CNN

CNN for image classification

Image Source:
twitter.com%2Fcats&psig=AOvVaw30_o-PCM-K21DiMAJQimQ4&ust=1553887775741551

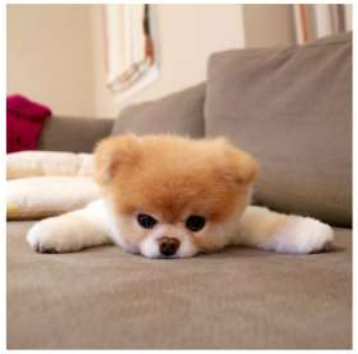
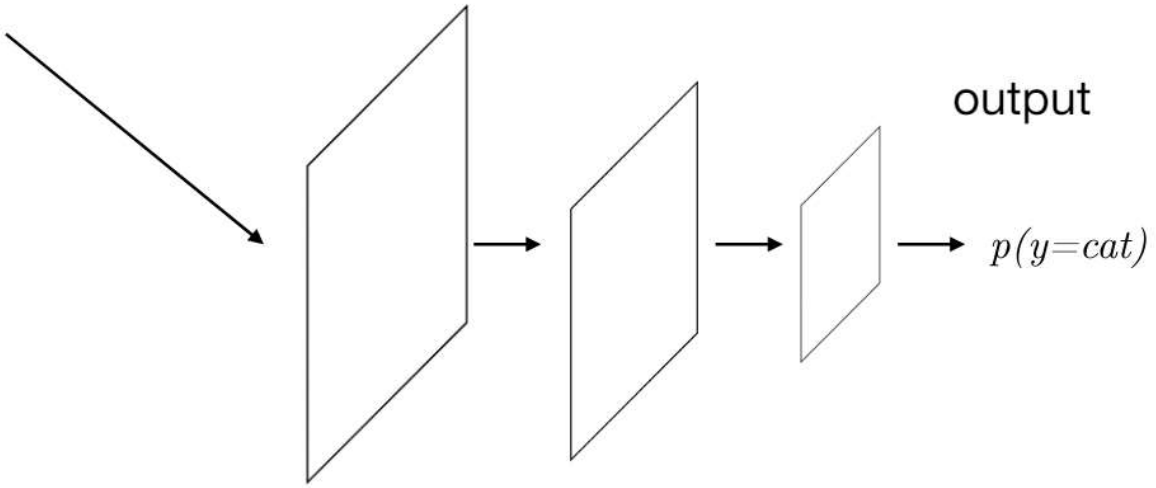


Image Source: https://www.pinterest.com/pin/244742560974520446



Object detection

Redmon, J., Divvala, S., Girshick, R., & Farhadi, A. (2016). You only look once: Unified, real-time object detection. In *Proceedings of the IEEE Conference on Computer Vision and Pattern Recognition* (pp. 779-788).

Object segmentation

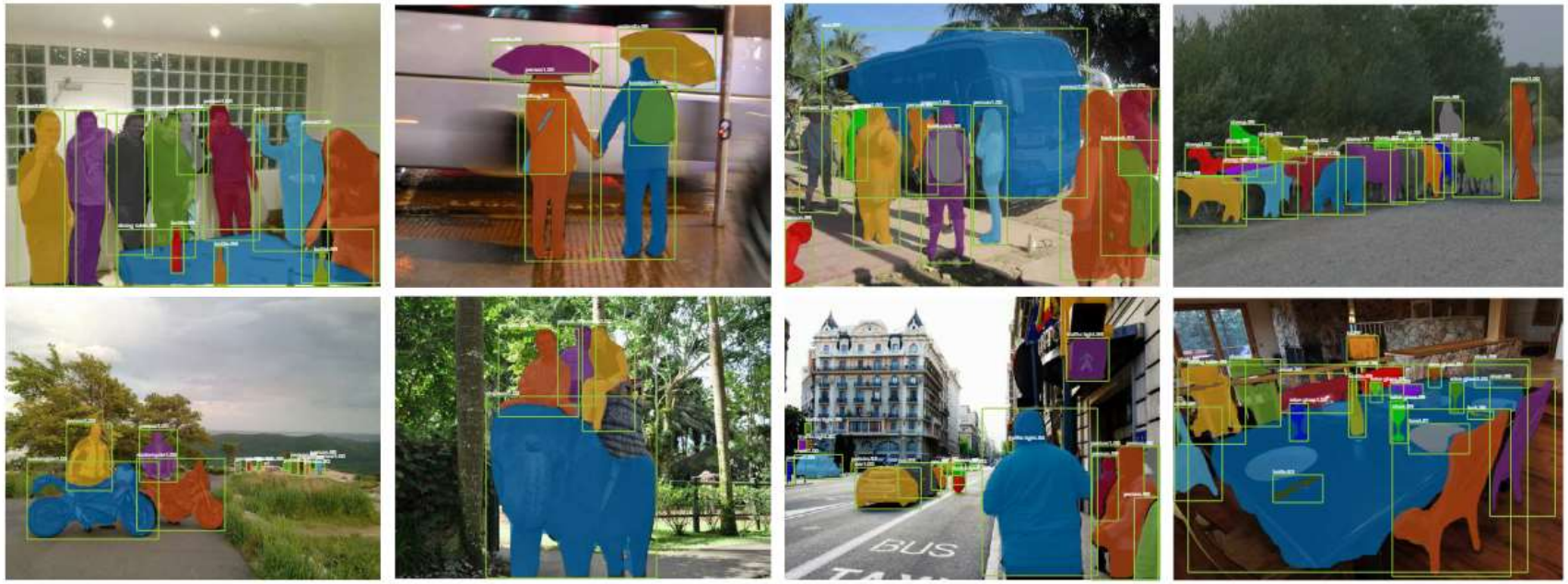
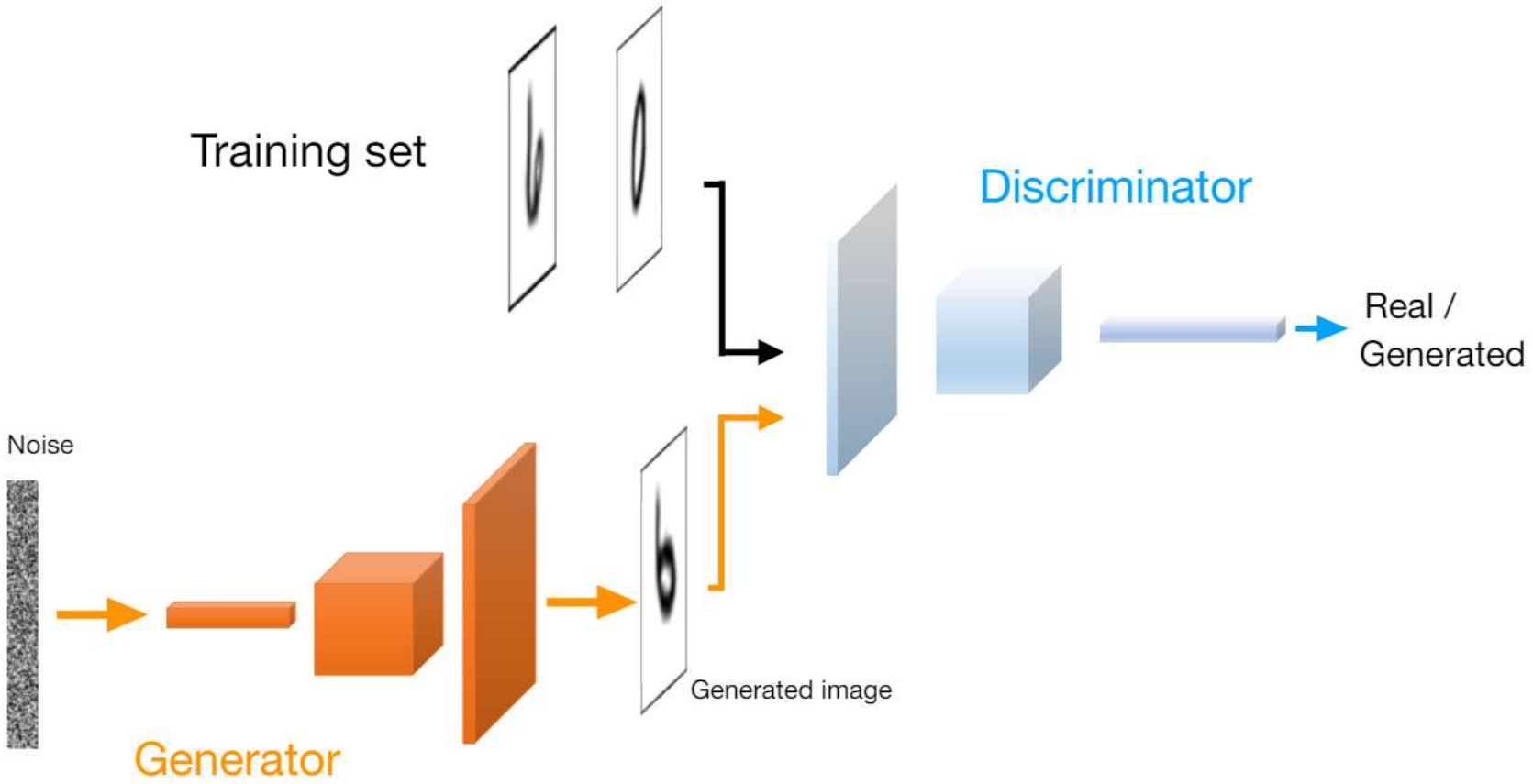


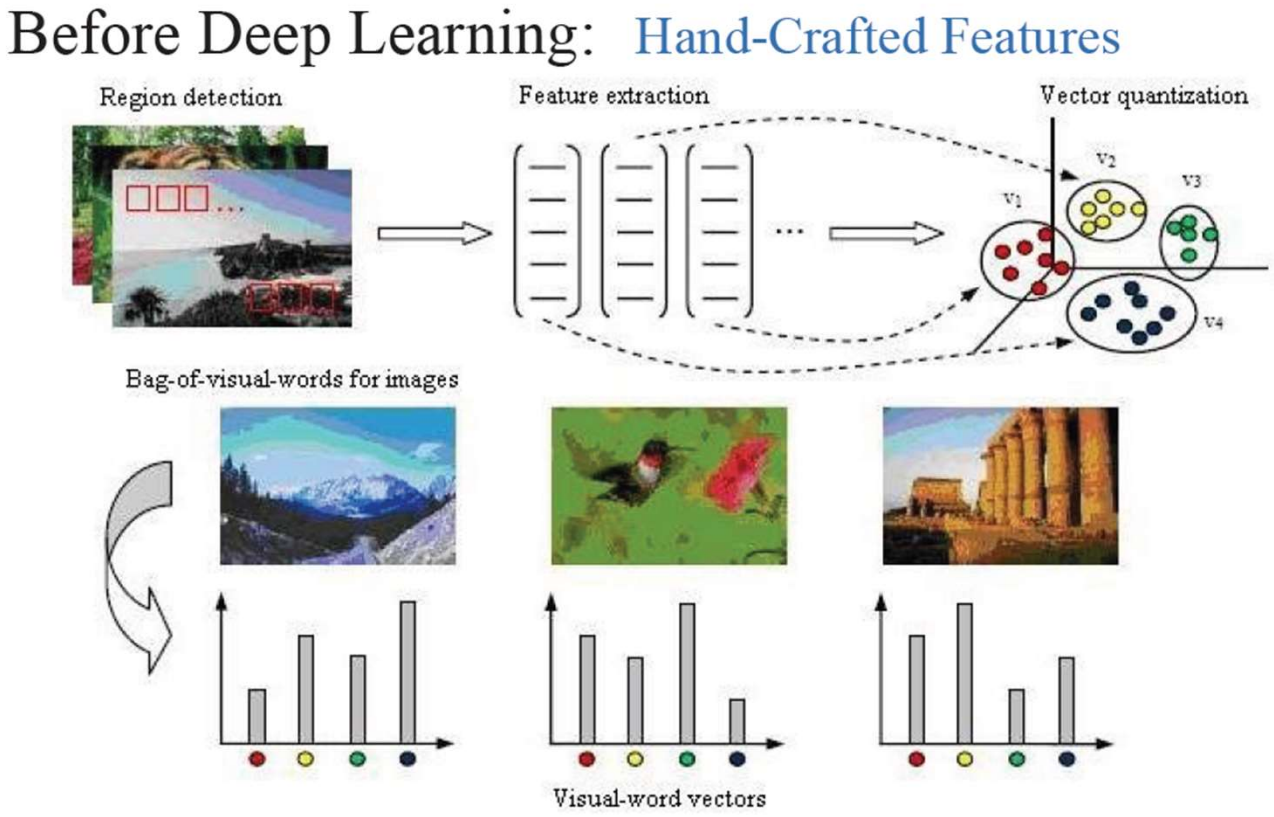
Figure 2. **Mask R-CNN** results on the COCO test set. These results are based on ResNet-101 [15], achieving a *mask* AP of 35.7 and running at 5 fps. Masks are shown in color, and bounding box, category, and confidences are also shown.

He, Kaiming, Georgia Gkioxari, Piotr Dollár, and Ross Girshick. "Mask R-CNN." In *Proceedings of the IEEE International Conference on Computer Vision*, pp. 2961-2969. 2017.

