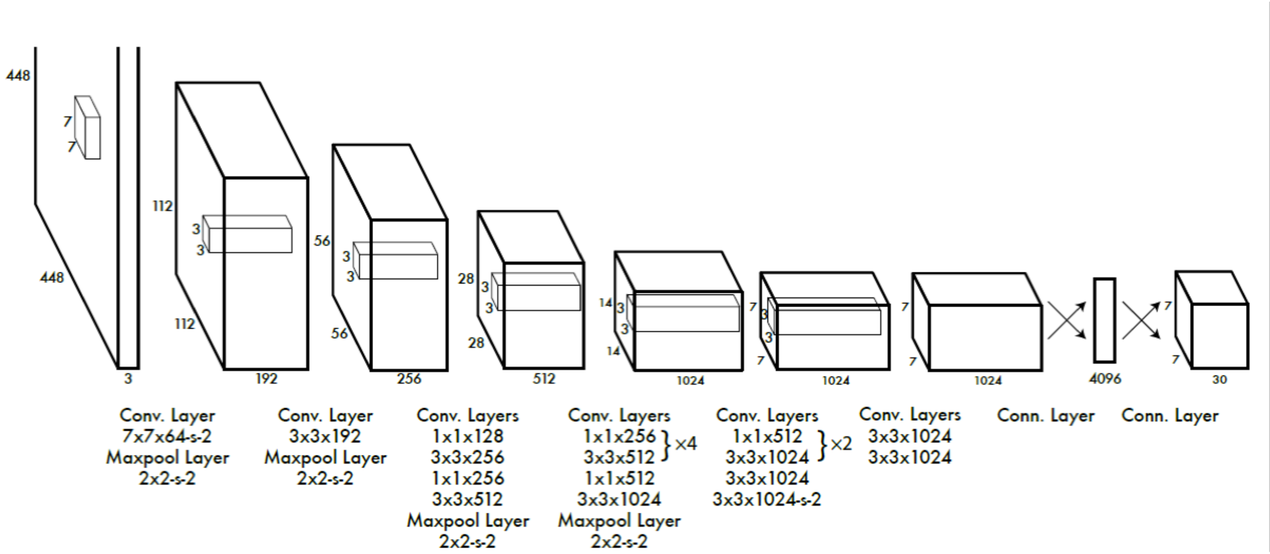
J. Redmon, S. Divvala, R. Girshick, and A. Farhadi, You Only Look Once: Unified, Real-Time Object Detection, CVPR 2016

Source: S. Lazebnik

YOLO detector

1. Take conv feature maps at 7x7 resolution
2. Predict, at each location, a score for each class and 2 bboxes w/ confidences
   - For PASCAL, output is 7x7x30 (30 = 20 + 2*(4+1))

- 7x speedup over Faster R-CNN (45-155 FPS vs. 7-18 FPS)
  but less accurate (e.g. 65% vs. 72 mAP%)



J. Redmon, S. Divvala, R. Girshick, and A. Farhadi, You Only Look Once: Unified, Real-Time Object Detection, CVPR 2016

Source: S. Lazebnik

Challenges in object detection

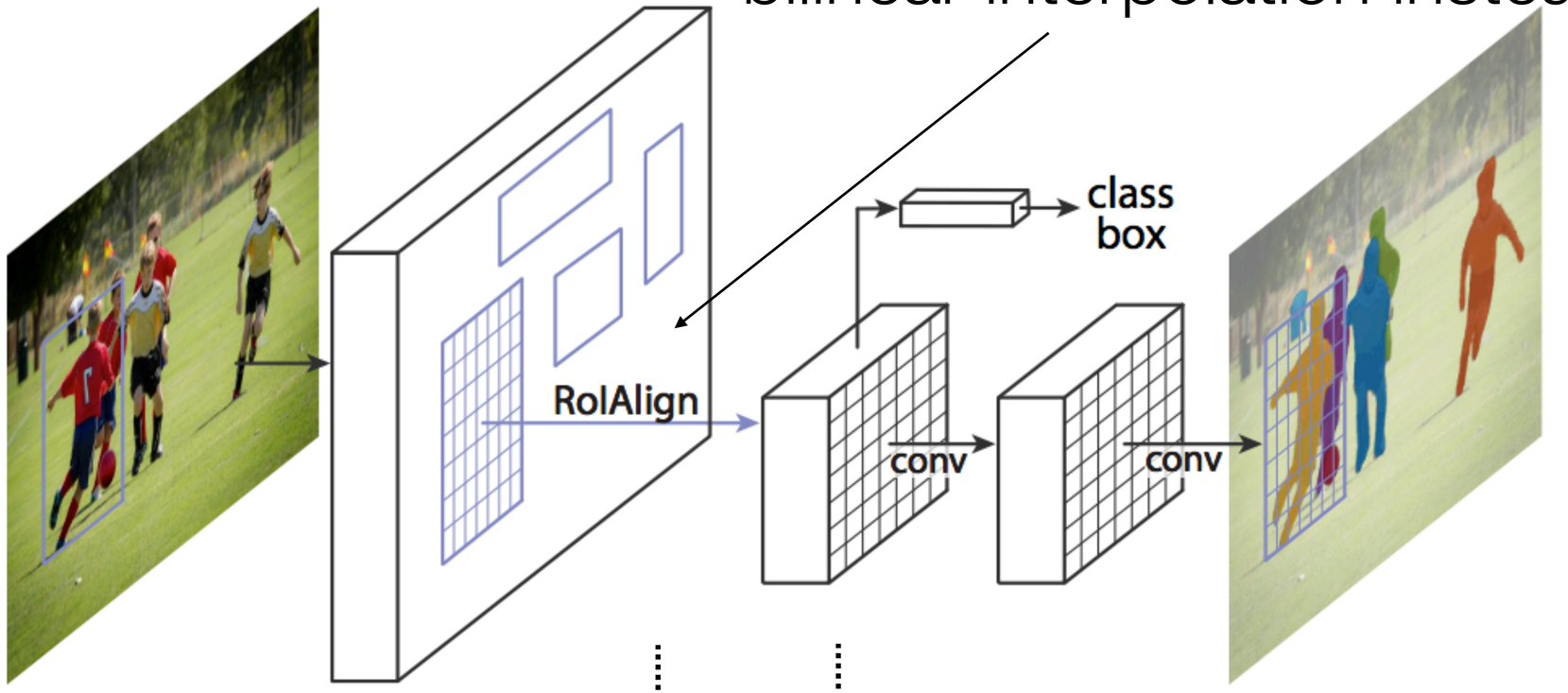
Beyond bounding boxes: instance segmentation

