Introduction to Deep Learning in Vision: Basics, Optimization, Networks and Coding

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Outline

Overview of the Journey

CNNs Basics

- **Standard Operations**: Convolutions , BN Pooling, Nonlinearities *etc.*
- **Special Terms:** Deconvolution, Upsampling, Skip Connection, Dense-block *etc.*
- **Popular Losses**: Entropy based, Standard l_2 and l_1, Adversarial Losses, *etc.*

Optimization

- **Mathematics**: Backpropagation on CNNs
- **Popular first order methods**: SGD, Momentum, Nesterov Acceleration, Adam, RMSprop *etc.*

Network Variants

- LeNet (1998), AlexNet (2012), VGGNet (2014), GoogLeNet (2014), **FCN (2014)**, **ResNet (2015)**, **U-Net (2015),** { SegNet (2015), DenseNet (2017), Dense-UNet (2017) } ***GAN (2014)*** { C-GAN (2014), Cycle-GAN (2017)}

Coding

- **Frameworks**: Caffe (Berkeley), Caffe2 (Facebook), **Theano** (Bengio), Torch (Facebook), **Pytorch** (Facebook), **Tensorflow** (Google)

Outline

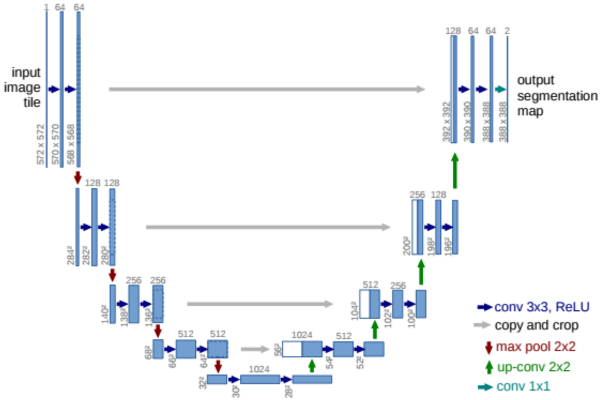
Basic Operations in CNNs

Standard operations in a Convolutional Neural Network:

- Convolution
- Pooling
- Batch Normalization
- Nonlinear Activation
- Others: Deconvolution, Upsampling, Skip Connections *etc.*

A Quick Example: UNet

One of the most popular networks in semantic segmentation.



Olaf Ronneberger, Philipp Fischer, Thomas Brox. *U-Net: Convolutional Networks for Biomedical Image Segmentation*, MICCAI 2015.

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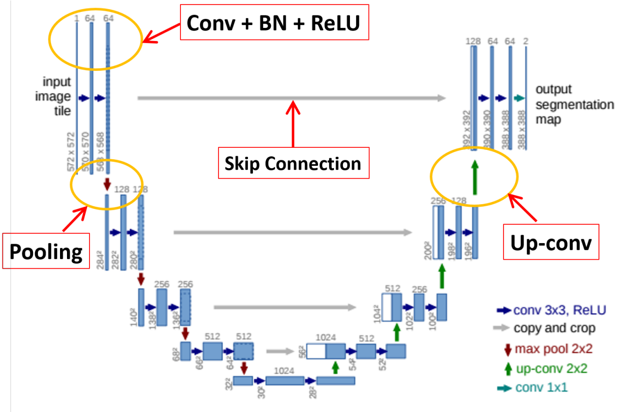

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Convolution and Convolution Layer (Conv + BN + ReLU)

Keywords in Convolution: • **Kernel Size** • **Stride** • **Padding**

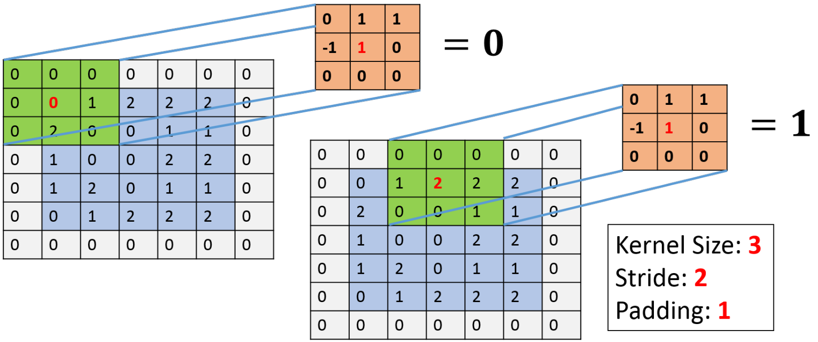

Figure: Illustration of Convolution[1].

[1] To make it simple, the kernel is already **rotated**. Only point-wise product and summation is needed

Convolutions in CNNs: (Conv + BN + ReLU)

Different types of convolutions.

