# Image Segmentation and Detection

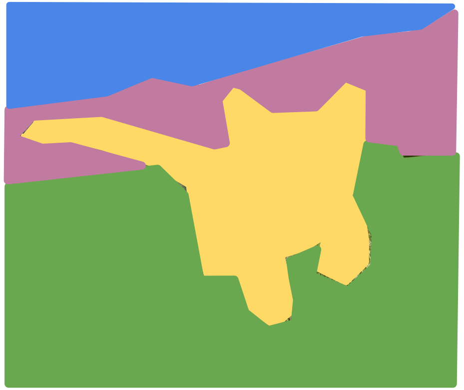
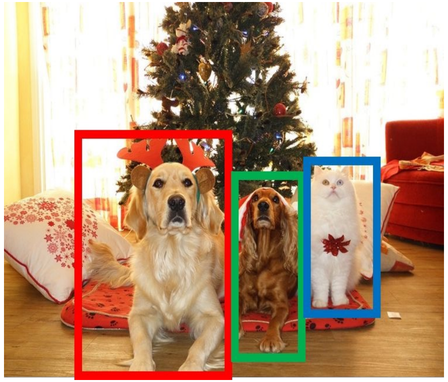
**Executive Program on AI/ML**

IIIT Hyderabad

MML

TECHNOLOGY INNOVATION HUB ON DATA DRIVEN TECHNOLOGIES

# Computer Vision Tasks

| Classification | Semantic Segmentation | Object Detection | Instance Segmentation |
| --- | --- | --- | --- |
|  |  |  |  |
| **CAT** | **GRASS, CAT, TREE, SKY** | **DOG, DOG, CAT** | **DOG, DOG, CAT** |

No spatial extent

No objects, just pixels

Multiple Object

# Semantic Segmentation

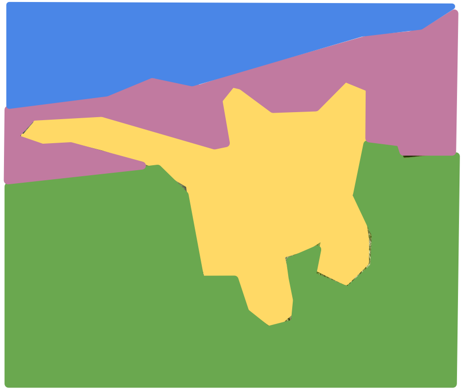
Classification



CAT

No spatial extent

**Semantic Segmentation**



GRASS, CAT, TREE, SKY

No objects, just pixels

Object Detection



DOG, DOG, CAT

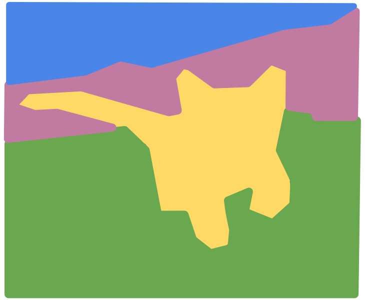
Instance Segmentation



DOG, DOG, CAT

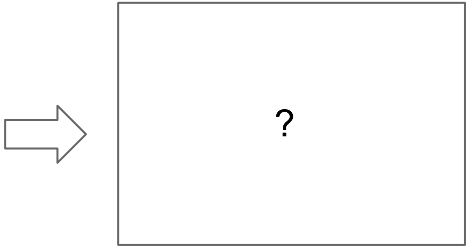
Multiple Object

# Semantic Segmentation: The Problem



GRASS, CAT,
TREE, SKY, ...

Paired training data: for each training image, each pixel is labeled with a semantic category.




At test time, classify each pixel of a new image.

# Semantic Segmentation Idea: Sliding Window

Full image

# Semantic Segmentation Idea: Sliding Window

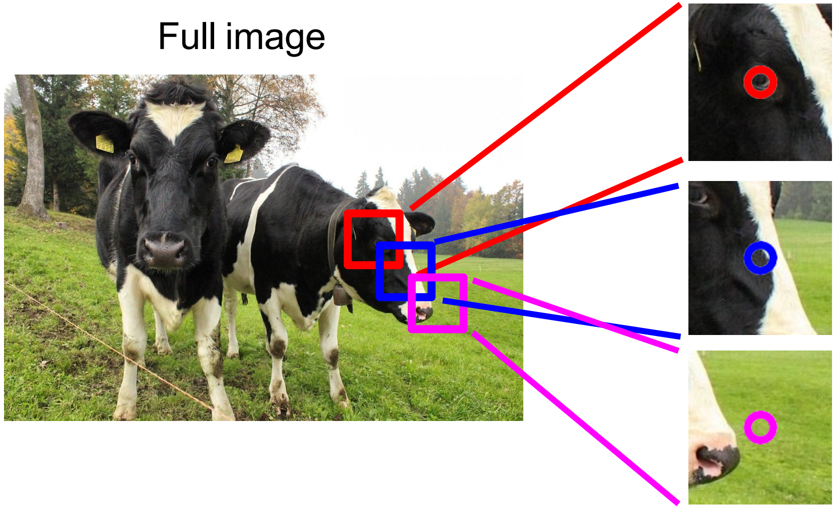
Full image


Impossible to classify without context

Q: how do we include context?

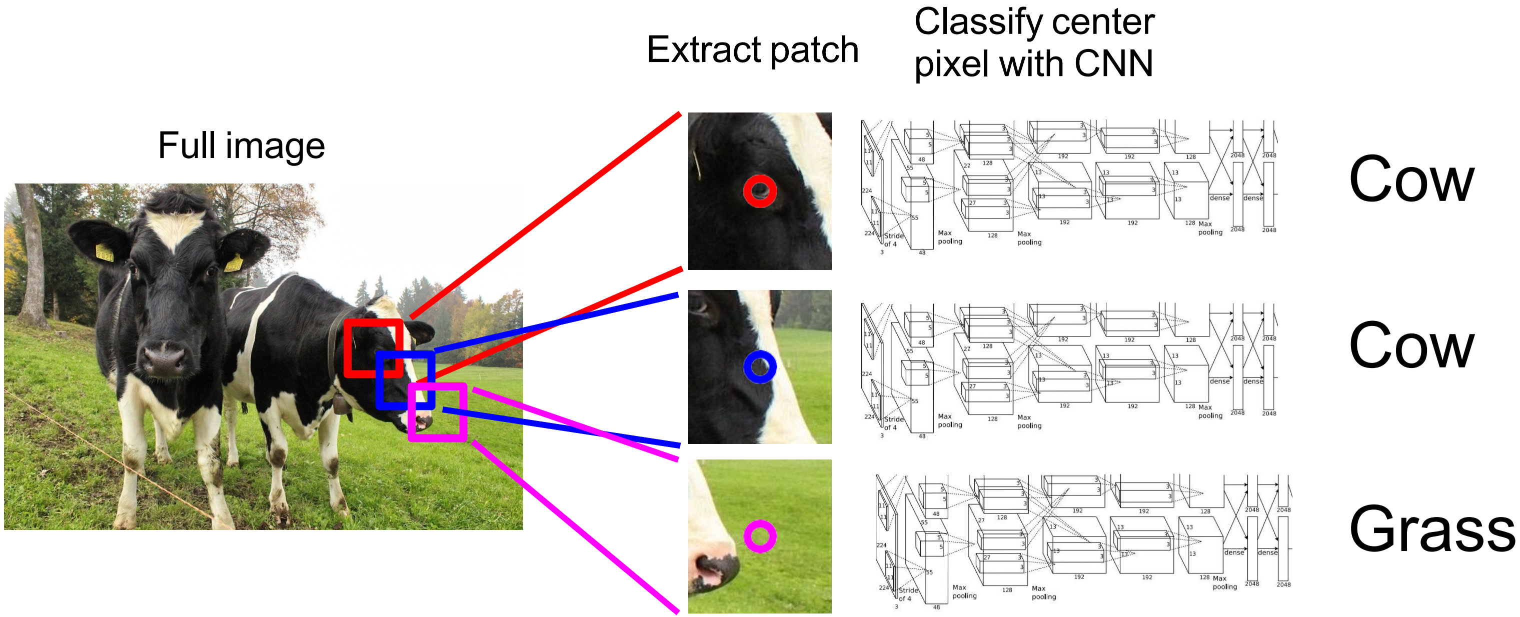
# Semantic Segmentation Idea: Sliding Window

Full image



Q: how do we model this?

# Semantic Segmentation Idea: Sliding Window



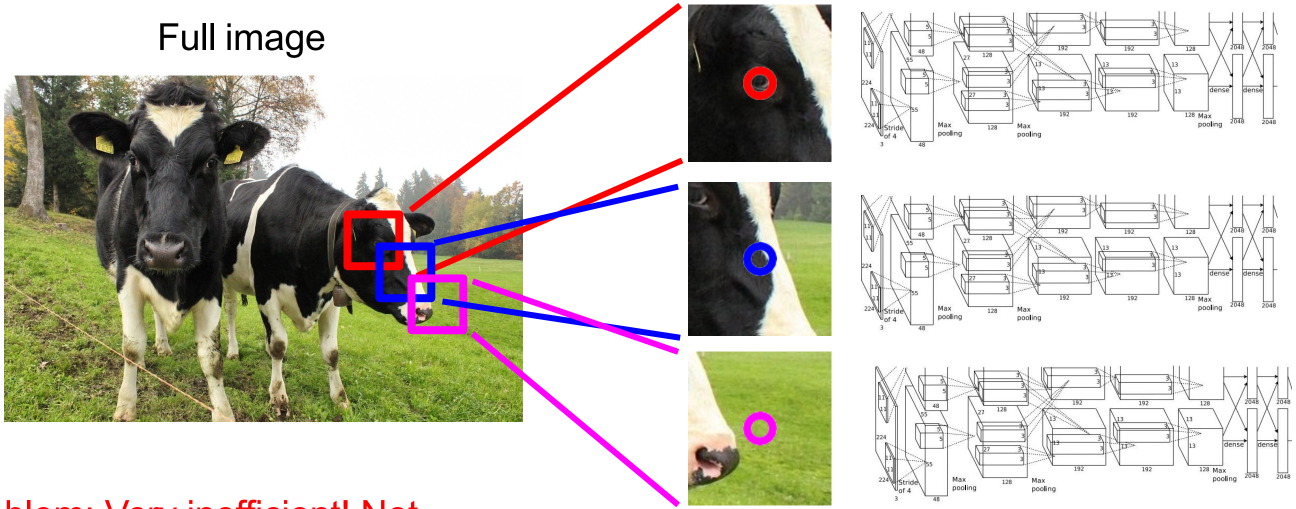

Farabet et al, "Learning Hierarchical Features for Scene Labeling," TPAMI 2013
Pinheiro and Collobert, "Recurrent Convolutional Neural Networks for Scene Labeling", ICML 2014

# Semantic Segmentation Idea: Sliding Window

Full image

Extract patch

Classify center pixel with CNN



Cow

Cow

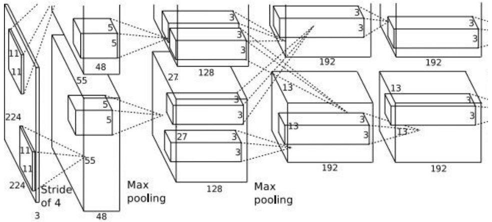
Grass

Problem: Very inefficient! Not reusing shared features between overlapping patches

Farabet et al, “Learning Hierarchical Features for Scene Labeling,” TPAMI 2013
Pinheiro and Collobert, “Recurrent Convolutional Neural Networks for Scene Labeling”, ICML 2014

# Semantic Segmentation Idea: Convolution

Full image

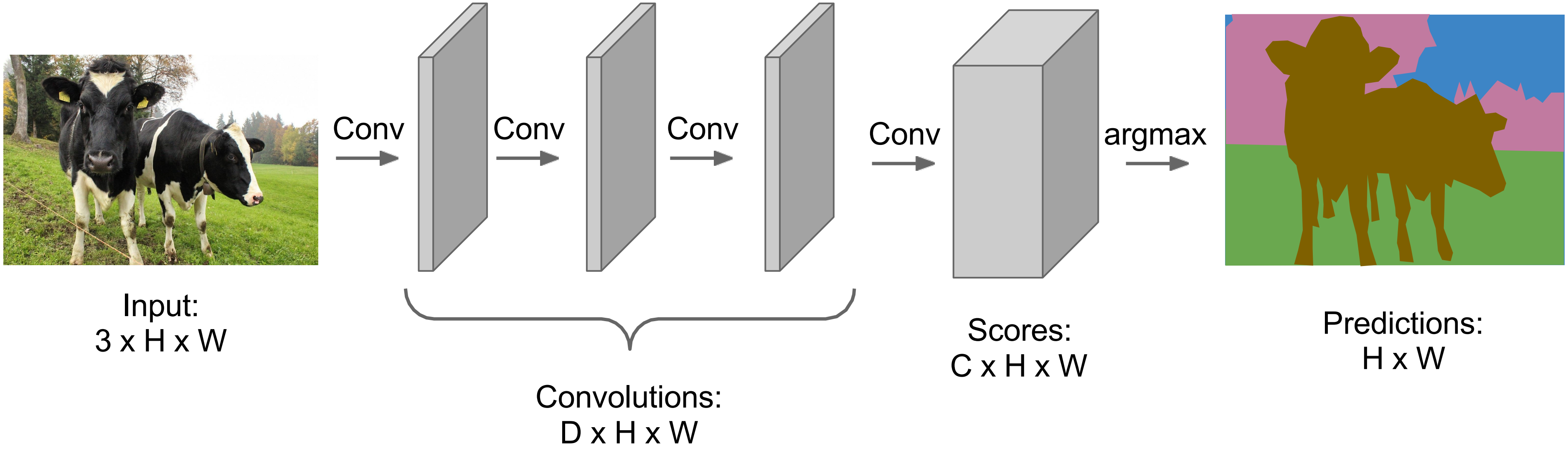



An intuitive idea: encode the entire image with conv net, and do semantic segmentation on top.

Problem: classification architectures often reduce feature spatial sizes to go deeper, but semantic segmentation requires the output size to be the same as input size.

# Semantic Segmentation Idea: Fully Convolutional

Design a network with only convolutional layers without downsampling operators to make predictions for pixels all at once!



# Semantic Segmentation Idea: Fully Convolutional

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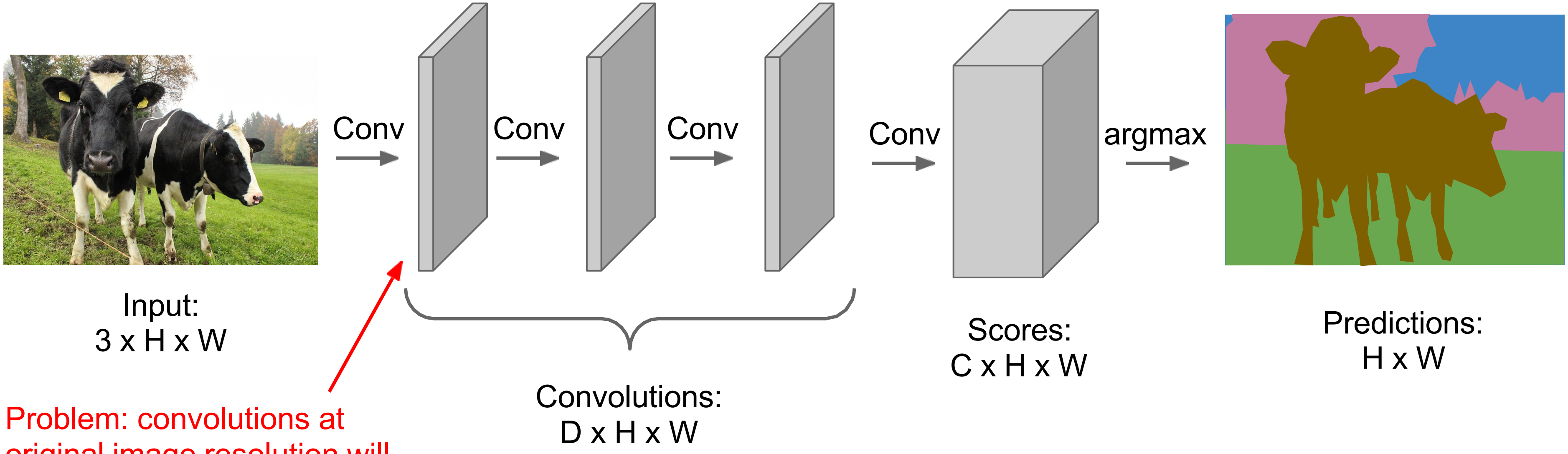
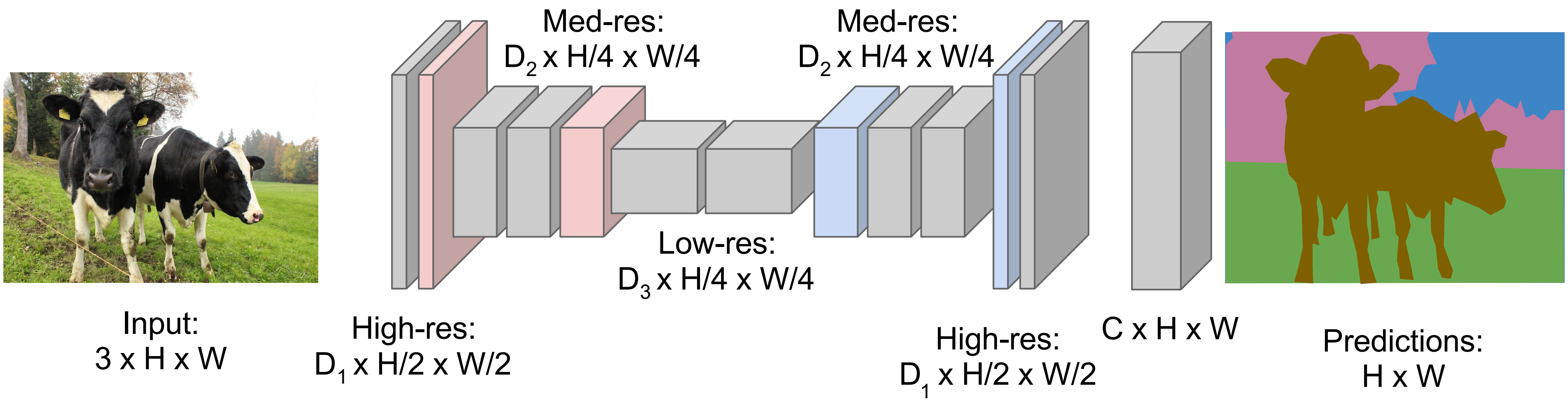



Problem: convolutions at original image resolution will be very expensive ...

# Semantic Segmentation Idea: Fully Convolutional

Design network as a bunch of convolutional layers, with **downsampling** and **upsampling** inside the network!





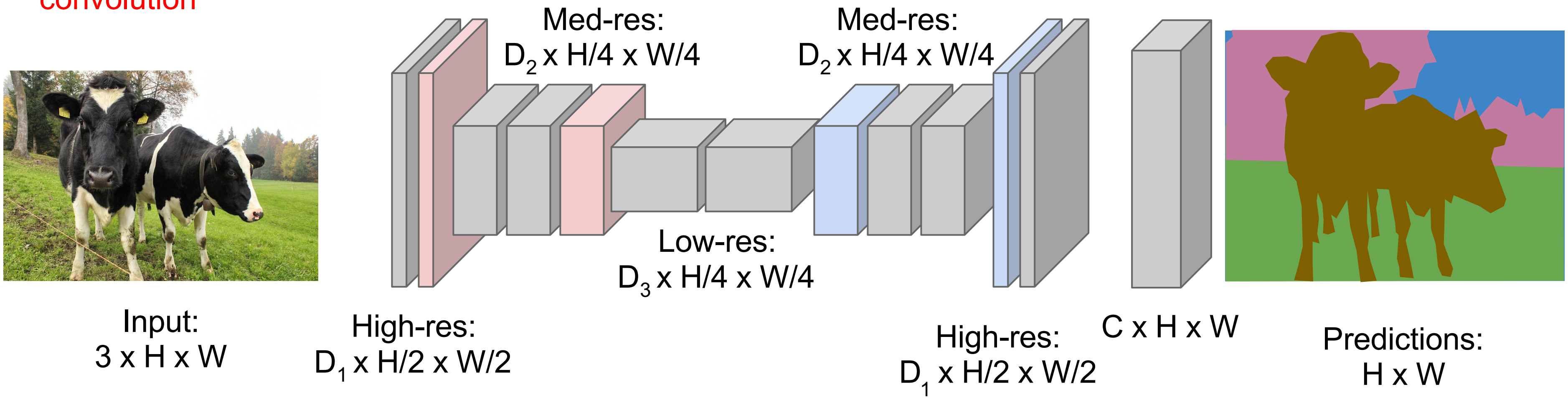
Long, Shelhamer, and Darrell, “Fully Convolutional Networks for Semantic Segmentation”, CVPR 2015
Noh et al, “Learning Deconvolution Network for Semantic Segmentation”, ICCV 2015

# Semantic Segmentation Idea: Fully Convolutional

**Downsampling**: Pooling, strided convolution

Design network as a bunch of convolutional layers, with **downsampling** and **upsampling** inside the network!

**Upsampling**: ???




Long, Shelhamer, and Darrell, “Fully Convolutional Networks for Semantic Segmentation”, CVPR 2015
Noh et al, “Learning Deconvolution Network for Semantic Segmentation”, ICCV 2015

# In-Network upsampling: “Unpooling”

**Nearest Neighbor**

| | |
|---|---|
| 1 | 2 |
| 3 | 4 |

Input: 2 x 2

| | | | |
|---|---|---|---|
| 1 | 1 | 2 | 2 |
| 1 | 1 | 2 | 2 |
| 3 | 3 | 4 | 4 |
| 3 | 3 | 4 | 4 |

Output: 4 x 4

**“Bed of Nails”**

| | |
|---|---|
| 1 | 2 |
| 3 | 4 |

Input: 2 x 2

| | | | |
|---|---|---|---|
| 1 | 0 | 2 | 0 |
| 0 | 0 | 0 | 0 |
| 3 | 0 | 4 | 0 |
| 0 | 0 | 0 | 0 |

Output: 4 x 4

# In-Network upsampling: “Max Unpooling”

**Max Pooling**
Remember which element was max!

| | | | |
|---|---|---|---|
| 1 | 2 | 6 | 3 |
| 3 | 5 | 2 | 1 |
| 1 | 2 | 2 | 1 |
| 7 | 3 | 4 | 8 |

Input: 4 x 4

| | |
|---|---|
| 5 | 6 |
| 7 | 8 |

Output: 2 x 2

…

Rest of the network

**Max Unpooling**
Use positions from pooling layer

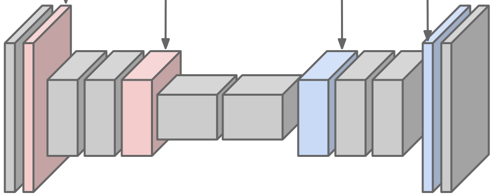
| | |
|---|---|
| 1 | 2 |
| 3 | 4 |

Input: 2 x 2

| | | | |
|---|---|---|---|
| 0 | 0 | 2 | 0 |
| 0 | 1 | 0 | 0 |
| 0 | 0 | 0 | 0 |
| 3 | 0 | 0 | 4 |

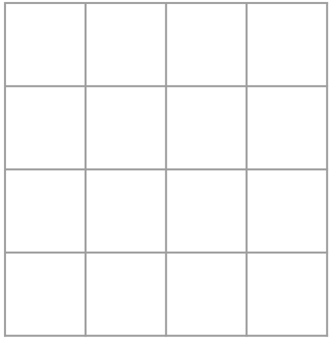
Output: 4 x 4

Corresponding pairs of downsampling and upsampling layers

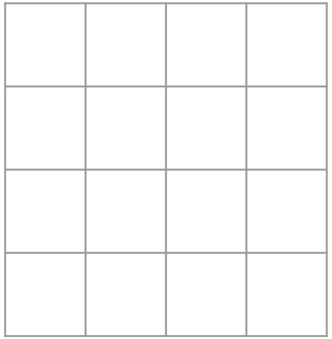


# Learnable Upsampling

**Recall:** Normal 3 x 3 convolution, stride 1 pad 1



Input: 4 x 4



Output: 4 x 4

# Learnable Upsampling

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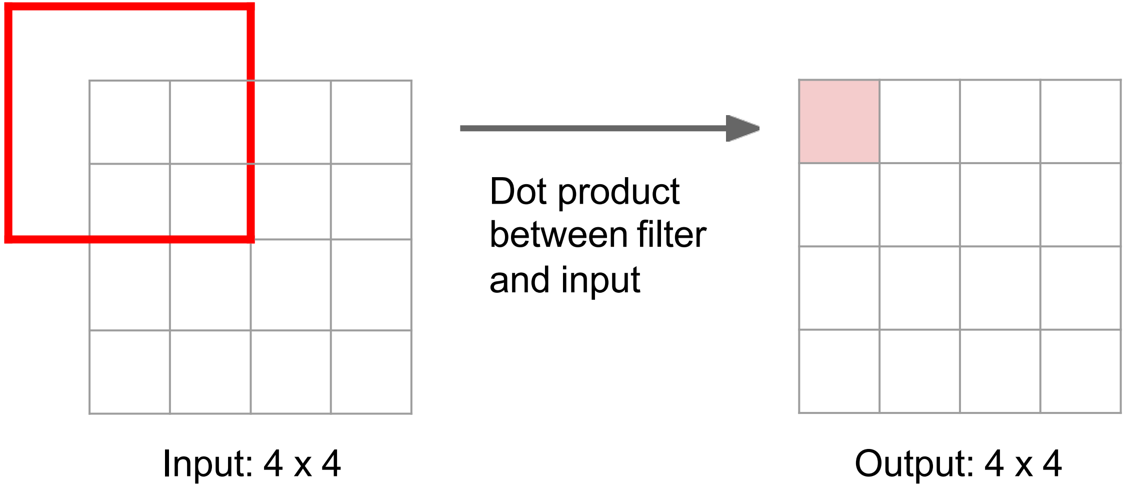
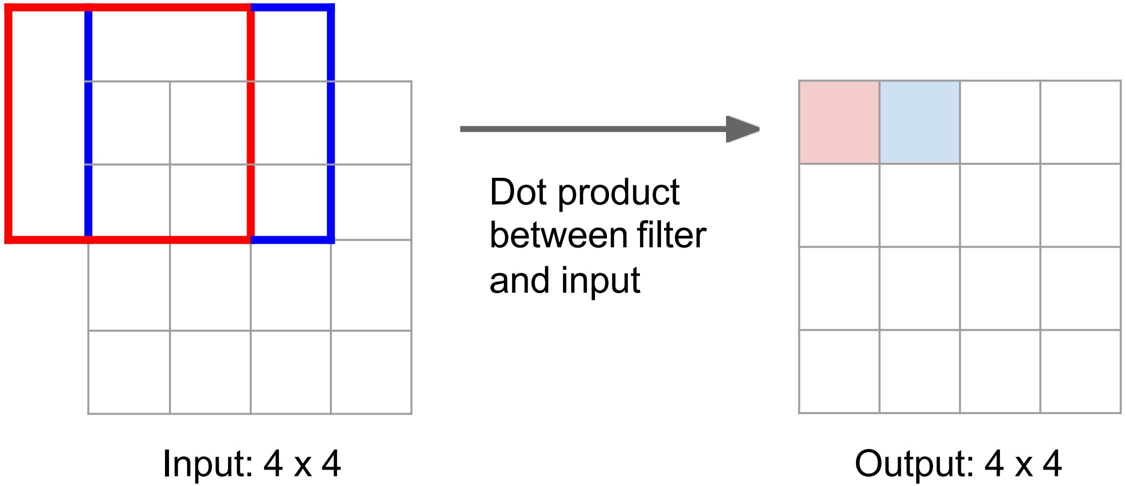


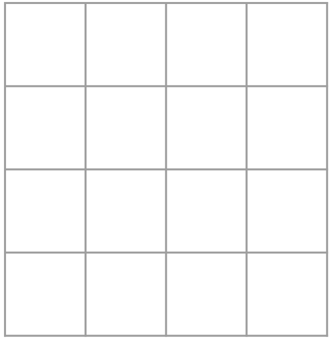
# Learnable Upsampling

**Recall:** Normal 3 x 3 convolution, stride 1 pad 1

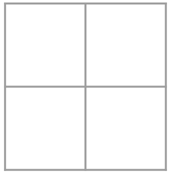


# Learnable Upsampling

**Recall:** Normal 3 x 3 convolution, stride 2 pad 1



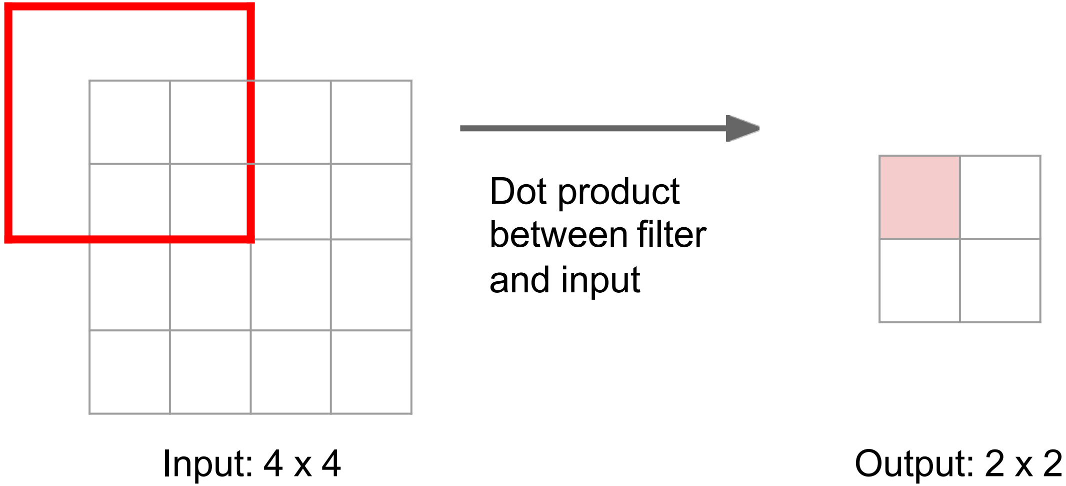
Input: 4 x 4



Output: 2 x 2

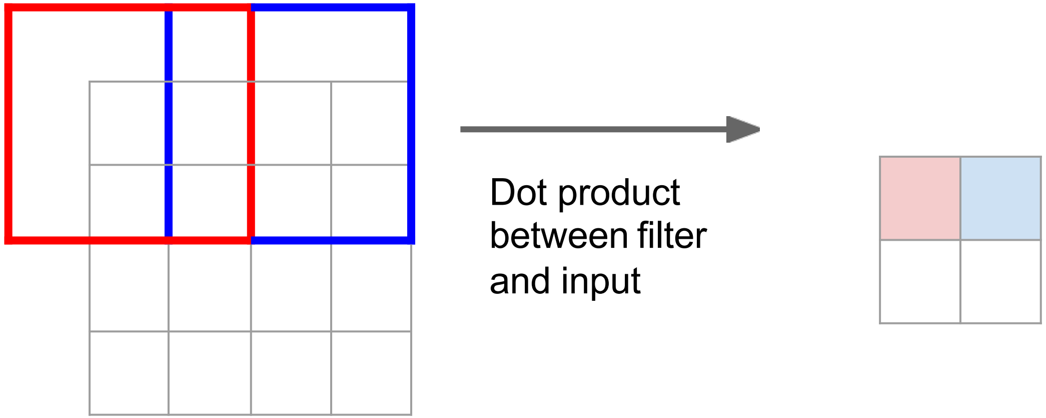
# Learnable Upsampling

**Recall:** Normal 3 x 3 convolution, stride 2 pad 1



# Learnable Upsampling

- **Recall:** Normal 3 x 3 convolution, stride 2 pad 1




Input: 4 x 4

Output: 2 x 2

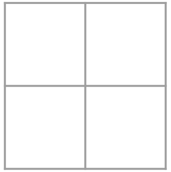
Filter moves 2 pixels in the input for every one pixel in the output.