Predict segmentation mask for each object
From COCO [Lin et al., 2014]

Source: B. Hariharan

Instance segmentation

ROI pooling with tiny change:
bilinear interpolation instead of max



Faster R-CNN

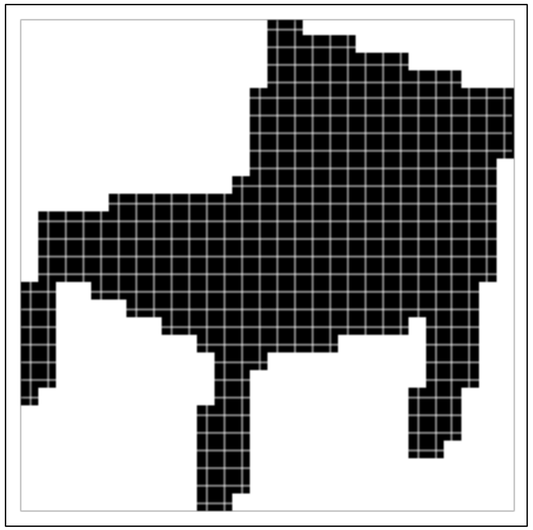
Extra “head” on network
predicts binary mask

[He et al., “Mask R-CNN”, 2017]

Example Mask Training Targets

Image with training proposal

28x28 mask target