Image generation



History of Computer Vision



History of Computer Vision

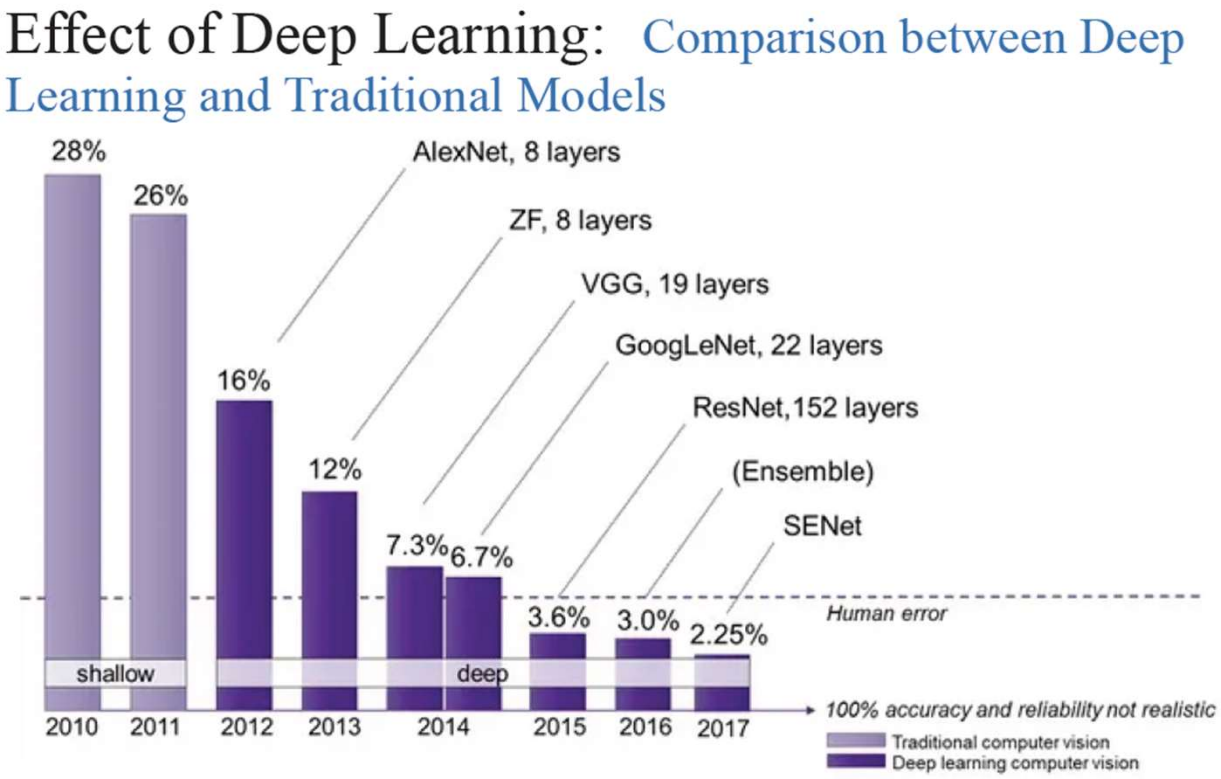
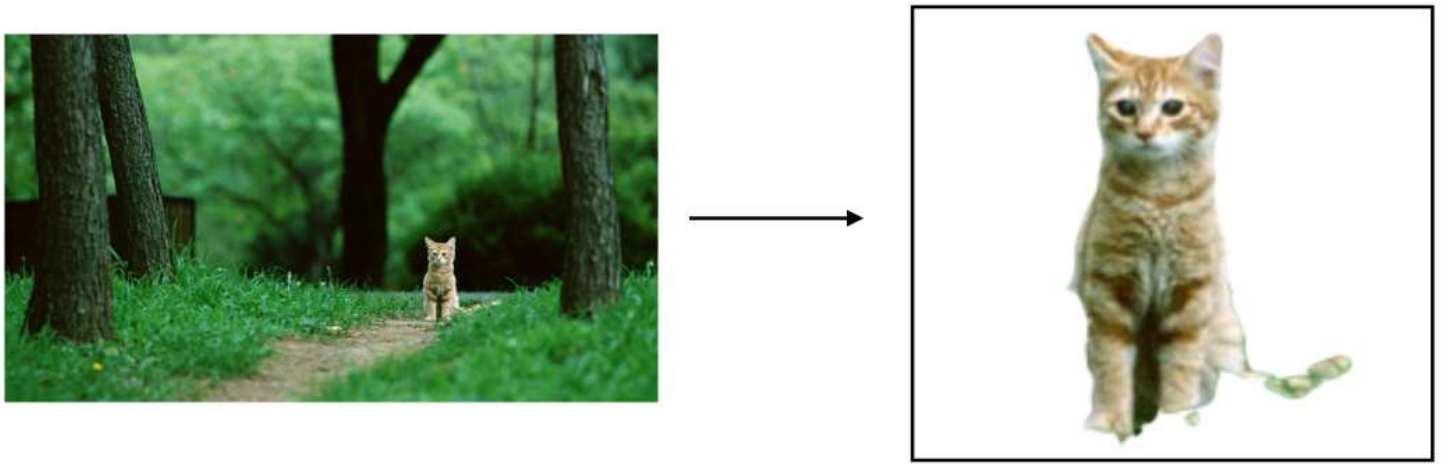


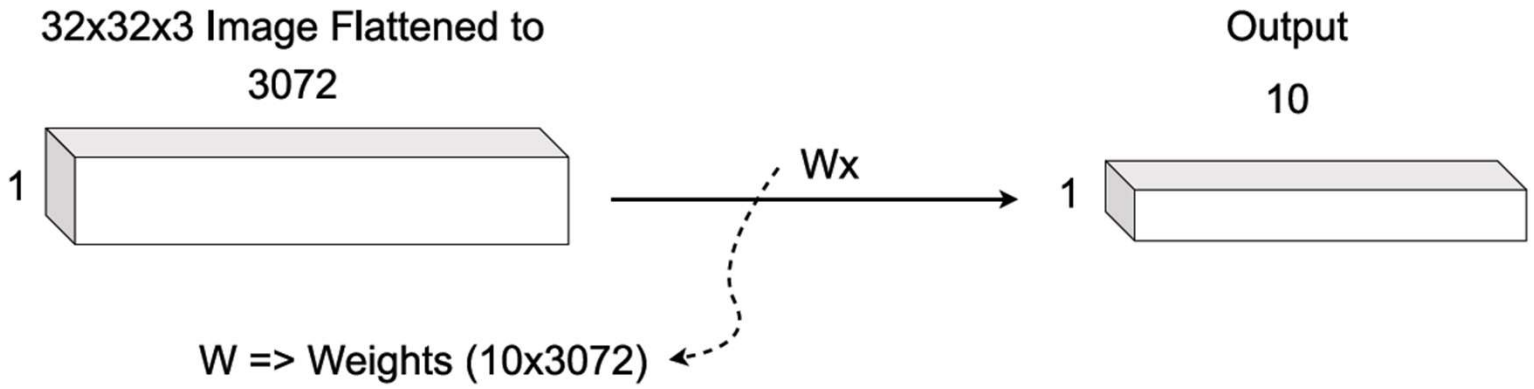
Figure: ImageNet Competetion Results Over Time, Source

Traditional approaches

b) Preprocess images (centering, cropping, etc.)

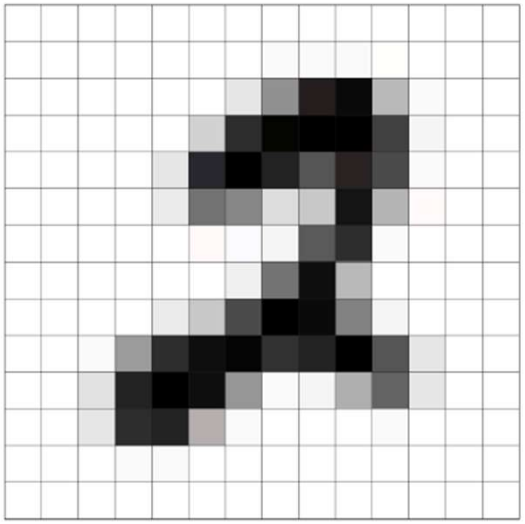


Using Fully Connected Artichecture



- What is the Problem with FC ?

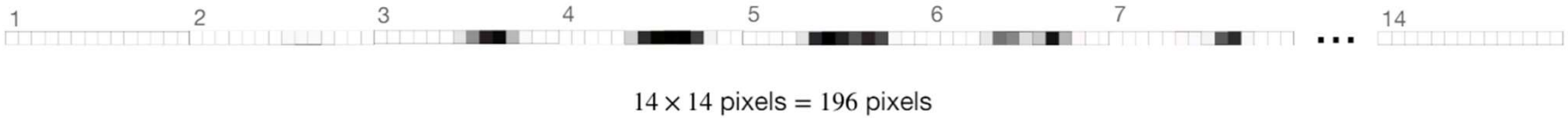
Multi layer perceptron on image data



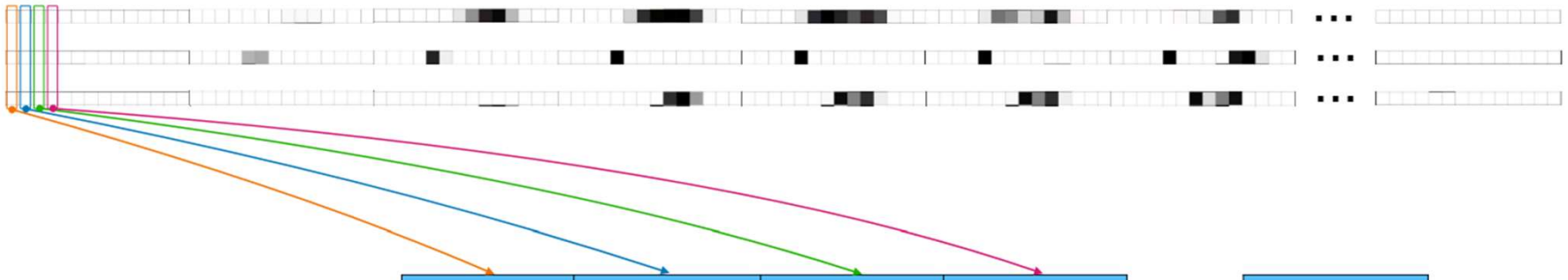
14x14-dimensional image

Concatenate the rows

get a 196-dimensional row vector

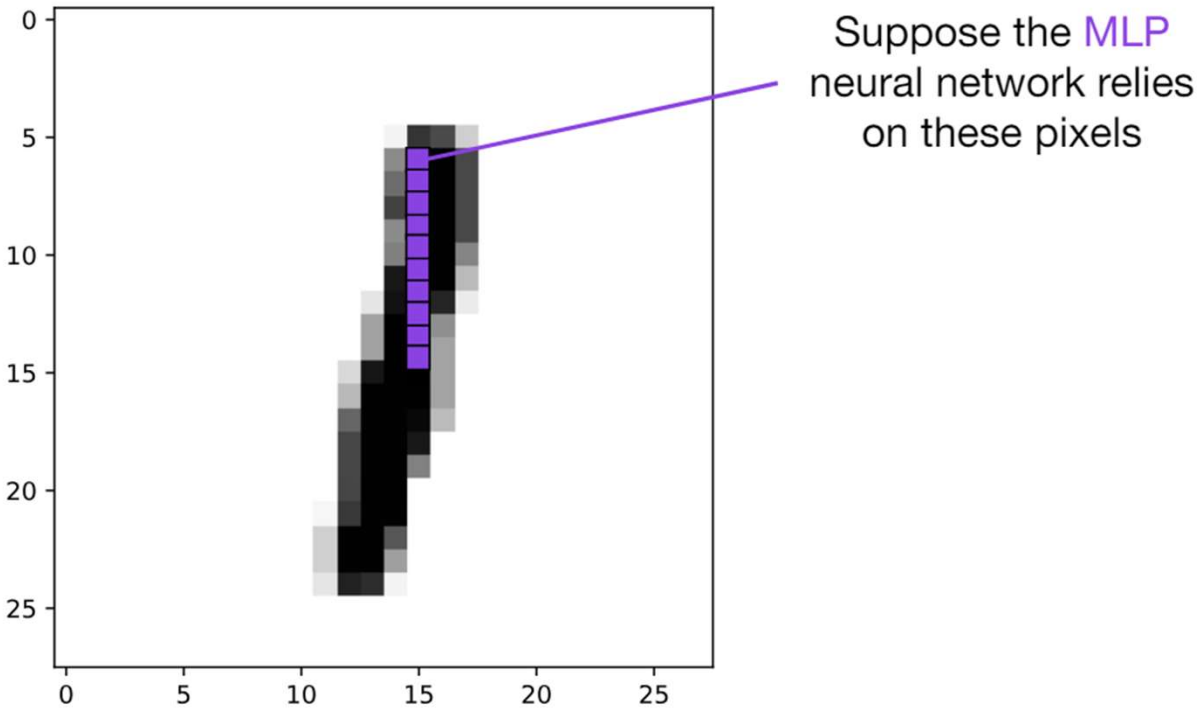


Training examples



Position 1	Position 2	Position 3	Position 4	...	Position 196
0	0	0	0		0
0	0	0	0	...	0
0	0	0	0		0
...	...	...	...		...

Problem with MLP for images



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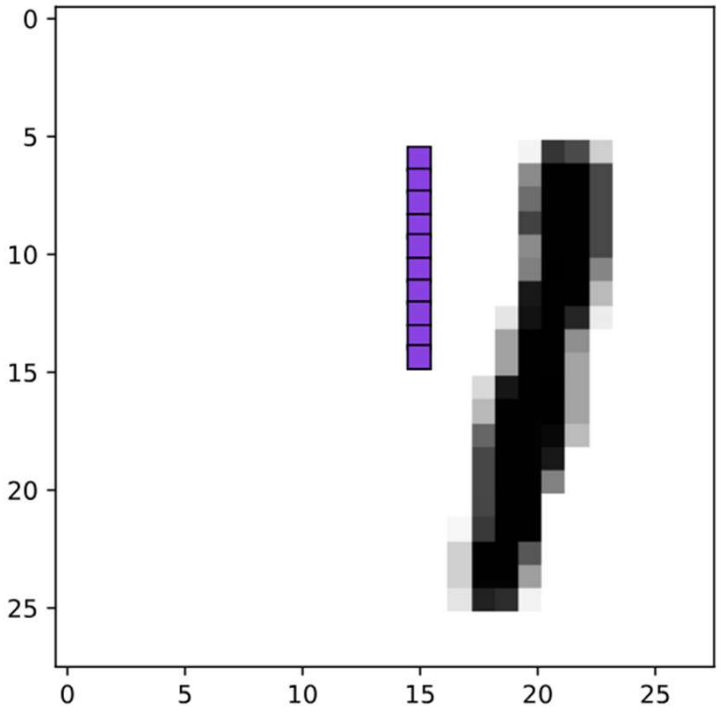


An MLP will not recognize the digit if it is in slightly different position

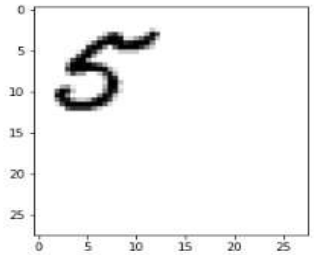
Why Image Classification is Hard

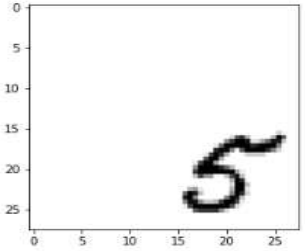
Different lighting, contrast, viewpoints, etc.