Stride gives ratio between movement in input and output

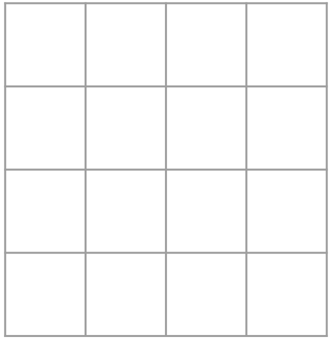
We can interpret strided convolution as “learnable downsampling”.

# Learnable Upsampling: Transposed Convolution

3 x 3 **transposed** convolution, stride 2 pad 1



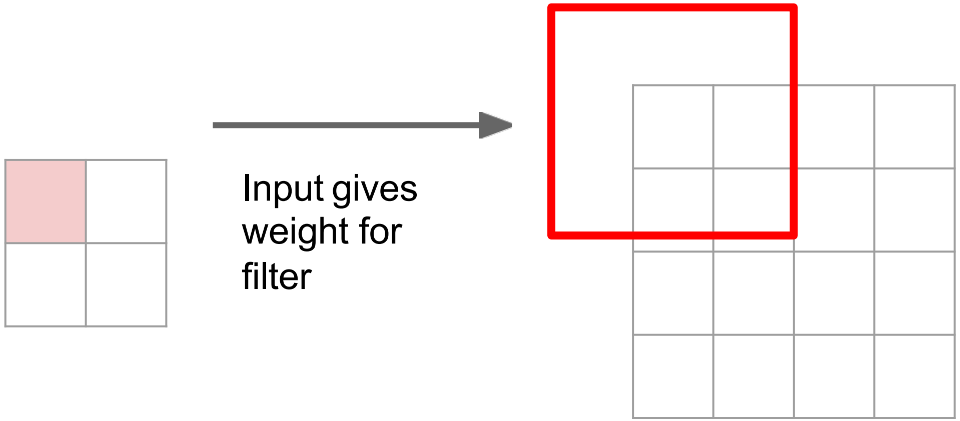
Input: 2 x 2



Output: 4 x 4

# Learnable Upsampling: Transposed Convolution

3 x 3 **transposed** convolution, stride 2 pad 1

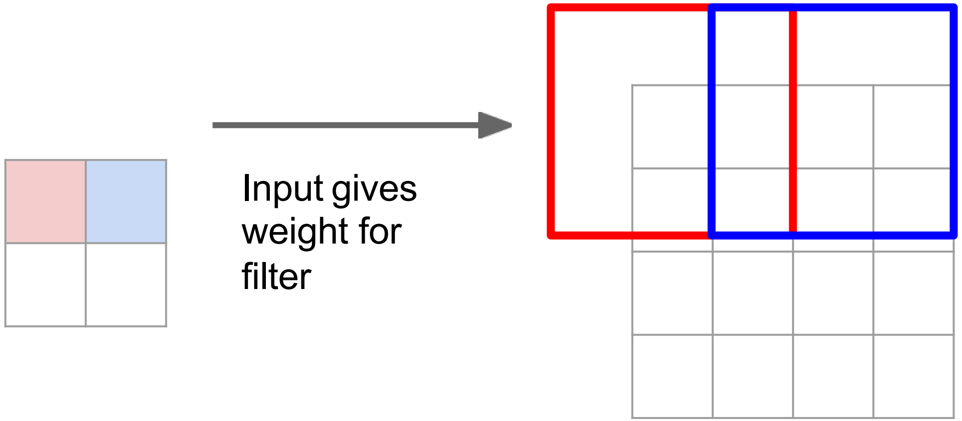



Input: 2 x 2

Output: 4 x 4

# Learnable Upsampling: Transposed Convolution

3 x 3 **transposed** convolution, stride 2 pad 1




Input: 2 x 2

Output: 4 x 4

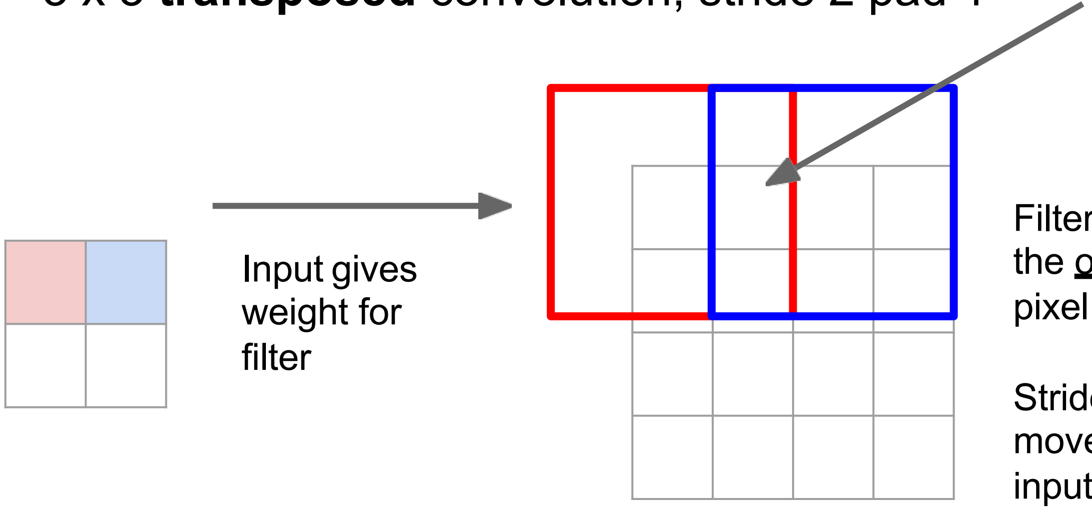
Filter moves 2 pixels in the output for every one pixel in the input

Stride gives ratio between movement in output and input

# Learnable Upsampling: Transposed Convolution

3 x 3 **transposed** convolution, stride 2 pad 1

Sum where output overlaps




Input: 2 x 2

Output: 4 x 4

Filter moves 2 pixels in the output for every one pixel in the input

Stride gives ratio between movement in output and input

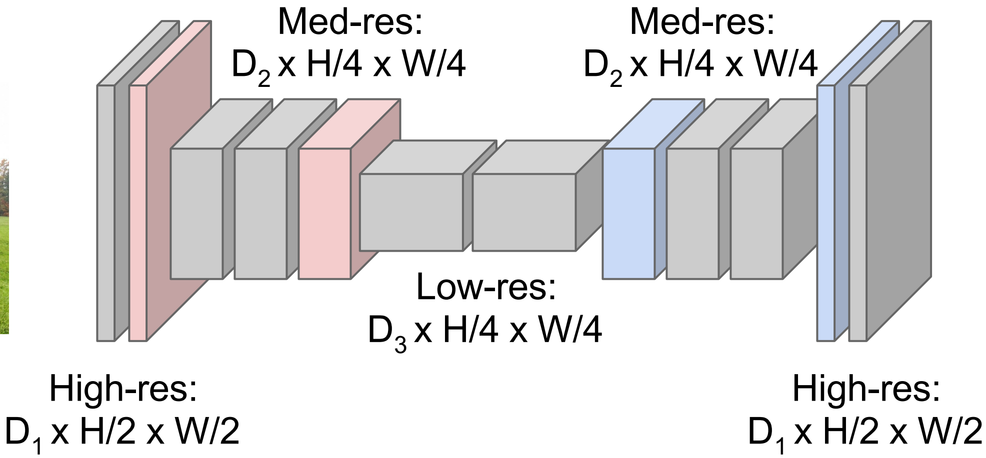
# Semantic Segmentation Idea: Fully Convolutional

**Downsampling**: Pooling, strided convolution

Design network as a bunch of convolutional layers, with **downsampling** and **upsampling** inside the network!

**Upsampling**: Unpooling or strided transposed convolution

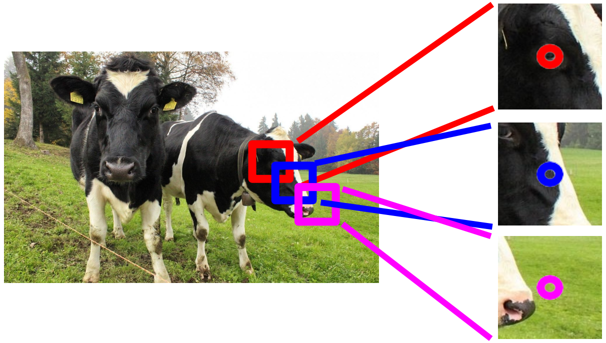
Input: 3 x H x W

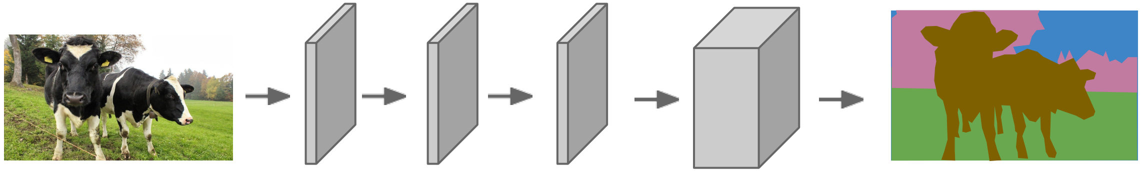


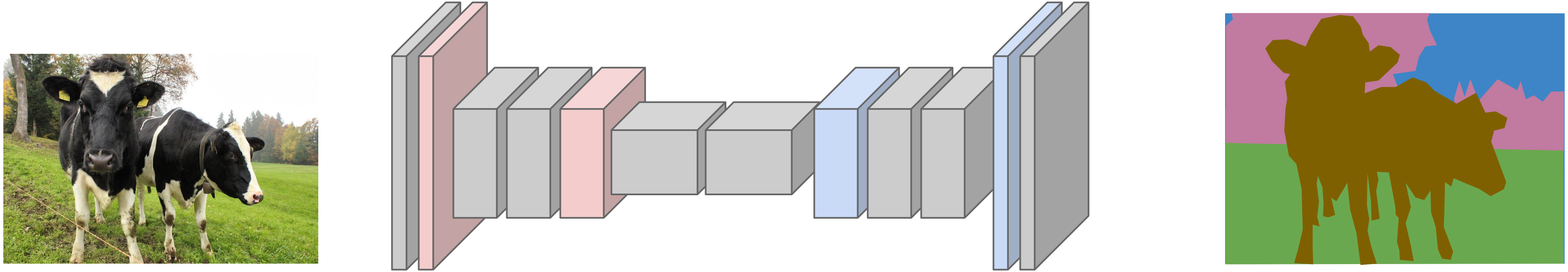

Predictions: H x W

Long, Shelhamer, and Darrell, "Fully Convolutional Networks for Semantic Segmentation", CVPR 2015
Noh et al, "Learning Deconvolution Network for Semantic Segmentation", ICCV 2015

# Semantic Segmentation: Summary







# U-Net

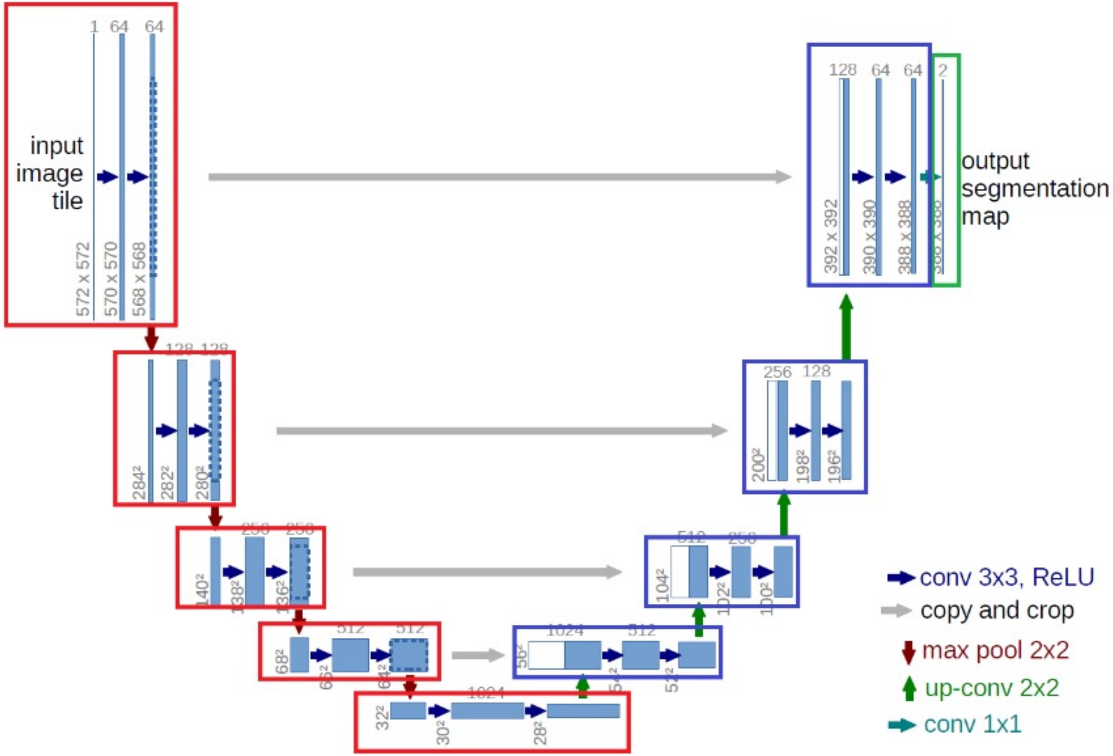


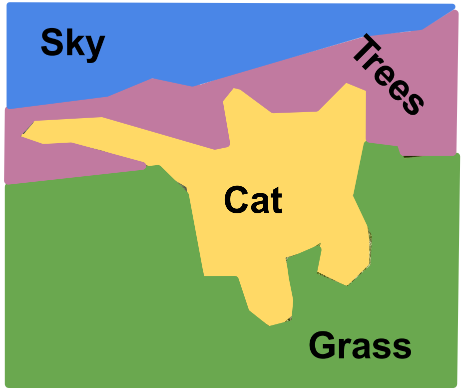

**Fig. 1.** U-net architecture (example for 32x32 pixels in the lowest resolution). Each blue box corresponds to a multi-channel feature map. The number of channels is denoted on top of the box. The x-y-size is provided at the lower left edge of the box. White boxes represent copied feature maps. The arrows denote the different operations.

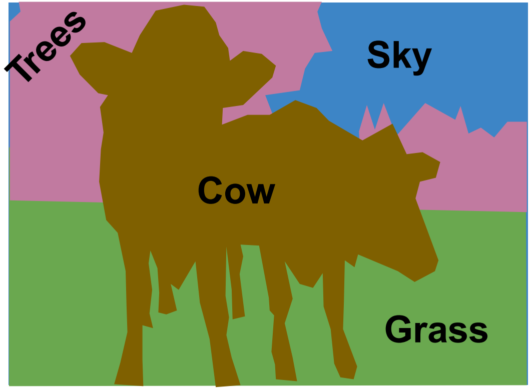
# Semantic Segmentation

Label each pixel in the image with a category label

Don’t differentiate instances, only care about pixels





# Object Detection

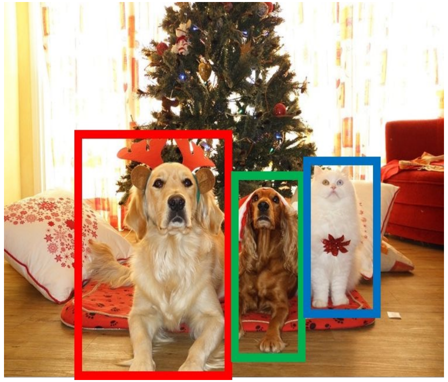
| Classification | Semantic Segmentation | Object Detection | Instance Segmentation |
|---|---|---|---|
|  |  |  |  |
| CAT | GRASS, CAT, TREE, SKY | DOG, DOG, CAT | DOG, DOG, CAT |

No spatial extent

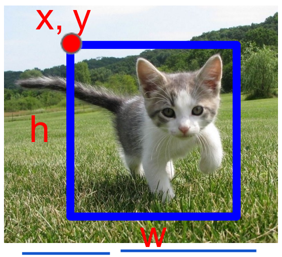
No objects, just pixels

Multiple Object

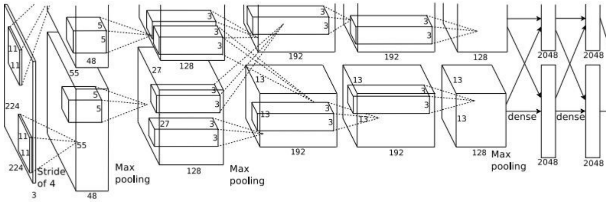
# Object Detection

| Classification | Semantic Segmentation | Object Detection | Instance Segmentation |
|---|---|---|---|
|  |  |  |  |
| **CAT** | **GRASS, CAT, TREE, SKY** | **DOG, DOG, CAT** | **DOG, DOG, CAT** |
| No spatial extent | No objects, just pixels | Multiple Object | |

# Object Detection: Single Object (Classification + Localization)




This image is CC0 public domain




**Vector:** 4096

**Fully Connected:** 4096 to 1000

**Class Scores**
Cat: 0.9
Dog: 0.05
Car: 0.01
...

**Fully Connected:** 4096 to 4

**Box Coordinates**
(x, y, w, h)

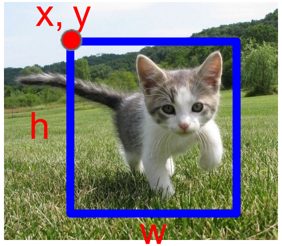
# Object Detection: Single Object (Classification + Localization)

**Correct label:**
Cat

**Class Scores**
Cat: 0.9
Dog: 0.05
Car: 0.01
...

**Softmax Loss**

**Fully Connected:**
4096 to 1000

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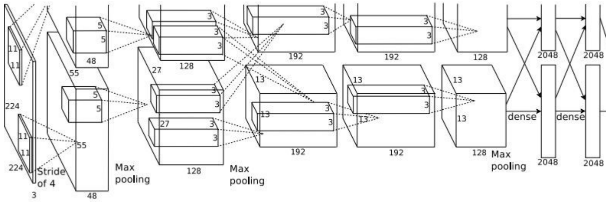



**Vector:**
4096

**Fully Connected:**
4096 to 4

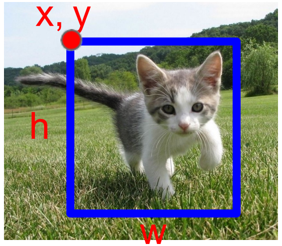
**Box Coordinates**
(x, y, w, h)

**L2 Loss**

**Correct box:**
(x’, y’, w’, h’)

Treat localization as a regression problem!

# Object Detection: Single Object (Classification + Localization)

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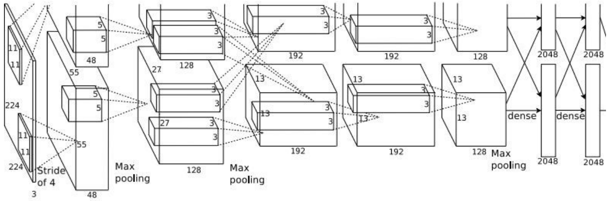



**Vector:** 4096

**Fully Connected:** 4096 to 1000

**Class Scores**
Cat: 0.9
Dog: 0.05
Car: 0.01
...

**Correct label:** Cat

**Softmax Loss**

**Fully Connected:** 4096 to 4

**Box Coordinates** (x, y, w, h)

**L2 Loss**

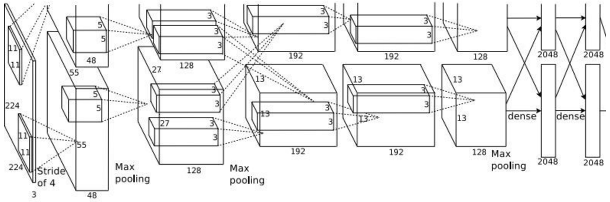
**Correct box:** (x’, y’, w’, h’)

Multitask Loss

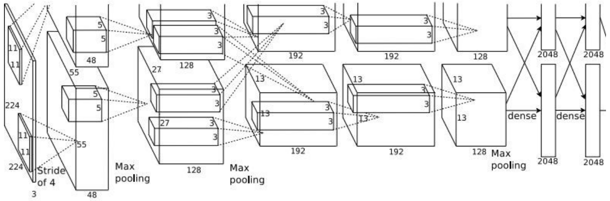
**+** → **Loss**

Treat localization as a regression problem!

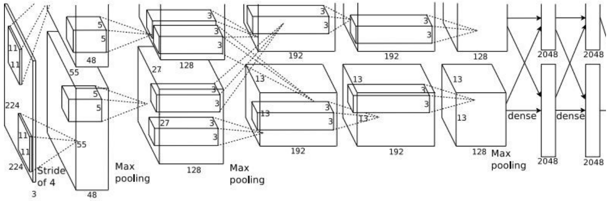
# Object Detection: Multiple Objects




CAT: (x, y, w, h)



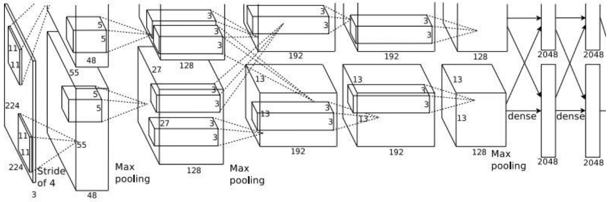

DOG: (x, y, w, h)
DOG: (x, y, w, h)
CAT: (x, y, w, h)




DUCK: (x, y, w, h)
DUCK: (x, y, w, h)
....

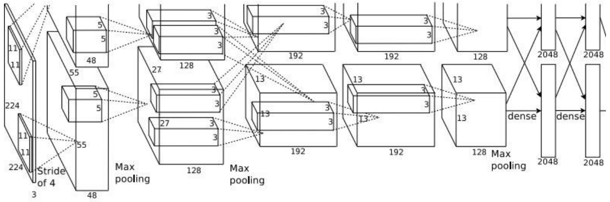
# Object Detection: Multiple Objects

Each image needs a different number of outputs!



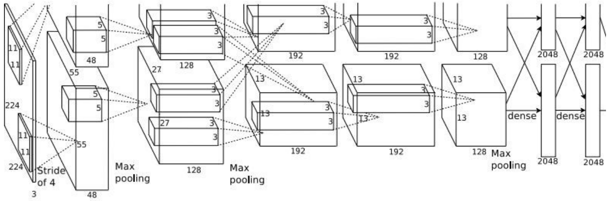

CAT: (x, y, w, h)

4 numbers




DOG: (x, y, w, h)
DOG: (x, y, w, h)
CAT: (x, y, w, h)

12 numbers

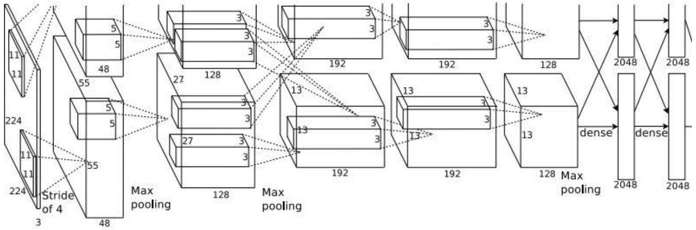



DUCK: (x, y, w, h)
DUCK: (x, y, w, h)
....

Many numbers!

# Object Detection: Multiple Objects

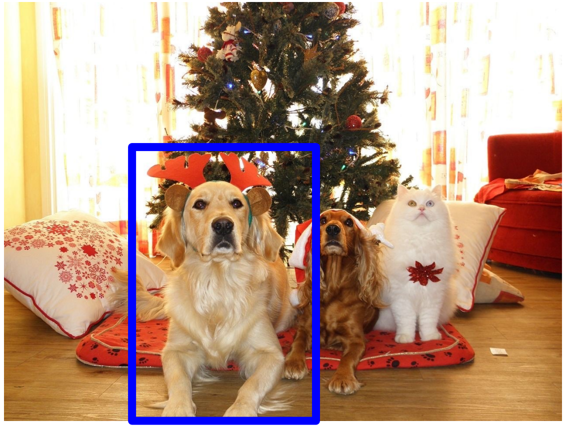
Apply a CNN to many different crops of the image, CNN classifies each crop as object or background

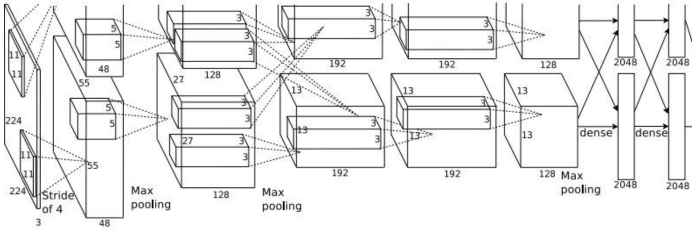



Dog? NO
Cat? NO
Background? YES

# Object Detection: Multiple Objects

Apply a CNN to many different crops of the image, CNN classifies each crop as object or background

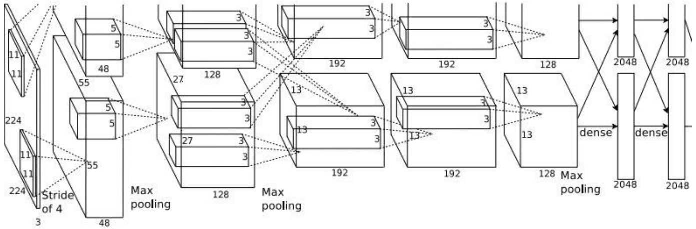





Dog? YES
Cat? NO
Background? NO

# Object Detection: Multiple Objects

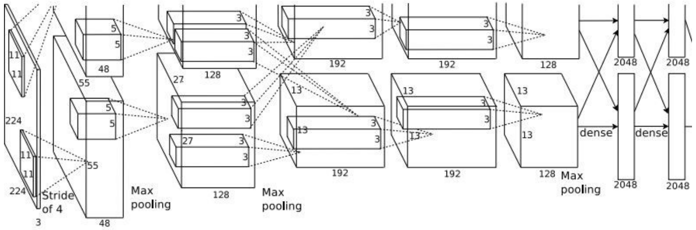
Apply a CNN to many different crops of the image, CNN classifies each crop as object or background




Dog? YES
Cat? NO
Background? NO

# Object Detection: Multiple Objects

Apply a CNN to many different crops of the image, CNN classifies each crop as object or background

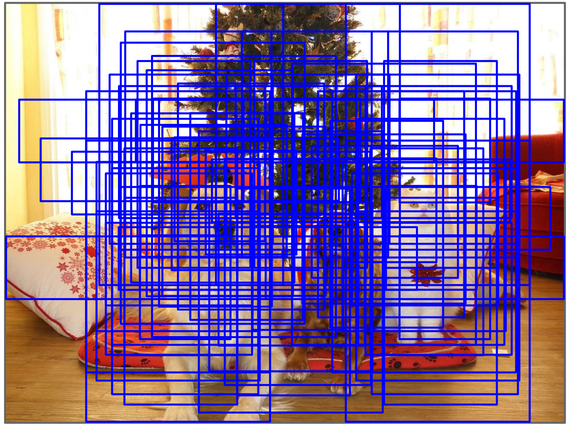


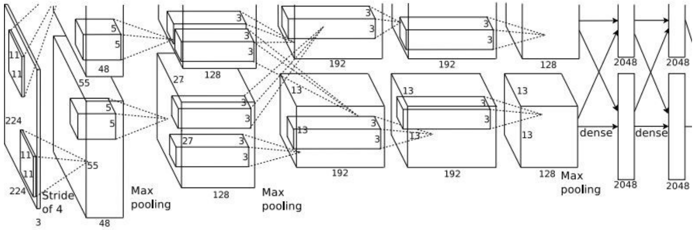

Dog? NO
Cat? YES
Background? NO

Q: What's the problem with this approach?

