Real Time Balloons detection in Videos Using Deep Learning

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**Abstract**

Deep learning was able to produce significant breakthrough in the field of computer vision in recent years. This, along with the advances in hardware for deep learning allows for running real time object detection from video on hardware mounted on a small drone.

In this project I created an environment setup for training deep neural networks and utilized it to train a neural network to detect balloons from a video. In addition, the balloons detection was optimized to run at real time on the Nvidia Jetson TX2.

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# Introduction

Recent years advances in deep learning along with the progress of hardware for deep learning and the potential of automatic Unmanned Aerial Vehicles, also known as drones, has allowed major progress in the field of autonomous drones. Deep learning algorithms, which until recently were too heavy to run on drone mountable hardware are now becoming more common. In this project I’ve implemented an algorithm to detect balloons on sky background in videos. The project included all the phases for constructing a computer vision system based on deep learning: learning phase, dataset collection and preprocessing, CNN training, CNN usage for detection in video and optimization of the detection algorithm.

The goal of the project was twofold:

* The first part was to create a scalable and modular deep learning environment setup for the Autonomous Indoors Drone Lab at Tel Aviv University, based on the DL4CV book [[1]](#DL4CV).
* The second part consisted of 3 phases:
  + Utilize the environment for the first part of the project to train a convolutional neural network (CNN) to detect balloons on sky background.
  + Use the trained CNN to produce an algorithm for balloons detection on sky background in videos.
  + Optimize the balloons detection algorithm to run in real time when being run on the Nvidia Jetson TX2 [[2]](#Nvidia).

All project goals were achieved.

The project consisted of 3 main phases. At first, a learning phase was done in which I read the DL4CV book [[1]](#DL4CV). Next, in the implementation phase, the balloons detection algorithm was developed. Finally, the optimization phase took place in which the algorithm was modified to run in real time. This report will discuss the phases and challenges of the project as well as the project’s results.

# Learning

The first part of the project was to read the DL4CV book [[1]](#DL4CV). The books consist of 3 bundles. Reading the book and running the code provided in the book allowed me to get deeper understanding of the computer vision field, mainly in relation to deep learning.

## Starter bundle

The first bundle reviews the fundamentals of the computer vision and the neural network fields. This bundle provides the reader with the tools to construct and run simple CNN based computer vision algorithms.

The first bundle includes:

* Induction to deep learning and historical review of deep learning.
* A thorough review of the basics of image processing and image classification.
* Review of commonly used datasets for image classification algorithms.
* Neural networks fundamentals followed by convolutional neural network fundamentals.
* CNN building blocks presentation: convolution layers, activation function layers, pooling layers, batch normalization layers and dropout.
* Presentation of learning methods and optimization techniques utilized by CNN based algorithms, such as: Linear classification, loss functions, gradient descent, SGD, regularization and learning rate scheduling.
* Demonstration of deep learning algorithm development important tools, such as: Techniques for spotting underfitting and overfitting, checkpoint modeling and network visualization.

From this section several building blocks to construct convolution neural networks (CNN) were used. The basic building block of a CNN is the convolutional layer [[3]](#Conv). The convolutional layer is a set of trainable parameters with varying size and a small receptive field that is used to propagate the output of the previous layer to the current layer, using the convolution operation. Another basic building block in a CNN is the activation function [[4]](#Activation). In artificial neural networks, a non-linear activation function is used. The most common activation functions are: the hyperbolic tangent, the sigmoid and the RelU. In the project the RelU activation function was used. The pooling operation [[5]](#Pool), which is another important building block, is a non-linear operation that allows to down-sample the output of the previous layer.

Additionally, several regularization and optimization techniques discussed in this section were used in the project. Batch normalization [[6]](#BatchNorm) is a regularization technique that is used to improve performance and stability of a CNN. While Dropout [[7]](#Dropout) is a regularization technique that is used to reduce overfitting during the training of a CNN. Stochastic gradient descent (SGD) [[8]](#SGD), is an optimization technique based on the gradient descent method that allows for faster calculation of descent direction when searching for local minima.

## Practitioner bundle

The second bundle takes a deeper look at the field of computer vision for deep learning. This bundle reviews more advance deep learning techniques which provides the reader with the tools to construct sophisticated computer vision algorithms.

The second bundle includes:

* Exploring and understanding the advantages of data augmentation.
* Discussion about utilization of neural network for transfer learning by treating a CNN as a feature extractor.
* Introduction to computer vision commonly used metrics, such as: rank1 and rank5.
* Suggestion of improving deep learning algorithm results using: Fine-tuning and ensembles.
* Presentation of advanced optimization techniques: Adagrad, adadelta, RMSprop and Adam.
* Demonstration of how to deal with very large datasets using HDF5 files.
* Introduction to state of the art DNN architectures: GoogLeNet, ResNet, Generative Adversarial Networks (GAN)
* A glance at neural style transfer algorithms

From this section several additional methods were applied in the project. Data augmentation, which is a technique used to artificially extent the dataset. In addition to the SGD [8] optimizer, I also experimented training CNN’s with the Adam [[9]](#Adam) optimizer. The Adam optimizer is a computational efficient low memory optimizer when compared to the SGD [[8]](#SGD) optimizer. Moreover, Hierarchical Data Format 5 (HDF5) [[10]](#HDF5), which is a file format designed to store large amount of data so that later it can be read efficiently was in extensive use in the project.