Image Source:
twitter.com%2Fcats&psig=AOvVaw30_o-PCM-K21DiMAJQimQ4&ust=1553887775741551

Image Source: https://www.123rf.com/photo_76714328_side-view-of-tabby-cat-face-over-white.html

Or even simple translation



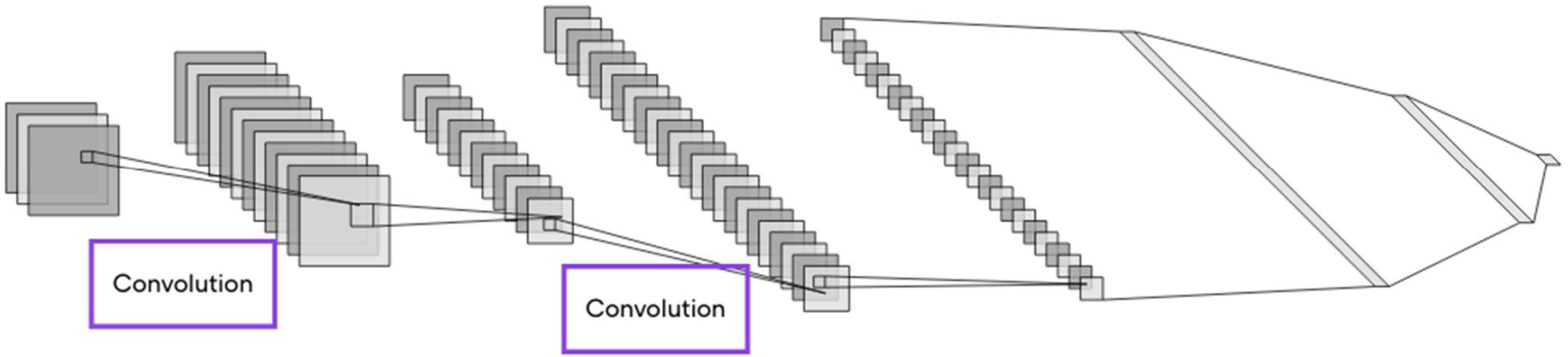


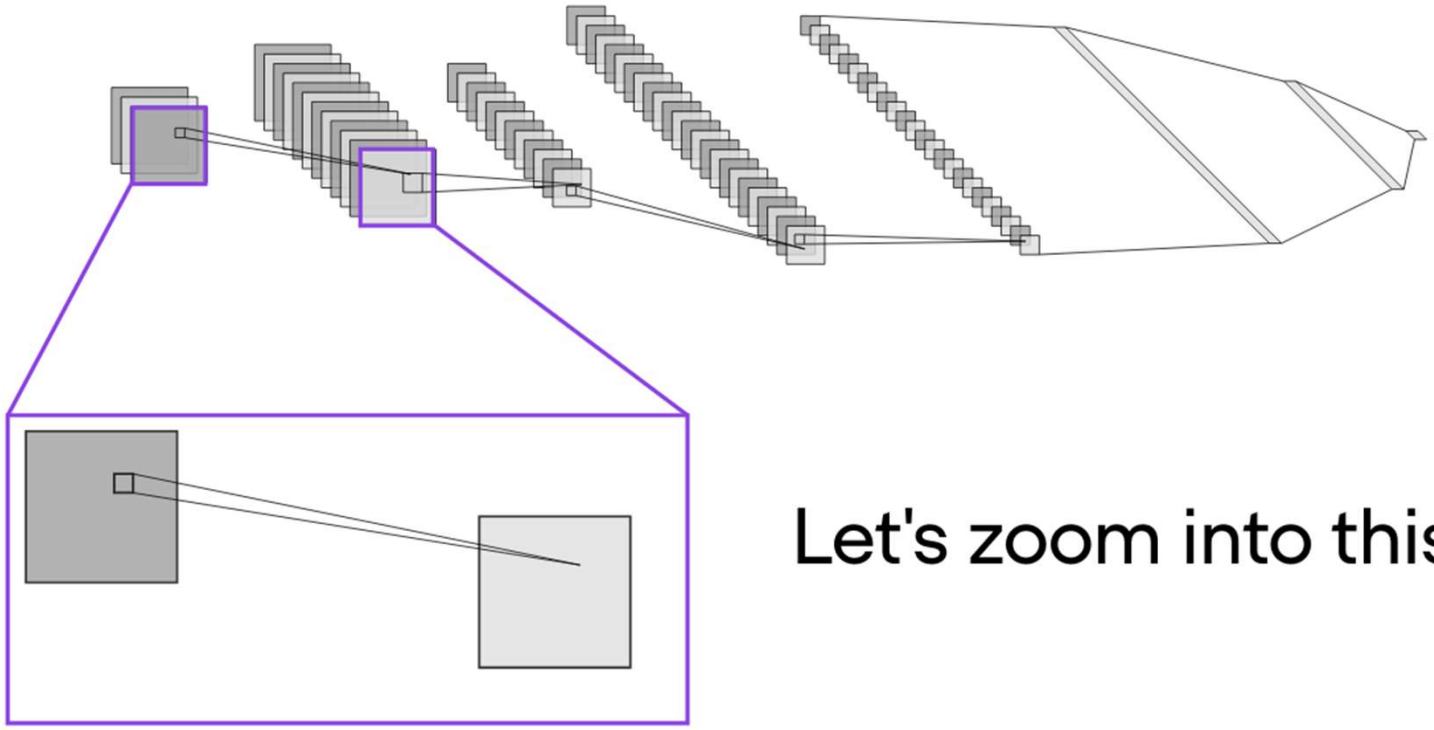
This is hard for traditional methods like multi-layer perceptrons, because the prediction is basically based on a sum of pixel intensities

Main concept behind convolutional neural networks

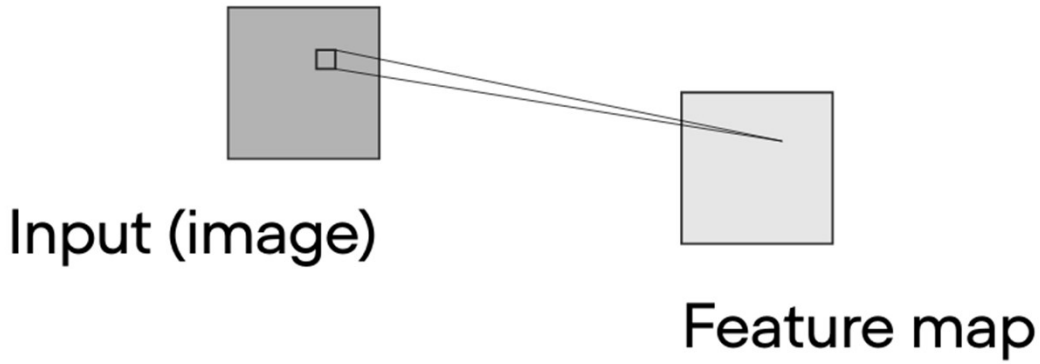
- Sparse-connectivity: A single element in the feature map is connected to only a small patch of pixels. (This is very different from connecting to the whole input image, in the case of multilayer perceptrons.)
- Parameter-sharing: The same weights are used for different patches of the input image.
- Many layers: Combining extracted local patterns to global patterns

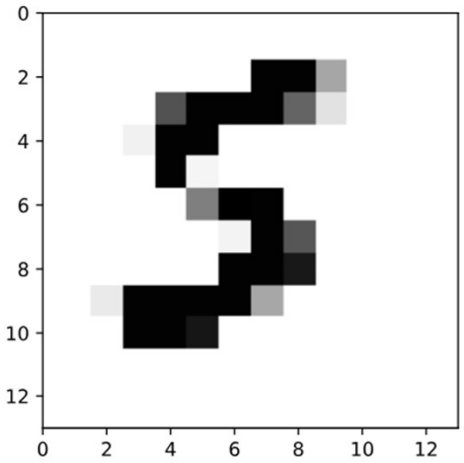
Looking at convolutional layers in more detail



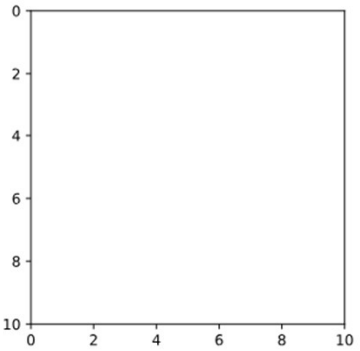


Let's zoom into this part

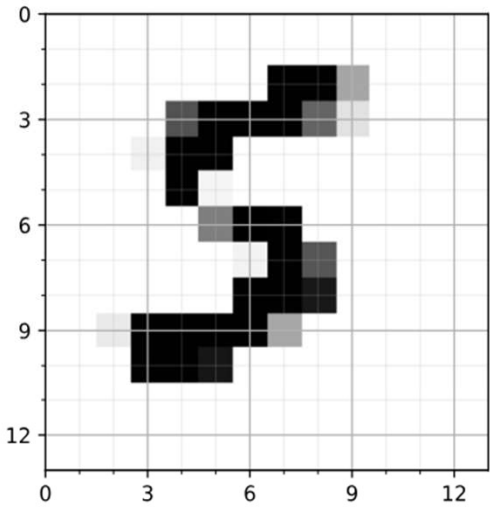

Input (image)
Feature map



Input (image)

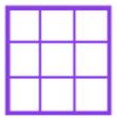


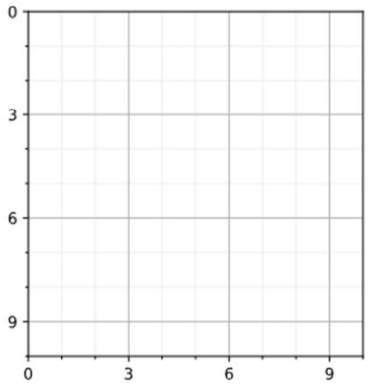
Feature map



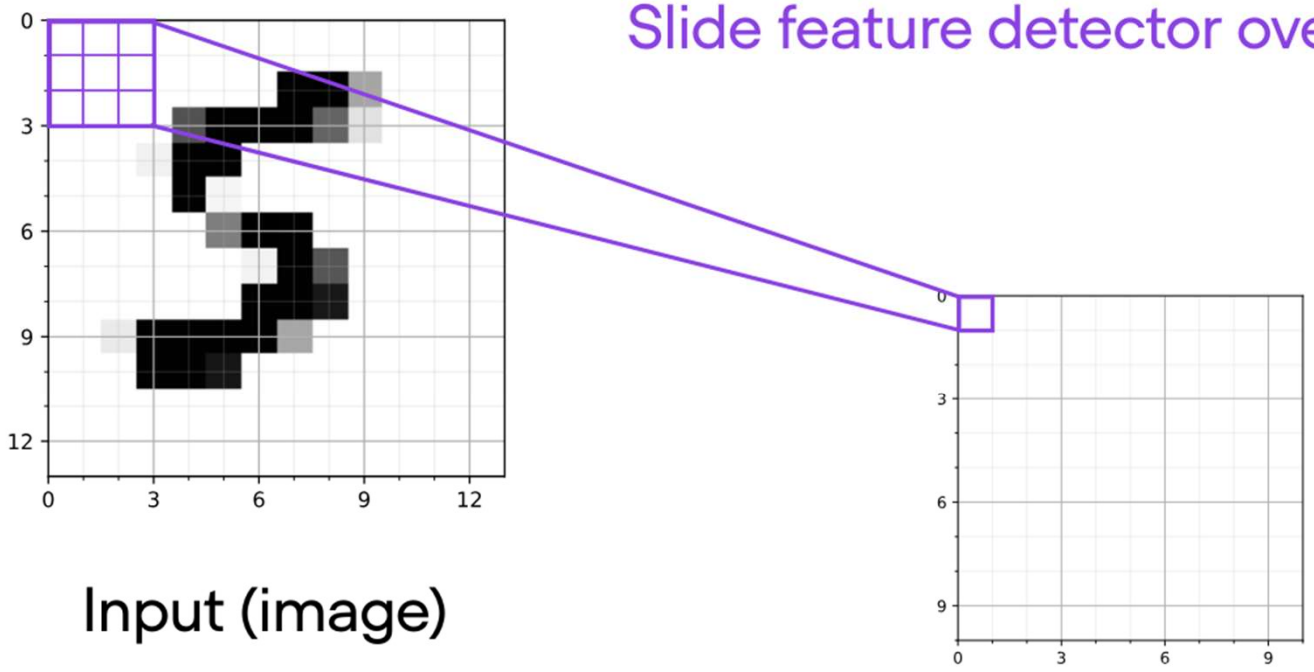
Input (image)

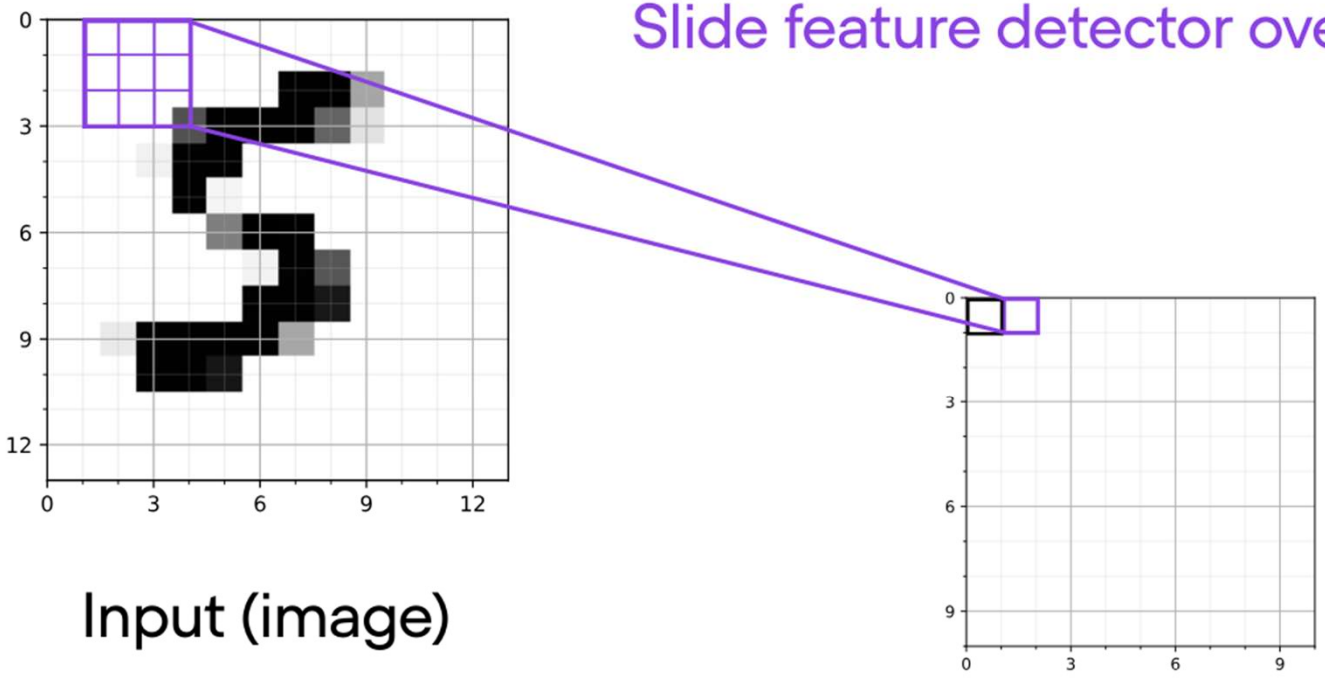
3x3 feature detector (kernel, filter)