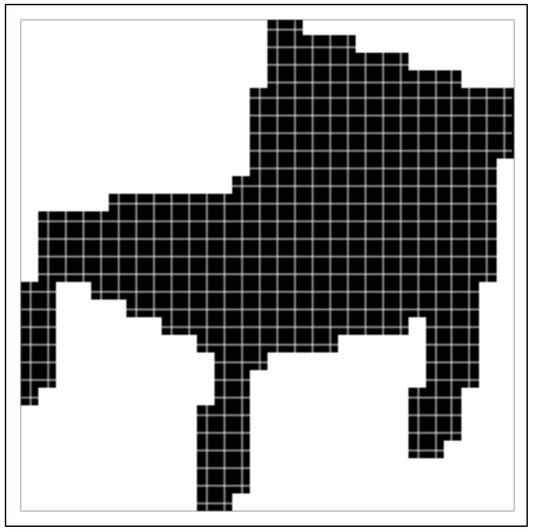


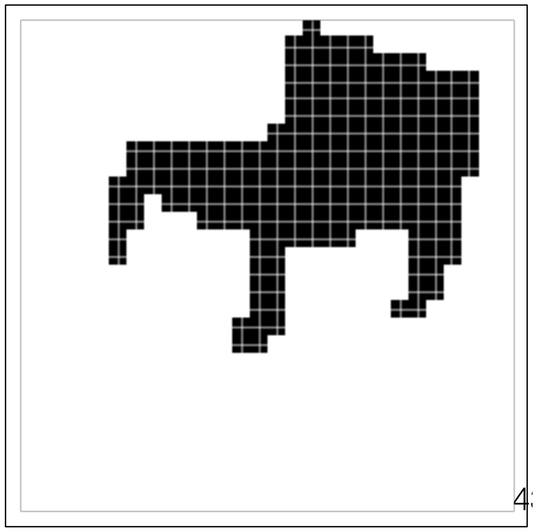
Source: R. Girshick

Example Mask Training Targets

Image with training proposal

28x28 mask target





Source: R. Girshick

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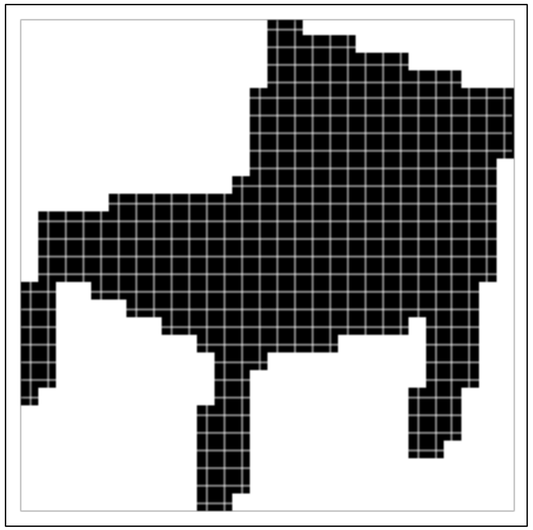
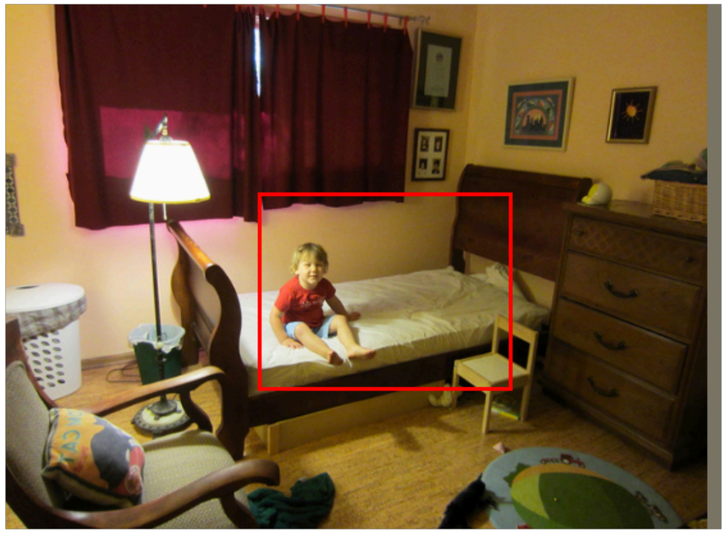
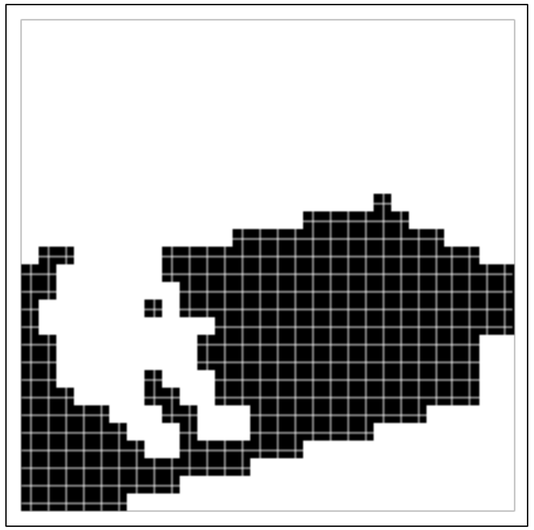
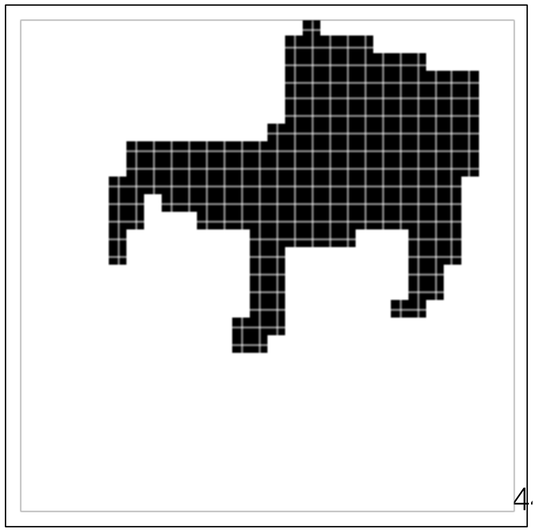