From the CNN introduction part, both the GoogLeNet [[11]](#GoogleNet) and the ResNet [[12]](#RESNET) architectures provided a schema for CNN architectures used in this project. Several experiments were made on CNN’s which are based on the original GoogLeNet [[11]](#GoogleNet) architecture and original ResNet [[12]](#RESNET) architecture.

## ImageNet bundle

The third bundle introduces the reader with the ImageNet dataset. It discusses the challenges of training a CNN for ImageNet classification and provides suggestions to accomplish the task of training a CNN on ImageNet from scratch.

The third bundle includes:

* Neural network training extension to use multiple GPU’s.
* Introduction to the ImageNet dataset.
* Review of additional state of the art DNN architectures: AlexNet, VGGNet, SqueezeNet and faster R-CNN.

In the project the VGGNet [[13]](#VGGNet) architecture was used extensively. Several experiments were made on CNN’s which are based on the original VGGNet architecture.

# Setup

## Environment

In order to complete the deep learning based project, a Python based deep learning dedicated library had to be chosen. The library that was chosen was Keras since the DL4CV book [[1]](#DL4CV) that was used in the learning phase discusses its examples in Keras. Additionally, since I’m familiar with the TensoFlow and PyTorch libraries I preferred to experience deep learning dedicated coding with another high-level library. Keras library is a wrapper library that is based on one of the so-called backend libraries: TensorFlow and PyTourch. The coding was done in Keras in a way that both backends are supported. But, only the TensorFlow version was tested. The project ran with Python 3.6.3 and Keras version 2.2.4.

The project was developed both on a CPU and a GPU machine. Early development was done on a CPU. Once the compute power wasn’t strong enough, the project was migrated to a GPU machine. Since the project was written based on the Keras library, the migration from CPU to GPU was relatively smooth.

## Dataset

The base for every computer vision algorithm based on deep learning is the dataset. Looking for relevant open source dataset for completing the project didn’t bear any fruits. Hence, the dataset had to be generated from scratch. To acquire the data, four videos of balloons on sky background each with at least 20 seconds duration were recorded. The videos were divided so that 3 videos will be used as the training and validation data and one video will be used to test the final algorithm which is based on a neural network that was trained on the 3 videos dedicated for training.

The CNN model was chosen in a way such that the input is a single 3D image and the output is a single value indicating the probability of the input image to contain balloons. To be able to utilize the videos as training data, the videos had to be processed to generate a dataset of cropped images and their respective labels. Manual cropping and labeling of balloons and sky images from videos to create the dataset can become a very exhausting task. Therefore, to complete the task in reasonable time and without executing the same action thousands of times all over again. The videos processing into annotated images had to be made partially automated.

To do so, a semi-automatic program was created which takes as an input the video the user would like to process. The program then prompts the user to manually capture a rectangle in the first frame of the video. The area in the frame which contains the balloons and is of interest will be referred to as the Region of Interest (ROI). After that, the rectangle is shown on top of the frame and the user can confirm the selection or select a new rectangle if the results are not as expected. Upon confirmation, the automatic cropping and labeling algorithm starts looking for the balloons in the next frame. The detection of the ROI’s is done using classical estimation theory and computer vision techniques. In case the automatic cropping fails to locate a balloon in the frame, the user is prompted and can re-select the ROI so the semi-automatic program can proceed.

It is worth mentioning that the semi-automatic program can run in two modes of operation. One, in which after the first selection by the user the program will run until it is unable to find an ROI. At which point the user will be prompted to assist with the detection of the balloons in the current frame. The other, in which after each frame the user is prompted to approve or correct the proposed selection.

So far only the cropping and labeling of the balloons data was discussed. To generate images of sky without balloons, which is needed for the CNN, the semi-automatic cropping program was exploited. In every frame, along with the ROI which contains the balloons, another rectangle is generated which is used to crop an image which doesn’t contain balloons. The rectangle is chosen randomly between the 4 rectangle neighbors of the ROI rectangle. Meaning, a neighbor rectangle is a rectangle that is built on one of the ROI’s sides. If the working mode is the one in which the user is prompted and allowed to correct the ROI’s selection, the user can also choose another neighbor rectangle incase the random result isn’t suitable. This can happen in case the neighbor rectangle has a different background then sky or the background rectangle has its boundaries outside of the image.

Once I was able to split the 3 videos into around 2,000 annotated images of each label (balloons and sky). I manually selected around 3,000 images which had the best cropping, splitted evenly between the two labels. The even splitting was done in order to avoid the requirement to add weights to the labels when performing back propagation during training.