# Object Detection: Multiple Objects

Apply a CNN to many different crops of the image, CNN classifies each crop as object or background



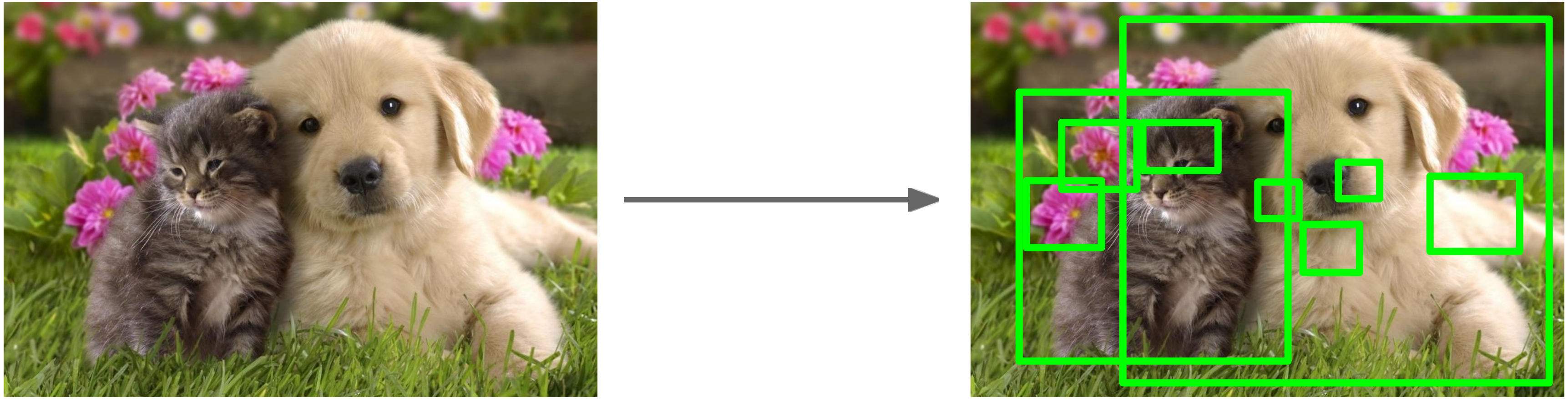



Dog? NO
Cat? YES
Background? NO

Problem: Need to apply CNN to huge number of locations, scales, and aspect ratios, very computationally expensive!

# Region Proposals: Selective Search

- Find “blobby” image regions that are likely to contain objects
- Relatively fast to run; e.g. Selective Search gives 2000 region proposals in a few seconds on CPU



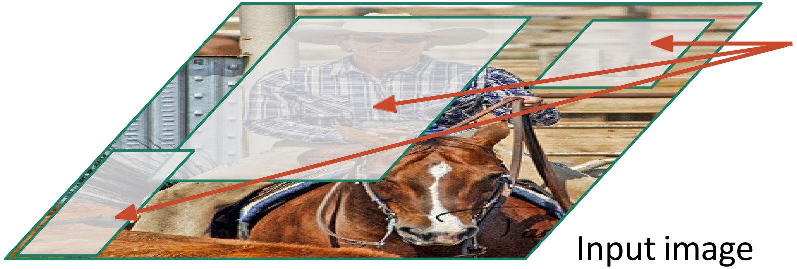
Alexe et al, “Measuring the objectness of image windows”, TPAMI 2012
Uijlings et al, “Selective Search for Object Recognition”, IJCV 2013
Cheng et al, “BING: Binarized normed gradients for objectness estimation at 300fps”, CVPR 2014
Zitnick and Dollar, “Edge boxes: Locating object proposals from edges”, ECCV 2014

# R-CNN

Input image

Girshick et al, "Rich feature hierarchies for accurate object detection and semantic segmentation", CVPR 2014.
Figure copyright Ross Girshick, 2015; source. Reproduced with permission.

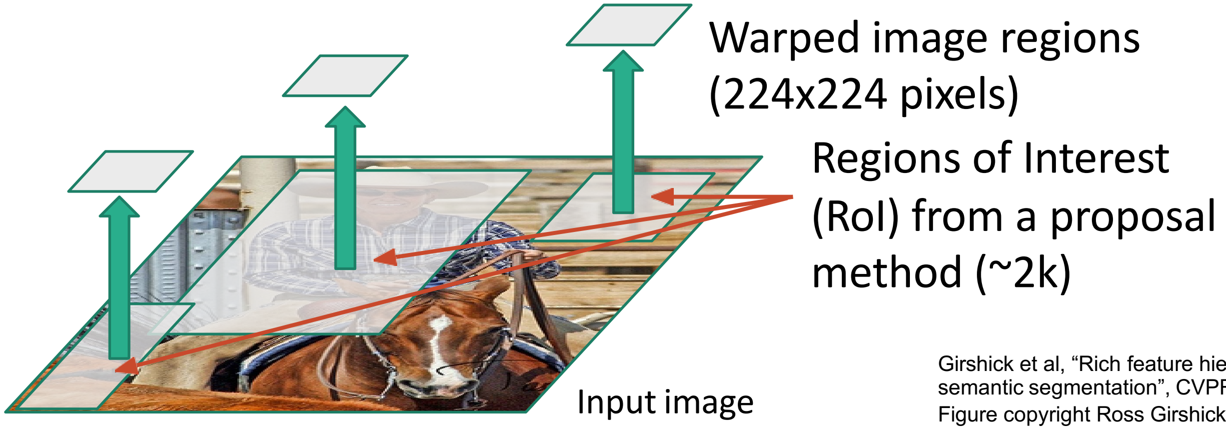
# R-CNN




Regions of Interest (RoI) from a proposal method (~2k)

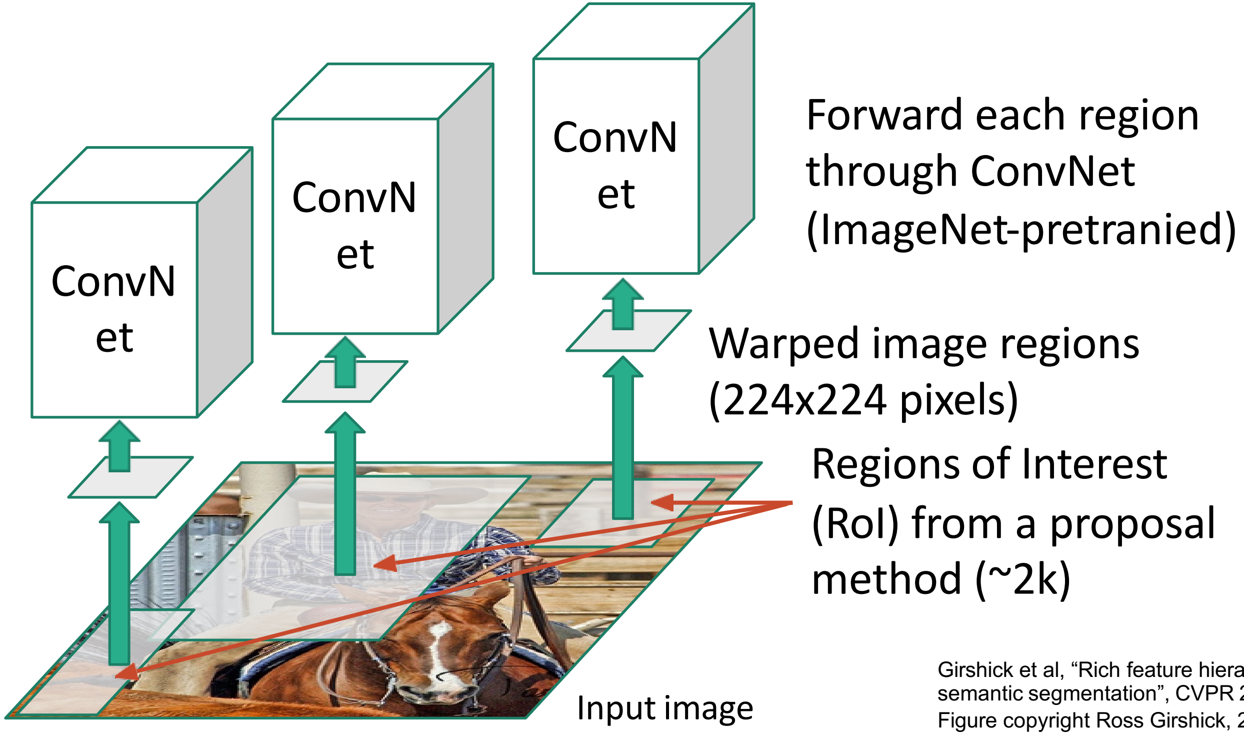
Girshick et al, “Rich feature hierarchies for accurate object detection and semantic segmentation”, CVPR 2014.
Figure copyright Ross Girshick, 2015; source. Reproduced with permission.

# R-CNN



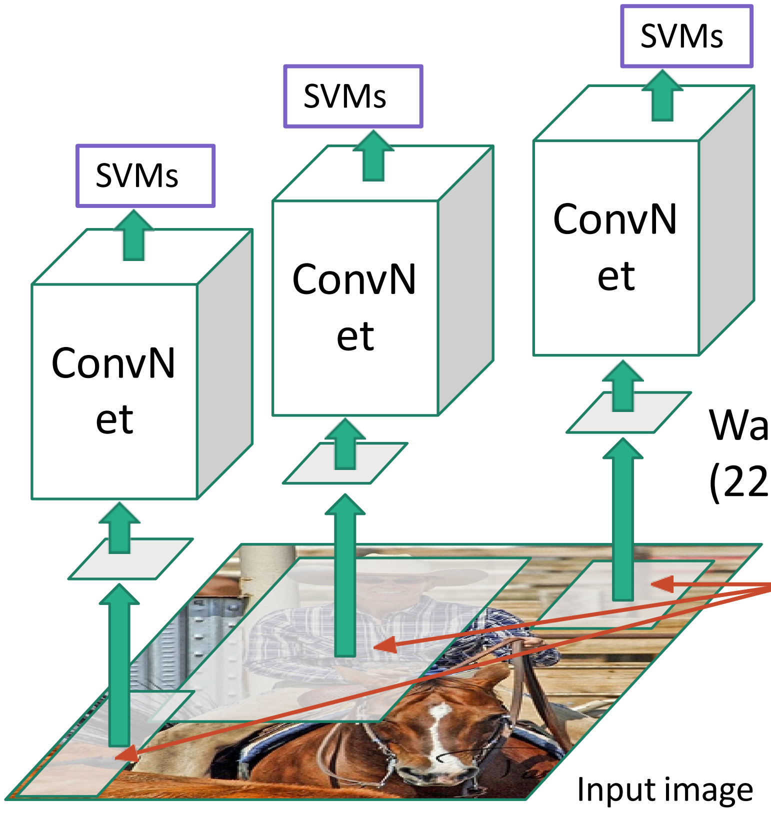

Girshick et al, “Rich feature hierarchies for accurate object detection and semantic segmentation”, CVPR 2014.

# R-CNN




Girshick et al, "Rich feature hierarchies for accurate object detection and semantic segmentation", CVPR 2014.

# R-CNN




Classify regions with SVMs

Forward each region through ConvNet (ImageNet-pretranied)

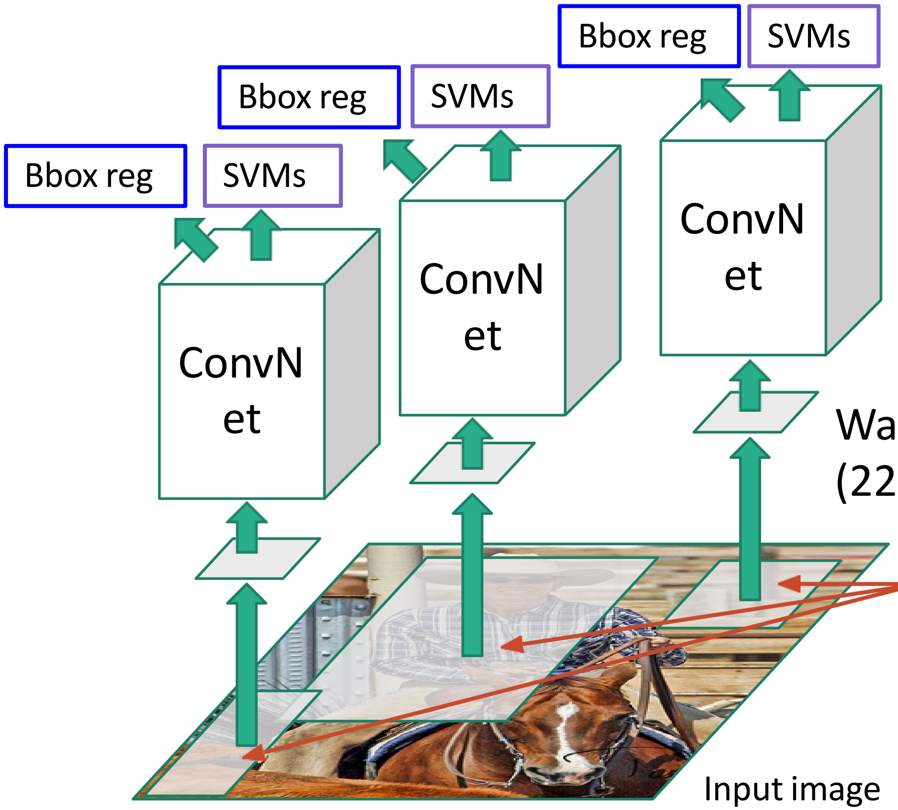
Warped image regions (224x224 pixels)

Regions of Interest (RoI) from a proposal method (~2k)

Girshick et al, “Rich feature hierarchies for accurate object detection and semantic segmentation”, CVPR 2014.
Figure copyright Ross Girshick, 2015; source. Reproduced with permission.

# R-CNN

Predict “corrections” to the RoI: 4 numbers: (dx, dy, dw, dh)

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Regions of Interest (RoI) from a proposal method (~2k)

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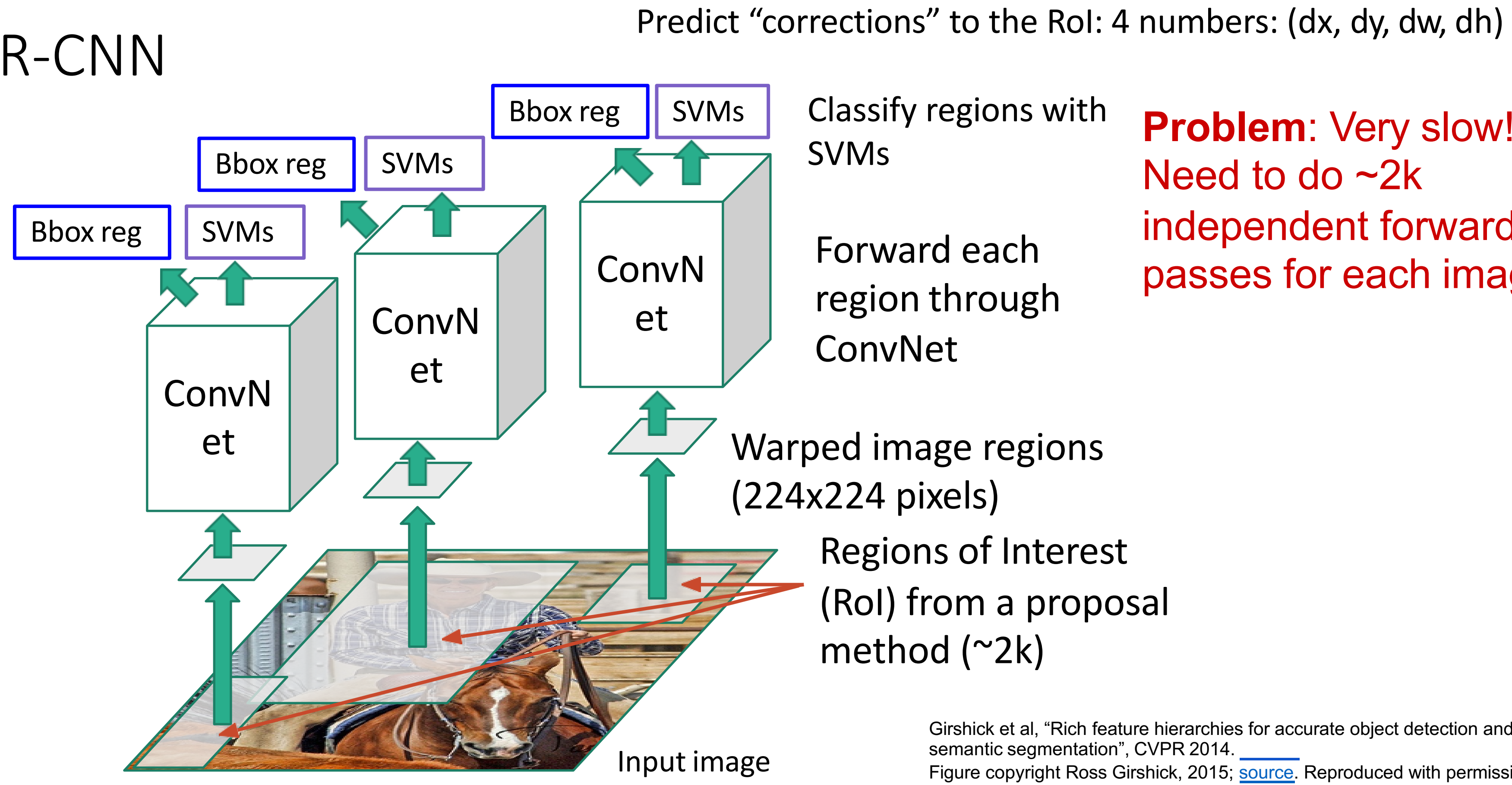
Figure copyright Ross Girshick, 2015; source. Reproduced with permission.

# R-CNN

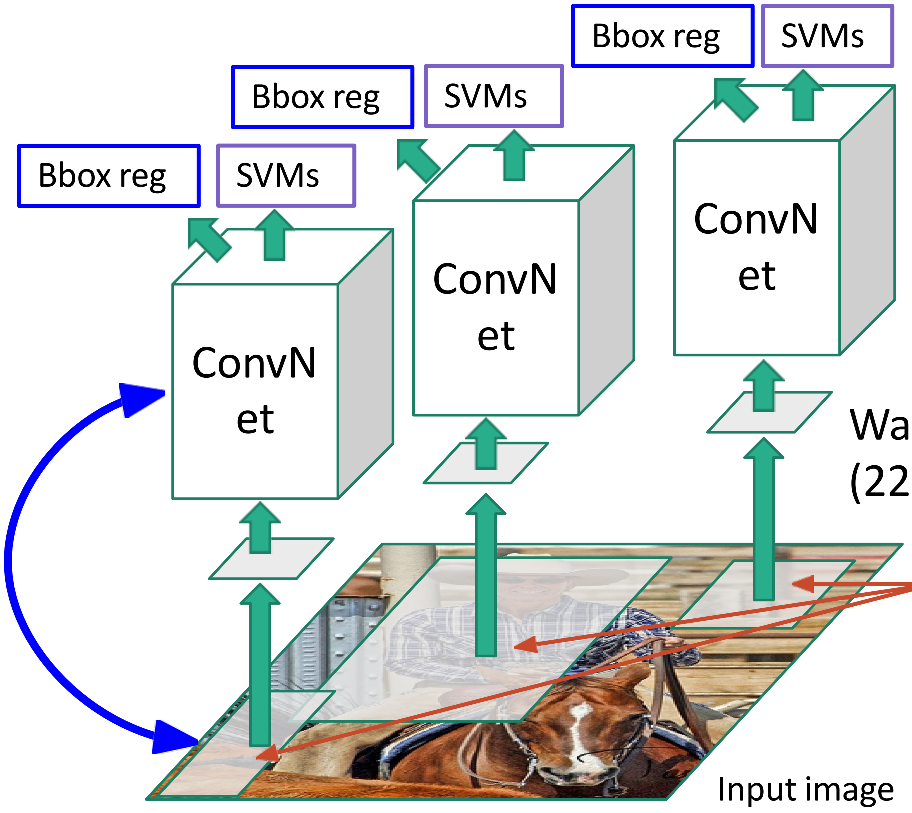



**Problem**: Very slow! Need to do ~2k independent forward passes for each image!

Girshick et al, “Rich feature hierarchies for accurate object detection and semantic segmentation”, CVPR 2014.

# “Slow” R-CNN

Predict “corrections” to the RoI: 4 numbers: (dx, dy, dw, dh)




Classify regions with SVMs

Forward each region through ConvNet

Warped image regions (224x224 pixels)

Regions of Interest (RoI) from a proposal method (~2k)

**Problem**: Very slow! Need to do ~2k independent forward passes for each image!

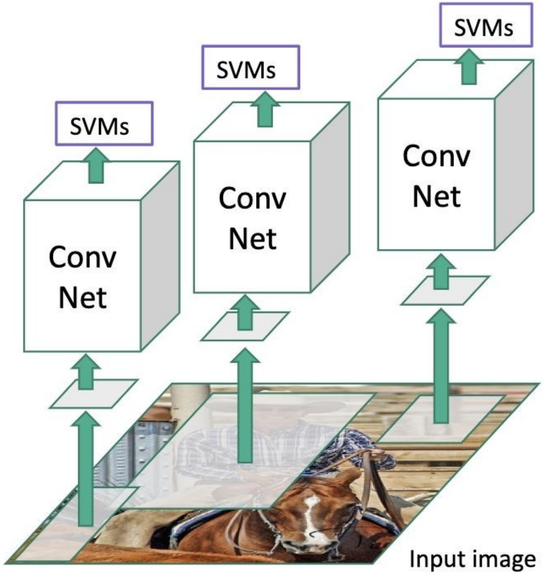
**Idea:** Pass the image through convnet before cropping! Crop the conv feature instead!

Girshick et al, “Rich feature hierarchies for accurate object detection and semantic segmentation”, CVPR 2014.

# Fast R-CNN

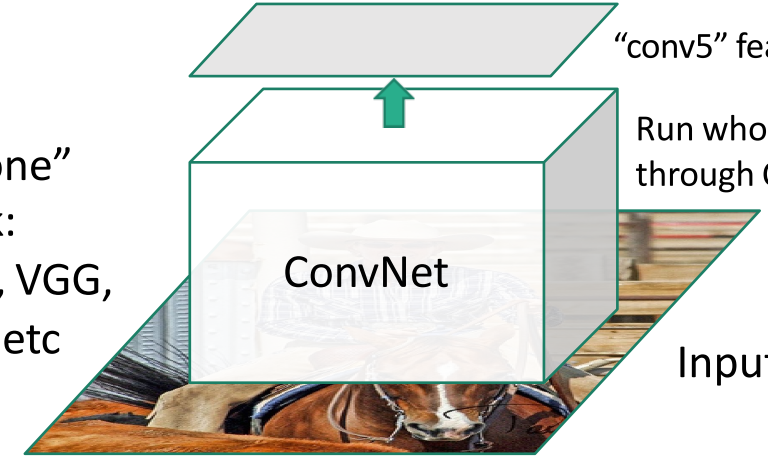
Input image

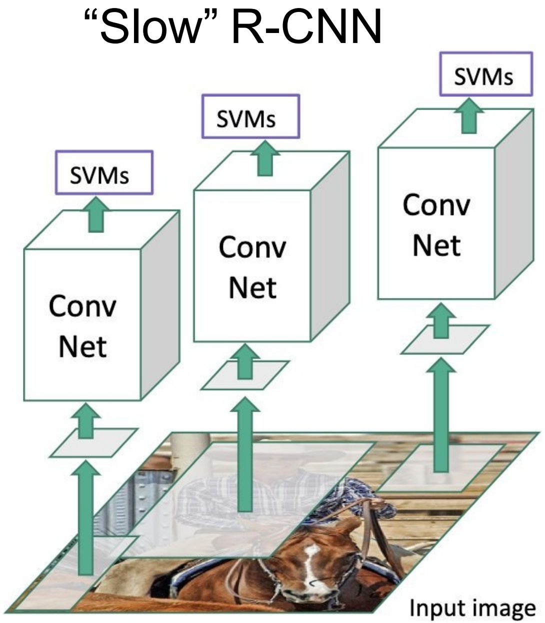
“Slow” R-CNN



# Fast R-CNN

"Backbone" network: AlexNet, VGG, ResNet, etc

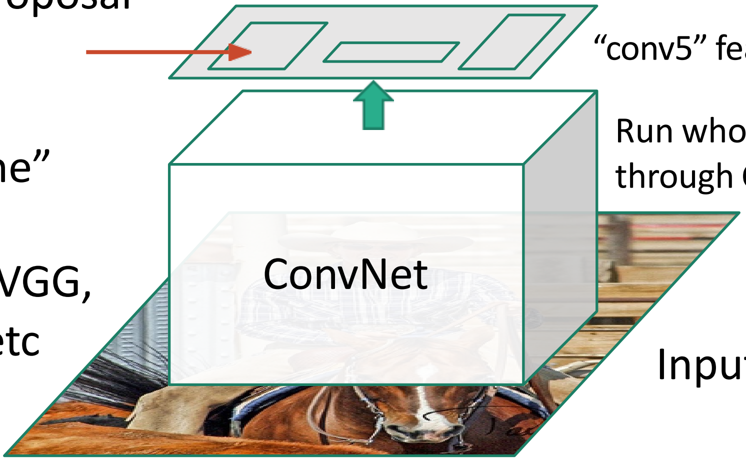


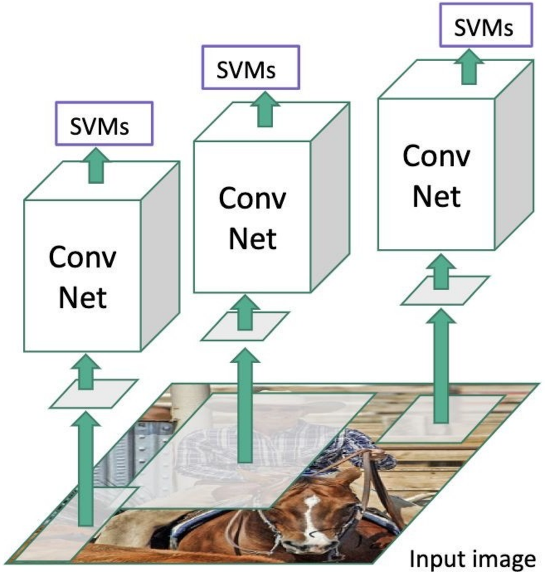
# Fast R-CNN

Regions of Interest (RoIs) from a proposal method

"Backbone" network: AlexNet, VGG, ResNet, etc




"Slow" R-CNN

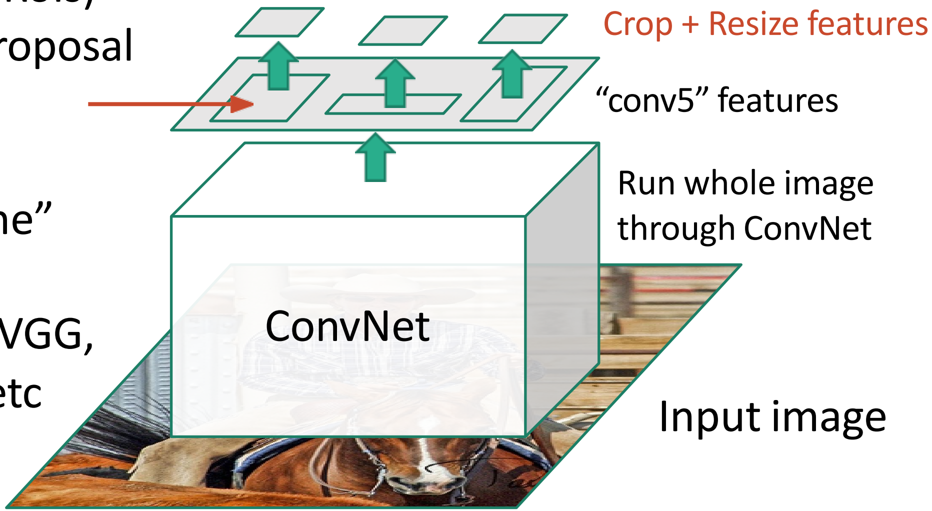



Girshick, "Fast R-CNN", ICCV 2015. Figure copyright Ross Girshick, 2015; source. Reproduced with permission.