Image with training proposal



28x28 mask target





Source: R. Girshick

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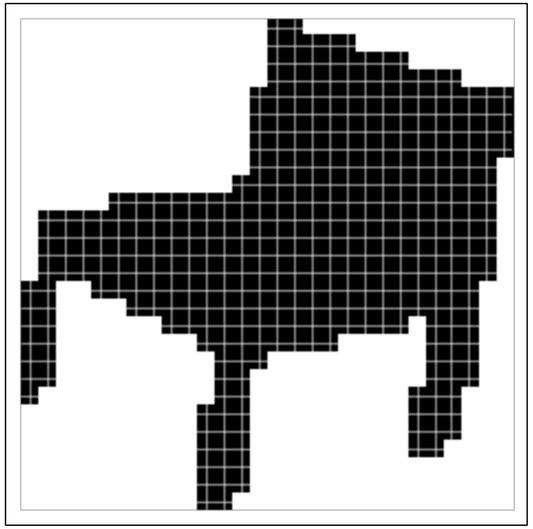
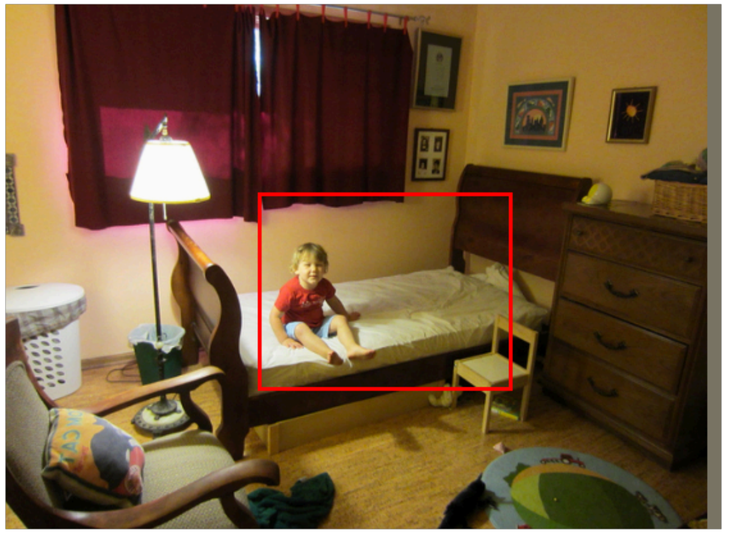
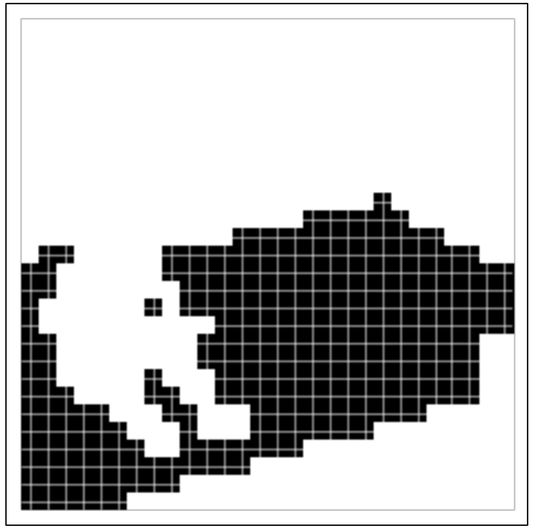
28x28 mask target