Below presented an example of a frame with a red rectangle to mark the balloons image crop and a blue rectangle to mark the sky background crop. The original frame with the rectangles can be seen on the right. On the left the cropped images can be seen, the sky background on the top and balloons on the bottom.

A picture containing sky, outdoor, tree

Description automatically generated

# Implementation

At this stage of the project I had the dataset available to me, along with the plan to use Python with Keras and start my work on a CPU and later proceed to a GPU. In this section I will discuss the two main parts of the implantation phase: training the neural network and utilizing the trained neural network to detect balloons on sky background in a video stream. Additionally, in this section I will explain which techniques were used to debug various parts of the project.

It is worth mentioning that each implementation related phase. Including: parsing the dataset, training a CNN and evaluating the trained CNN. Were constructed in a way which allows for a relatively small and elegant change to be done in case a change in the training scheme was needed. Possible changes may be: a different dataset, a different CNN or a different CNN training parameter. This, to meet the goal of creating a scalable CNN training platform for the Autonomous Indoors Drone Lab at the Tel Aviv University.

## Training

The purpose of the training part in the implementation phase was to train a neural network which can perform images classification into two categories: balloons and background. Since the dataset was already acquired, the next part was to organize the dataset so it can be easily and quickly read from disk and injected into the CNN during training.

This was achieved by preprocessing and splitting the dataset into three HDF5 [[10]](#HDF5) files, each one containing an array of images. Naturally, each image in the array is assigned to it’s appropriate label. Each HDF5 [[10]](#HDF5) file will be used for a different purpose during the CNN development: training, evaluation and testing. At this point the images of the dataset were preprocessed to produce images of equal dimensions, that are equal to the CNN input shapes. Additionally, the dataset mean was calculated so it can be subtracted later.

The next step was to train the CNN. This step required a lot of trial and error as many training configurations were attempted. Training was done based on the following state-of-the-art CNN architectures: VggNet [[13]](#VGGNet), GoogLeNet [[11]](#GoogleNet) and ResNet [[12]](#RESNET). Attempts to achieve the best results both accuracy and inference time wise were experimented using the previously mentioned architectures and other architectures which are derived from the state-of-the-art architectures.

Along with the CNN architecture, other configurations were experimented to achieve the best results. Input image dimensions was tested with the following options: 32x32x1, 32x32x3 and 64x64x3. SGD [[8]](#SGD) and ADAM [[9]](#Adam) optimizers were examined during the training process. Batch size used during training was chosen to be 64 and mean pixel per channel value was subtracted from each CNN input. Eventually, the 32x32x3 input dimension was chosen as it produced the best results while training was done with the SGD optimizer.

Several learning rates and learning duration were experimented. Both automatic learning rate decay and manual ctrl-c techniques were tested. The learning rate decay scheme was eventually found to be redundant to produce the required result. A constant learning rate of 0.01 was found to produce very good results, due to the low complexity of the dataset along with the chosen CNN being not too deep. The training converged after 10 epochs.

## Detection

Once the training was done, I was able to proceed to the detection part of the project. The detection part was the main part of the project. In this part the trained CNN was used as part of a more sophisticated balloons detection algorithm. This part of the project combines both traditional computer vision techniques along with the CNN based techniques.

In this section I’ll discuss the first steps that were taken to detect the balloons in a video. These steps were able to provide good results detection wise, but the run time was far from what was expected. In addition, these steps were needed to set a baseline for future results comparison. The improvements will be discussed in the optimization section.

In this section the correlation between the balloons location in successive frames was ignored and detection was performed on each frame. Each frame was downscaled to reduce the execution time of the detection. Then, from each frame a gaussian pyramid [[14]](#GaussianPyramid) was created. For each image in the gaussian pyramid, a sliding window divided the image into smaller images. The sliding window was performed with overlapping to try to assure that an image without balloons cuts is available in the images produced by the sliding window operation on the image pyramid. The Gaussian pyramid [[14]](#GaussianPyramid) along with the sliding window, allows the detection algorithm to deal with balloons in different sizes inside the frame.

The just discussed three concepts: downscale, gaussian pyramid and sliding window, produced a division of the initial frame into a collection of images each of which with the same input size as the previously trained CNN. The collection of images can now be divided into batches and driven into the pretrained CNN. The CNN, as it was trained to, produces for each image the probability the image contains balloons. After all images were assigned a probability that balloons exist in the image, the image with the highest probability is chosen.

Besides the detection logic in this part of the project, another important part is the execution time calculation which is done throughout the detection. The runtime monitoring is available in different levels, from the time it takes to detect balloons in a single frame to the inference time of a batch by the CNN. The run time analysis was mainly needed in the optimization phase and allowed me to understand which parts of the algorithm needed optimization. Since low level execution time calculation can impact the high-level execution time calculation, the low-level calculations are available only in debug mode which will be discussed later. At this point the detection algorithm was able to perform at the rate of 0.05 fps on CPU and 2 fps on GPU.