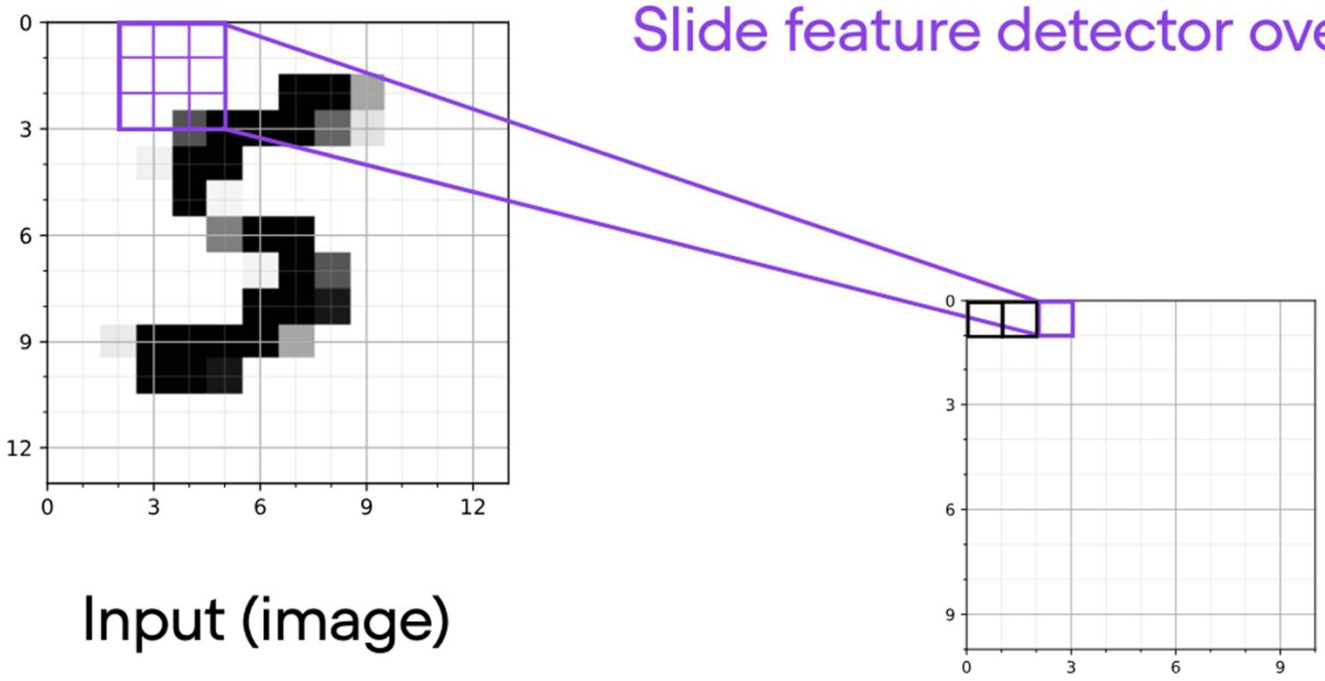


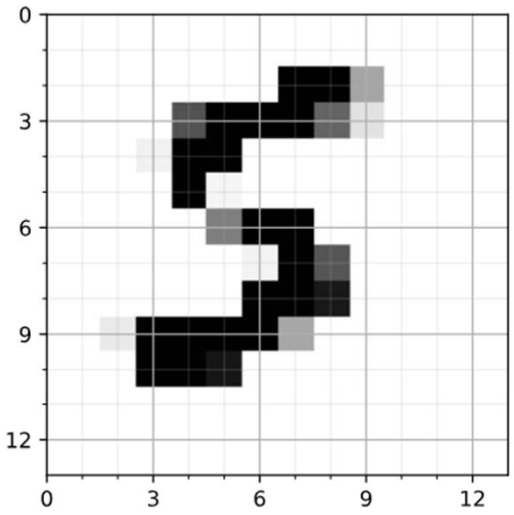


Feature map


Slide feature detector over inputs
0
3
6
9
12
0
3
6
9
12
Input (image)
0
3
6
9
0
3
6
9
Feature map

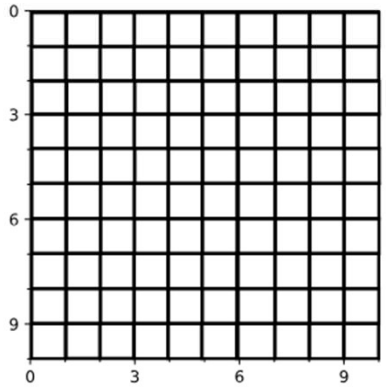

Slide feature detector over inputs
0
3
6
9
12
0
3
6
9
12
Input (image)
0
3
6
9
0
3
6
9
Feature map


Slide feature detector over inputs
0
3
6
9
12
0
3
6
9
12
0
3
6
9
0
3
6
9
Input (image)

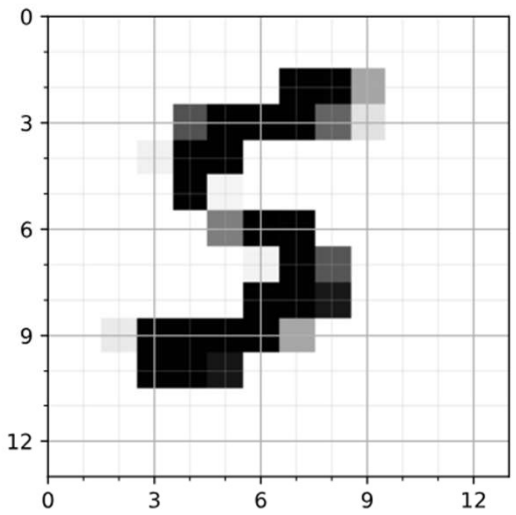


Input (image)

Slide feature detector over inputs

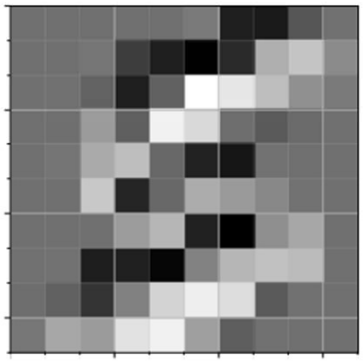


Feature map



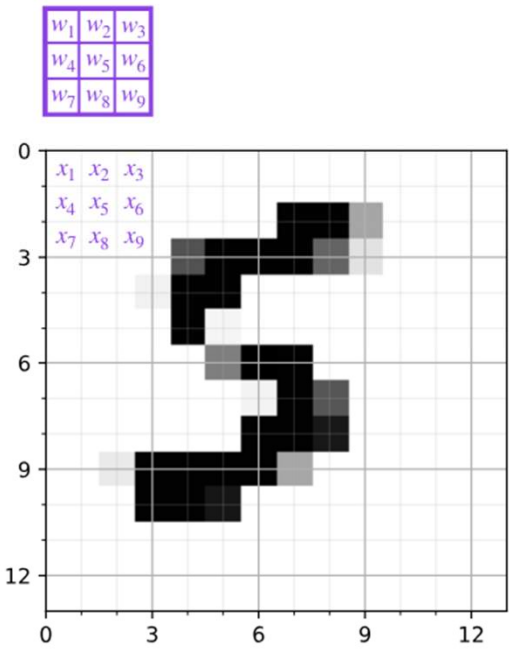
Input (image)

Slide feature detector over inputs



Feature map

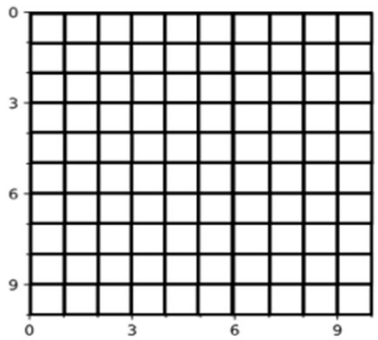
What is happening during this operation?

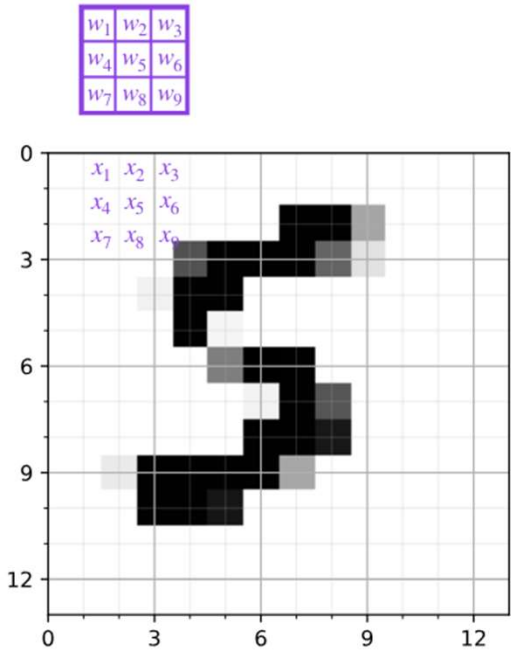


The inputs (x's) differ as we slide over the image.

The weights (w's) do not differ. → weight sharing

$$z = b + \sum_j w_j x_j$$





weight sharing

- Rationale: A feature detector that works well in one region may also work well in another region
- A reduction in parameters to fit (compared to MLP)

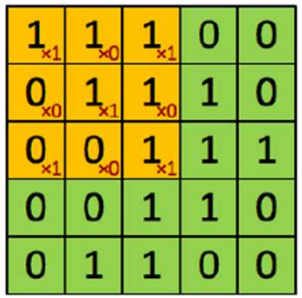
Convolution

- This is how we calculate the convolutional layer's output:

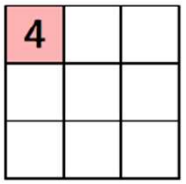
$$ConvolvedFeature(i,j) = (I * K)(i,j) = \sum_{a=0}^{k_h-1} \sum_{b=0}^{k_w-1} I(i+a, j+b)K(a,b)$$

I: Input Image
K: Our Kernel
k_h and k_w: The height and width of the Kernel

Figure: Convolving Kernel



Image



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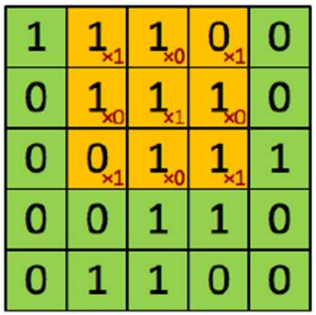

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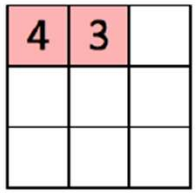

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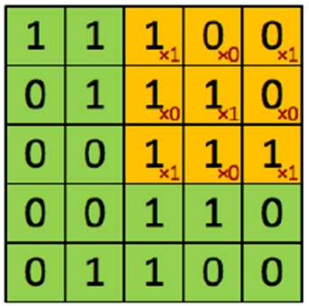
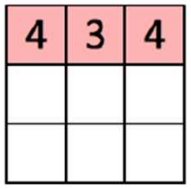


Image



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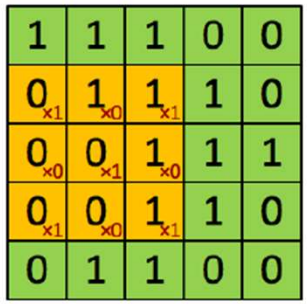
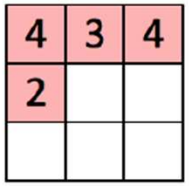


Image



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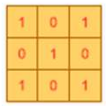
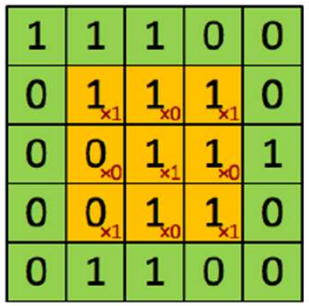
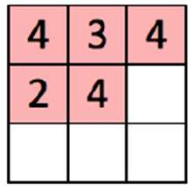


Figure: Convolving Kernel



Image



Convolved Feature

- This is how we calculate the convolutional layer's output:

$$ConvolvedFeature(i,j) = (I * K)(i,j) = \sum_{a=0}^{k_h-1} \sum_{b=0}^{k_w-1} I(i+a, j+b)K(a,b)$$

I: Input Image
K: Our Kernel
k_h and k_w: The height and width of the Kernel

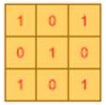
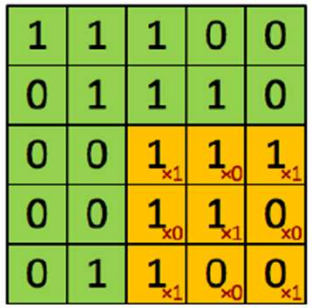
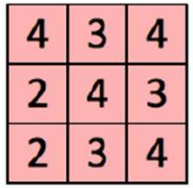