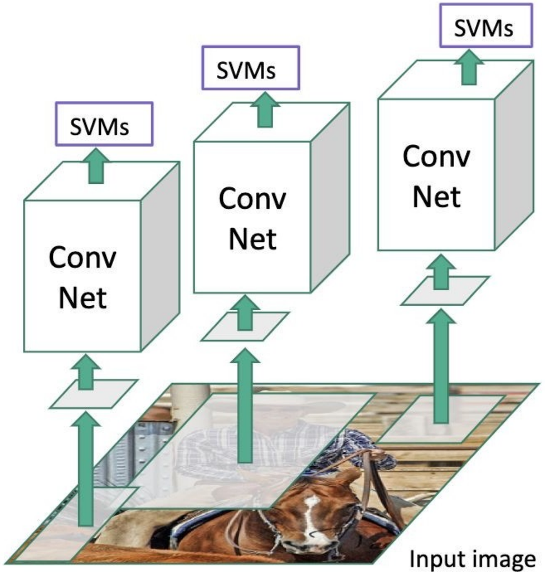
# Fast R-CNN

Regions of Interest (RoIs) from a proposal method

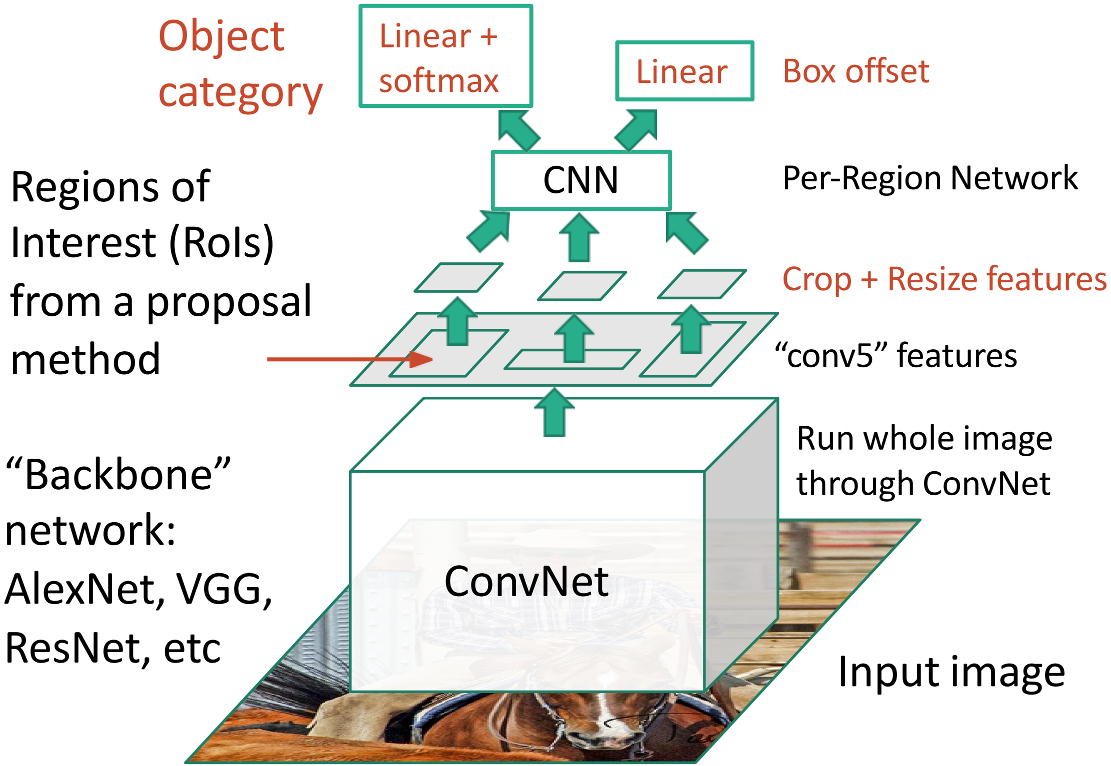
"Backbone" network: AlexNet, VGG, ResNet, etc

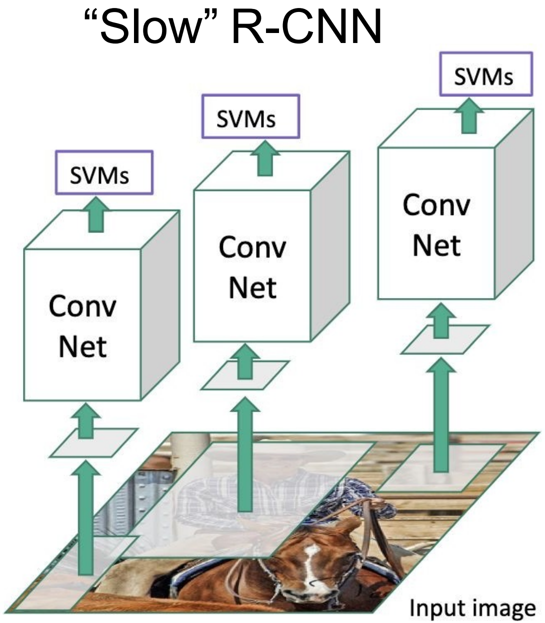



"Slow" R-CNN



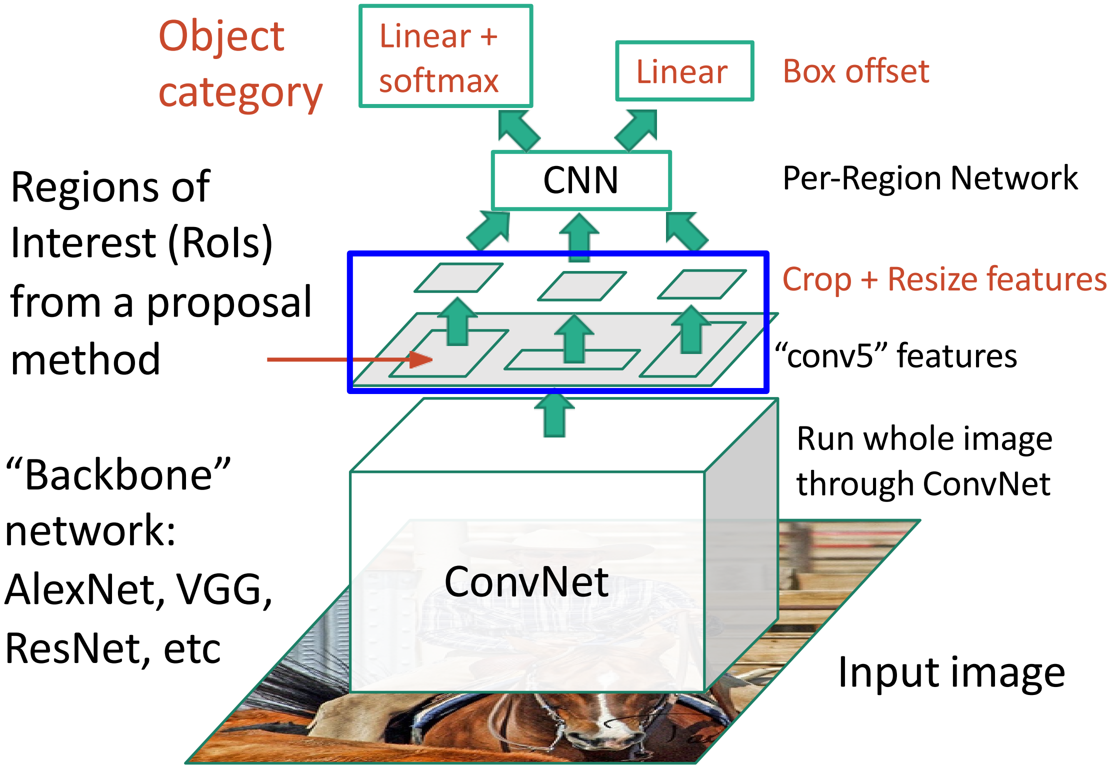
# Fast R-CNN

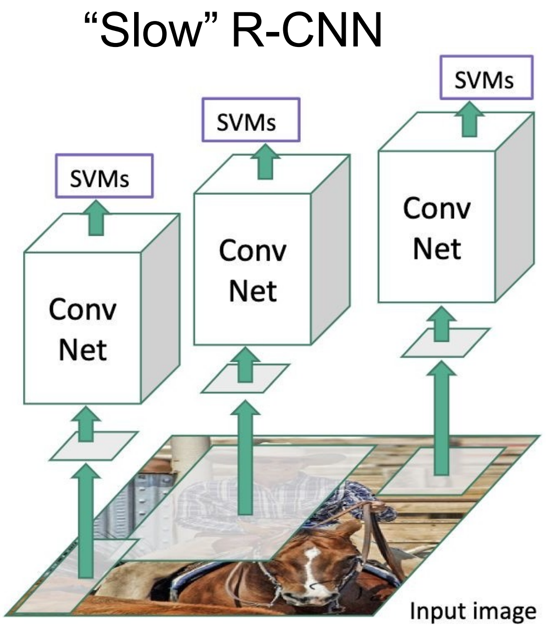



Girshick, "Fast R-CNN", ICCV 2015. Figure copyright Ross Girshick, 2015; source. Reproduced with permission.

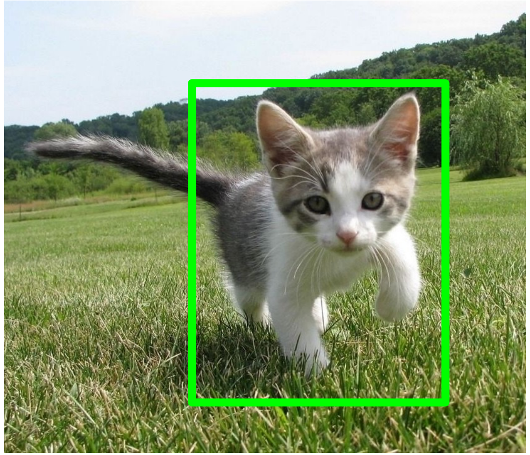
# Fast R-CNN




Girshick, "Fast R-CNN", ICCV 2015. Figure copyright Ross Girshick, 2015; source. Reproduced with permission.

# Cropping Features: RoI Pool



Input Image
(e.g. 3 x 640 x 480)

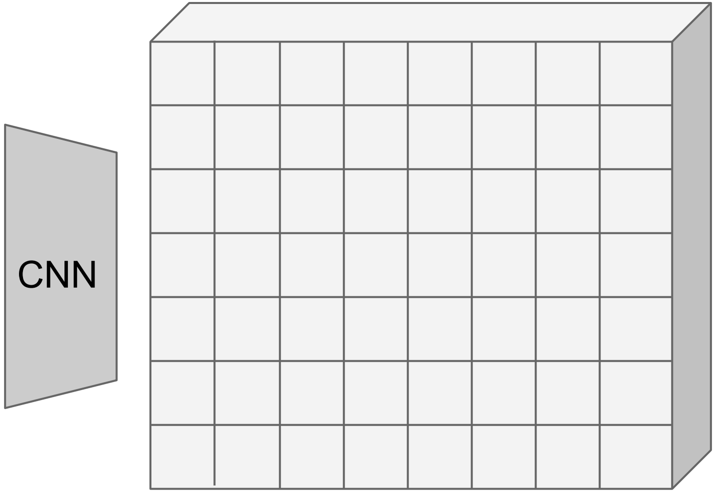
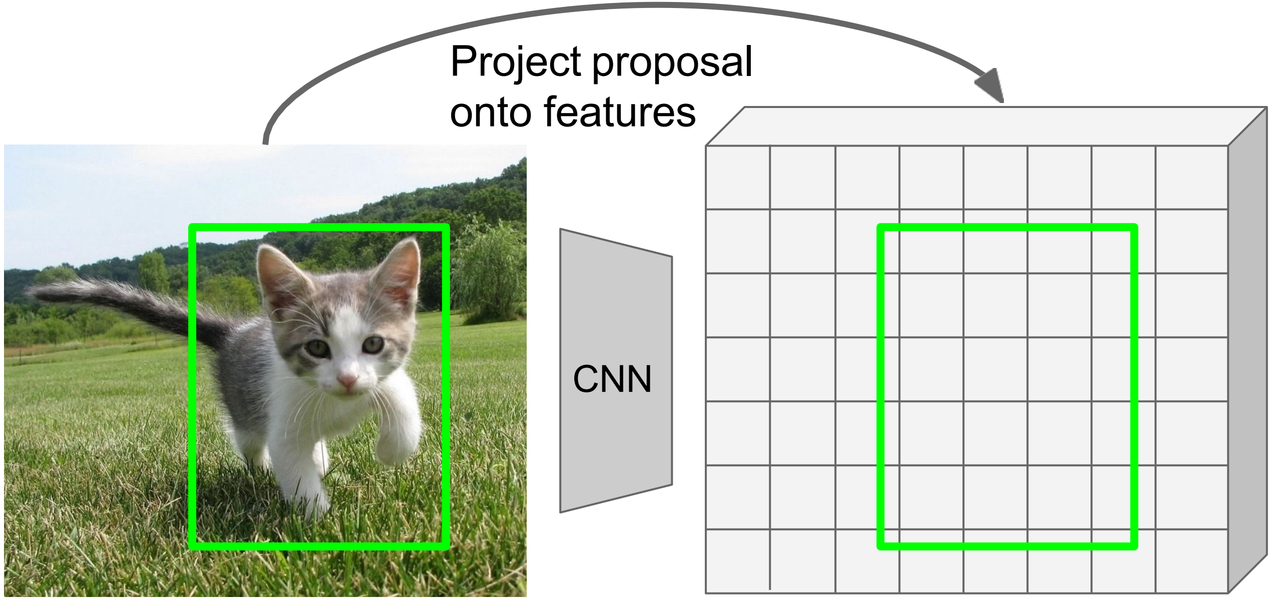



Image features: C x H x W
(e.g. 512 x 20 x 15)

Girshick, “Fast R-CNN”, ICCV 2015.

Girshick, “Fast R-CNN”, ICCV 2015.

# Cropping Features: RoI Pool




Input Image
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Image features: C x H x W
(e.g. 512 x 20 x 15)

Girshick, "Fast R-CNN", ICCV 2015.

Girshick, "Fast R-CNN", ICCV 2015.

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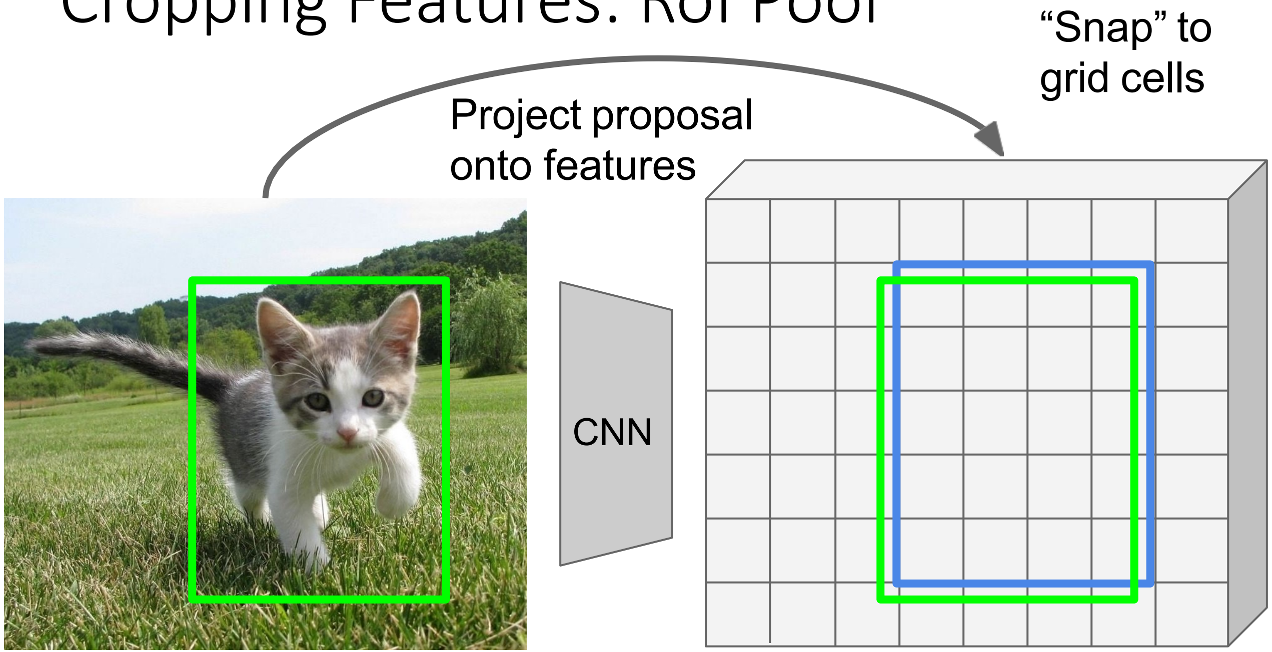


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Girshick, “Fast R-CNN”, ICCV 2015.

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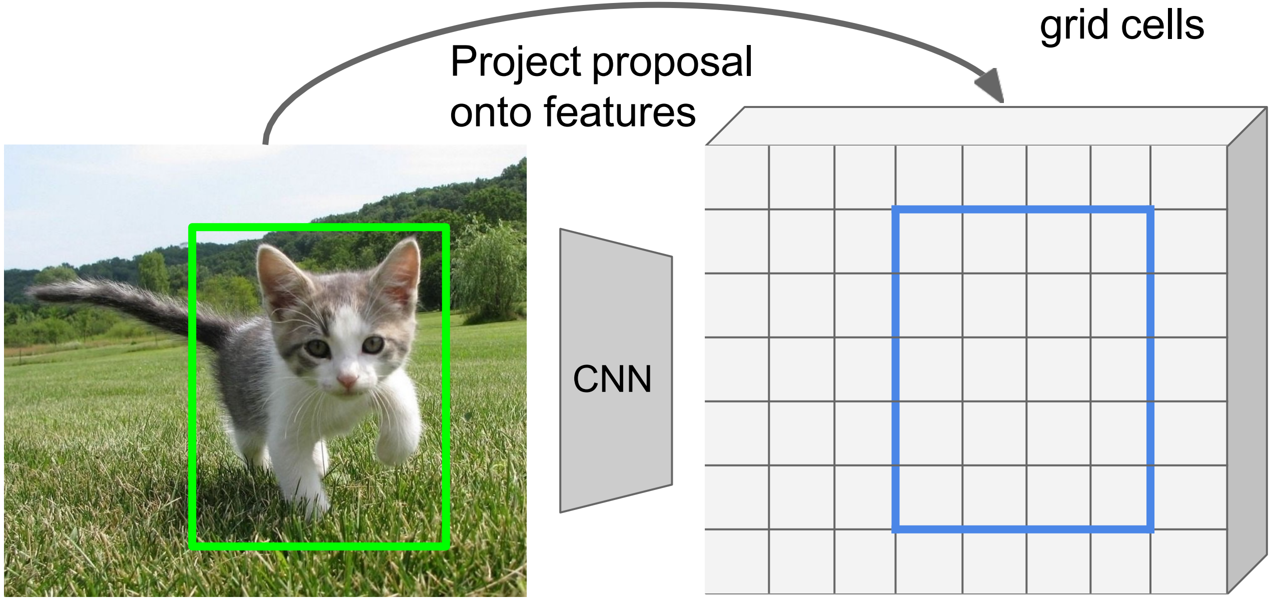


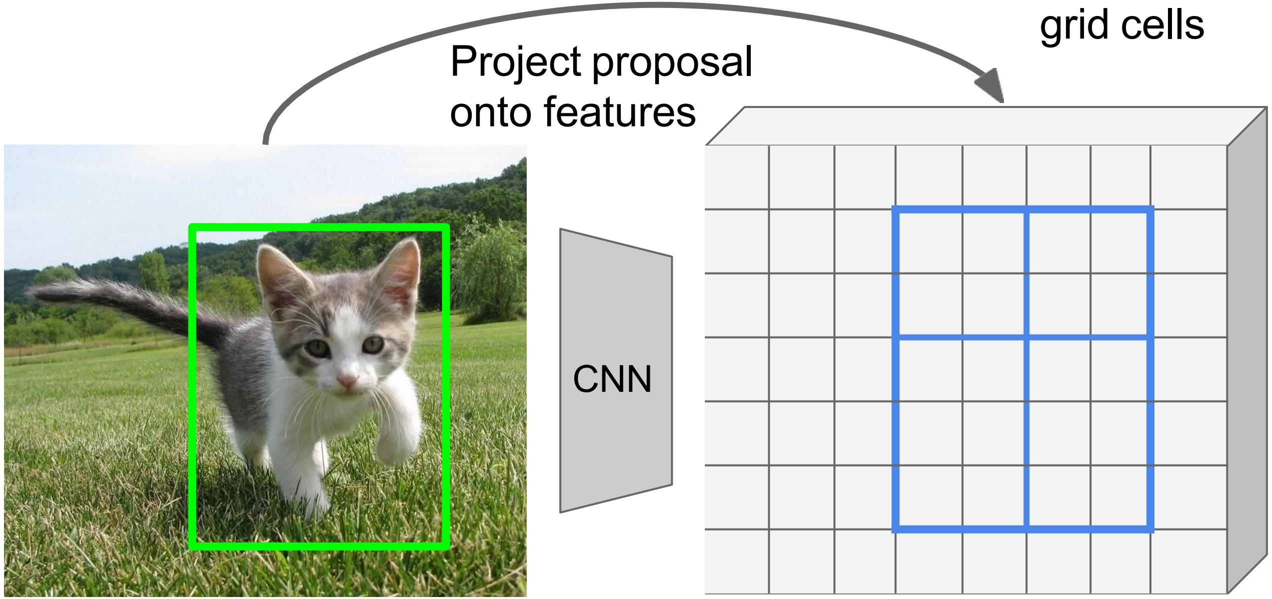

Input Image
(e.g. 3 x 640 x 480)

Image features: C x H x W
(e.g. 512 x 20 x 15)

Q: how do we resize the 512 x 5 x 4 region to, e.g., a 512 x 2 x 2 tensor?.

Girshick, "Fast R-CNN", ICCV 2015.

# Cropping Features: RoI Pool




Input Image
(e.g. 3 x 640 x 480)

Image features: C x H x W
(e.g. 512 x 20 x 15)

"Snap" to grid cells

Divide into 2x2 grid of (roughly) equal subregions

Q: how do we resize the 512 x 5 x 4 region to, e.g., a 512 x 2 x 2 tensor?.

Girshick, "Fast R-CNN", ICCV 2015.

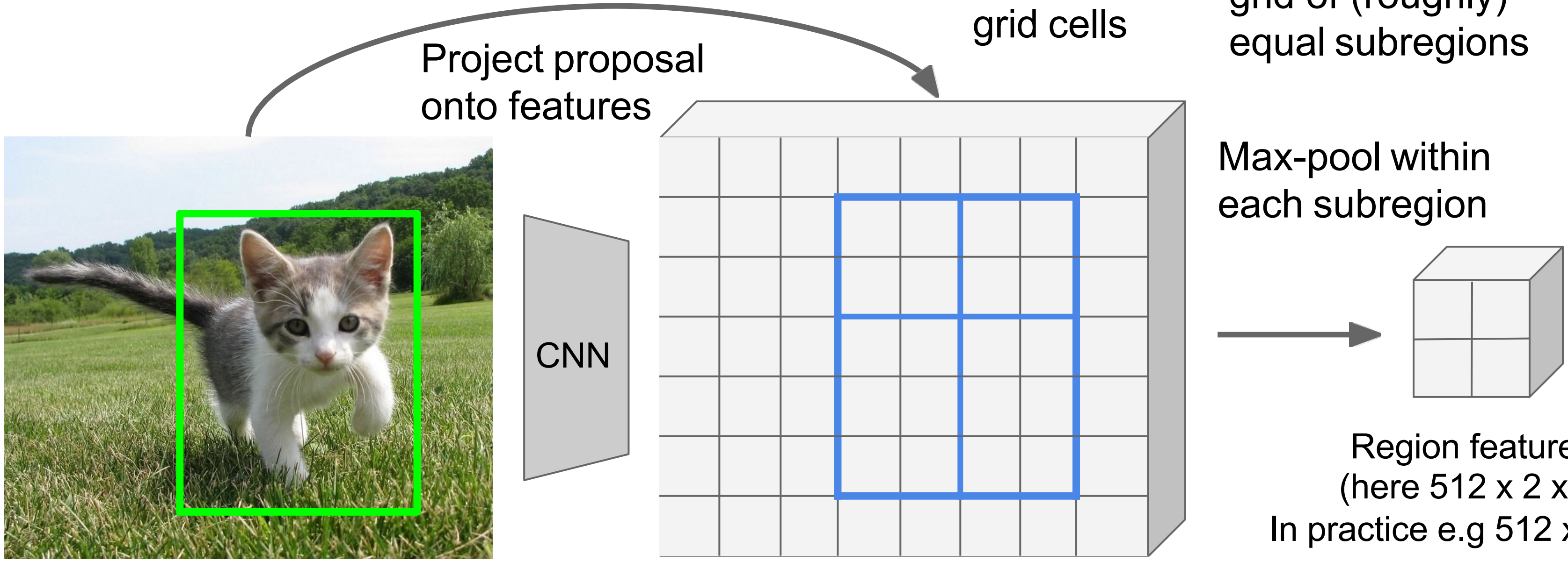
# Cropping Features: RoI Pool

"Snap" to grid cells

Divide into 2x2 grid of (roughly) equal subregions

Project proposal onto features

Max-pool within each subregion




Input Image
(e.g. 3 x 640 x 480)

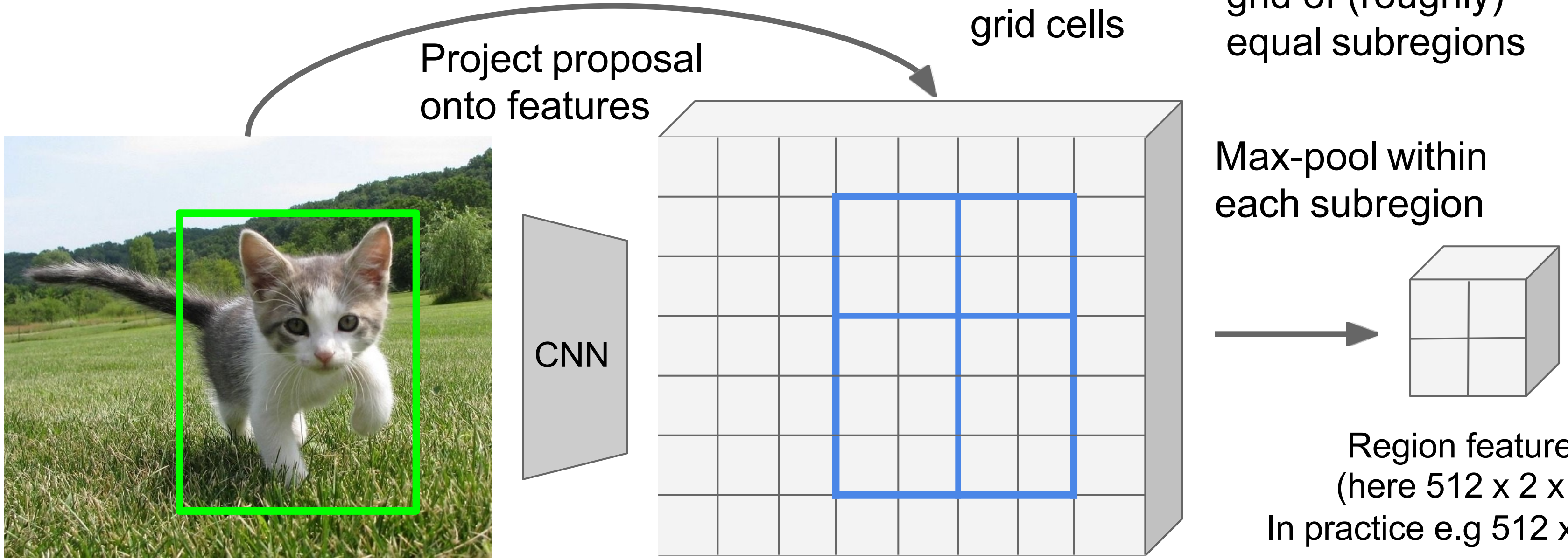
Image features: C x H x W
(e.g. 512 x 20 x 15)

Region features
(here 512 x 2 x 2;
In practice e.g 512 x 7 x 7)

Region features always the same size even if input regions have different sizes!