A small optimization was done in this early stage, manly to have a felling of how much improvement in execution time can be achieved and whether this is the correct path to achieve the project goals. In this optimization phase the parameters of the detection were fine-tuned in order to get improved detection run time without harming the accuracy. The fine-tuned parameters were: the initial downscale that is done on each frame, the downscale of the gaussian pyramid and the sliding window step size.

Two additional concepts were introduced to get improved run time. A second pass on the frame was done incase the first pass didn’t produce high enough balloons probability. The second pass included, like in the first pass, a gaussian pyramid [[14]](#GaussianPyramid) and a sliding window but with different parameters. In addition, an early stopping mechanism was added to reduce the runtime incase balloons were detected with high enough confidence. After the discussed small optimization modifications, the detection algorithm was able to run faster. The detection rate was 0.13 fps on CPU and 8 fps on GPU. A factor of 4 improvement from the initial performance baseline.

## Debug

Debugging the project was in many cases challenging. Among the reasons for the challenge were that it is not possible to debug by looking at pixel values of the input image and that debugging the CNN by checking the weights of the CNN is not possible.

The first level of debug in the project is allowed by using the debug flag (--debug 1), which is available in every program that is part of the project. In some cases, mainly in the detection part, the higher the value that is passes with the debug option the more debug information will be given for debug. The debug flag was usually used in cases where one of the project’s program flows was suspected to be faulted. Usually, in the cases where the issue was non-CV or non-DL related. In cases were debugging wasn’t possible with the debug flag, other options were used. Options such as saving the current frame in progress to disc or stopping the program in the middle of execution and restarting after adding debug hooks.

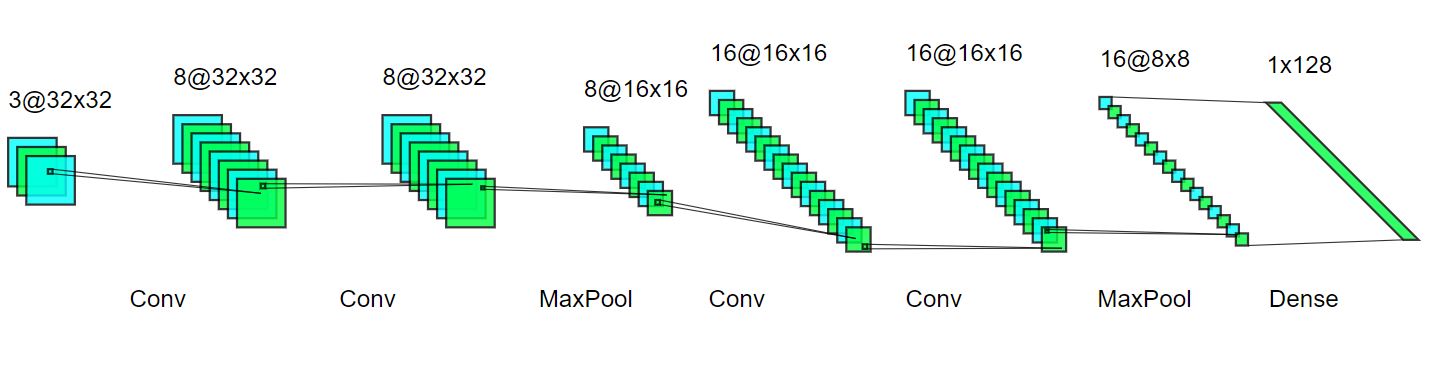
# Optimization

At this stage, I had the infrastructure for training various CNN architectures and an initial setup for detection using the trained CNN. In this section I will elaborate which actions were taken to improve run time and produce even more accurate detection results. Besides the below three main changes, several additional small changes were done. such as: more detection parameter finetuning, removal of the second pass and bug fixes. In this section I will elaborate only on the three main optimization modifications that were done to achieve real time detection.

## Shallowing

The first change that I thought will not be too complicated and can produce significant increase in execution time is using a shallower CNN architecture. I took a deeper look in the: VggNet [[13]](#VGGNet), GoogLeNet [[11]](#GoogleNet) and ResNet [[12]](#RESNET) architectures and experimented training the dataset on shallower CNN versions which are based on these architectures. After some investigation the NanoVGGNet architecture was chosen over the previously used DeepGoogLeNet. Besides being shallower than the DeepGoogLeNet, the NanoVGGNet was trained on input images of 32x32x3 as opposed to the 64x64x3 that the DeepGoogLeNet was trained on.

The NanoVGGNet architecture is presented below. Each convolution stage (depicted as Conv in the figure below) consists of a 3x3 2D convolution [[3]](#Conv), followed by a RelU activation function [[4]](#Activation), followed by batch normalization [[6]](#BatchNorm). Each max pooling stage (depicted as MaxPool in the figure below) consists of a 2x2 max pooling [[5]](#Pool), followed by dropout [[7]](#Dropout) with probability of 25%. In the Dense stage, the 16x8x8 Conv stage output is flatten into a 1,024 vector. The 1,024 vector is fully connected to a 128 vector which is driven through a RelU activation function [[4]](#Activation) followed by batch normalization [[6]](#BatchNorm) and dropout [[7]](#Dropout) of 50%. The last stage is a fully connected stage followed by a softmax activation function [[4]](#Activation).