Figure: Convolving Kernel

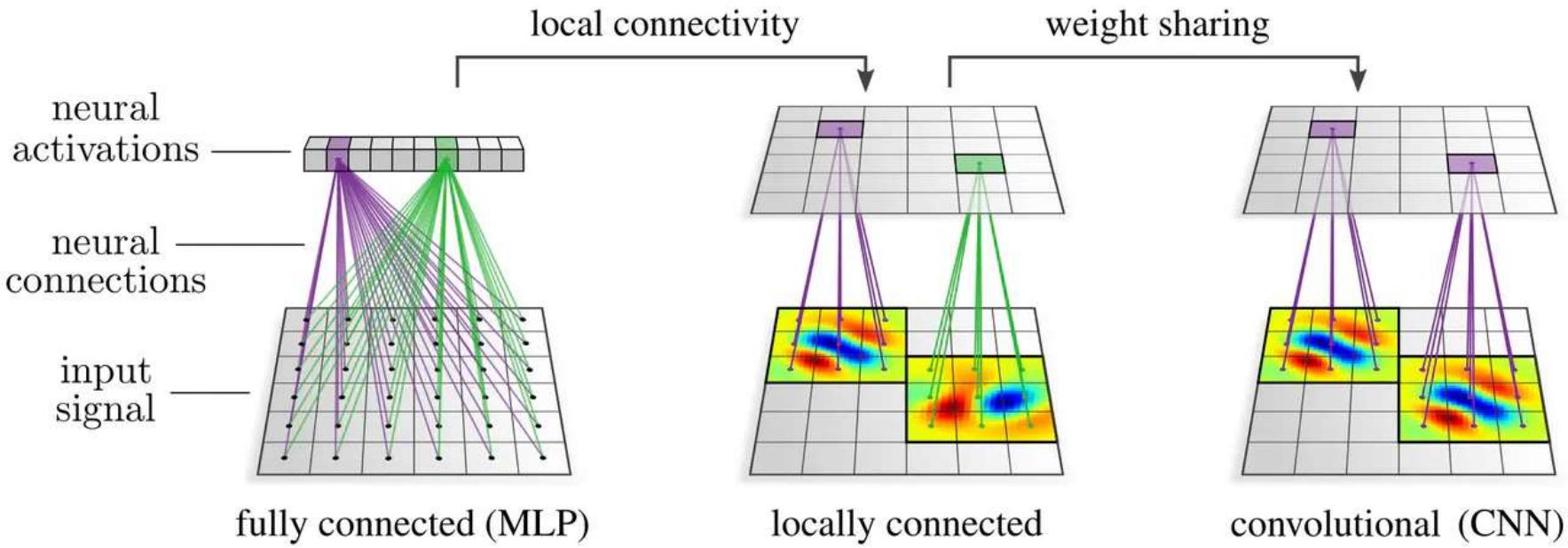


Image



Convolved Feature

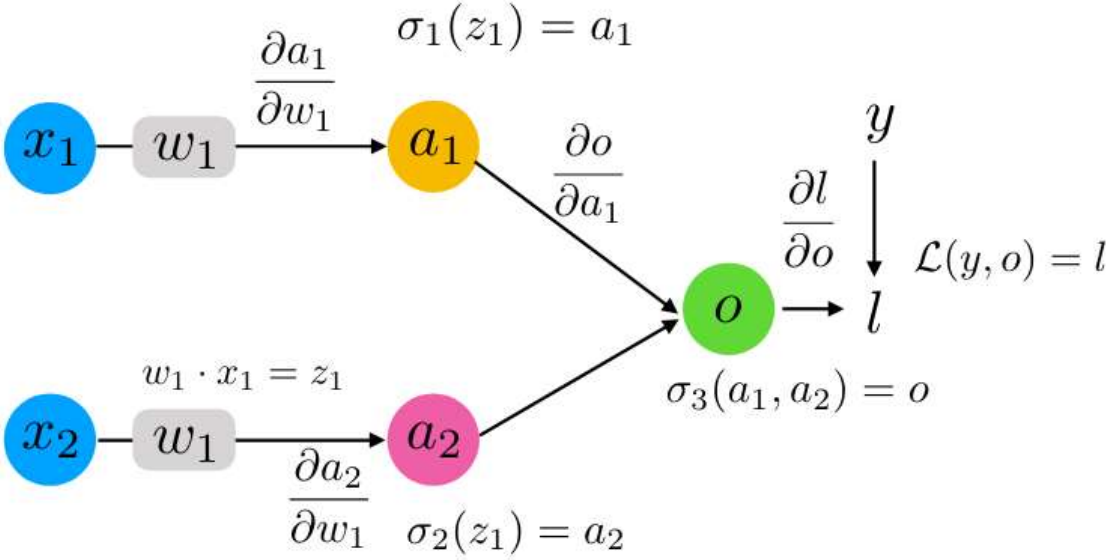
Locality and Weight sharing



Backpropagation in CNNs

- Same overall concept as before: Multivariable chain rule, but now with an additional weight sharing constraint

Graph with Weight Sharing



Upper path

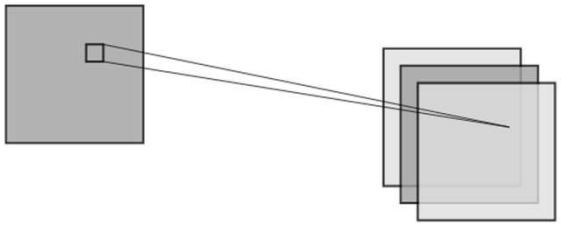
$$\frac{\partial l}{\partial w_1} = \frac{\partial l}{\partial o} \cdot \frac{\partial o}{\partial a_1} \cdot \frac{\partial a_1}{\partial w_1} + \frac{\partial l}{\partial o} \cdot \frac{\partial o}{\partial a_2} \cdot \frac{\partial a_2}{\partial w_1}$$ (multivariable chain rule)

Lower path

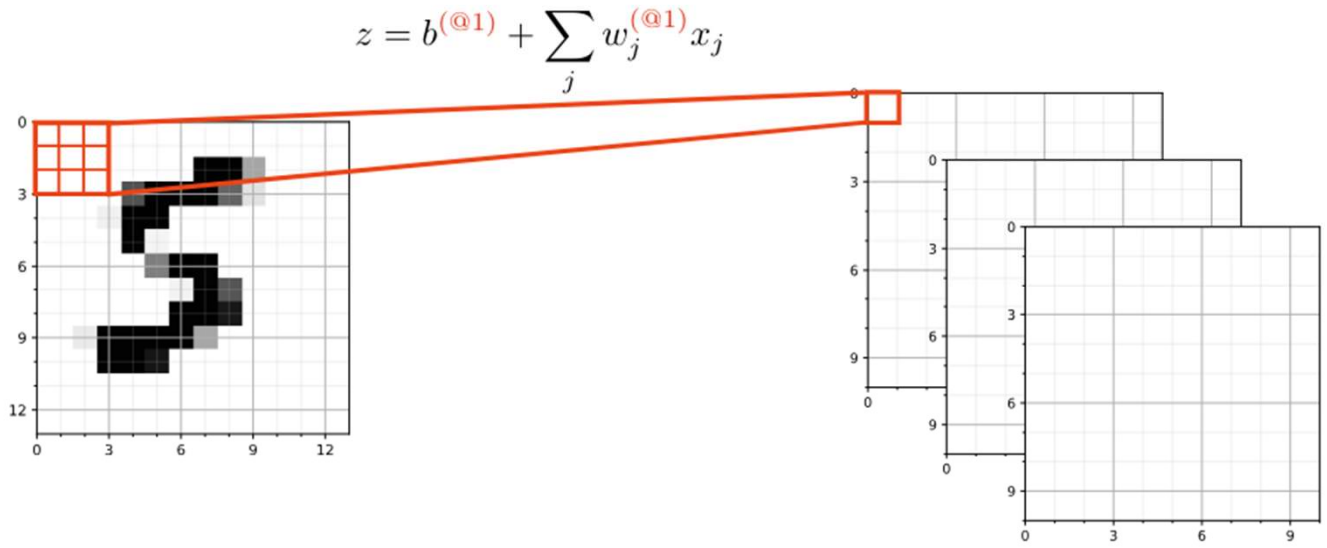
- Which problem is solved with weigh sharing and locality?