Girshick, "Fast R-CNN", ICCV 2015.

# Cropping Features: RoI Pool




Input Image
(e.g. 3 x 640 x 480)

"Snap" to
grid cells

Image features: C x H x W
(e.g. 512 x 20 x 15)

Divide into 2x2
grid of (roughly)
equal subregions

Max-pool within
each subregion

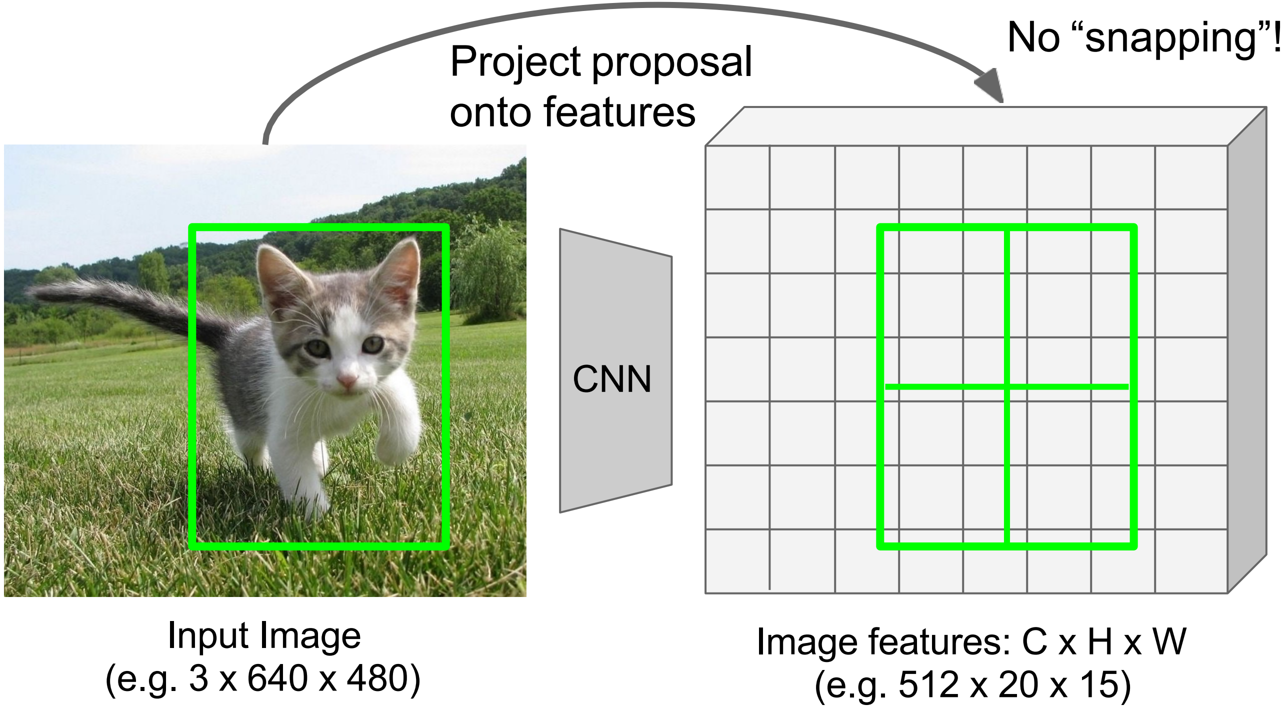
Region features
(here 512 x 2 x 2;
In practice e.g 512 x 7 x 7)

Region features always the
same size even if input
regions have different sizes!

**Problem**: Region features slightly misaligned

Girshick, "Fast R-CNN", ICCV 2015.

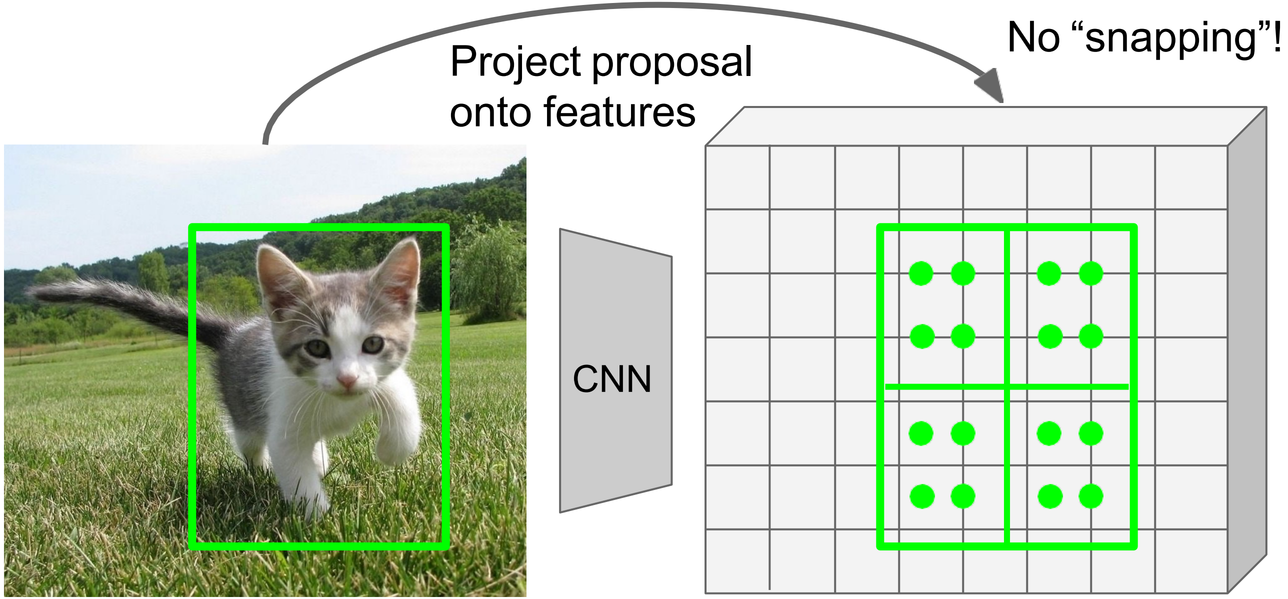
# Cropping Features: RoI Align




He et al, "Mask R-CNN", ICCV 2017

# Cropping Features: RoI Align

Sample at regular points in each subregion using bilinear interpolation



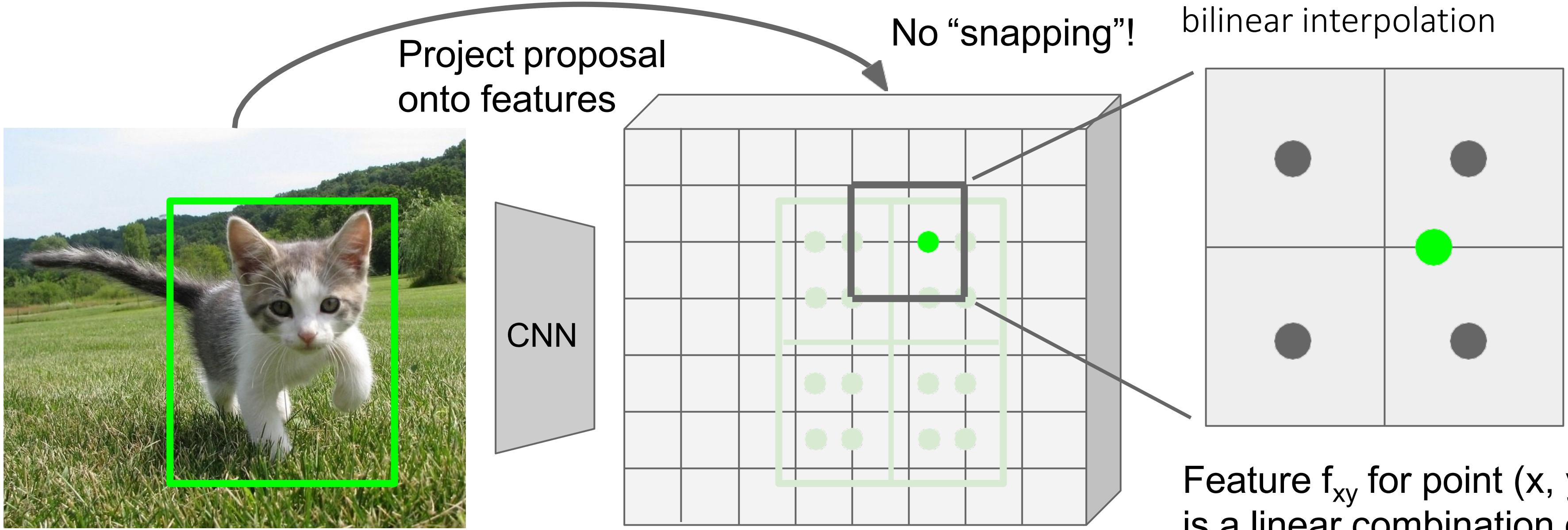

Input Image
(e.g. 3 x 640 x 480)

Image features: C x H x W
(e.g. 512 x 20 x 15)

He et al, “Mask R-CNN”, ICCV 2017

# Cropping Features: RoI Align

Sample at regular points in each subregion using bilinear interpolation




Input Image
(e.g. 3 x 640 x 480)

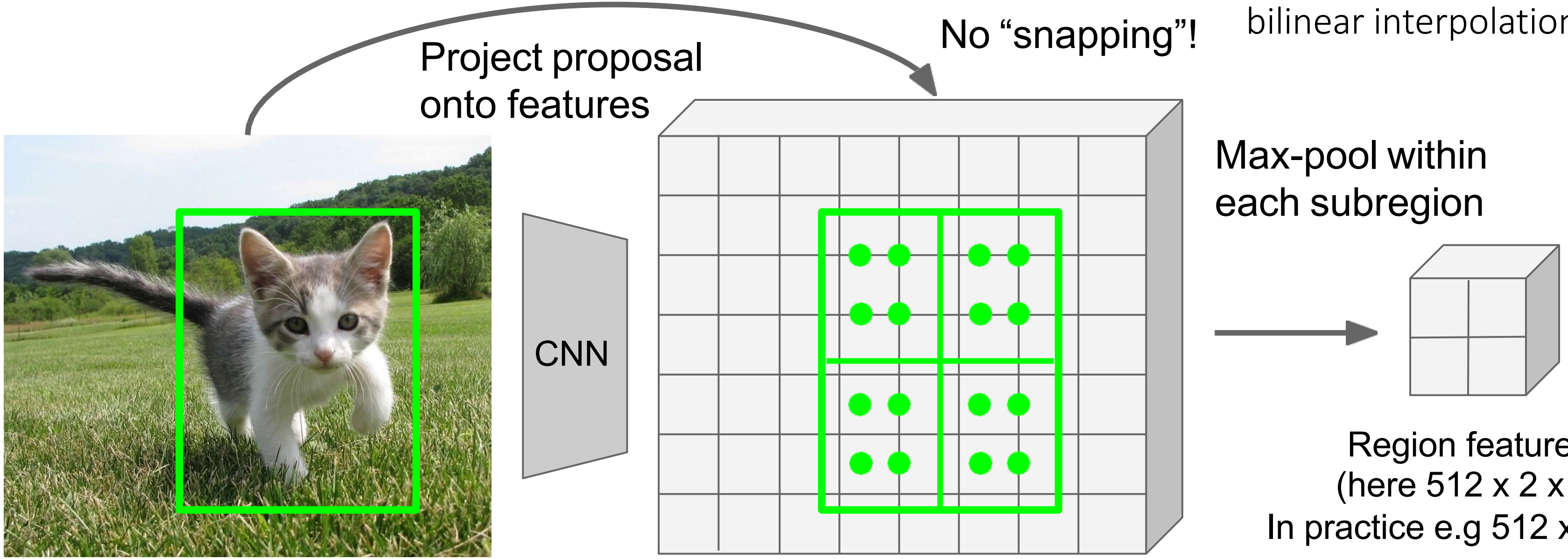
Image features: C x H x W
(e.g. 512 x 20 x 15)

Feature $f_{xy}$ for point (x, y) is a linear combination of features at its four neighboring grid cells:

He et al, “Mask R-CNN”, ICCV 2017

# Cropping Features: RoI Align

Sample at regular points in each subregion using bilinear interpolation




Input Image
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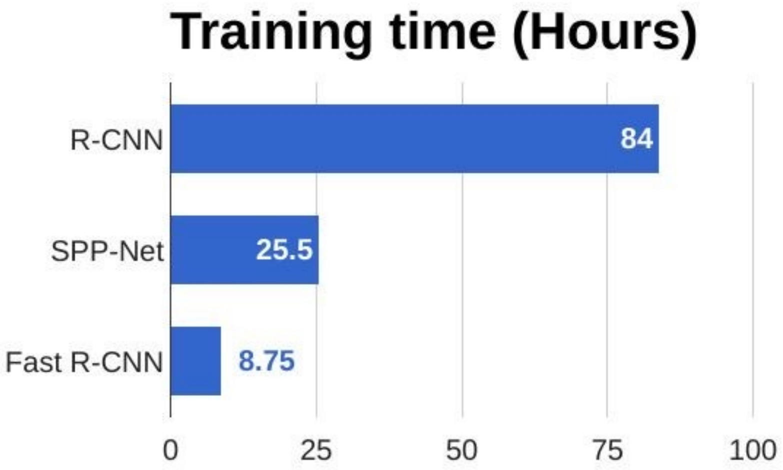
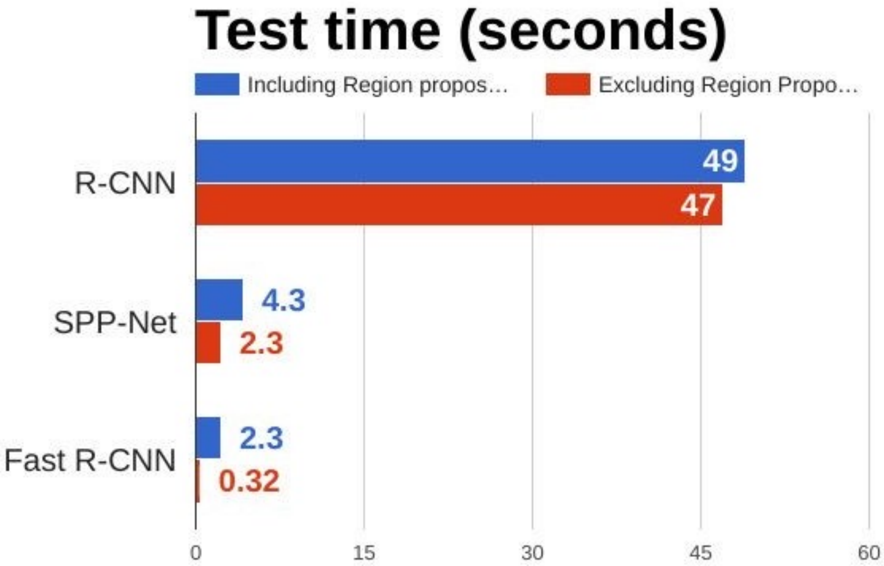
Image features: C x H x W
(e.g. 512 x 20 x 15)

Region features
(here 512 x 2 x 2;
In practice e.g 512 x 7 x 7)

He et al, “Mask R-CNN”, ICCV 2017

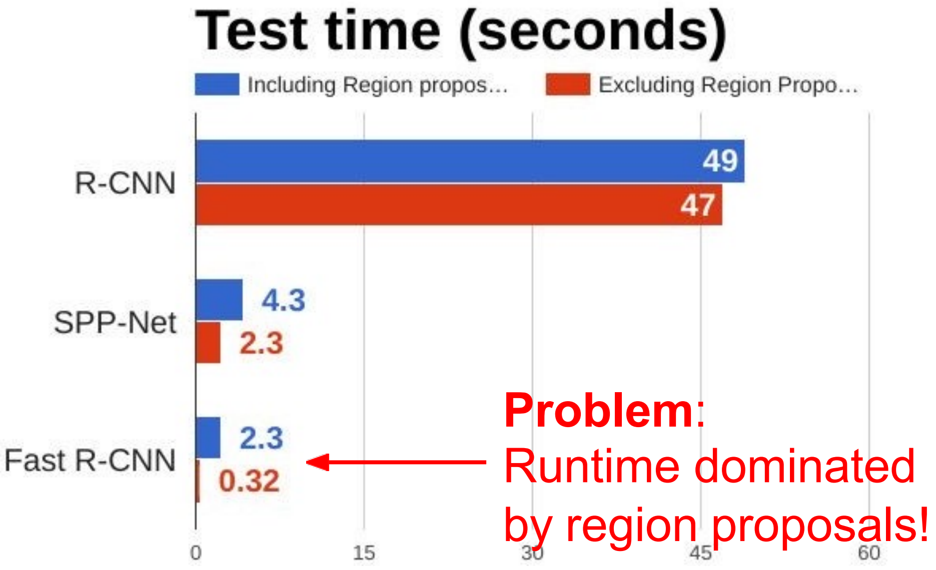
# R-CNN vs Fast R-CNN




Girshick et al, "Rich feature hierarchies for accurate object detection and semantic segmentation", CVPR 2014.
He et al, "Spatial pyramid pooling in deep convolutional networks for visual recognition", ECCV 2014
Girshick, "Fast R-CNN", ICCV 2015

# R-CNN vs Fast R-CNN

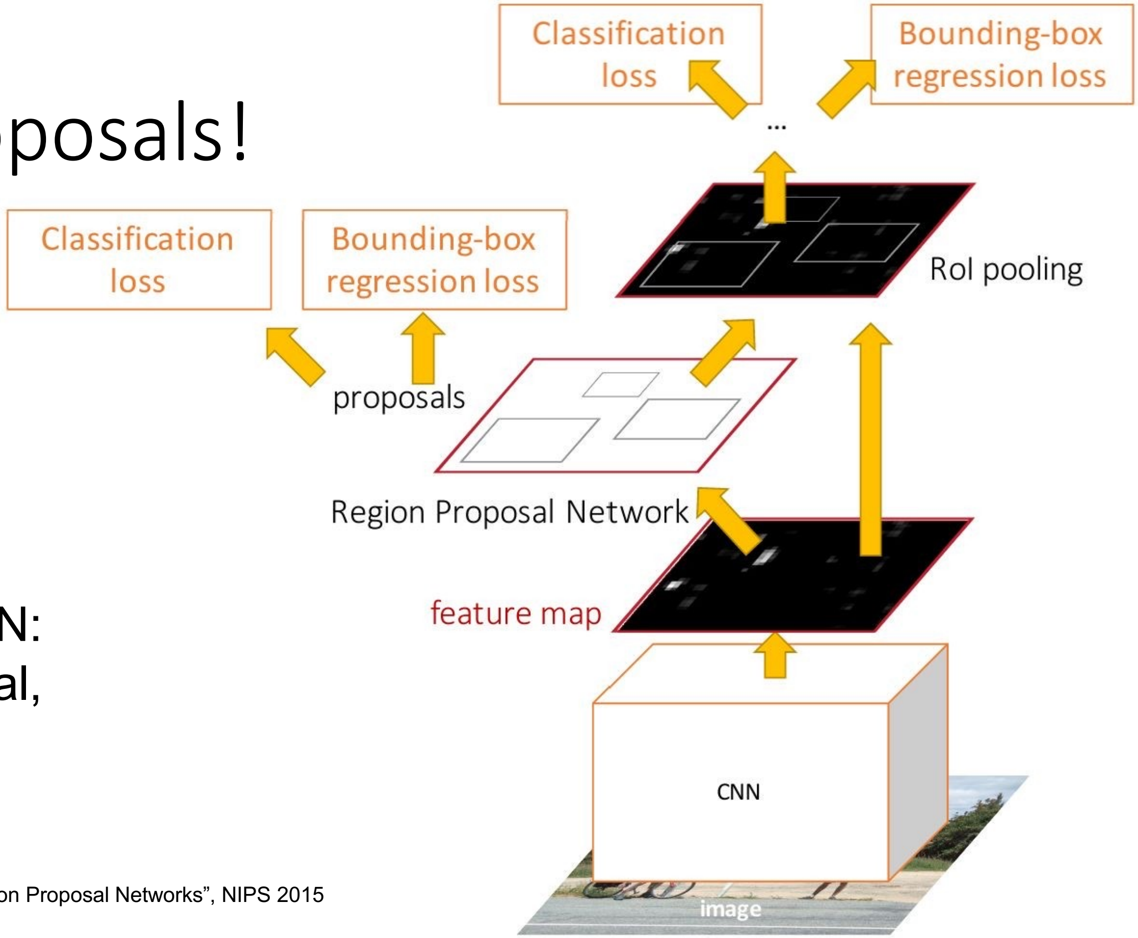




Girshick et al, “Rich feature hierarchies for accurate object detection and semantic segmentation”, CVPR 2014.
He et al, “Spatial pyramid pooling in deep convolutional networks for visual recognition”, ECCV 2014
Girshick, “Fast R-CNN”, ICCV 2015

# Fast**er** R-CNN:
# Make CNN do proposals!

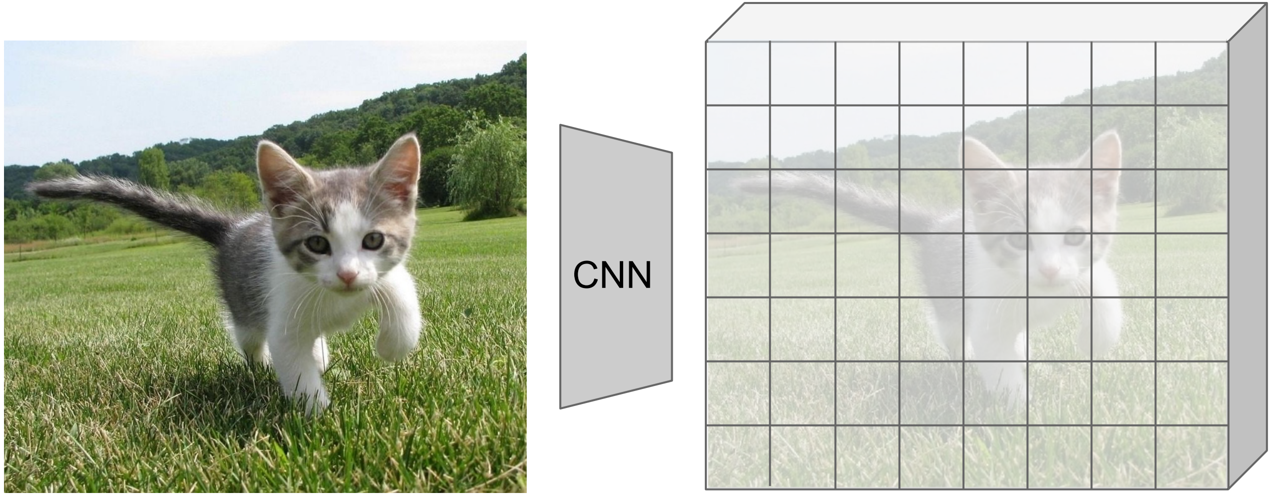
Insert **Region Proposal Network (RPN)** to predict proposals from features

Otherwise same as Fast R-CNN: Crop features for each proposal, classify each one




Ren et al, “Faster R-CNN: Towards Real-Time Object Detection with Region Proposal Networks”, NIPS 2015

# Region Proposal Network

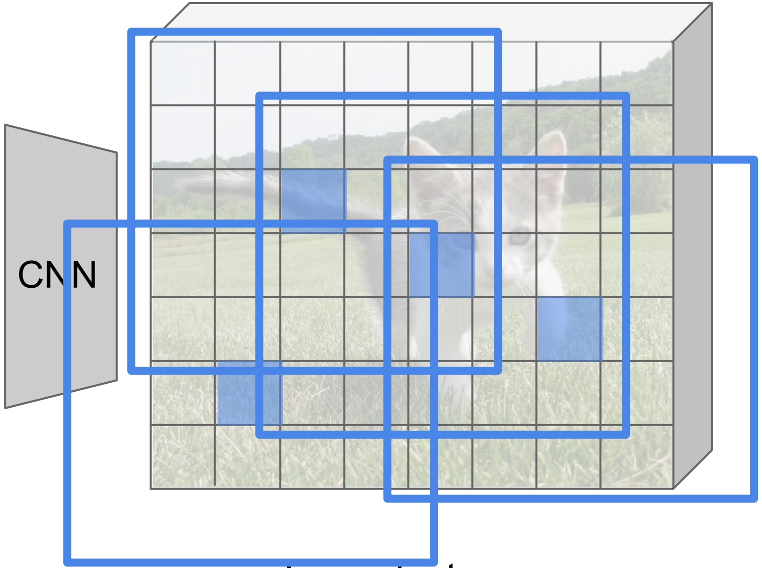



Input Image
(e.g. 3 x 640 x 480)

Image features
(e.g. 512 x 20 x 15)

# Region Proposal Network

Imagine an **anchor box** of fixed size at each point in the feature map

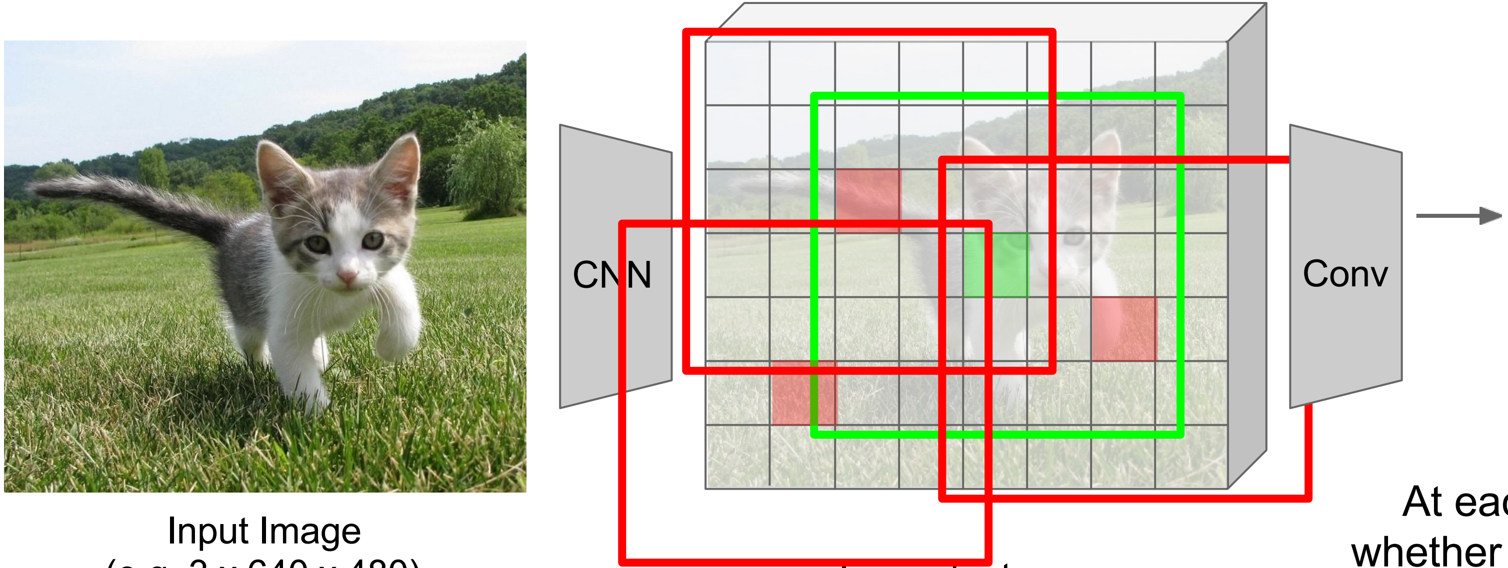



Input Image
(e.g. 3 x 640 x 480)

Image features
(e.g. 512 x 20 x 15)

# Region Proposal Network

Imagine an **anchor box** of fixed size at each point in the feature map




Input Image
(e.g. 3 x 640 x 480)