The inference time of the DeepGoogLeNet was around 0.02 seconds on GPU while the inference time of the NanoVGGNet is around 0.005 seconds, a factor of 4 increase. The structure reports of both CNN’s are presented below. On the left the NanoVGGNet and on the right the DeepGoogLeNet. While the DeepGoogLeNet had 678 thousand parameters the NanoVGGNet had only 136 thousand parameters. Which is, a factor of 5 decrease in the number of parameters with no decrease in accuracy.

![A screenshot of a cell phone

Description automatically generated](data:image/jpeg;base64,/9j/4AAQSkZJRgABAQEAYABgAAD/4RD+RXhpZgAATU0AKgAAAAgABAE7AAIAAAARAAAISodpAAQAAAABAAAIXJydAAEAAAAiAAAQ1OocAAcAAAgMAAAAPgAAAAAc6gAAAAgAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAFJvbWFuIEJ1ZGlsb3Zza3kAAAAFkAMAAgAAABQAABCqkAQAAgAAABQAABC+kpEAAgAAAAM5NwAAkpIAAgAAAAM5NwAA6hwABwAACAwAAAieAAAAABzqAAAACAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAA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bMgZlwSFJAJOMdKkfwp4dk0ZNIfQNLbTI33pZGzjMKtydwTG0Hk847mr1hp9lpVjHZaXaQWVrECI4LeJY0TJycKoAHJJp9yUrJLsc74nm1ebxToek6Tq8mlQ3kdy9zLFbxySER+WQFMgYKfmPJBGCeM4I5yDxZql14f02x+3apc6nc3l7DDPpVtaLPeQ28jL5wM5EKgjbnjkn5QBnHXa/4P03xNrGmXWtW1rfW1gkw+yXdqsyO0gXDfNwCNvoevaruoeG9D1aygs9V0bT721tseRBc2qSJFgYG1WBC8ccdqlJ2/r+vkUcFpXiXxH4h0PweLTVltJdTubuC8uhBE7vHEJAHUDdGJDsByuUyScMvynT1XUdd0my07RL3Ub+71i7nuDBJo8Nr9ont4zkMxuAsKEKybgF5J+XjJrsYdK0+2EAt7C2iFuzvCEhVfKZ87iuBwTk5I65NR6toOka9DHDrmlWWpRRtvRLy3SZUbpkBgcGnLV6CWm55Dd/EDxRN4Y069s9WWGRdKvryR/s0L/aGt7mOJN2NyjcrHdsODk7SOCOjttR8ZX/h+RbG8ur2Sy1q4tbuezS1jvHgTITyxKvk5DEZyAdo4Oevcnw9orReU2kWBj8t4thtkxsdgzrjHRmAJHcgE1FfeFPD2pw+TqWg6ZeRCVptlxZxyL5jfefBH3j3PU0P+vvv+Wgf1+Fvz1Mg6sNT+GcWo6f4obSPMRMavqcEO6NhIFYSIQse4kFOMDJyM8V1o6DnPvVObSNNudLGmXGn2stgqqgtJIVaIKuCo2EYwMDHHGBVzpTYlsilqsWpTWDJo13a2dySMS3Vq06Ad/kWRDn33fga4Twxo13qngfwteaDfW2nS6MZ0je7gN5FOo3wlxseL5W++pHGCOK7fV/D2i6+kSa7pFhqawkmNb22SYIT1I3A46Ump+HdE1u3ht9Z0fT9Qhg/1Md3apKsfGPlDAgcelT0YzlbLxxDc+B9N8RahpcN1rVw0trYWtp8zXcocofIZhkRvsD7jwE5JOM1u+B9CuPDXgrTdKvZEe4gjJl8v7iMzFiqf7KlsD2Aq5qnhnQtbjgj1rRNO1FLYEQLd2iSiIHGdoYHHQdPQVY03StP0ayWz0ewtrC1UkrBawrEgJ5JCqAOarS7DsW6KKKQBRRRQAUUUUAFFFFABRRRQAUUUUAFFFFABRRRQAUUUUAFFFFABRRRQAUUUUAFFFFABRRRQAUUUUAFFFFABRRRQAUjdKWkbpQBVnrBuP8AkZ9F/wCvp/8A0nlrenrBuP8AkZ9F/wCvp/8A0nloA5rxBmz+Kmp6ygH/ABLtKs2mOcfuHkuEk/AAh/8AtmKo+CdQ1DUtB0nRbfxBLoEGneGrW982GKBnnL71LMZlYeWnljOADl+WHFeqPp9nJNNNJaQPLcRCGZ2iBaSMZwjHHK/M3B45PrVG78KeHb+1tLa+0DS7mCxXbaxTWcbrbjjhARhRwOmOgoWzX9df8xt3d/66f5HD2GueJvFS2jR60+iB/D0WoyLaWkbFp2ZxkecrYQhQduM4xhhznqNP8S6lL4R0PUl0K91ae/so55hp7QIImZFY5E0qcEk4xnpzXQGztjcNObeIzPH5TSFBuZMk7SeuMk8dOTToIIbW3jt7WJIYYlCRxxqFVFAwAAOAAO1Po/66v/NfcLqn/Wy/yf3nA+NdOvLvx14Pmj13UdMWe5mjSOJLYiF/s0hypeJ8scEEEsMZwB1q9qQ8QTeMtP0Cx8RT2tr/AGTJPc3X2aB7iSRZEVWGU2KTk5+TGM4AOCOp1PSNN1uzNprOn2uoWxYMYbuFZUyOh2sCM0trpen2Xk/YrG2t/Ih8iHyoVTy4+DsXA4XgcDjil1/rs/1B+X9a/wCRwPiTxBrthZW+mS6hfJrVnpRvdQfRYrTykxlfNd7sqvlkqx2oAwwckDFHiG8vdV8F+EPEM1yqSTXmmSS2f2WCSBnmljBYeYjOrAO20qwIrt9R8O6LrF1Bc6vo9hfz23MEt1apK0XOflLAkcgHiq994O8M6oIBqfhzSbwW0QhgFxYxSeVGOiLlTtUeg4pp2d33T+5v/gA9duzX4L/gmH4gm1y88X3em6Zr02k2tvpC3Y+z20MjtKXkUcyKw24UZGMnAwV5ziar4z1K88P6Y1neanBqDaGmrXf9lQ2YSFWX78jXbbdmQ3yp83ynJHFei22k6dZqq2lhawKkAt1EUKqFiGcRjA+6Mn5enNVbrwt4fvjZm90LTbg2KhLQzWcb/Z1GMBMj5QMDpjpU2drf19r/ADX3Dv71/wCun+T+84S0uNU8Q67a6outnQ3n8LW13cz21vG5DFpG480MqoCSSCCSMYI5zZ1nU7vWfhX4W1LUo/Lu7vUNJlmULtG43MRJA7A9ce9dfeeEfDeoNbNf+HtKumtIxFbmayjfyUHRUyvygdgKfq3hXw9r06T65oWmalLGuxJLyzjmZVznALA4Ge1Umk7rvf8A8mb/AFt8ibO2va34JHKeLNd8QSeM20HQU1VPJ05bwPpiWReR2dl+f7UwBRdoyEGctyRxnstDm1G40Gxm1y2S01J4Ea6gjYMscmPmAIJGM57n6mq954U8O6jY2tlqGgaXdWtmu22gns43jgGMYRSMKMAdPStKCCG1t47e1iSGGJQkccahVRQMAADgADtSWisN6u5x+vTaxd+NLjTrPxHJomn22kreSPDbQu+/fIud0qsAuFBIxzgYK855+98a6vfeGdLaK41W01Q6GuqXi6bBZqsQIwJJGu22hCVY7U+YAHJHFdlqPgnSNZ8WDWtasbLUdlolvDDd2iS+Uyuzb1Zs4J3AcDt1rR1Hw7ousXUFzq+j2F/PbcwS3VqkrRc5+UsCRyAeKlJ8tuuv5u35r7vuq65r+n6X/X+t+NtdW8R+JtR8PwWusDSYL/w+NQu2treN5BKWjx5fmKwUfMQdwbj3wwi8SeINdsLK30yXUL5Nas9KN7qD6LFaeUmMr5rvdlV8slWO1AGGDkgYrv4NOsrVomtrO3haGHyIjHEqmOPj5FwOF4HA44FV9R8O6LrF1Bc6vo9hfz23MEt1apK0XOflLAkcgHiqlrt5/rb819xMNN9dv0v+p5fceNPFGoX1g9rqyWEc9ro7vFFaxuu+8aRZDlwTgBQVGeoGcjIN9Nd8W3ngrQ9aNzqDWIspZNRuNIS0F0ZFbhylwvllNqsSEAbdjAxxXoa6DpClCulWQKCJUxbJ8oiJMQHHGwk7f7uTjFVbrwd4Zv1txfeHNJuRartgE1jE/kjOcLlflGeeO9OVm3bvcUVbfsv+CQaje/atN0K6sPEsOmQ3N1A6yXESE6hGyk+QA+NrOMHKjcMcCugqvd6fZ3/kfbrSC5+zyrND50QfypF6OuRwwycEc81YoBX0ucf48u4VsZtI0zT4L/xDrdq9nBCVGREQQ0krYyIU3En1JAHLVt2bWXhjQtK0/UdSiTYkNjFNdSqhuJAu1VGTyzY6Dk0mq+FPDuvXK3OuaBpepTomxZbyzjmZVyTtBYE4yTx71n654Ktdah0fTl+zWejabcx3Isre1ClnjOY1Vs4RAeoCkkcArzlR007v8P6b+bG9de35/wBJGJrx1WT4pyNp9zpdm1loYnt59TheZFzK4m2qrpt4WLc+75RgYO7gnuNX1LQ7D4gaZeadpMw0NmmtNSt3li2ttl/1iyIUGVxu2twc47V2Wq6DpGurEut6VZaisLb4hd26SiNvVdwOD9KZqHhzRNWvLe71XRtPvbm2x5E1zapI8WDkbWYErzzxSV0rLf8Azv8A57eXmN2bu9tPwt/lc4D+1NY17xhZataf2dpEo8MxX0A1aGSYQeY7GZQoaPB4iDPngAfKd3He+GdXfX/CumavLbG1e+tY52hLbthZQcZ7j0PpUuq6DpGurEut6VZaisLb4hd26SiNvVdwOD9Kv9KrS1l/Wrf6/h5k63/rsl+n4hRRRSGFFFFABRRRQAUUUUAFFFFABRRRQAUUUUAFFFFABRRRQAUUUUAFFFFABRRRQAUUUUAFFFFABRRRQAUUUUAFFFFAH//Z)