- **Convolution**: (with/without) padding, $(1/>1)$ stride.
- **Transposed Convolution (Deconvolution)**: (with/without) padding, $(1/>1)$ stride.
- **Dilated Convolution**.

See the attached HTML file.

Helpful reading: Vincent Dumoulin, Francesco Visin. *A guide to convolution arithmetic for deep learning.*

Convolutional Layer (1st): (Conv + BN + ReLU)

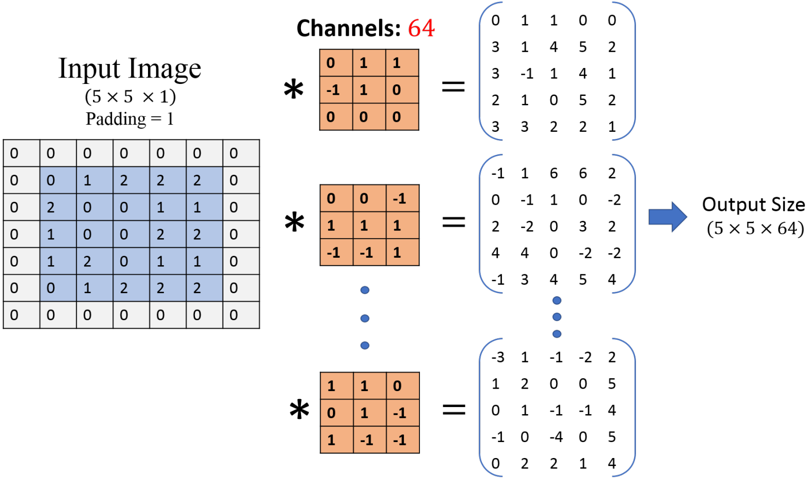

Figure: First Layer of CNN[2].

[2] Again, all the kernels are already **rotated**. Only point-wise product and summation is needed.

Convolutional Layer (2nd): (Conv + BN + ReLU)

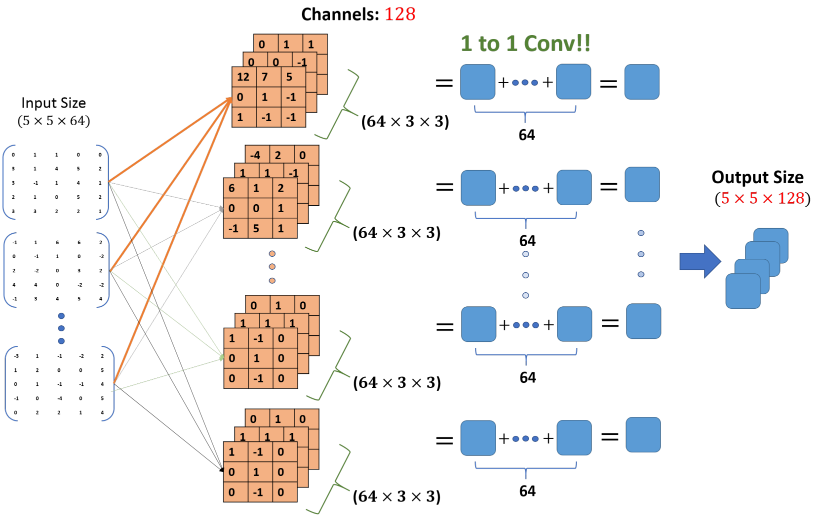

Figure: Each channel has 64 different 3 × 3 filters. Each filter convolves with only *one* channel of the input feature map!

A Short Break: A few questions ...

Suppose we have $4 \times 512 \times 1$ image as network input. That is, (batch size) 4 images where each of them is $512 \times 512 \times 1$ (gray images). Then,

- how many parameters (numbers in filters) do we have so far for the first two layers?

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  - $64 \times 3 \times 3 + 128 \times 64 \times 3 \times 3 = 576 + 73728 = 74,304$
- since both the batches, feature maps are stored in memory, how much memory do we need? (suppose padding $= 1$, stride $= 1$)

$$\begin{aligned} & 4 \times 512 \times 512 \times 1 + 4 \times 512 \times 512 \times 64 + 4 \times 512 \times 512 \times 128 \\ & \approx 1M + 67M + 134M = 202M \\ & = 202M \times 4 \text{ bytes} \approx 770\text{MB} \quad (202M \times 4/1024^2) \end{aligned}$$

Some background. Almost all deep learning models are trained on GPUs. A typical GPU now has $6 \sim 8$ GB memory. Advance GPUs has 12 GB memory (*e.g.* Nvidia GeForce GTX TITAN Z $\sim \$1.5K$ on amazon).