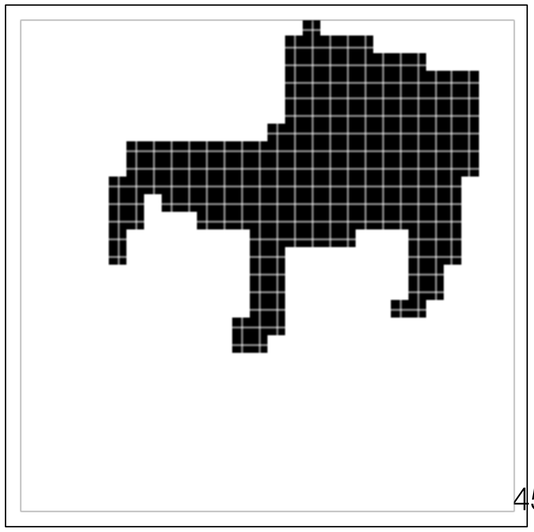
Image with training proposal

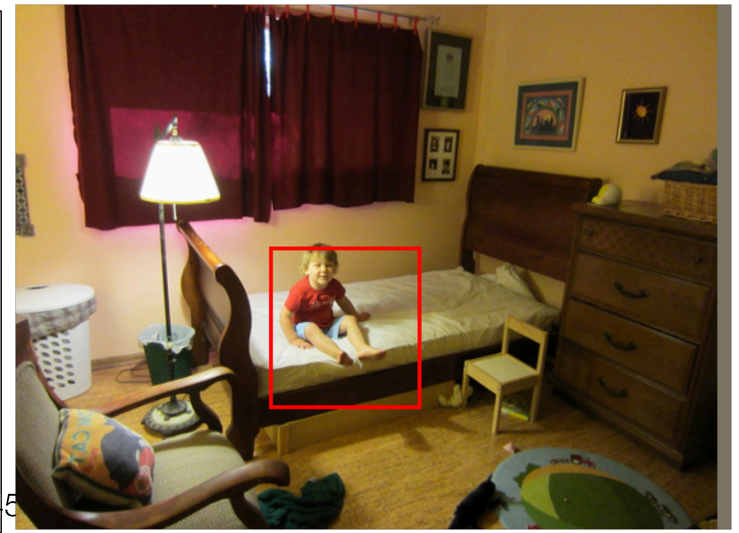
28x28 mask target

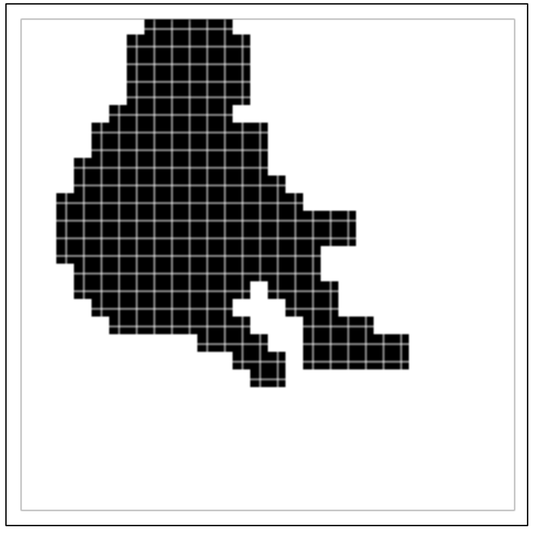