## Balloons rectangle tightening

Another feature I wanted to address in this stage of the project was to tighten the rectangle that marks the balloons location in the frame. The tightening was achieved based on standard image processing techniques. At the start of the tightening process, vertical and horizontal edges were searched inside the untighten rectangle (ROI). To find the real edges of the balloons, several decision mechanisms based on thresholds were added to filter out noise that can be added during the edge detection. The threshold mechanisms are based both on the size of the ROI and on the 3-dimensional pixel value.

Following the change of the CNN architecture to NanoVGGNet along with the small modifications mentioned in the beginning of this section and the addition of balloon rectangle tightening. The detection runtime improved to 5.5 fps on CPU and 27 fps on GPU. A factor of 3 increase from the previous baseline.

Below are two images that shows the result of the tightening. On the left, the initial rectangle. On the right, the tightened rectangle.

A group of people flying kites in a building

Description automatically generated

## Tracking

The last optimization modification was to add the tracking mode to the detection algorithm. Tracking mode saves valuable calculation time by using the detection result of the previous frame. At the start of operation, the system is in detection mode. In detection mode the system uses the previously discussed algorithm for balloons detection. Once balloons were detected, the system is moving to tracking mode. In tracking mode, the system tries to detect the balloons around the area were the balloons where located in the previous frame. Several iterations are done to try to locate the balloons near their previous location. In each iteration, the suggested location is checked using the trained CNN. In case detection in tracking mode is successful the system is proceeding to the next frame. In some cases, the tracking mode is unable to detect the balloons. In which case, the system will go back to the detection mode. Going back to the detection mode may happen in cases where there is a strong wind or there is a significant change in the video recording angle of the camera.

Following the addition of the tracking mode, the detection runtime improved to 170 fps on CPU and 190 fps on GPU. After additional global system parameter trial and error process, the final runtime achieved was 190 fps on CPU and 220 fps on GPU. A factor of 8 increase from the previous baseline.

# Usage

In this section it is explained how each Python program that was written as part of the project can be executed and which arguments can be added to the run command. All project specific configurations are in the config directory under project main directory. Each python script can be run along with the debug flag to generate debug prints that can be used for debug (i.e. --*debug* 1). A readme file, which is available in the project main directory contains more detailed examples of how to run the programs that are part of the project. Moreover, each script can be executed with the -h argument to display all execution options and their description.

## Dataset generation

python crop\_balloons\_from\_video.py --input <path to video file>

To start the semi-automatic program which allows to generate a dataset from an input video in reasonable time, the above command should be executed. The script takes an input video and generates 3 output images for each frame: A frame crop which contains balloons, a small image to be used as the sky background and the original frame with marking of where the balloons and sky crop were taken from.

Along with the mandatory input flag, the program can accept two additional flags. The *auto* flag (default is 0) which makes the program to not prompt the user on every frame. And the *start\_frame* flag (default is 0) which allows the user to declare from which frame to start generation of the dataset. The last can be useful incase program was abrupted during regular run. A directory with the output images is generated in the same location where the input video is located.

## Dataset building

python build\_balloons\_vs\_sky.py

To build the dataset the above command should be executed. The script splits the dataset, which is defined in the config file, into 3 HDF5 [[10]](#HDF5) files: train, val and test. The HDF5 files location is also defined in the config file. The config file also contains the percentage of test and validation images of the dataset to be used for test and validation during training.

## CNN training

python train\_balloons\_vs\_sky.py --net <CNN architecture> --optimizer <SGD/Adam>

To train the CNN the above command should be executed. All arguments provided in the command line are optional. Other argument that can be given to the script are: number of epochs to train (--*epochs*) and initial learning rate value (--*learning\_rate*). The script, trains a CNN of the architecture type that is provided as an argument to the script according to other optional arguments provided in the script. Other relevant training configuration can be found in the config file. The program saves a checkpoint of the CNN training every 5 epochs.