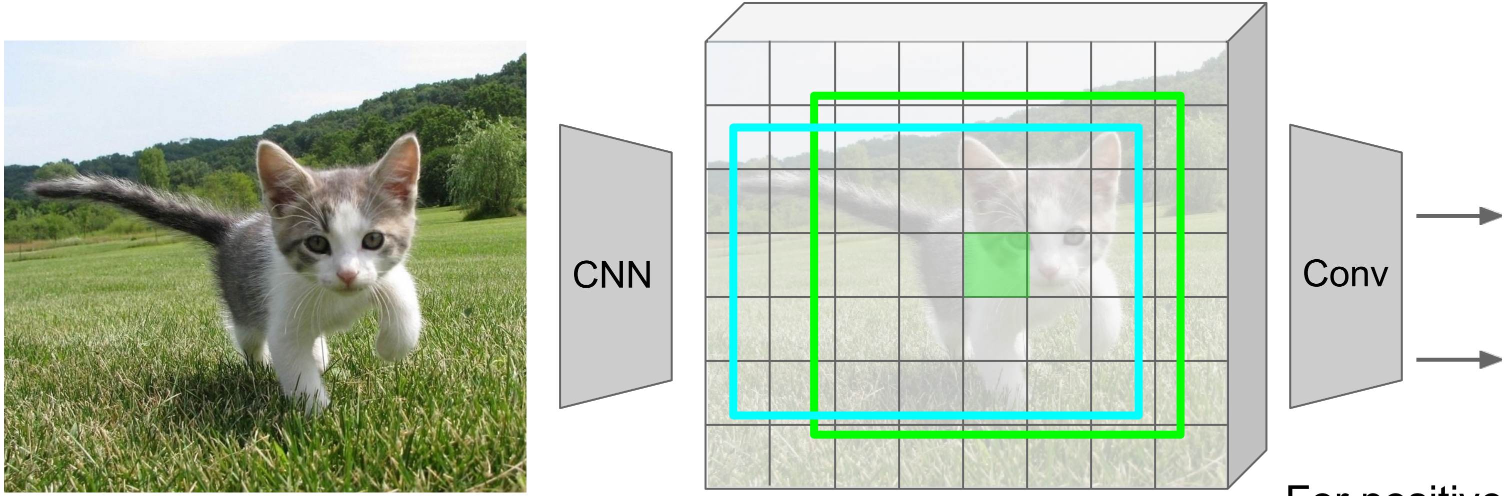
Image features
(e.g. 512 x 20 x 15)

Anchor has an object?
1 x 20 x 15

At each point, predict whether the corresponding anchor contains an object (binary classification)

# Region Proposal Network

Imagine an **anchor box** of fixed size at each point in the feature map




Input Image
(e.g. 3 x 640 x 480)

Image features
(e.g. 512 x 20 x 15)

Anchor has an object?
1 x 20 x 15

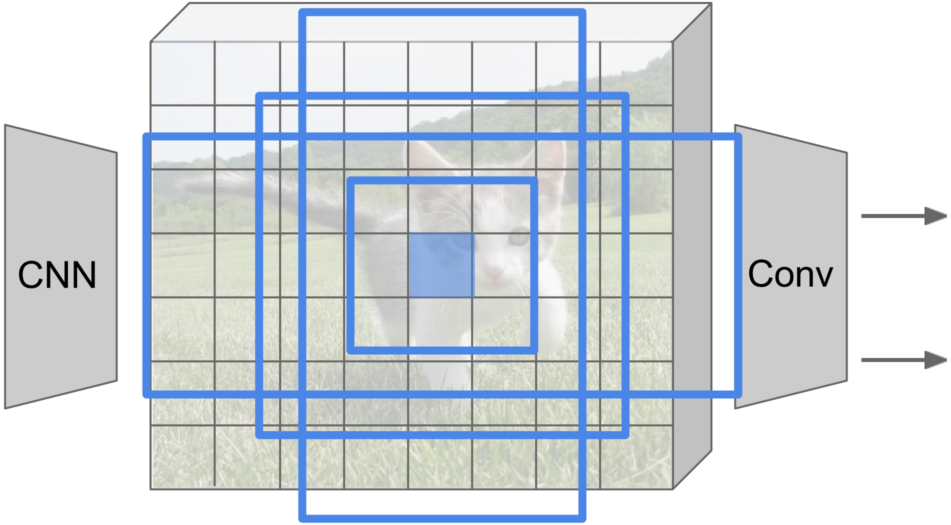
Box corrections
4 x 20 x 15

For positive boxes, also predict a corrections from the anchor to the ground-truth box (regress 4 numbers per pixel)

# Region Proposal Network

In practice use K different anchor boxes of different size / scale at each point

Input Image
(e.g. 3 x 640 x 480)



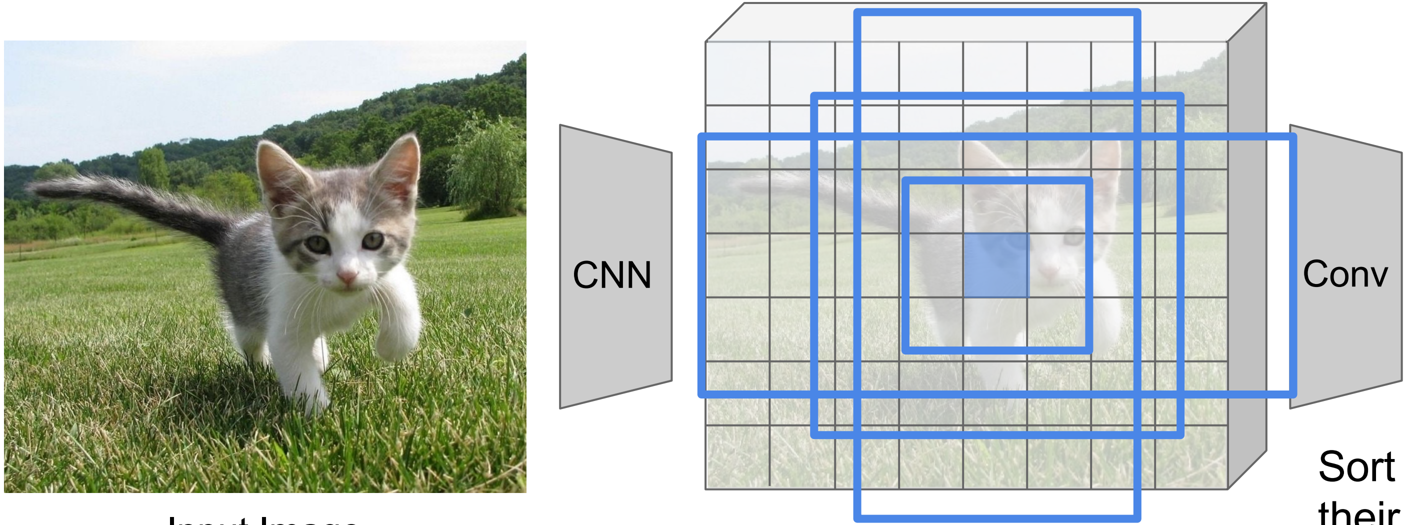

Anchor has an object?
**K** x 20 x 15

Box transforms
**4K** x 20 x 15

Image features
(e.g. 512 x 20 x 15)

# Region Proposal Network

In practice use K different anchor boxes of different size / scale at each point




Input Image
(e.g. 3 x 640 x 480)

Image features
(e.g. 512 x 20 x 15)

Anchor has an object?
**K** x 20 x 15

Box transforms
**4K** x 20 x 15

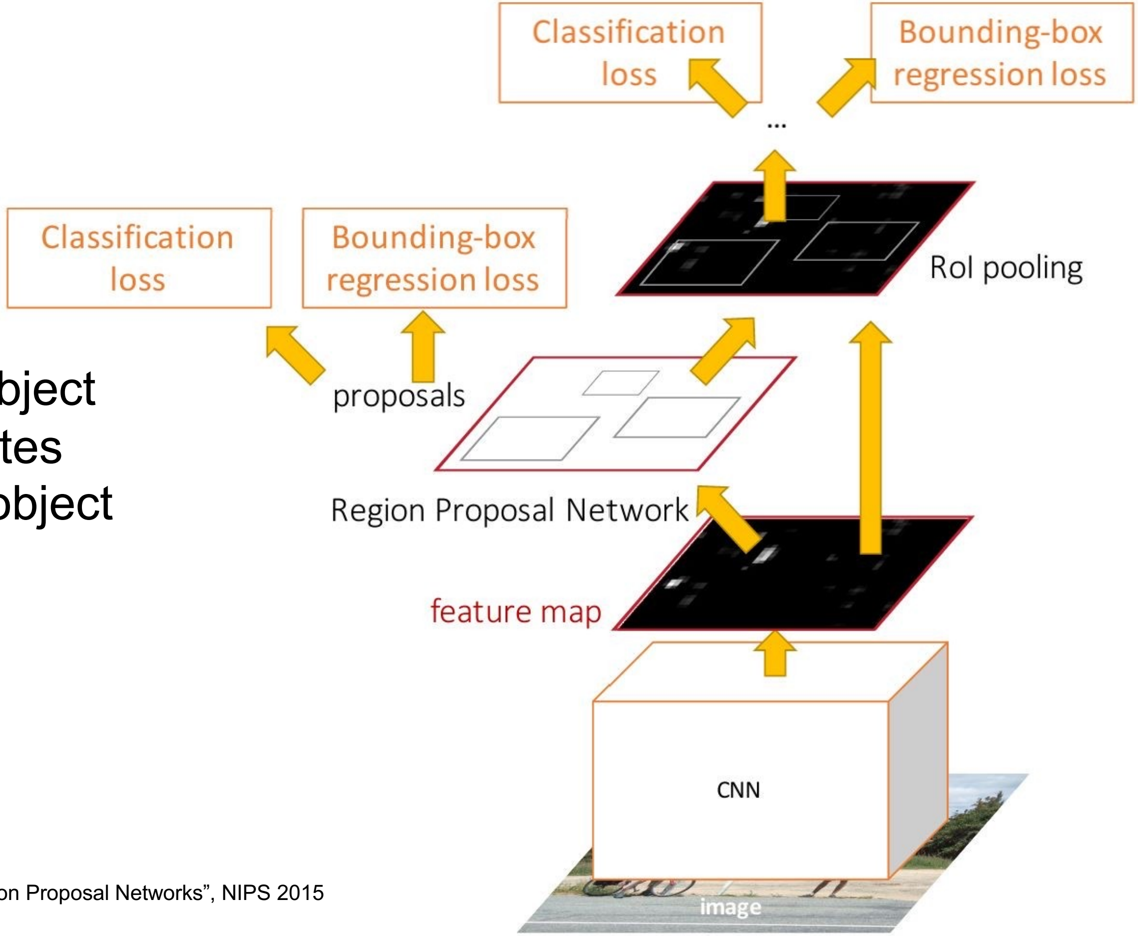
Sort the K*20*15 boxes by their “objectness” score, take top ~300 as our proposals

Fast**er** R-CNN:

# Make CNN do proposals!

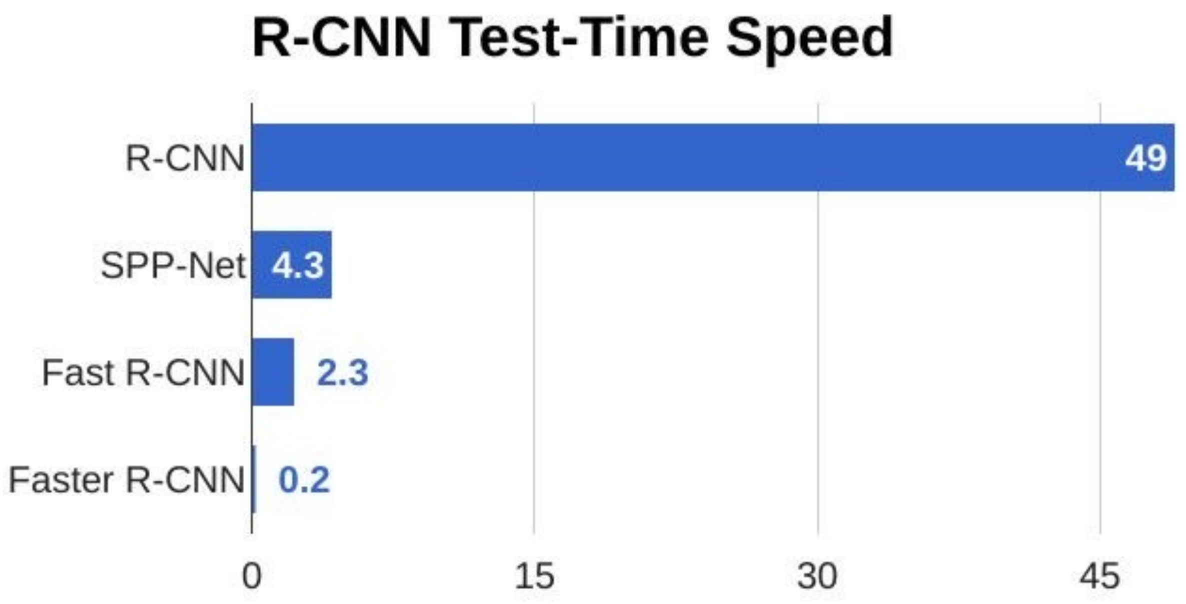
Jointly train with 4 losses:

1. RPN classify object / not object
2. RPN regress box coordinates
3. Final classification score (object classes)
4. Final box coordinates




Ren et al, “Faster R-CNN: Towards Real-Time Object Detection with Region Proposal Networks”, NIPS 2015

# Fast**er** R-CNN:
# Make CNN do proposals!

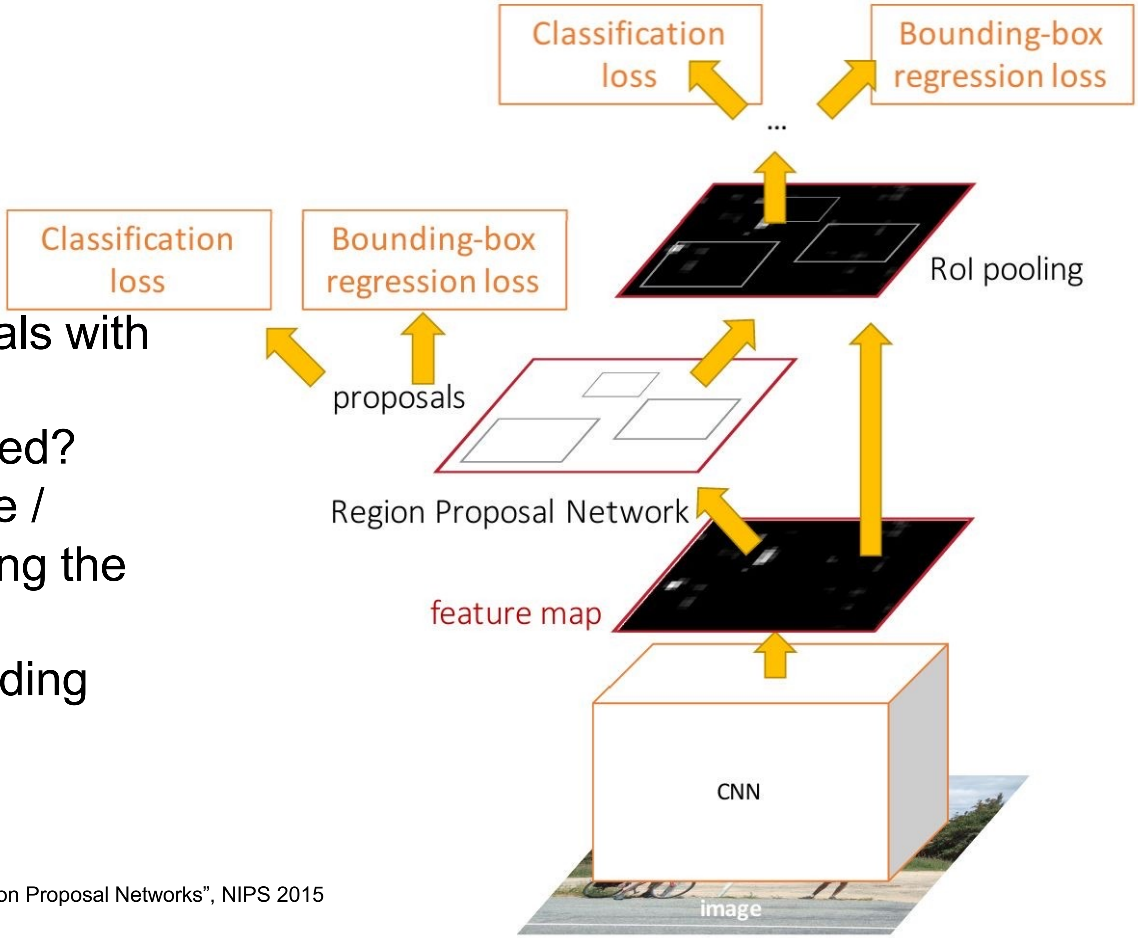


Faster R-CNN:

# Make CNN do proposals!

Glossing over many details:

- Ignore overlapping proposals with **non-max suppression**
- How are anchors determined?
- How do we sample positive / negative samples for training the RPN?
- How to parameterize bounding box regression?




Ren et al, "Faster R-CNN: Towards Real-Time Object Detection with Region Proposal Networks", NIPS 2015

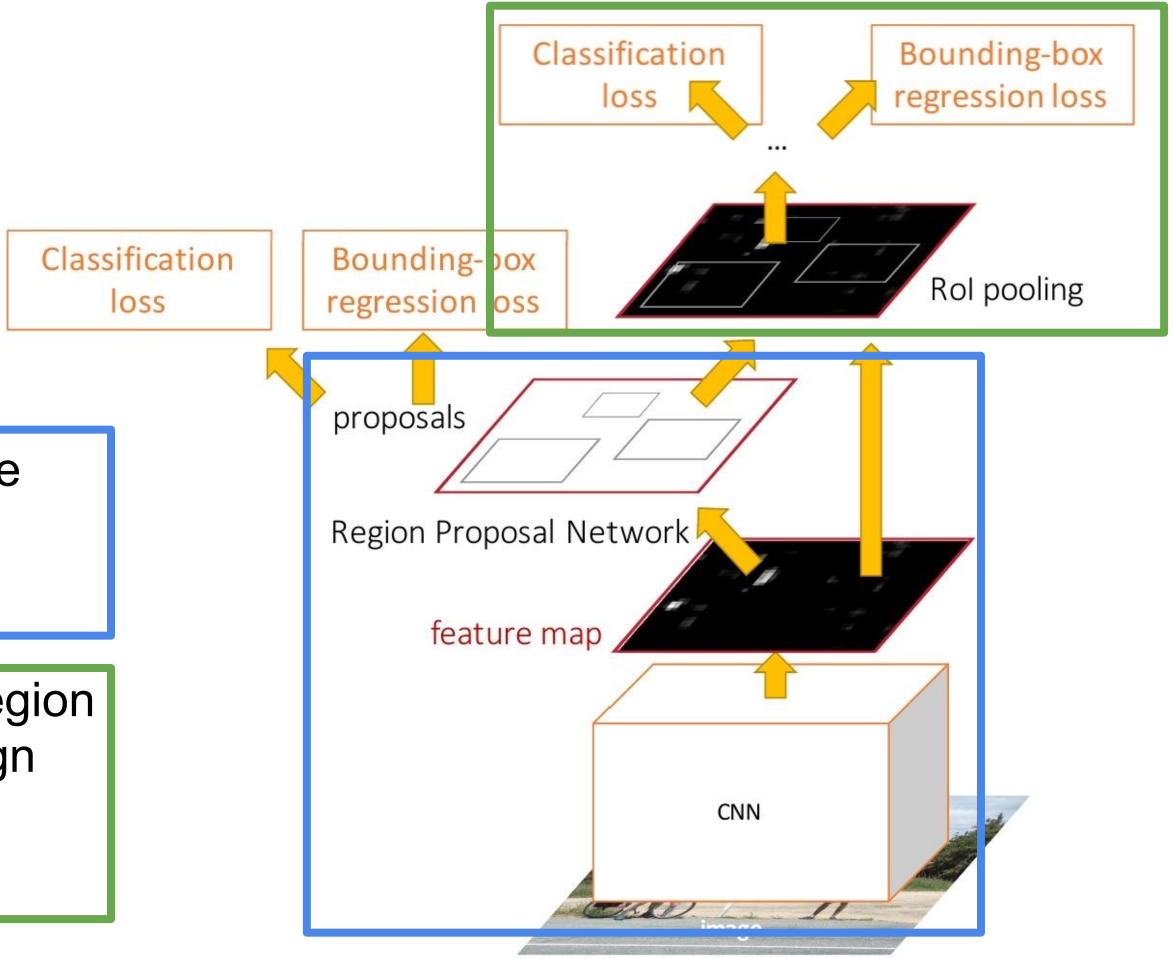
Fast**er** R-CNN:

# Make CNN do proposals!

Faster R-CNN is a
**Two-stage object detector**

First stage: Run once per image
- Backbone network
- Region proposal network

Second stage: Run once per region
- Crop features: RoI pool / align
- Predict object class
- Prediction bbox offset



Fast**er** R-CNN:

# Make CNN do proposals!

Do we really need the second stage?

Faster R-CNN is a
**Two-stage object detector**

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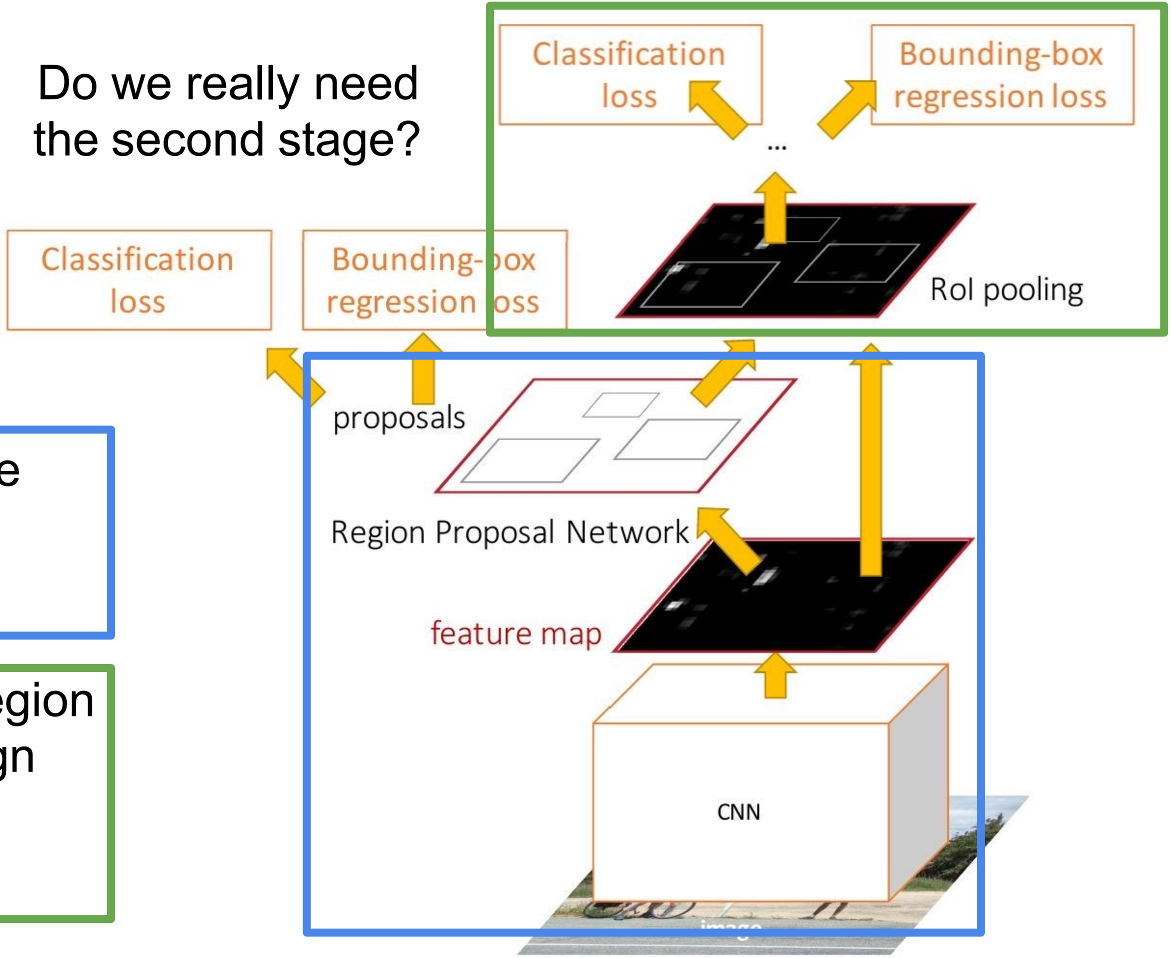
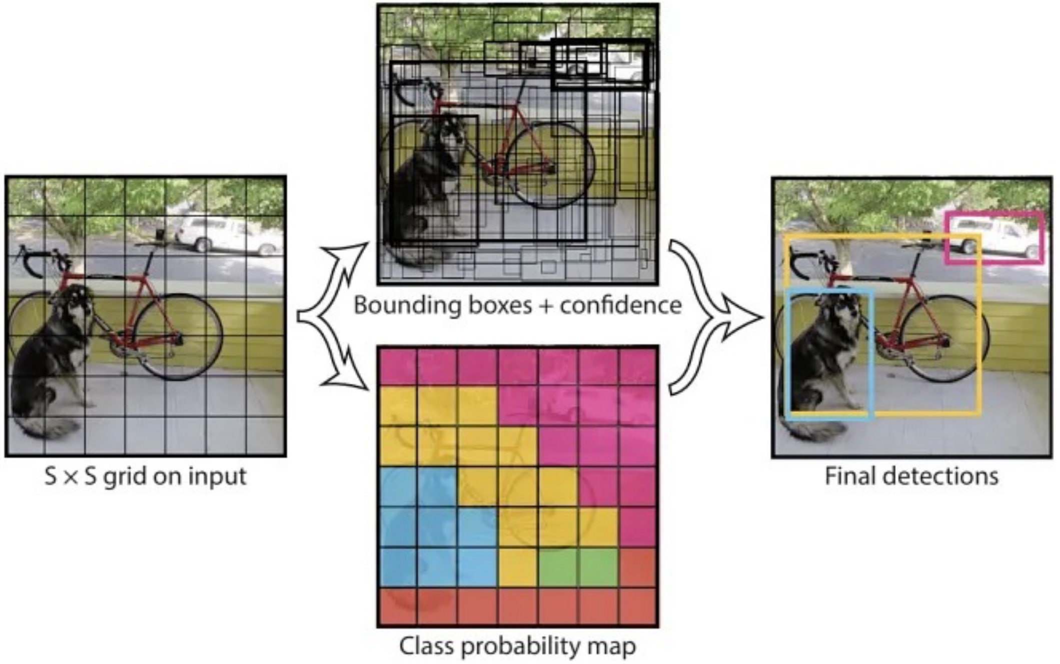


# Single-Stage Object Detectors: YOLO / SSD / RetinaNet




Within each grid cell:

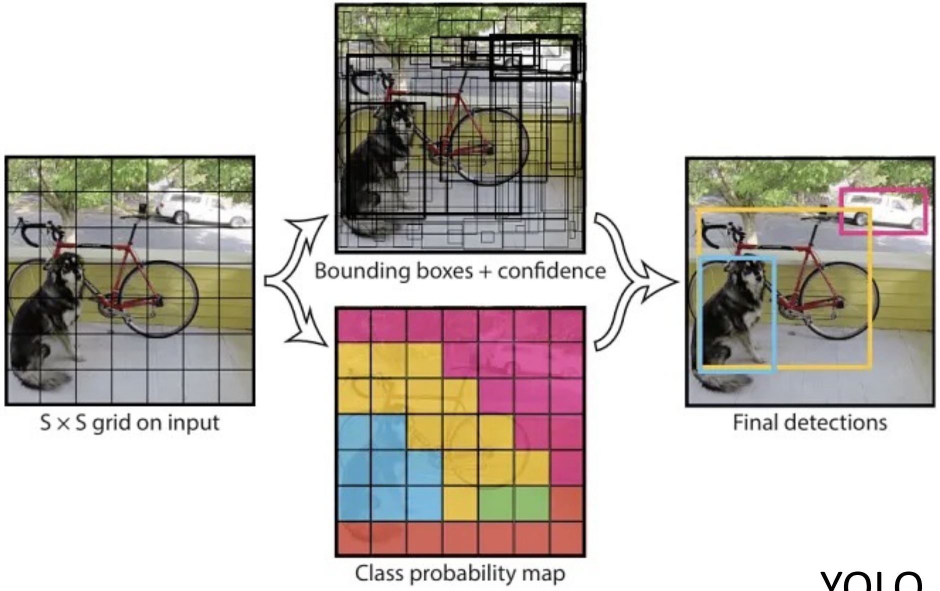
- Regress from each of the B base boxes to a final box with 5 numbers: (dx, dy, dh, dw, confidence)
- Predict scores for each of C classes (including background as a class)
- Looks a lot like RPN, but category-specific!