Batch Normalization (Conv + BN + ReLU)

In practice, to increase the training as well as testing speed, we usually feed **multiple** images to the network. The following figure shows a training batch of 4 images,

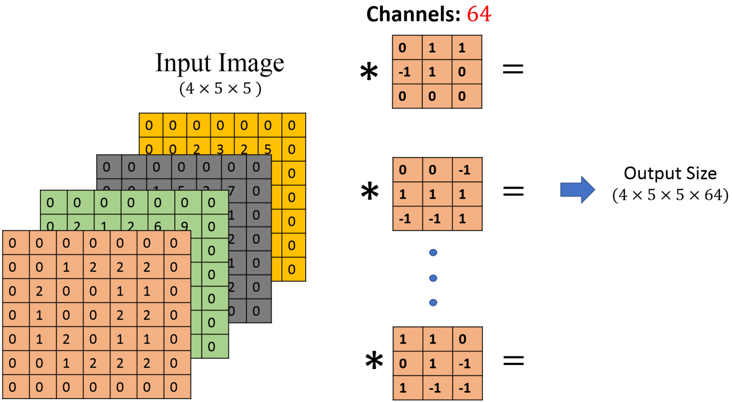


Figure: Batch Size is 4. Each Image is independently processed.

Batch Normalization : (Conv + BN + ReLU)

For each ***channel***, normalize the layers. Mean bad variance are computed across all the values in each channel.

Input: Values of x over a mini-batch: $\mathcal{B} = \{x_{1\ldots m}\}$;
Parameters to be learned: γ, β

Output: $\{y_i = \mathrm{BN}_{\gamma,\beta}(x_i)\}$

$$\mu_{\mathcal{B}} \leftarrow \frac{1}{m}\sum_{i=1}^{m} x_i \qquad \text{// mini-batch mean}$$

$$\sigma_{\mathcal{B}}^2 \leftarrow \frac{1}{m}\sum_{i=1}^{m} (x_i - \mu_{\mathcal{B}})^2 \qquad \text{// mini-batch variance}$$

$$\widehat{x}_i \leftarrow \frac{x_i - \mu_{\mathcal{B}}}{\sqrt{\sigma_{\mathcal{B}}^2 + \epsilon}} \qquad \text{// normalize}$$

$$y_i \leftarrow \gamma \widehat{x}_i + \beta \equiv \mathrm{BN}_{\gamma,\beta}(x_i) \qquad \text{// scale and shift}$$

Algorithm 1: Batch Normalizing Transform, applied to activation x over a mini-batch.

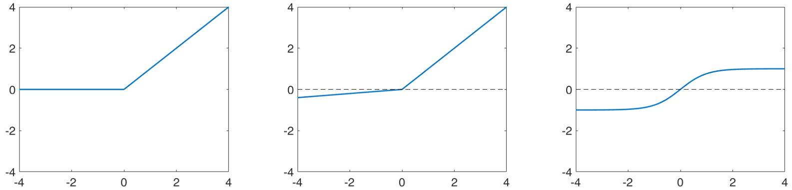
An effective way to resolve ***vanishing gradient*** problem!

Sergey Ioffe, Christian Szegedy. *Batch Normalization: Accelerating Deep Network Training by Reducing Internal Covariate Shift*, NIPs 2015.

Nonlinear Activations: (Conv + BN + ReLU)

Popular nonlinearities used through all **but** last layer:

- ReLU: $\max(0, x)$.
- Leaky ReLU: $\max(0, x) + \gamma^2 \min(0, x)$
- Tanh: $\frac{\exp(x)-\exp(-x)}{\exp(x)+\exp(-x)}$
- Others [3]: ELU, SELU, PRELU, Threshold *etc.*



(a) ReLU (b) Leaky ReLU (c) Tanh

[3] A good place to find all these is the document of deep learning software frameworks, eg. `http://pytorch.org/docs/master/nn.html`

Pooling

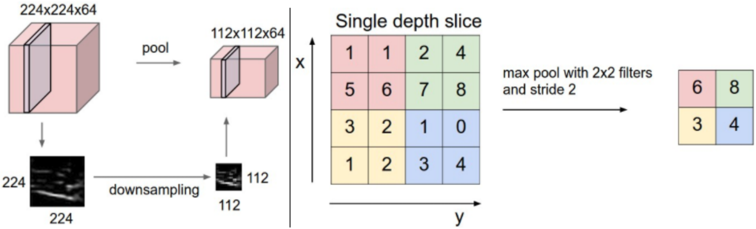


Figure: Illustration of *Max Pooling*. Here batch size 1 is omitted. [4]

There is also average pooling which takes average rather than maximum.

[4] Image courtesy of CS231n: Convolutional Neural Networks for Visual Recognition. Stanford.