## CNN evaluation

python eval\_balloons\_vs\_sky.py – model <path to HDF5 checkpoint file>

To evaluate the trained CNN the above command should be executed. The script evaluates the trained CNN that is provided in the command line in the form of and HDF5 [[10]](#HDF5) file. The evaluation is done on the tests split which was described in previous sections. The checkpoint files are generated by the CNN training program.

## Balloons detection

python detect\_balloons.py --input <path to input video file> --model <path to HDF5 checkpoint file>

To run the final detection program, the above command should be executed. The script detects the balloons in the video and adds a green rectangle around the balloons to mark their location. The output video will be written to the same location were the input video is located but with a “with\_balloons” postfix. The program can also take as an input a folder of images instead of a video file. Additionally, the program can start running from a certain frame by adding the *start\_frame* argument to the command line. Or, the *frame* argument to run a single frame.

## Splitting video into images

python split\_video.py --input <path to input video file>

The above program can be used incase splitting the input video is needed before running the detection program. The output of the program is a folder which contains an image for each frame of the input video. The output folder will be in the same location as the input video.

## HDF5 dataset display

python show\_hdf5.py --path <path to a folder which contains HDF5 files>

The above command is used to debug the HDF5 [[10]](#HDF5) files which were generated during the dataset building phase. The program saves to disk the images encrypted inside the HDF5 files.

## Running on the Jetson

All the above programs can be executed on the Nvidia Jetson TX2 [[2]](#Nvidia), as well as on CPU and GPU. In order to execute any of the programs on a certain machine, both Python and Keras needs to be installed properly. The run command is the same for all machine types: CPU, GPU and Nvidia Jetson TX2 [[2]](#Nvidia).

# Results

The algorithm was tested on a single video and produced very accurate results while running in real time. The output video can be found [here](https://drive.google.com/drive/folders/1giZRlxxv3ZNGfFF80seVfzVT_ay9tIBo). In the folder, besides the output video, the result of the algorithm when executed on a folder of images can also be found. The original input video is in the results folder as well. The output video and output folder of image both have the “with\_balloons” postfix.

Below presented several frames of the video that was tested, along with the balloons marking in green rectangle. It can be noticed that in the 1st image on the right in the 1st row, the ROI optimization mechanism has miscalculated the real balloons boundaries.

A picture containing sky, outdoor, building

Description automatically generated

A group of people flying kites in a city

Description automatically generated

As for the run time, running the detection both on CPU and GPU showed that a significant progress was done in execution time during the optimization phase. At this point, the detection algorithm was run on the Nvidia Jetson TX2 [[2]](#Nvidia). After overcoming several integration problems, the detection was running on the Nvidia Jetson TX2 in 73 fps rate while maintaining the same detection accuracy. The final execution time that was achieved in the project were: 190 fps on CPU, 220 fps on GPU and 73 fps on the Nvidia Jetson TX2 [[2]](#Nvidia).

# Conclusions

In the project I have dealt with all the main stage needed for developing a deep-learning based computer-vision system. Stages included: dataset collection, CNN training and CNN usage for a specific task. In addition, I’ve enhanced my knowledge in DL and CV by reading the DL4CV book [[1]](#DL4CV) and was able to assist to create a deep learning environment setup for the Autonomous Indoors Drone Lab at Tel Aviv University.

I was able to achieve the goal of running a balloons detection algorithm in real time on the Nvidia Jetson TX2 [[2]](#Nvidia). While overcoming the main challenge of the project which was to optimize the initial setup to run 100 times faster, with even better detection accuracy. All, while combining both traditional computer vision and image processing techniques with the newer CNN based methods.

# Future Work

Even though a lot of work was invested to allow detection of balloons in a video stream. There are many areas where the project can be future enhanced. Firstly, more research can be done on selecting a better CNN to allow for better accuracy and faster inference time. Which brings me to the second enhancement, which is trying to leverage the algorithm to work on a more complex dataset. A more complex dataset either with different object for detection besides balloons or varying background besides sky background, may require a deeper CNN.

Additional path for future enhancement can be looking for a way to train the CNN on a video stream without splitting it to frames. This can be achieved by modifying the 3rd dimension of the neural network input to be several frames, when each frame contains 3 color channels. This opposed to a single frame with 3 color channels as was done in this project.

Additional improvement can be done in the tracking mode. When instead of working on a single frame at each time, several frames can be analyzed simultaneously. After acquiring the location of the balloons in a certain frame, the location information can be used as the initial guess for multiple frames following the initial frame. Then, the CNN can be used to simultaneously analyze the initial guess of each successive frame.

Another possible enhancement that can be done, is to the ROI rectangle optimization. As was seen in the results section, in some cases the ROI rectangle tightening was done too aggressively. This may be fixed by finetuning the tightening mechanism thresholds.

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