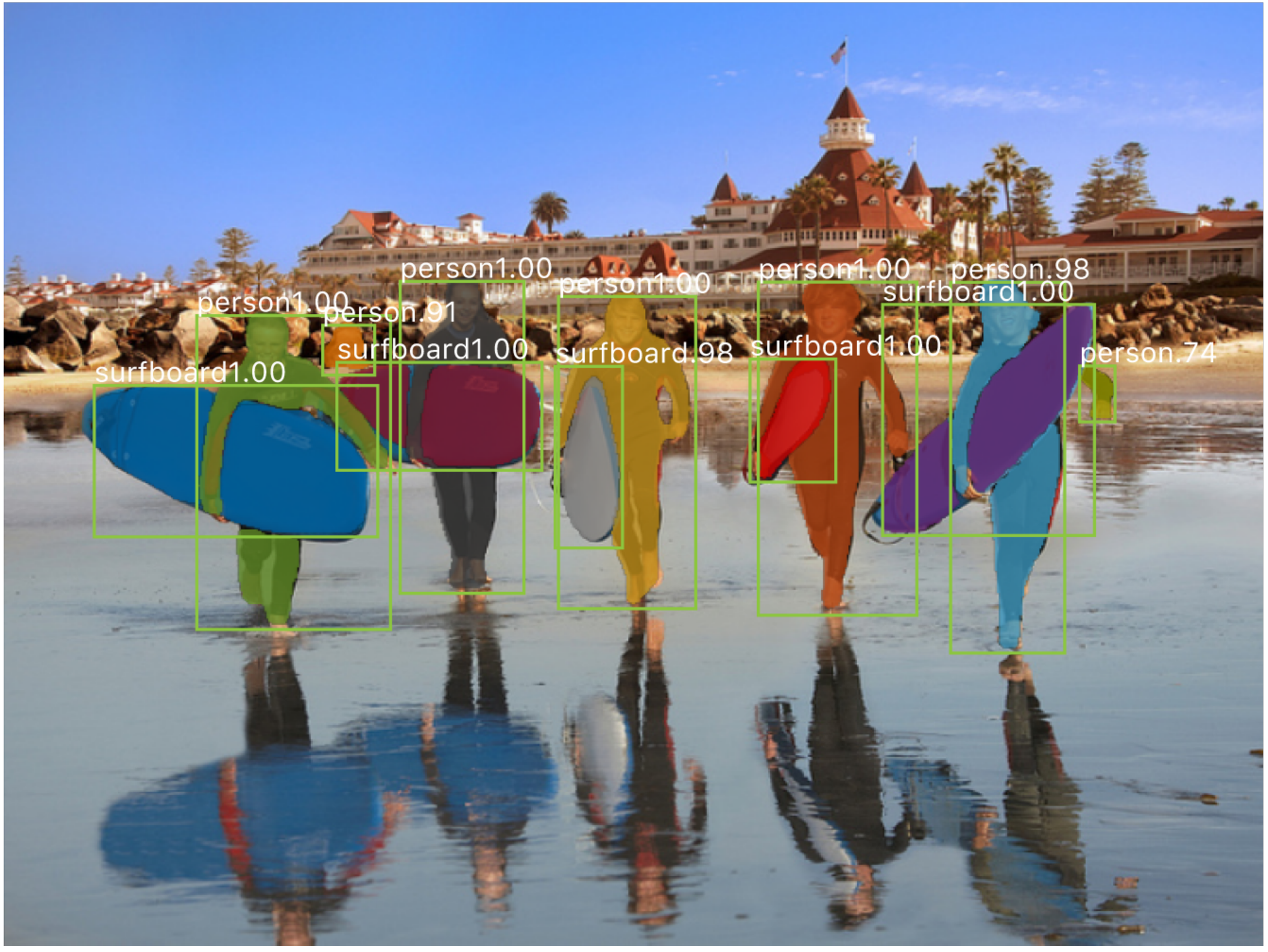








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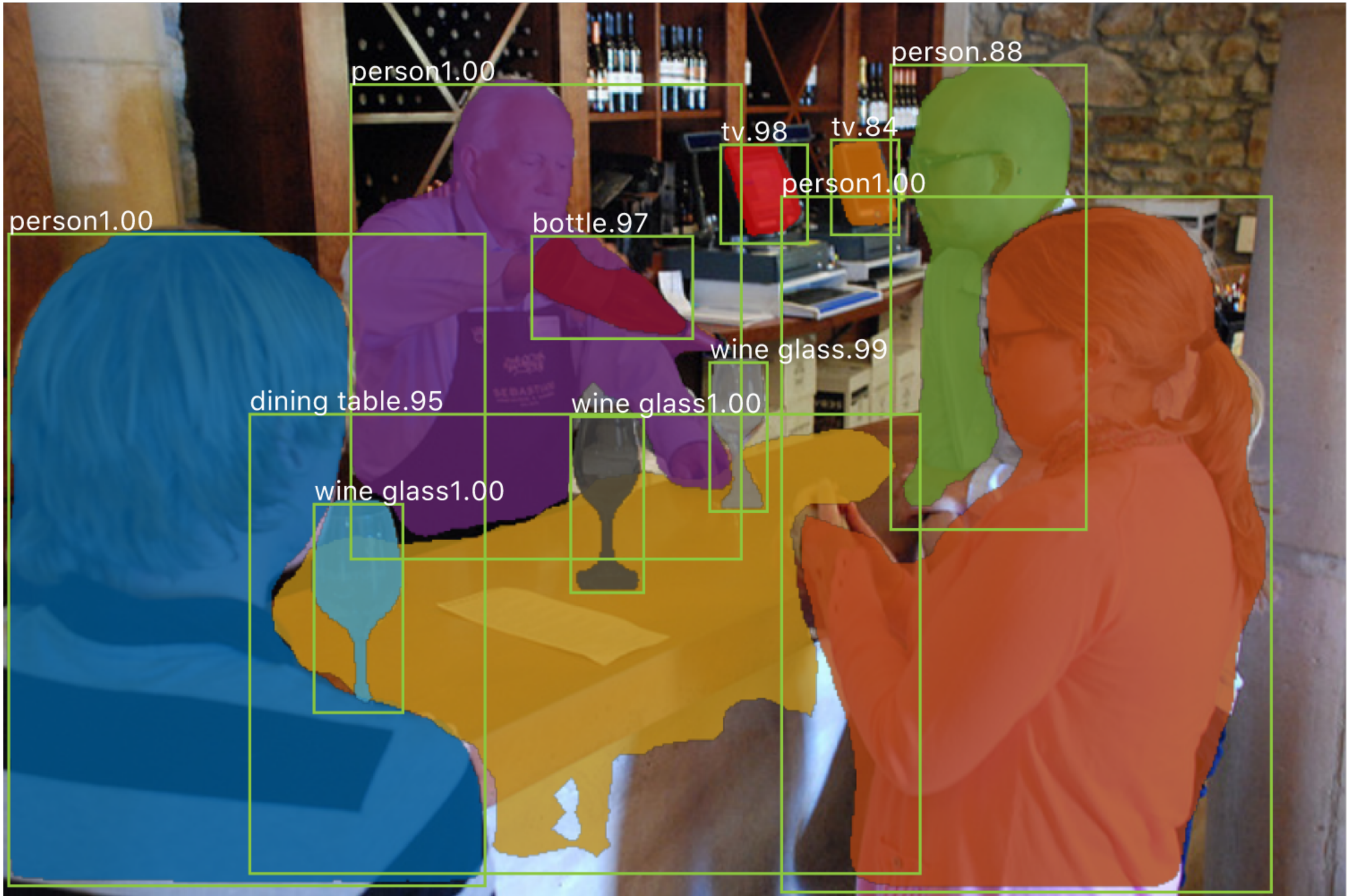