Multiple Output Channels

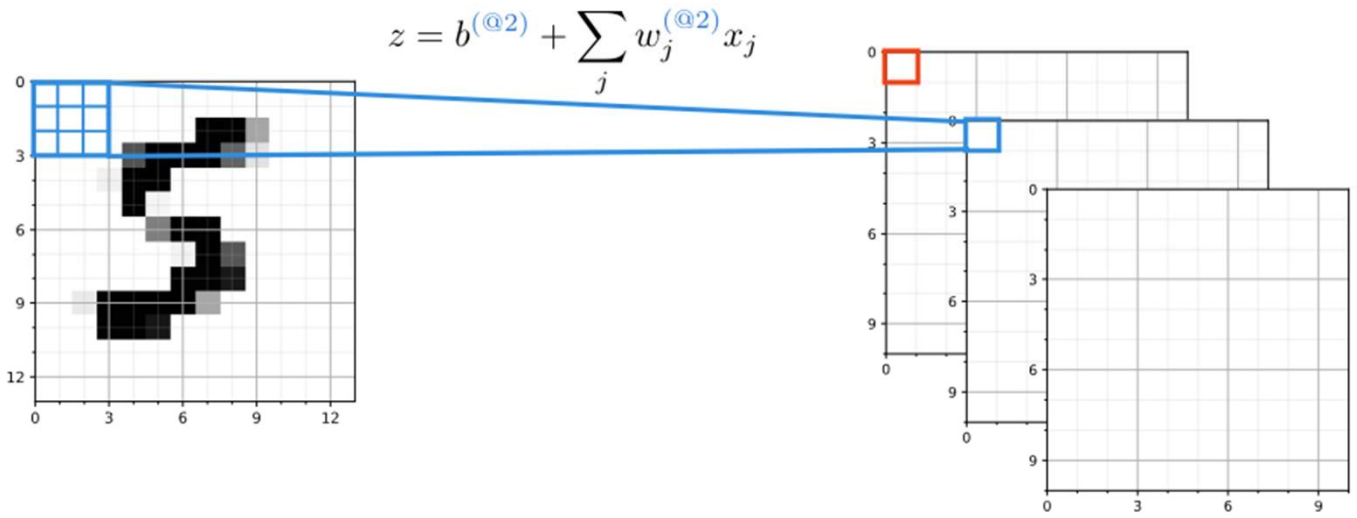
1 input channel, 3 output channels



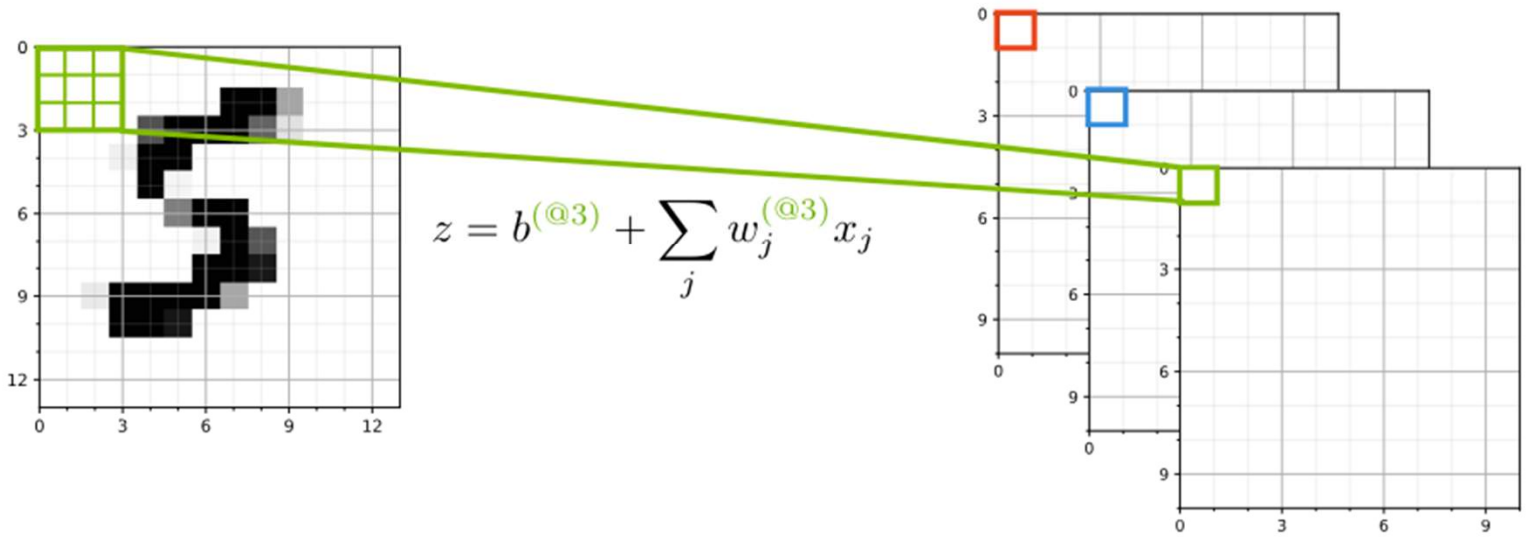
1 input channel 3 output channel



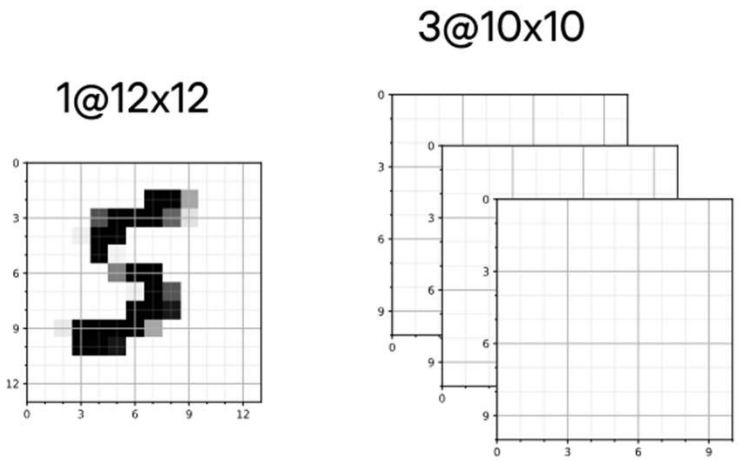
1 input channel 3 output channel



1 input channel 3 output channel

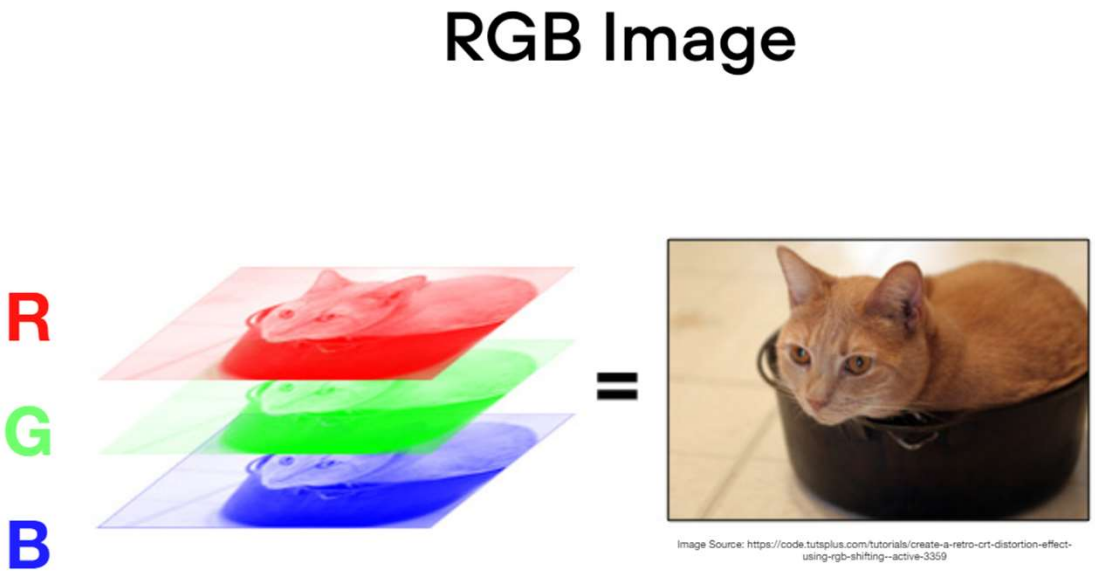


1 input channel 3 output channel



Multiple "feature detectors" (kernels)
are used to create multiple feature maps

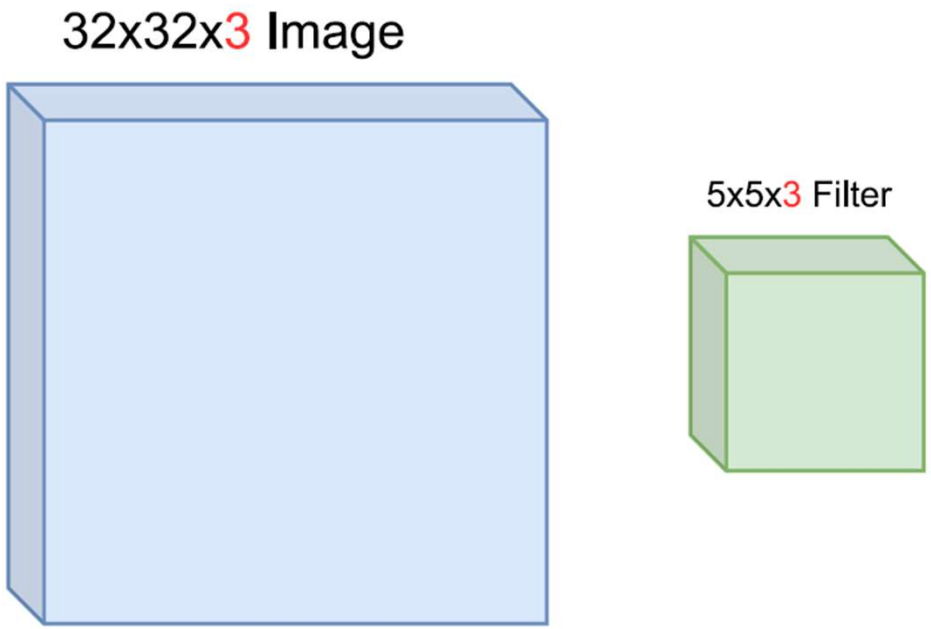
Multiple input channel



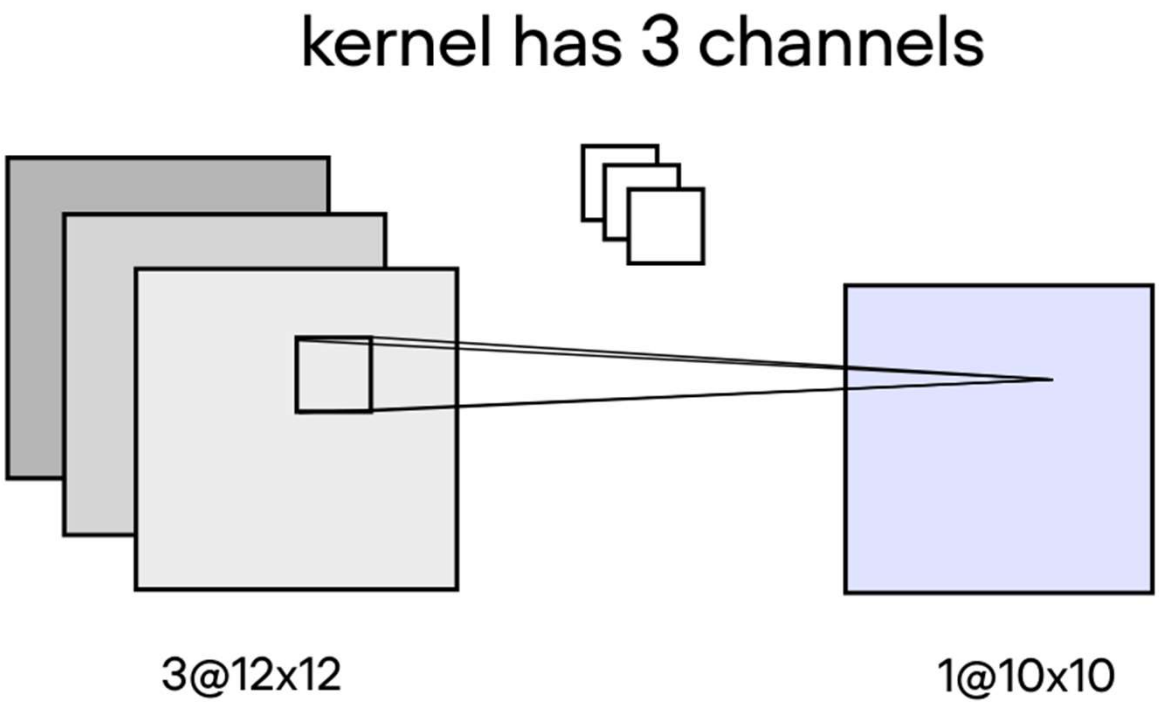
Color image as a stack of matrices

Input channels

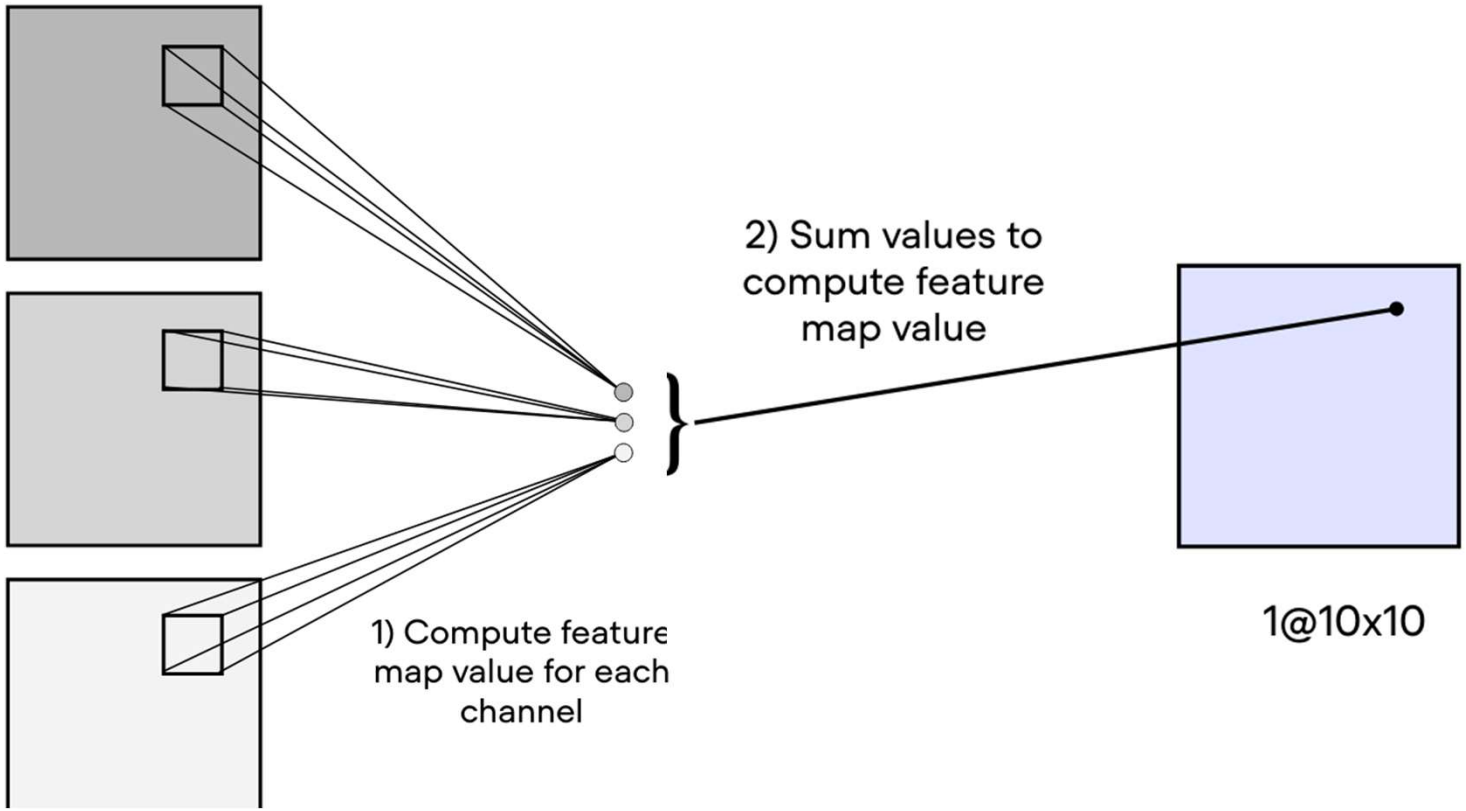
Filters always extend the full depth of the input.
(#Input channels == #Filter Channels)