Skip Connection

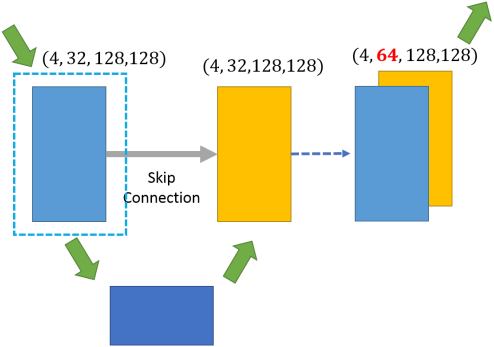


Figure: Skip connection is simply concatenating two feature maps (along channel dimension). Central crop is performed is there is a miss-match of the dimension.

Comment. Adding skip connections can usually increase the performance (at least) in segmentation.

Now We Know $(+ - \times \div)$ ...

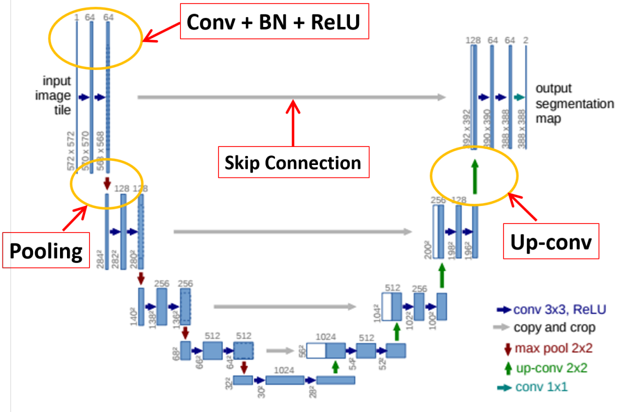
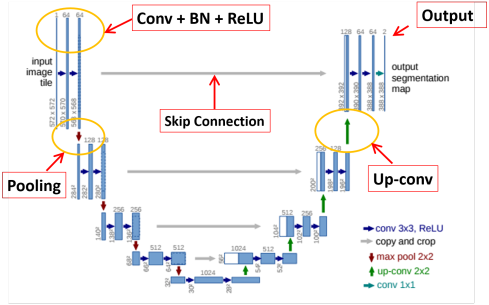


Figure: Networks are just special ways to stack all these operations.

Function Representation



$$\underbrace{\qquad\qquad}_{f(I;W)}$$

Figure: The entire network is just another representation of $f(I;W)$, where I is input image(s), W are the parameters in the network.

Optimization Problem

In training state, we are given ground truth images and its labels for recognition/classification, or masks for segmentation, high-resolution image for super-resolution, clear image for de-noising *etc.*.

Let I be the truth images and g be their labels, the optimization problem is

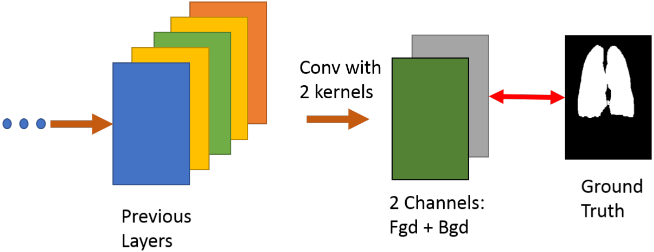
$$\min_{W} \quad Loss\{f(I;W) - g\}$$

Popular losses,

- l_2 **distance**: image denoising, super-resolution, recognition.
- **Entropy**: binary/categorical cross-entropy, KL-divergence for segmentation.
- Many other **customized losses**, *e.g.* l_1 for GAN, smoothed dice loss for segmentation.

Loss Function Example: Cross Entropy

Suppose we are doing a single object segmentation, *e.g.* lung. The last convolutional channel will have 2 channels corresponding foreground and background.



Softmax + Cross-entropy

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Overview

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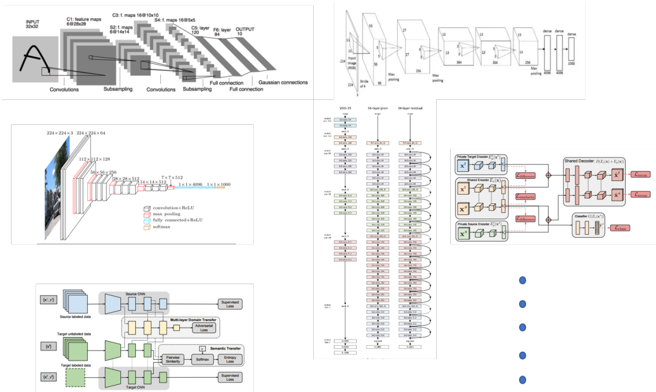
Networks



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Frameworks

Thank you!