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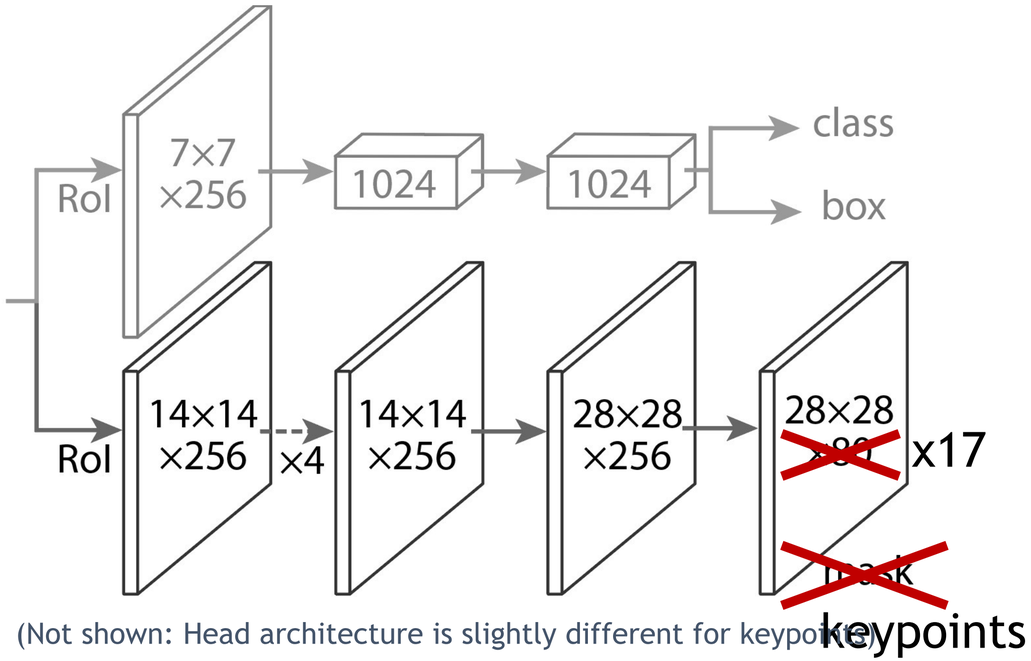
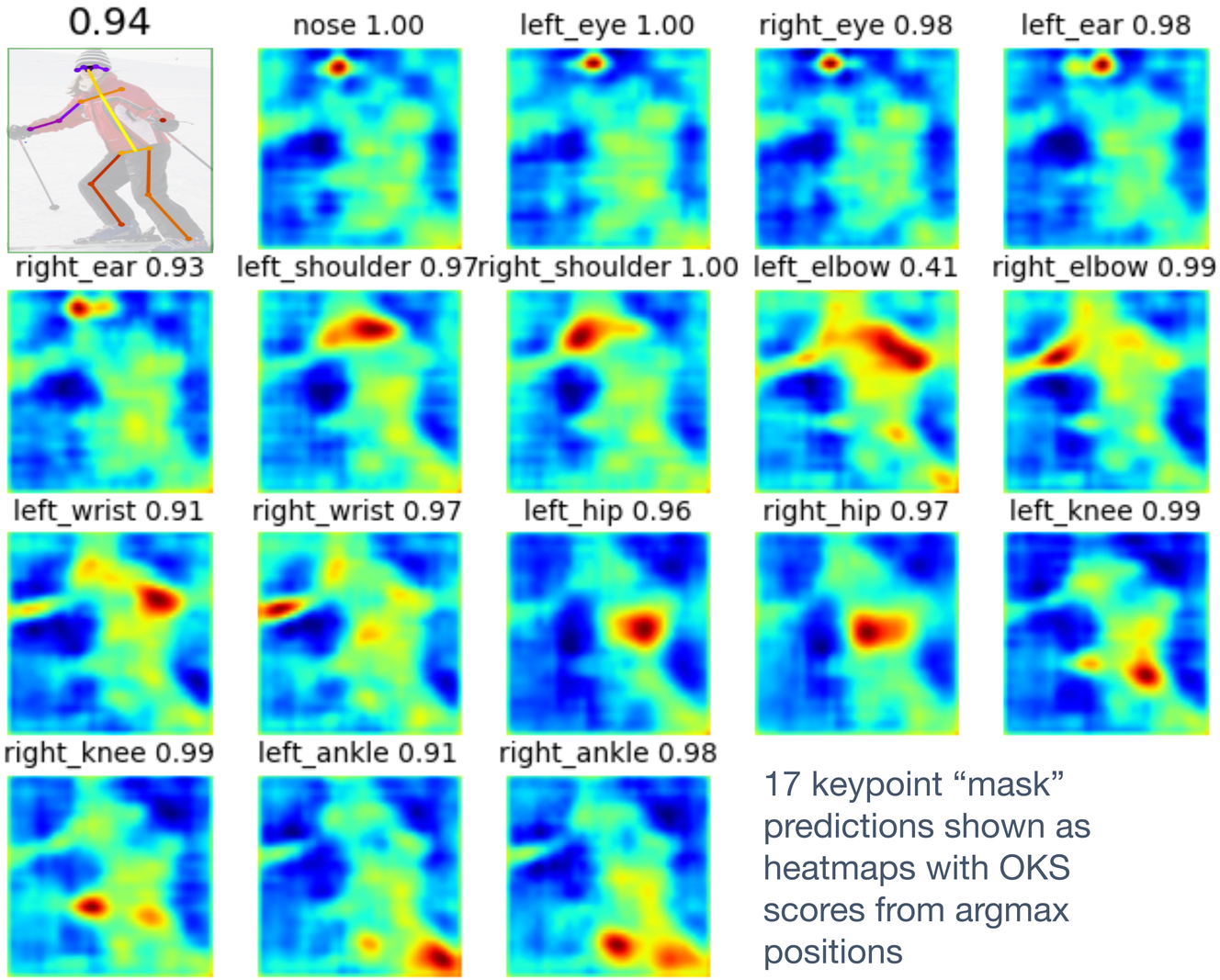
dining table.95
wine glass1.00
wine glass1.00