Imagine a set of **base boxes** centered at each grid cell Here B = 3

Output:
7 x 7 x (5 * B + C)

Redmon et al, "You Only Look Once: Unified, Real-Time Object Detection", CVPR 2016
Liu et al, "SSD: Single-Shot MultiBox Detector", ECCV 2016
Lin et al, "Focal Loss for Dense Object Detection", ICCV 2017

# Single-Stage Object Detectors: YOLO / SSD / RetinaNet




YOLO

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# Object Detection: Lots of variables ...

**Backbone Network**
VGG16
ResNet-101
Inception V2
Inception V3
Inception ResNet
MobileNet

**"Meta-Architecture"**
Two-stage: Faster R-CNN
Single-stage: YOLO / SSD
Hybrid: R-FCN

**Image Size**
**# Region Proposals**
**…**

**Takeaways**
Faster R-CNN is slower but more accurate

SSD is much faster but not as accurate

Bigger / Deeper backbones work better

Huang et al, "Speed/accuracy trade-offs for modern convolutional object detectors", CVPR 2017

R-FCN: Dai et al, "R-FCN: Object Detection via Region-based Fully Convolutional Networks", NIPS 2016
Inception-V2: Ioffe and Szegedy, "Batch Normalization: Accelerating Deep Network Training by Reducing Internal Covariate Shift", ICML 2015
Inception V3: Szegedy et al, "Rethinking the Inception Architecture for Computer Vision", arXiv 2016
Inception ResNet: Szegedy et al, "Inception-V4, Inception-ResNet and the Impact of Residual Connections on Learning", arXiv 2016
MobileNet: Howard et al, "Efficient Convolutional Neural Networks for Mobile Vision Applications", arXiv 2017

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Zou et al, "Object Detection in 20 Years: A Survey", arXiv 2019

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# Instance Segmentation

**Classification**



CAT

No spatial extent

**Semantic Segmentation**



GRASS, CAT, TREE, SKY

No objects, just pixels

**Object Detection**



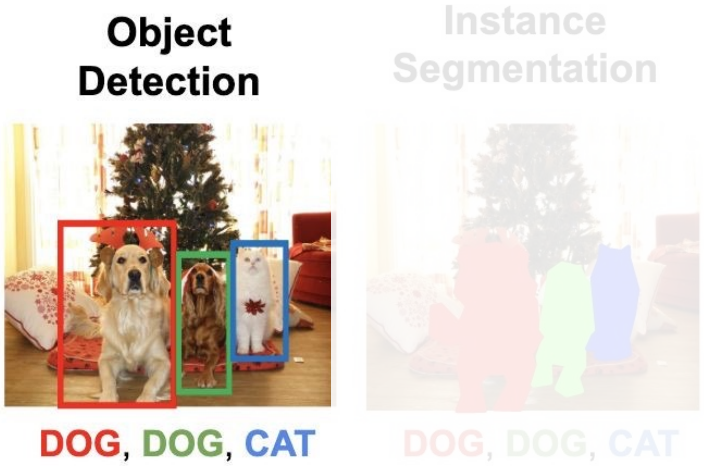
DOG, DOG, CAT

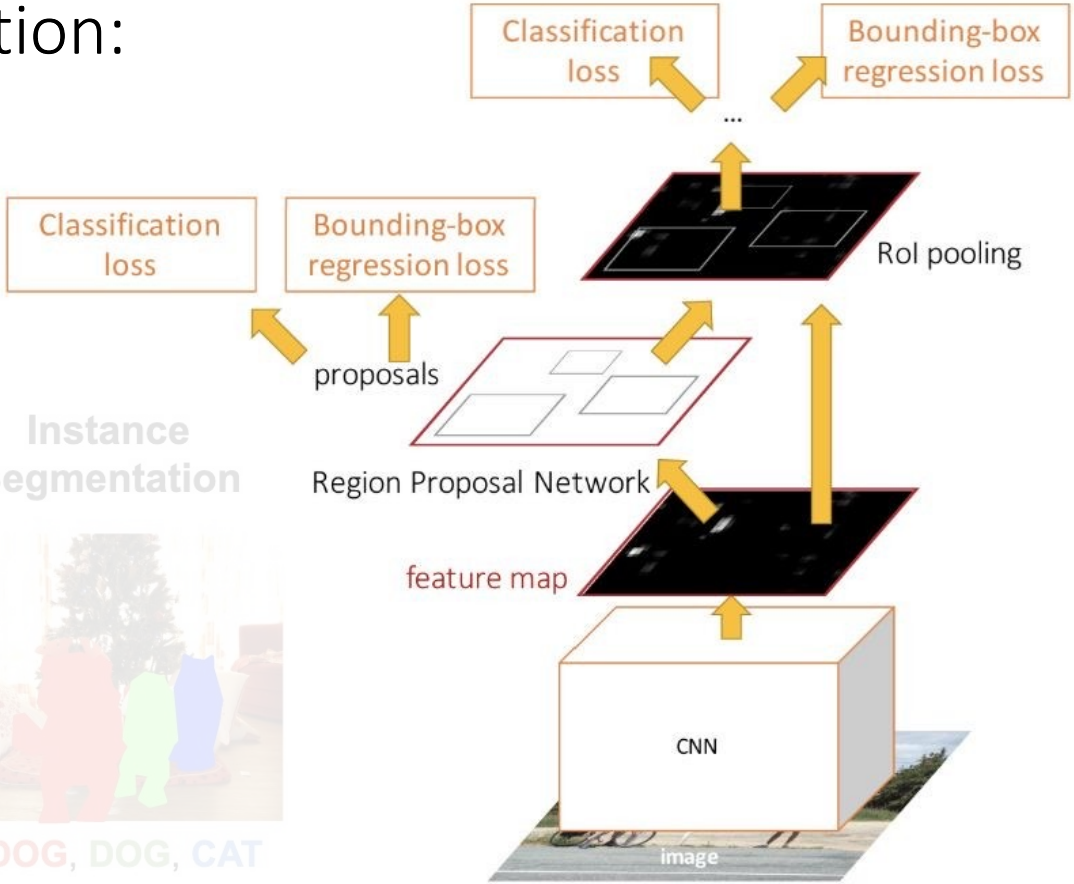
**Instance Segmentation**

DOG, DOG, CAT

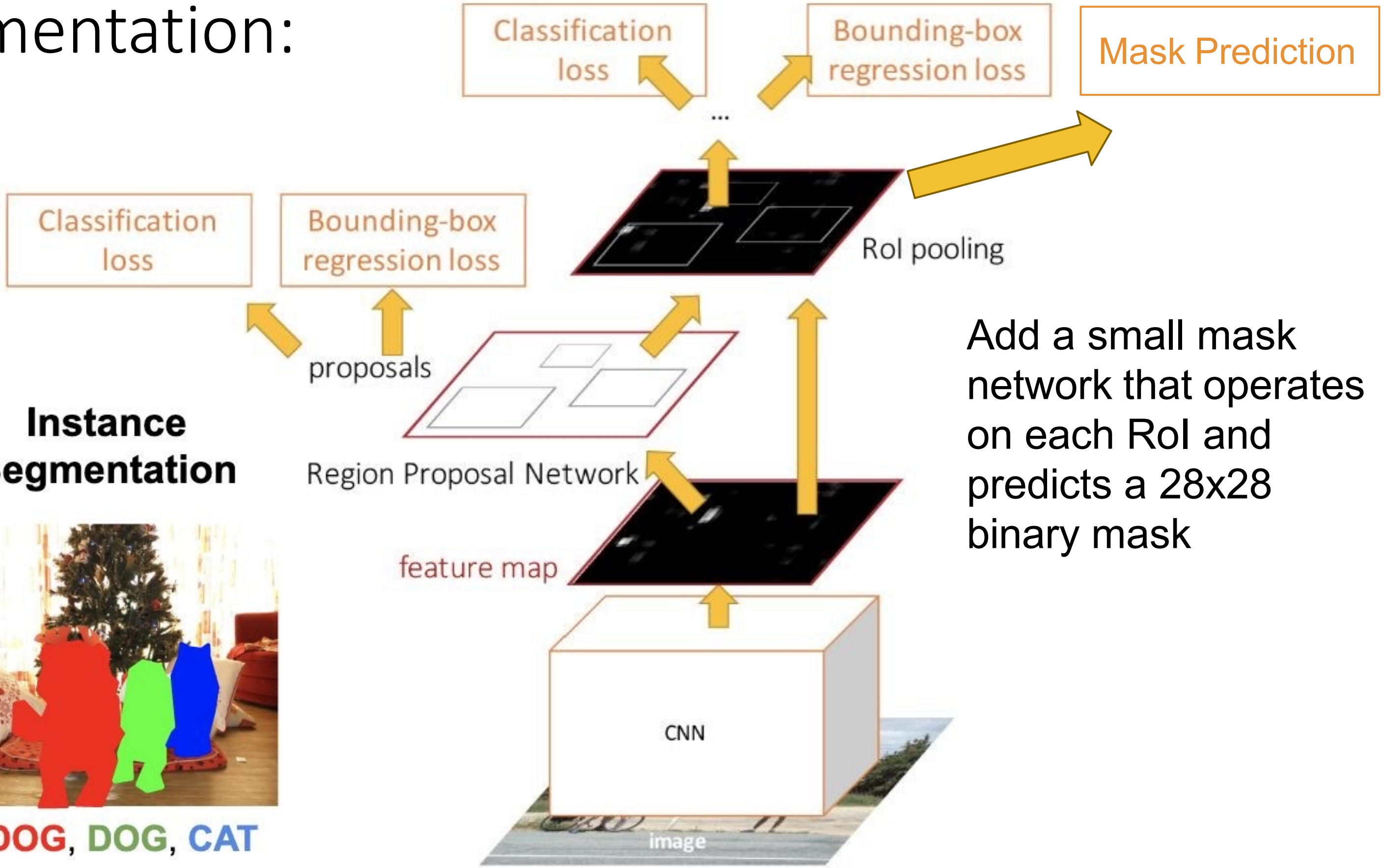
Multiple Object

# Object Detection:
# Faster R-CNN



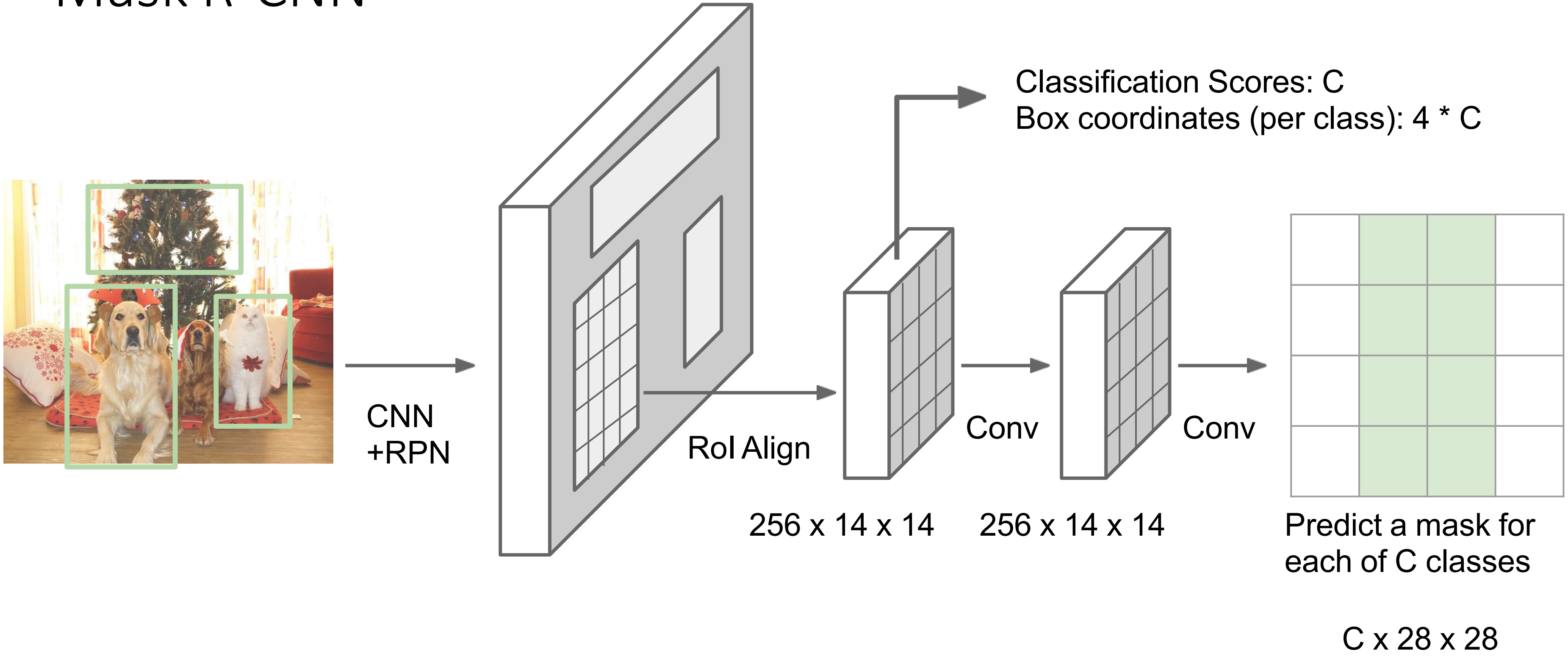
# Instance Segmentation: Mask R-CNN


Add a small mask network that operates on each RoI and predicts a 28x28 binary mask

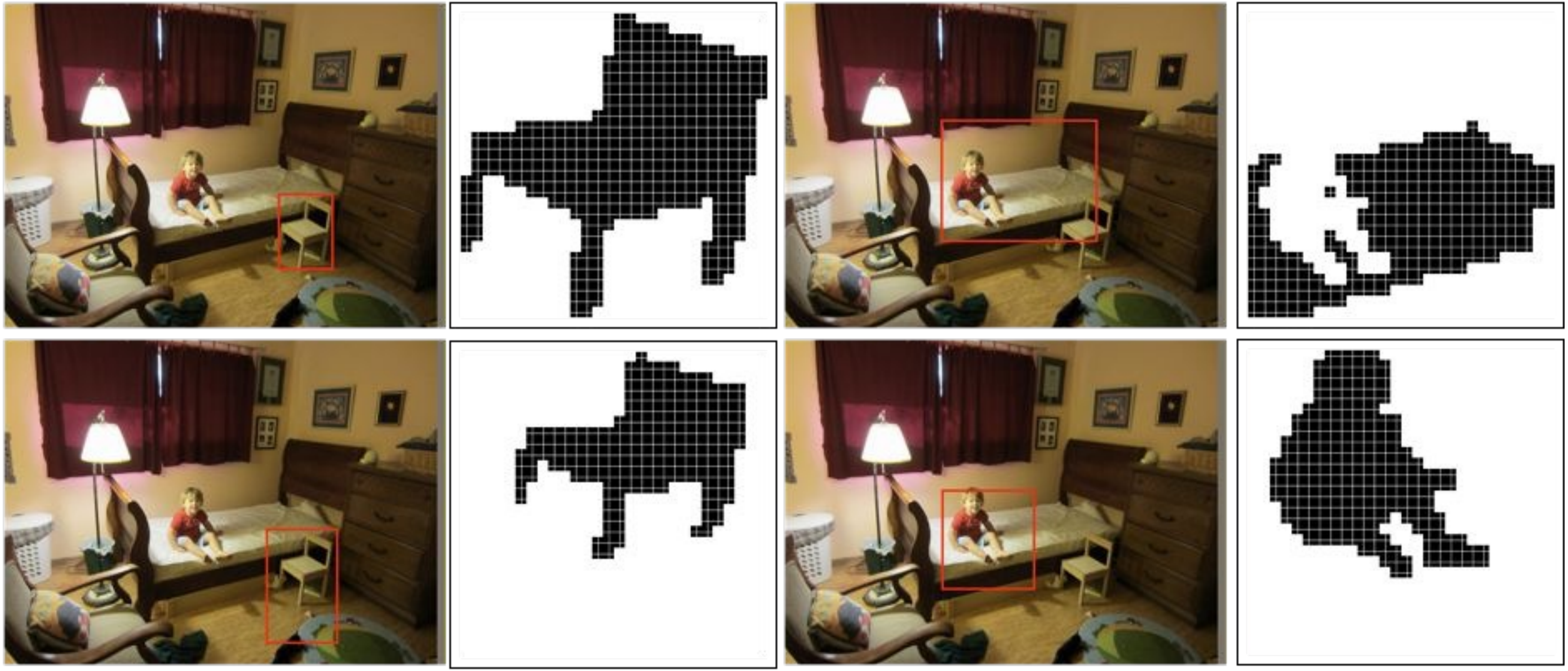
He et al, "Mask R-CNN", ICCV 2017

# Mask R-CNN

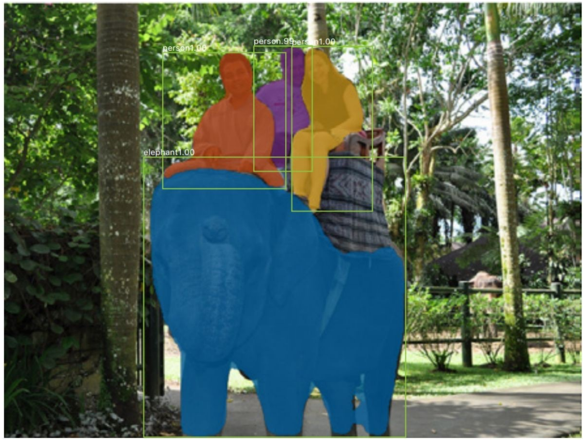



He et al, “Mask R-CNN”, arXiv 2017

# Mask R-CNN: Example Mask Training Targets



# Mask R-CNN: Very Good Results!




He et al, “Mask R-CNN”, ICCV 2017

# Mask R-CNN
# Also does pose


He et al, “Mask R-CNN”, ICCV 2017

# Segment Parts and Objects

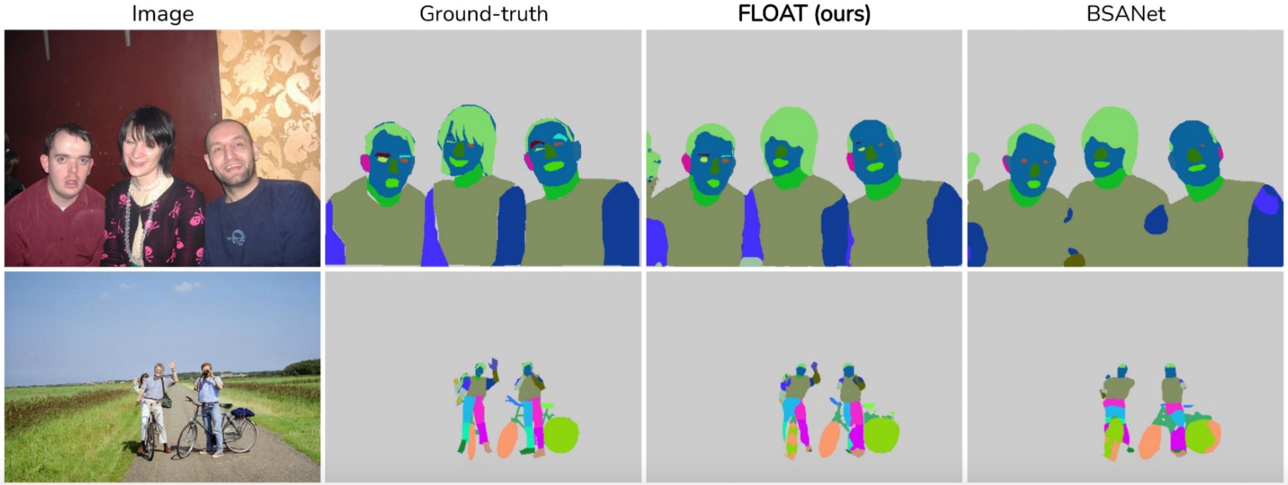
## FLOAT: Factorized Learning of Object Attributes for Improved Multi-object Multi-part Scene Parsing

Rishubh Singh[1] Pranav Gupta[2] Pradeep Shenoy[1] Ravi Kiran Sarvadevabhatla[2]

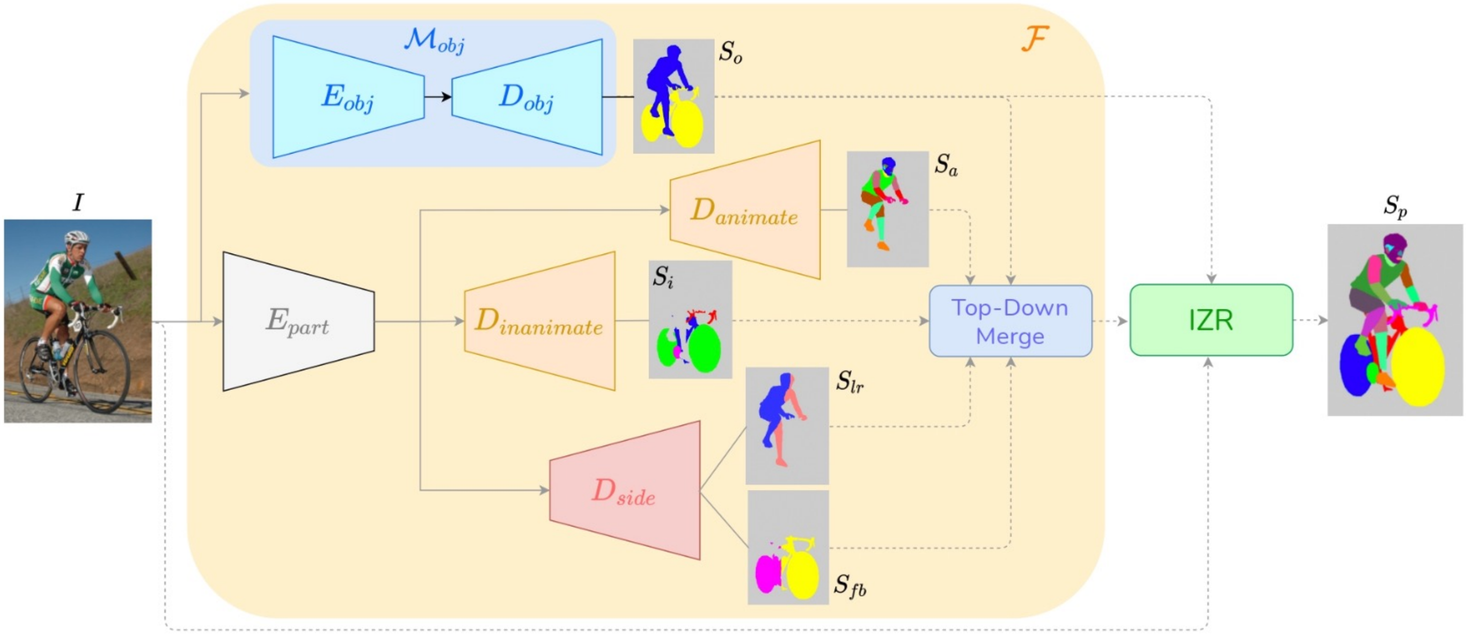
[1]Google Research [2]International Institute of Information Technology, Hyderabad

In CVPR 2022

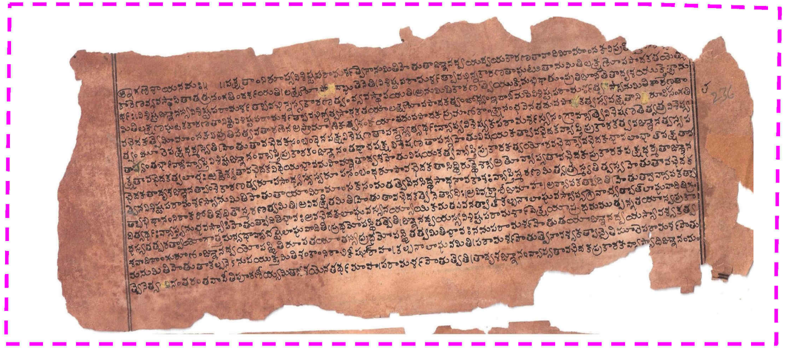
[Paper] [Code] [Dataset]

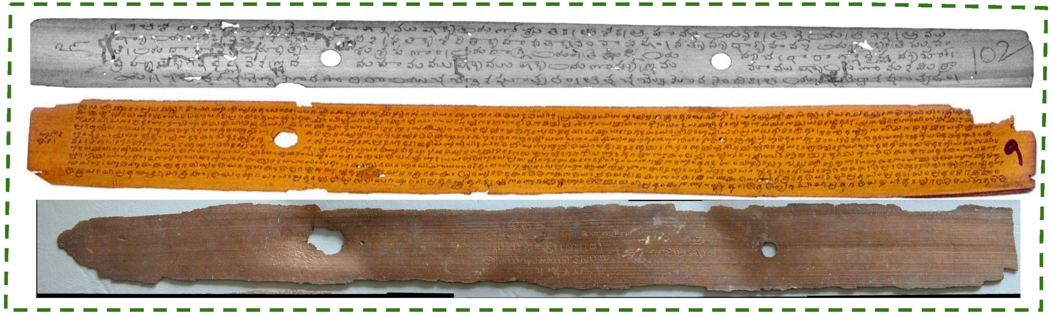


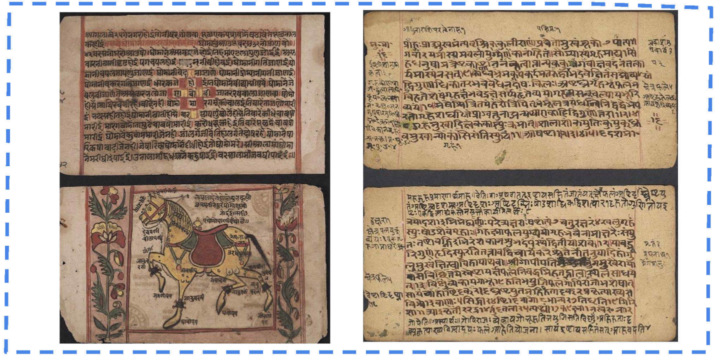
# Segment Parts and Objects



# Application: Parsing Historical Manuscripts

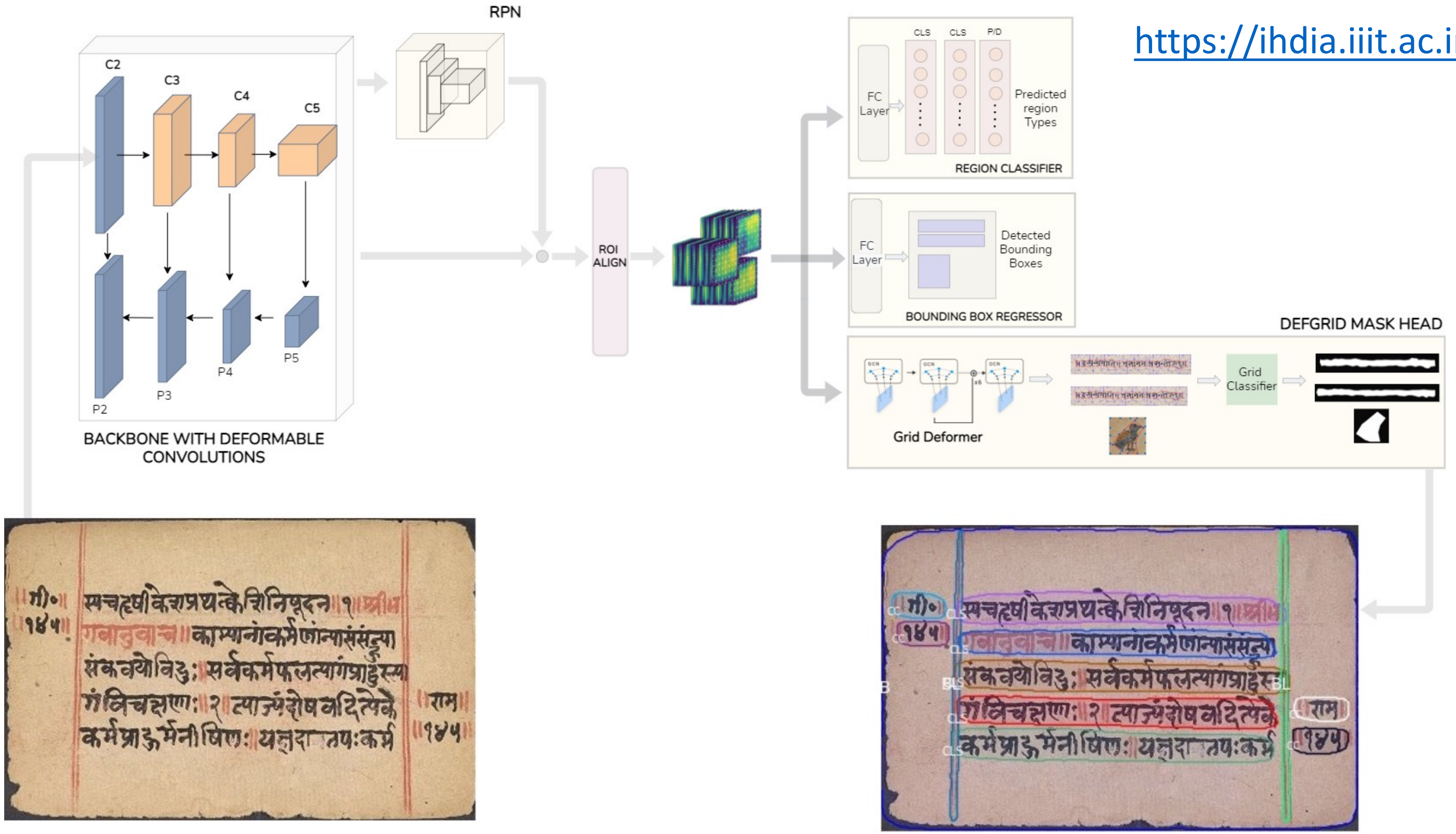






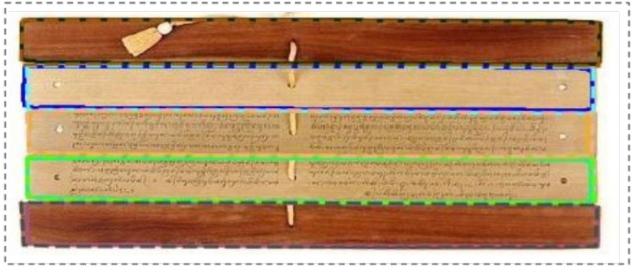
# Application: Parsing Historical Manuscripts

https://ihdia.iiit.ac.in/Palmira/



# Segmenting **page** instances

im2pages



# Open Source Frameworks

Lots of good implementations on GitHub!

TensorFlow Detection API:

https://github.com/tensorflow/models/tree/master/research/object_detection

Faster RCNN, SSD, RFCN, Mask R-CNN, ...

Detectron2 (PyTorch)

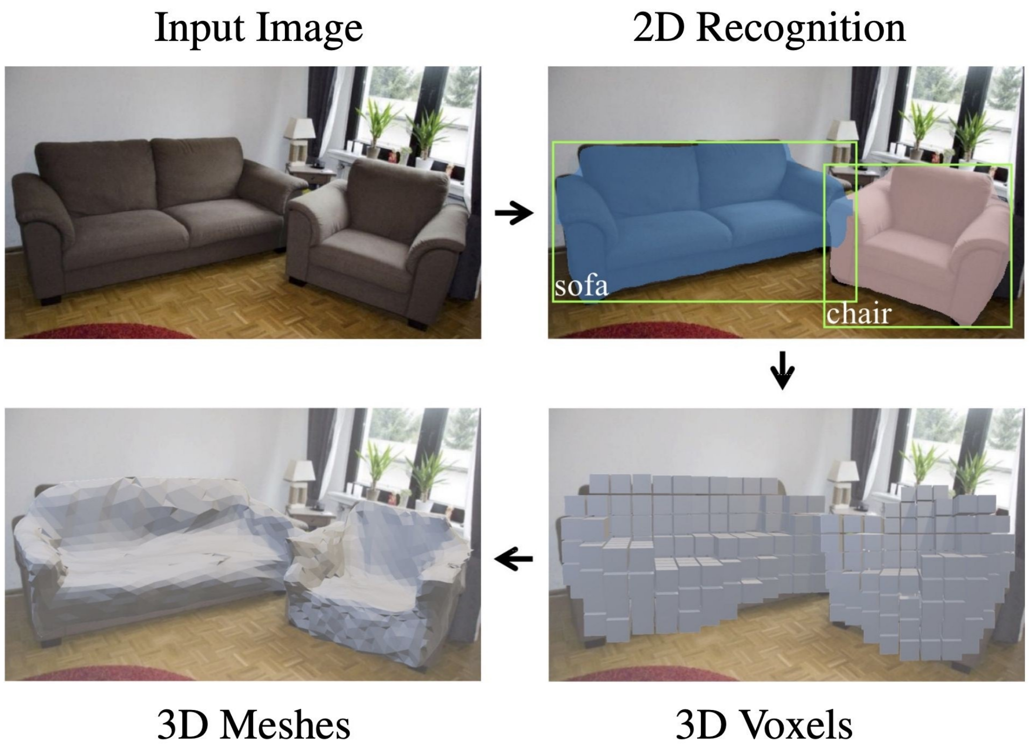
https://github.com/facebookresearch/detectron2

Mask R-CNN, RetinaNet, Faster R-CNN, RPN, Fast R-CNN, R-FCN, ...

Finetune on your own dataset with pre-trained models

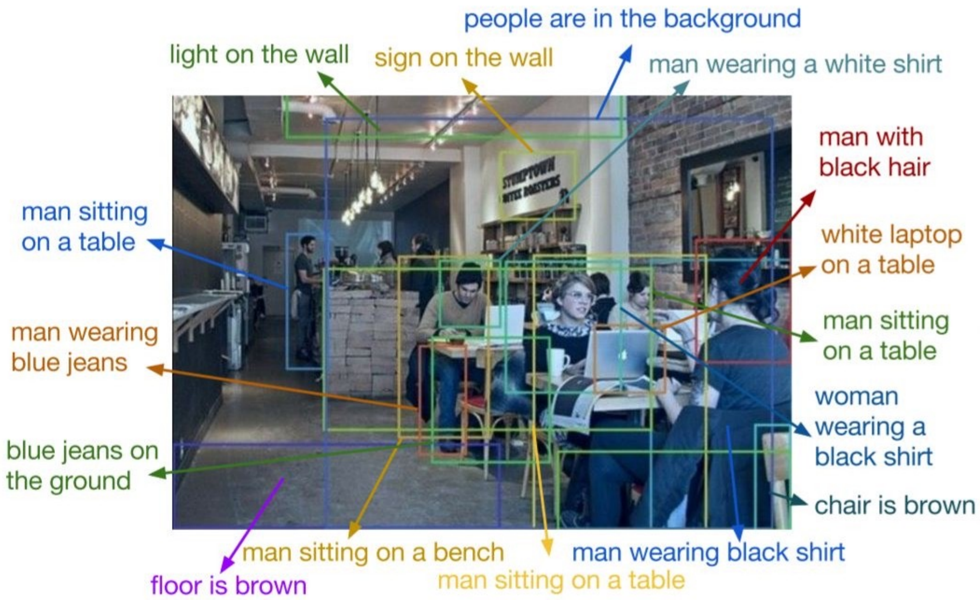
# Beyond 2D Object Detection...

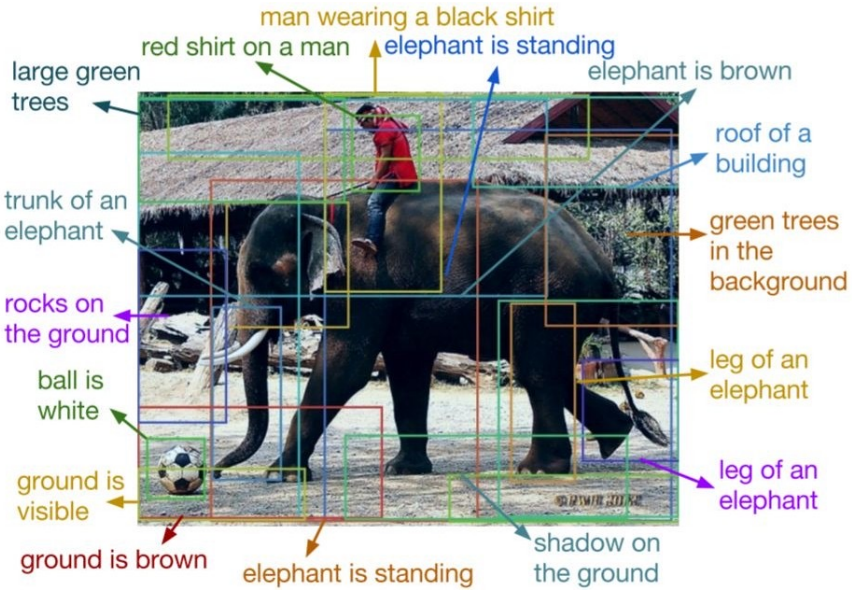
# 3D Shape Prediction: Mesh R-CNN



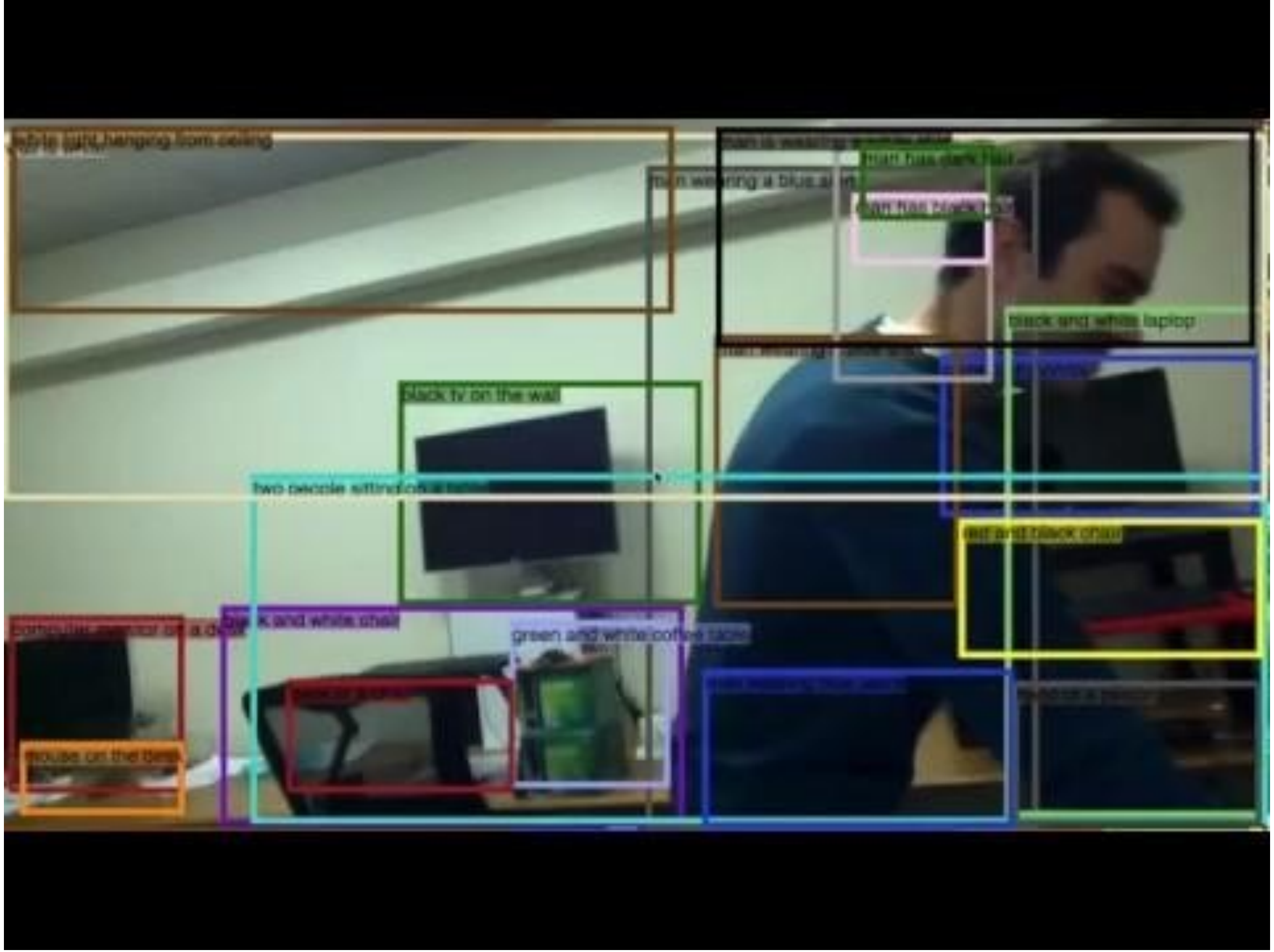

Gkioxari et al., Mesh RCNN, ICCV 2019

# Object Detection + Captioning = Dense Captioning

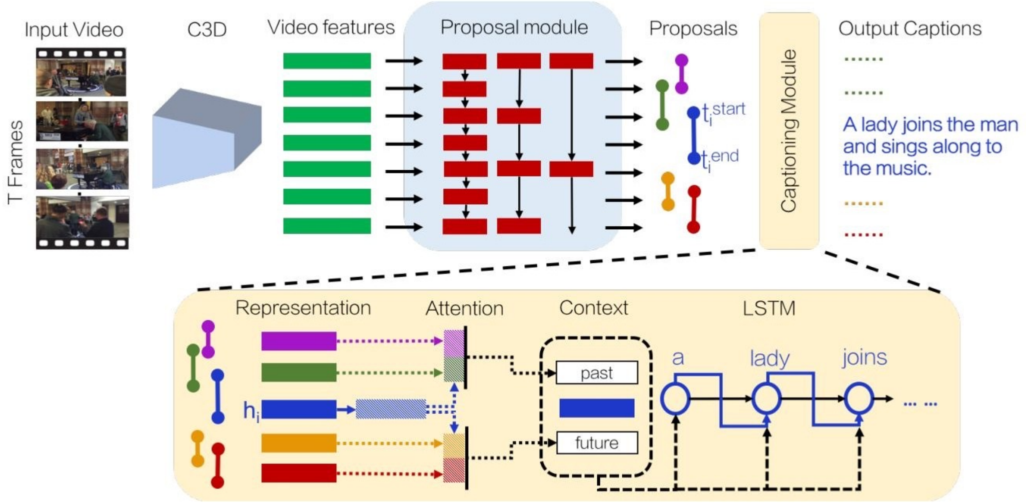


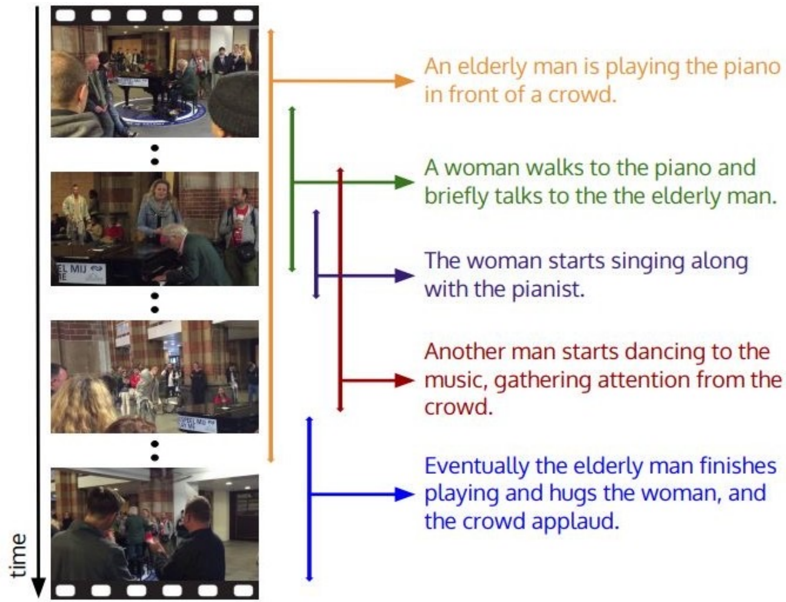




Johnson, Karpathy, and Fei-Fei, “DenseCap: Fully Convolutional Localization Networks for Dense Captioning”, CVPR 2016


white light hanging from ceiling
man has dark hair
black and white laptop
black tv on the wall
red and black chair
green and white coffee table

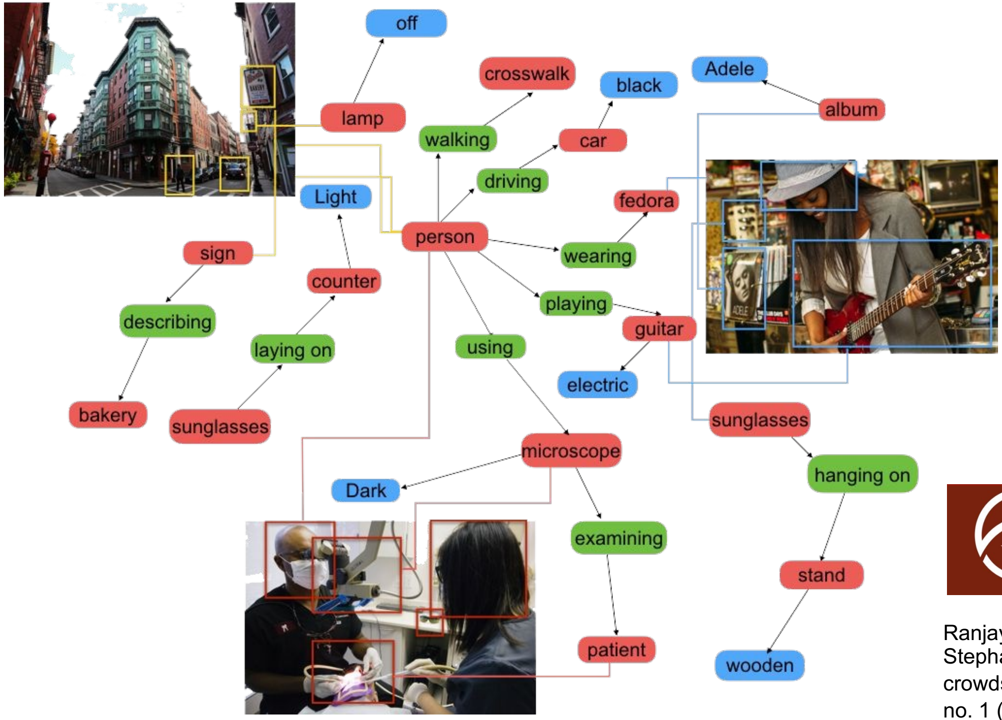
# Dense Video Captioning




Ranjay Krishna et al., "Dense-Captioning Events in Videos", ICCV 2017

# Objects + Relationships = Scene Graphs

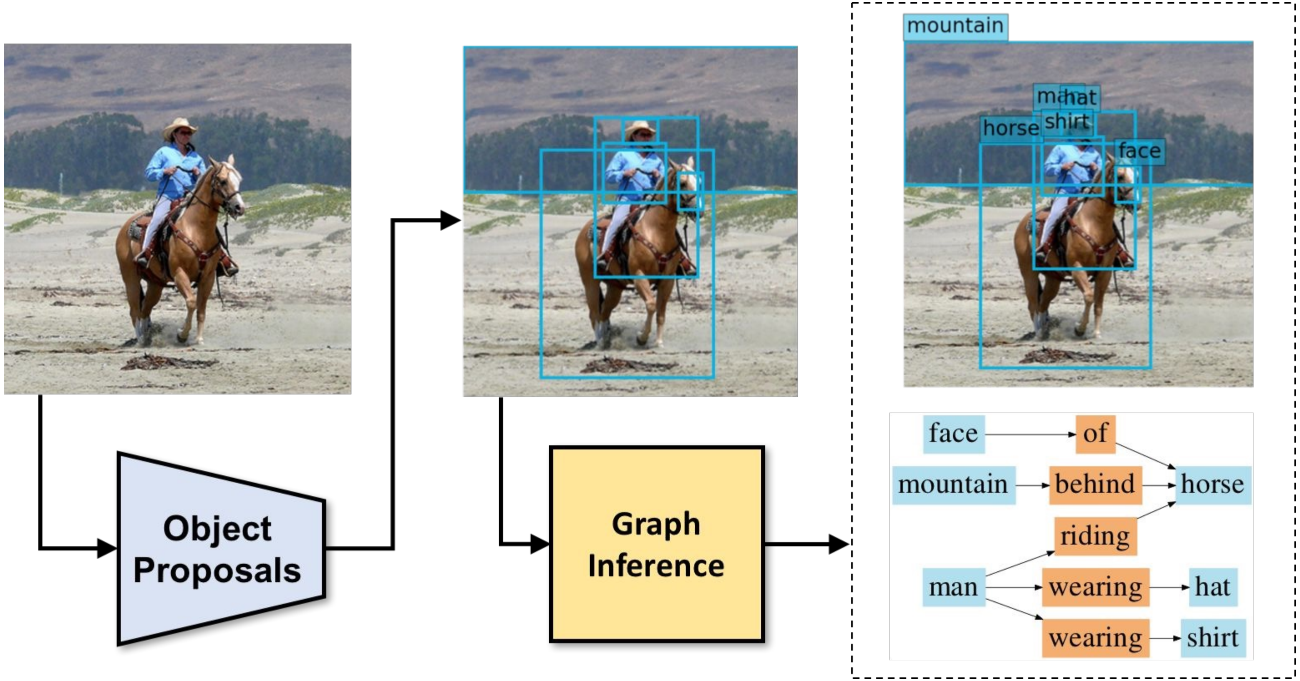



108,077 Images
5.4 Million Region Descriptions
1.7 Million Visual Question Answers
3.8 Million Object Instances
2.8 Million Attributes
2.3 Million Relationships
Everything Mapped to Wordnet Synsets

VISUALGENOME

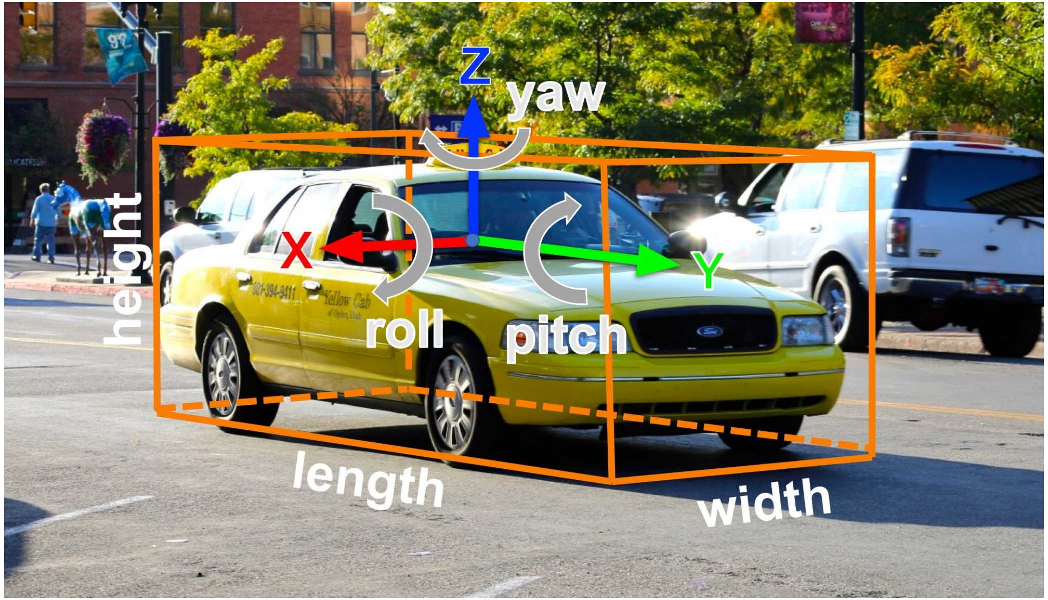
Ranjay Krishna, Yuke Zhu, Oliver Groth, Justin Johnson, Kenji Hata, Joshua Kravitz, Stephanie Chen et al. "Visual genome: Connecting language and vision using crowdsourced dense image annotations." International Journal of Computer Vision 123, no. 1 (2017): 32-73.

# Scene Graph Prediction




Xu, Zhu, Choy, and Fei-Fei, "Scene Graph Generation by Iterative Message Passing", CVPR 2017

# 3D Object Detection



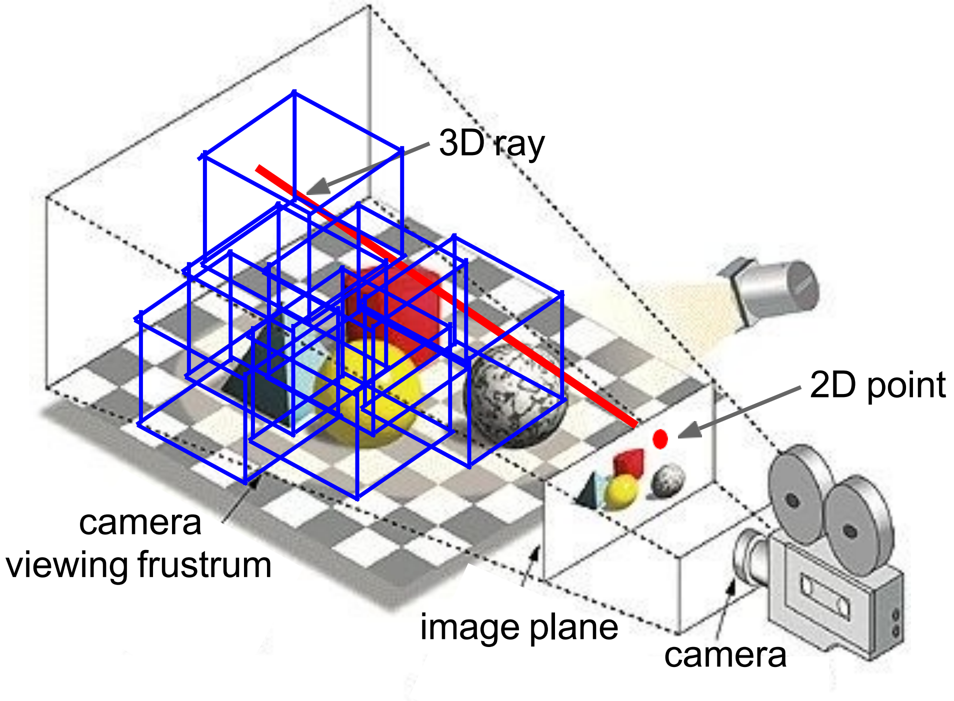

2D Object Detection:
2D bounding box
(x, y, w, h)

3D Object Detection:
3D oriented bounding box
(x, y, z, w, h, l, r, p, y)

Simplified bbox: no roll & pitch

Much harder problem than 2D object detection!

# 3D Object Detection: Simple Camera Model



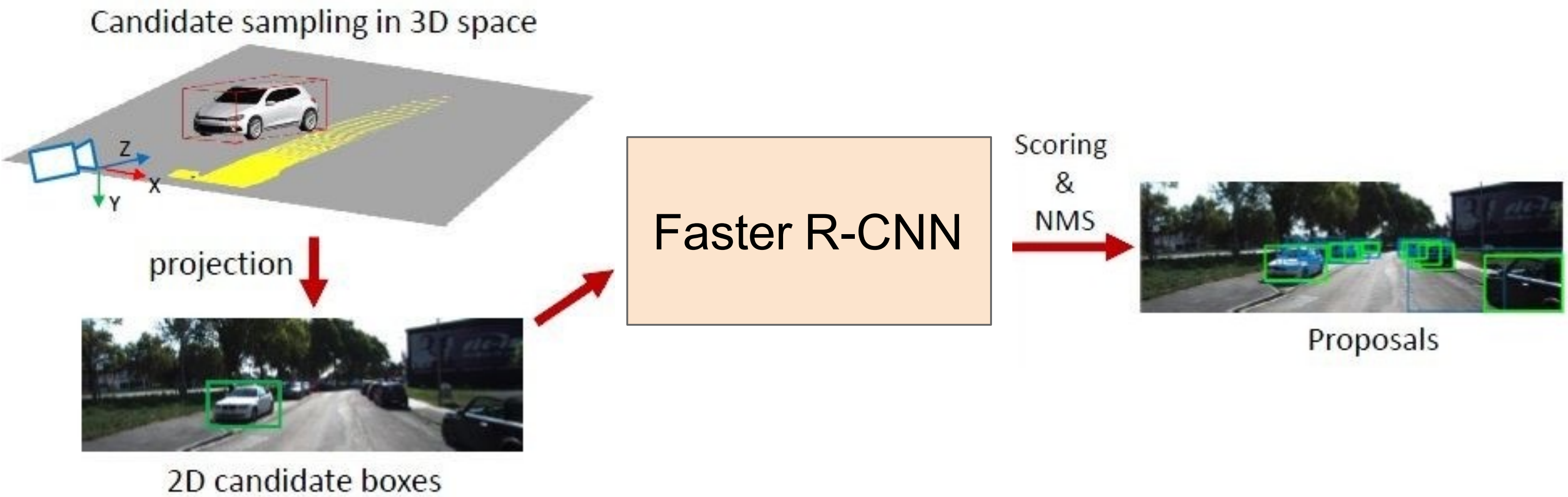

A point on the image plane corresponds to a **ray** in the 3D space

A 2D bounding box on an image is a **frustrum** in the 3D space

Localize an object in 3D:
The object can be anywhere in the **camera viewing frustrum**!

Image source: https://www.pcmag.com/encyclopedia_images/_FRUSTUM.GIF

# 3D Object Detection: Monocular Camera




- Same idea as Faster RCNN, but proposals are in 3D
- 3D bounding box proposal, regress 3D box parameters + class score

Chen, Xiaozhi, Kaustav Kundu, Ziyu Zhang, Huimin Ma, Sanja Fidler, and Raquel Urtasun. "Monocular 3d object detection for autonomous driving." CVPR 2016.