Human Pose



(Not shown: Head architecture is slightly different for keypoints)



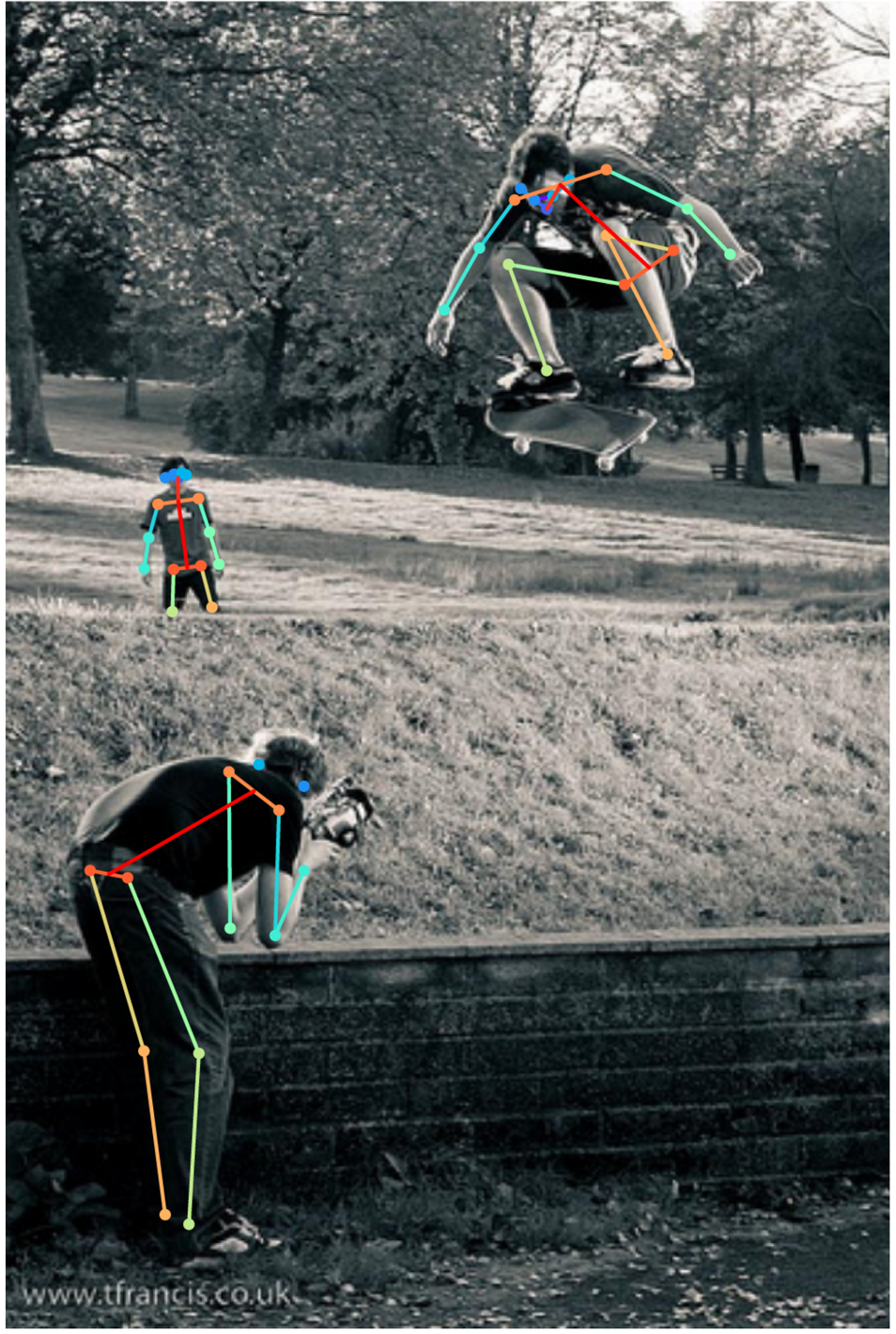
17 keypoint “mask” predictions shown as heatmaps with OKS scores from argmax positions

➢ Add keypoint head (28x28x17)

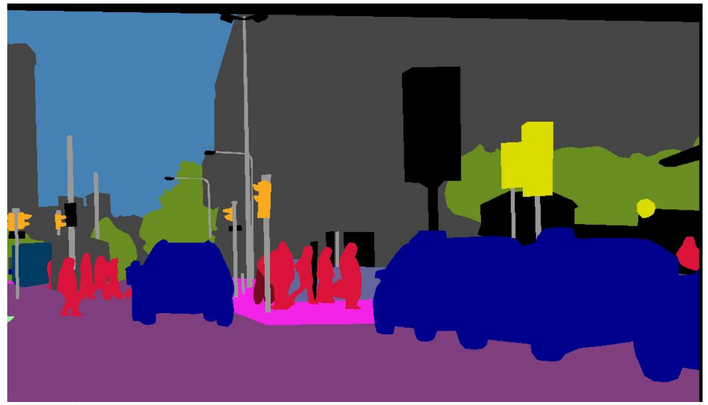
➢ Predict one “mask” for each keypoint

➢ Softmax over spatial locations (encodes one keypoint per mask “prior”)

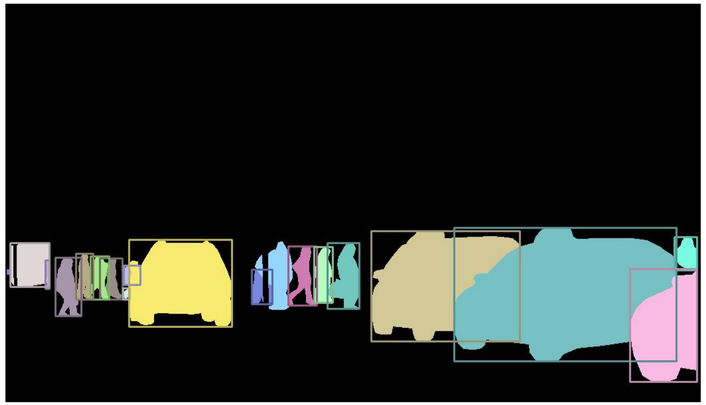
Source: R. Girshick


www.tfrancis.co.uk

Panoptic Segmentation



Semantic segmentation “stuff”



Instance detection, “things”

panoptic segmentation [Kriilov et al. 2018]
predict label + instance id per pixel

Source: ?


UPSNet-101-M: Cityscapes