3 input channel, 1 output channel

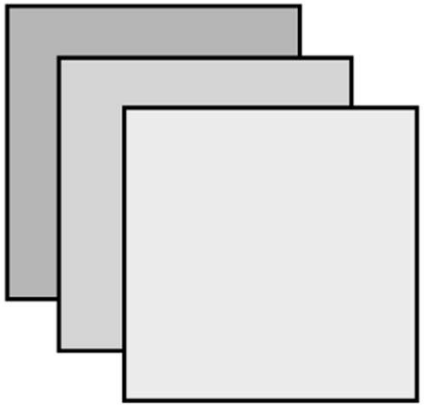


3 input channel, 1 output channel



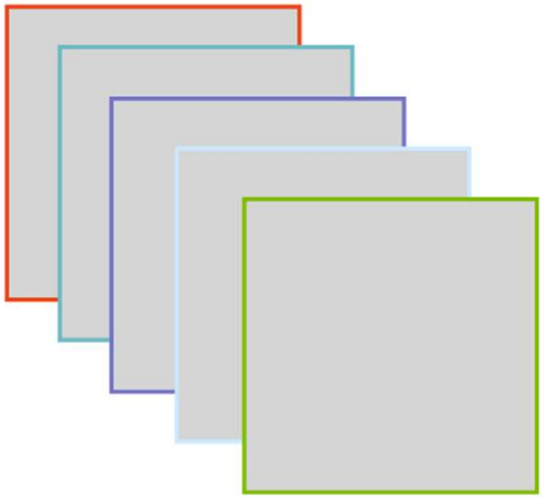
Multiple input and output channels

3 input channels



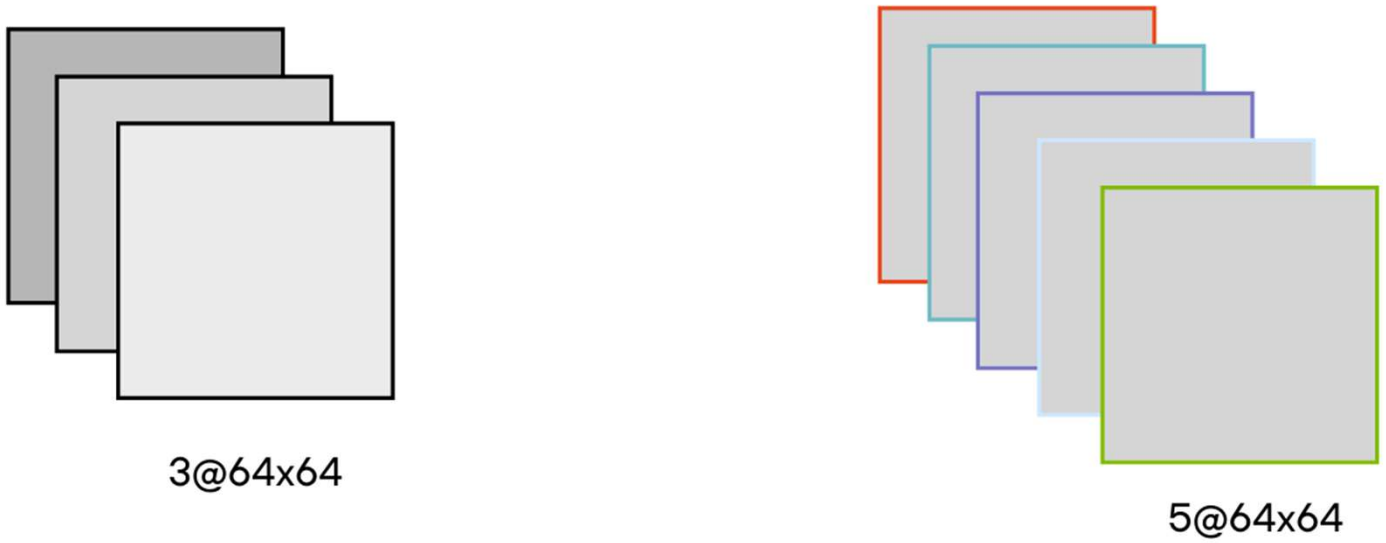
3@64x64

5 output channels

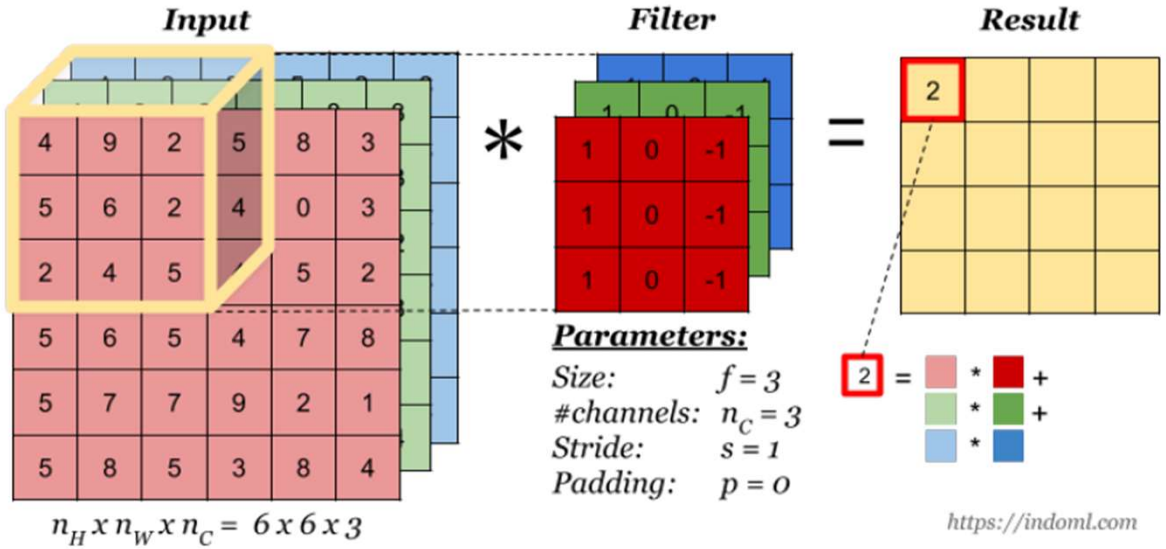


5@64x64

Multiple input and output channels

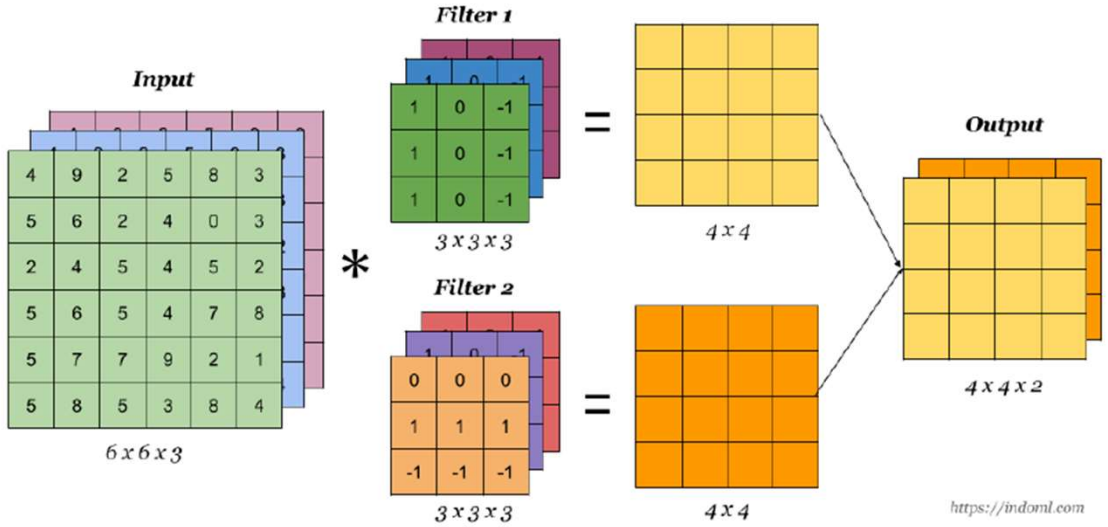


- As said before: ”Filters always extend the full depth of the input. (#Input channels == #Filter Channels)”

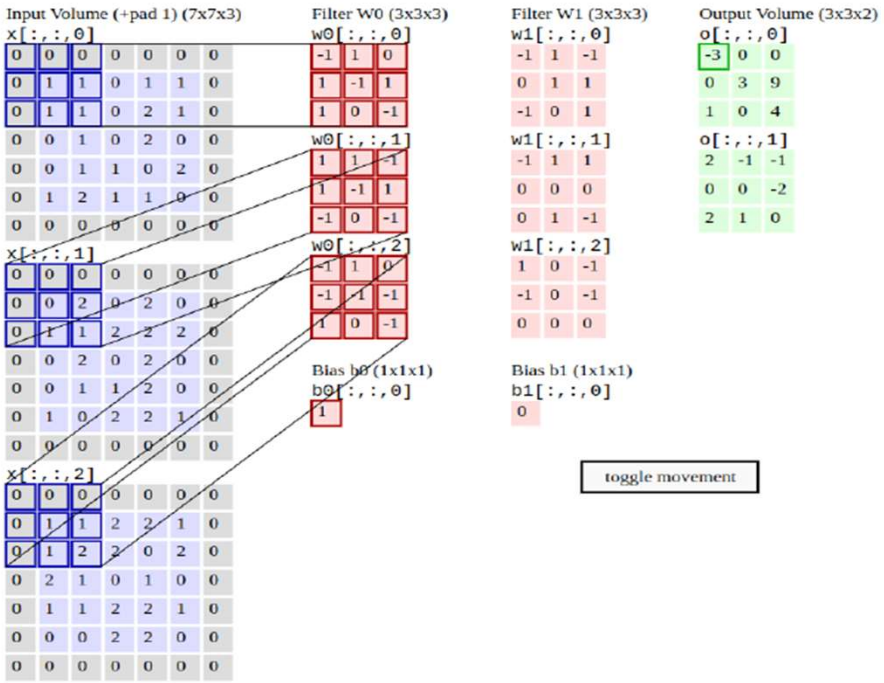


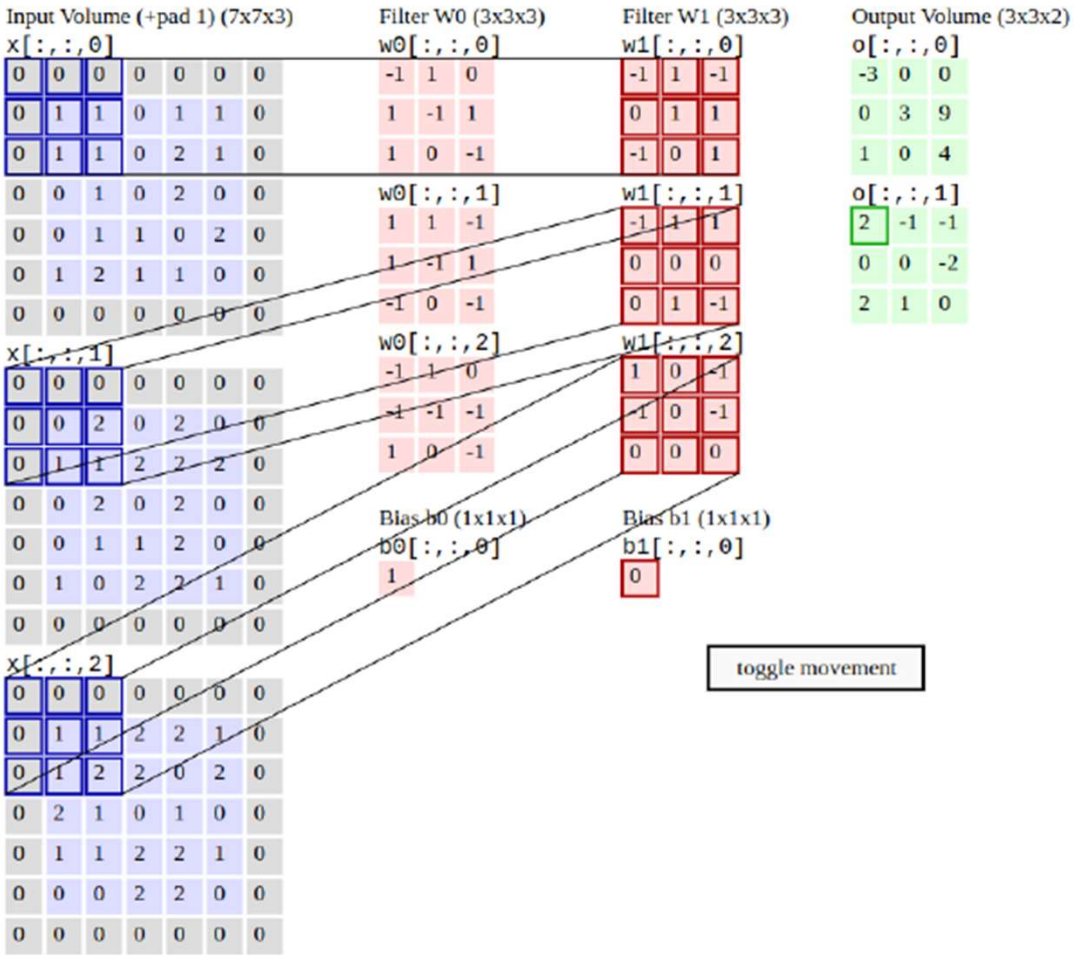
- As said before: ”Filters always extend the full depth of the input volume. (#Input channels == #Filter Channels)”

- Each filter results in one output channel. We can apply multiple different filters to obtain multiple output channels. Each channel can learn something distinct.

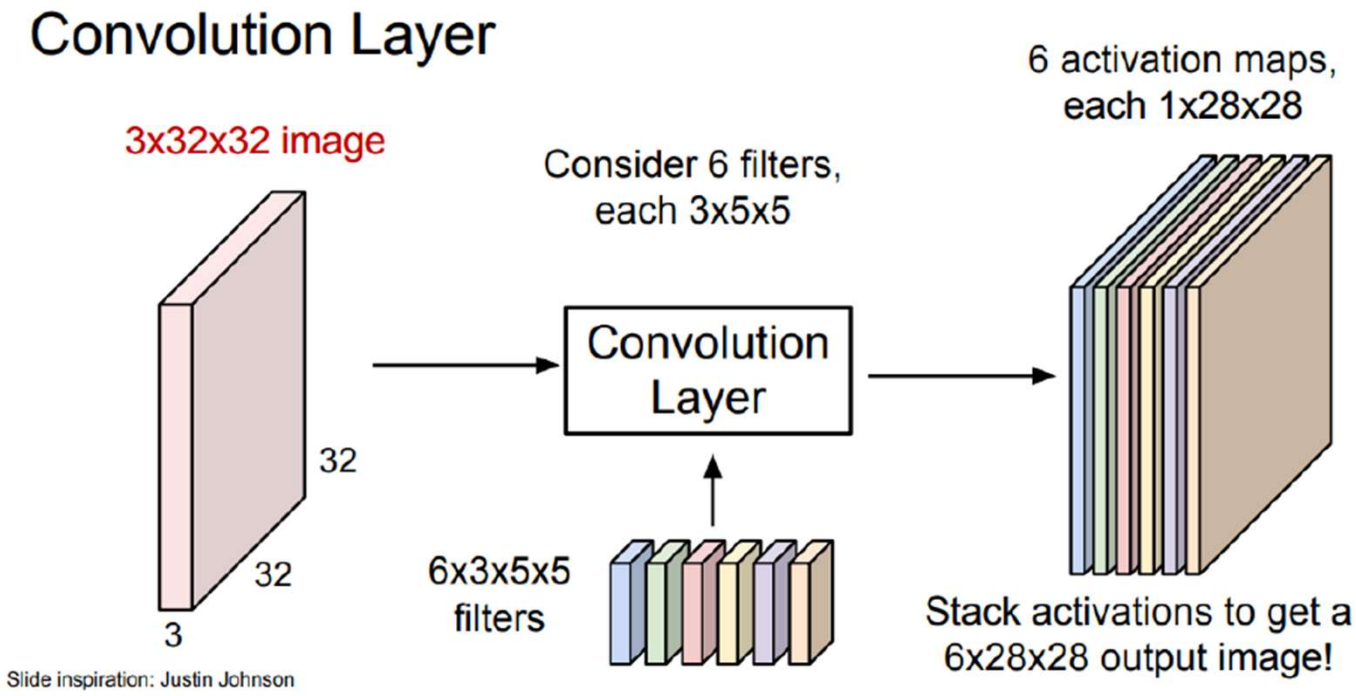


Let's have a closer look to how the calculations with more than one filter work:

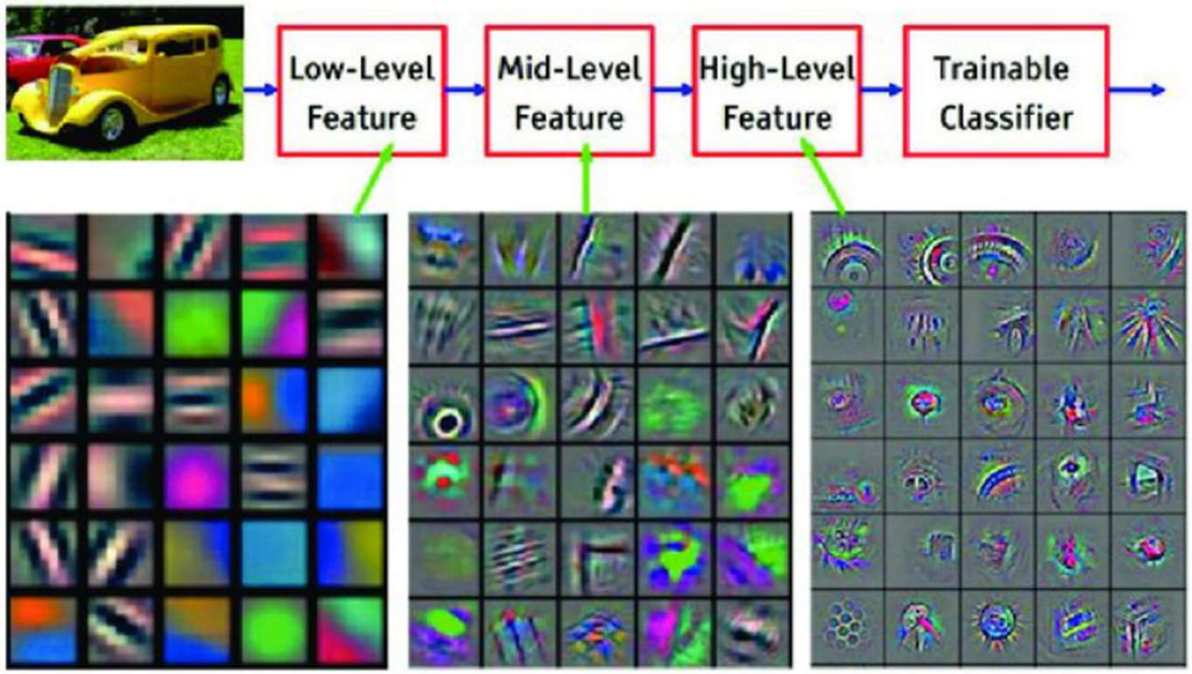


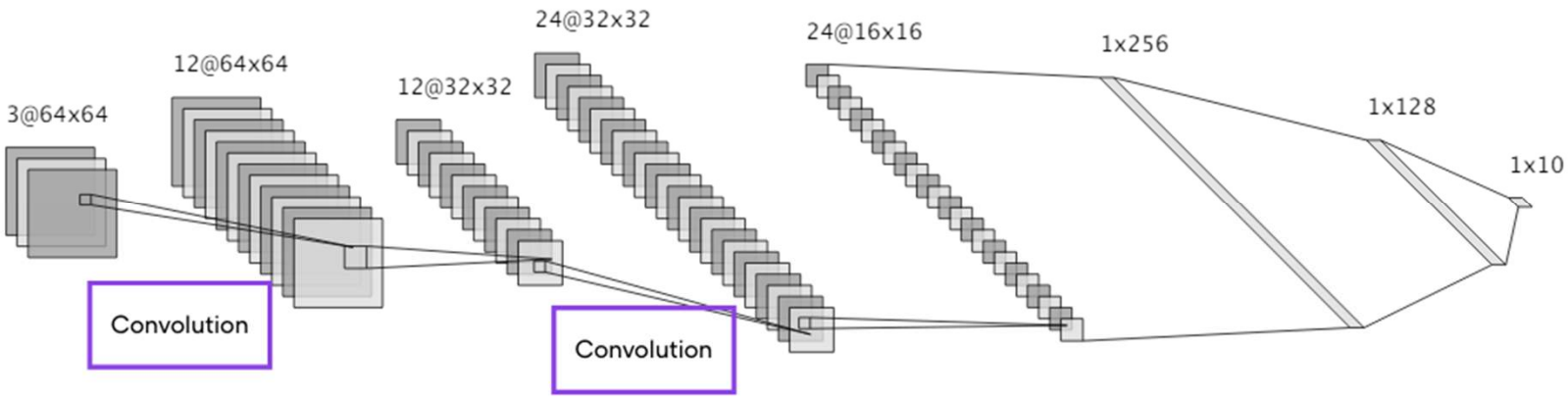

Input Volume (+pad 1) (7x7x3)
x[:,:,0]
0 0 0 0 0 0 0
0 1 1 0 1 1 0
0 1 1 0 2 1 0
0 0 1 0 2 0 0
0 0 1 1 0 2 0
0 1 2 1 1 0 0
0 0 0 0 0 0 0
x[:,:,1]
0 0 0 0 0 0 0
0 0 2 0 2 0 0
0 1 1 2 2 2 0
0 0 2 0 2 0 0
0 0 1 1 2 0 0
0 1 0 2 2 1 0
0 0 0 0 0 0 0
x[:,:,2]
0 0 0 0 0 0 0
0 1 1 2 2 1 0
0 1 2 2 0 2 0
0 2 1 0 1 0 0
0 1 1 2 2 1 0
0 0 0 2 2 0 0
0 0 0 0 0 0 0
Filter W0 (3x3x3)
w0[:,:,0]
-1 1 0
1 -1 1
1 0 -1
w0[:,:,1]
1 1 -1
1 -1 1
-1 0 -1
w0[:,:,2]
-1 1 0
-1 -1 -1
1 0 -1
Bias b0 (1x1x1)
b0[:,:,0]
1
Filter W1 (3x3x3)
w1[:,:,0]
-1 1 -1
0 1 1
-1 0 1
w1[:,:,1]
-1 1 1
0 0 0
0 1 -1
w1[:,:,2]
1 0 -1
-1 0 -1
0 0 0
Bias b1 (1x1x1)
b1[:,:,0]
0
Output Volume (3x3x2)
o[:,:,0]
-3 0 0
0 3 9
1 0 4
o[:,:,1]
2 -1 -1
0 0 -2
2 1 0
toggle movement

- We apply several filters and stack the output together to get a multilayer output, with each layer representing something it learned.



- We apply several filters and stack the output together to get a multilayer output, with each layer representing something it learned.
- Some kernels learn to recognize vertical lines, some circles, and some, specific objects:



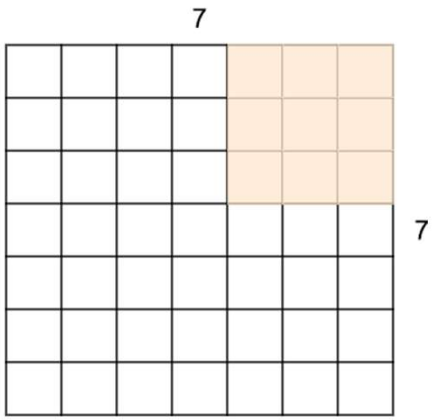

3@64x64
12@64x64
12@32x32
24@32x32
24@16x16
1x256
1x128
1x10
Convolution
Convolution

What is a Stride

The amount of movement between applications of the filter to the input image is referred to as the stride, and it is almost always symmetrical in height and width dimensions.

Closer look

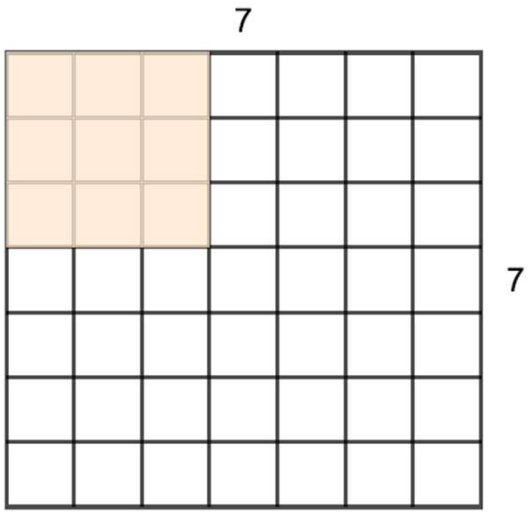
- 7x7 input with 3x3 filter
- This was a Stride 1 filter
- => Outputs 5x5



Strides

Now let's use Stride 2

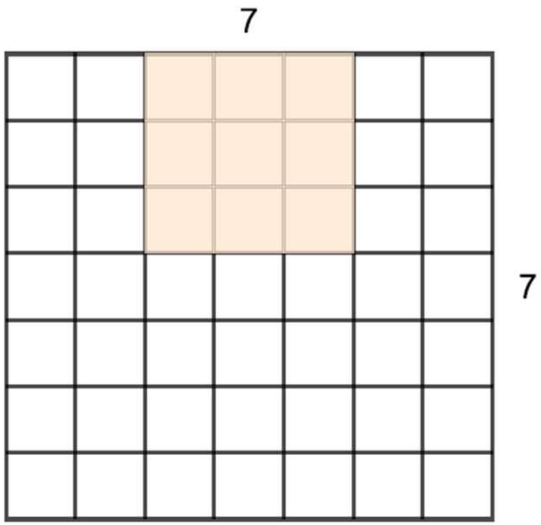
- 7x7 input with 3x3 filter



Strides

Now let's use Stride 2

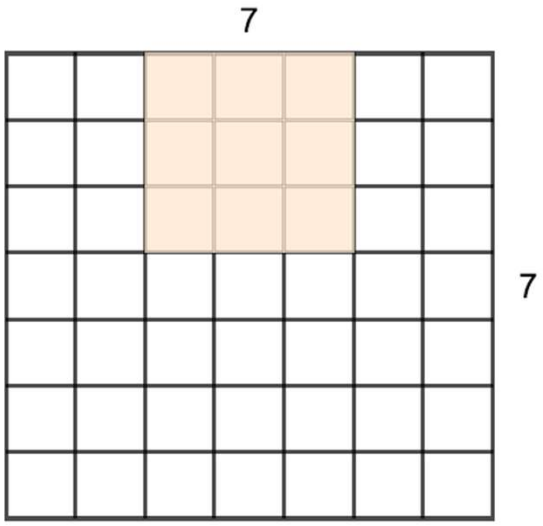
- 7x7 input with 3x3 filter



Strides

Now let's use Stride 2

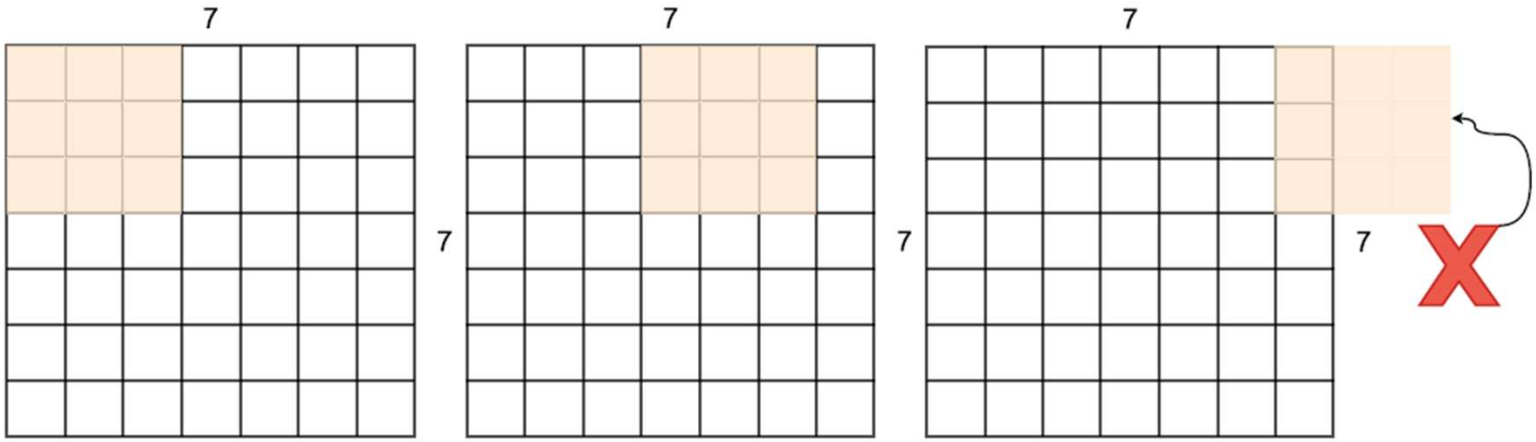
- 7x7 input with 3x3 filter



Strides

Stride 3?

- 7x7 input with 3x3 filter

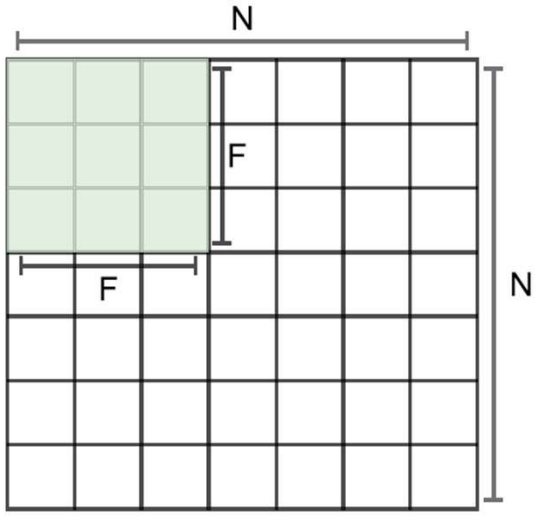


Strides

So 7x7 input with 3x3 filter and stride 3 doens't work!

Let't do the calculations:

$$OutputSize = (N - F)/Stride + 1$$

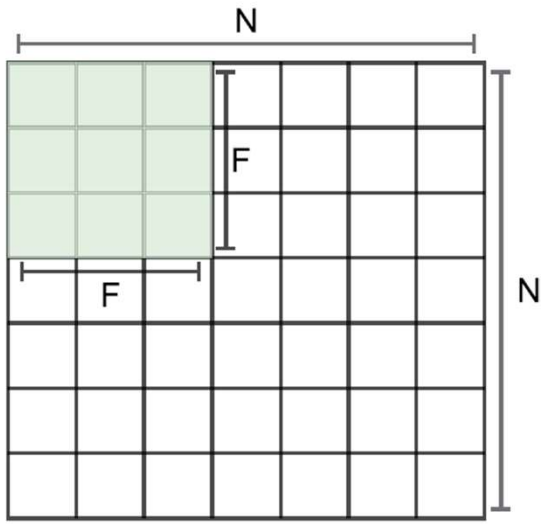


Strides

$$OutputSize = (N - F)/Stride + 1$$

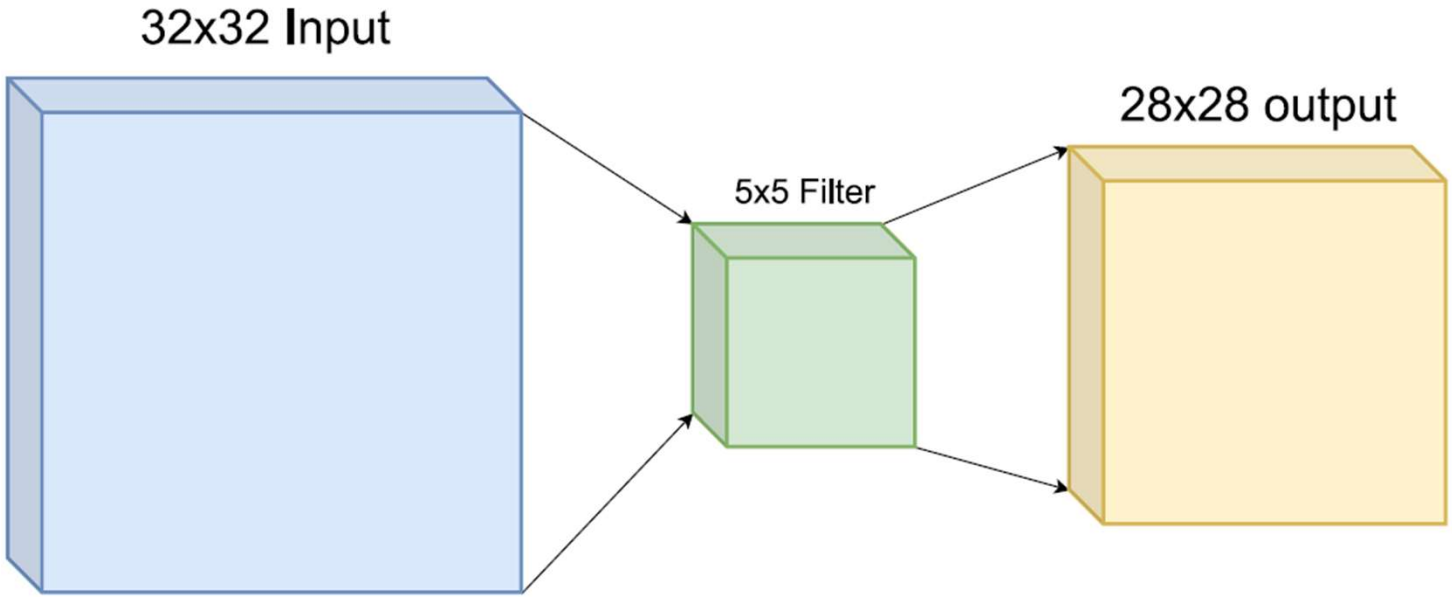
N = 7, F = 3 =>

- Stride 1 ==> $(7 - 3)/1 + 1 = 5$
- Stride 2 ==> $(7 - 3)/2 + 1 = 3$
- Stride 3 ==> $(7 - 3)/3 + 1 = 2.33$:))



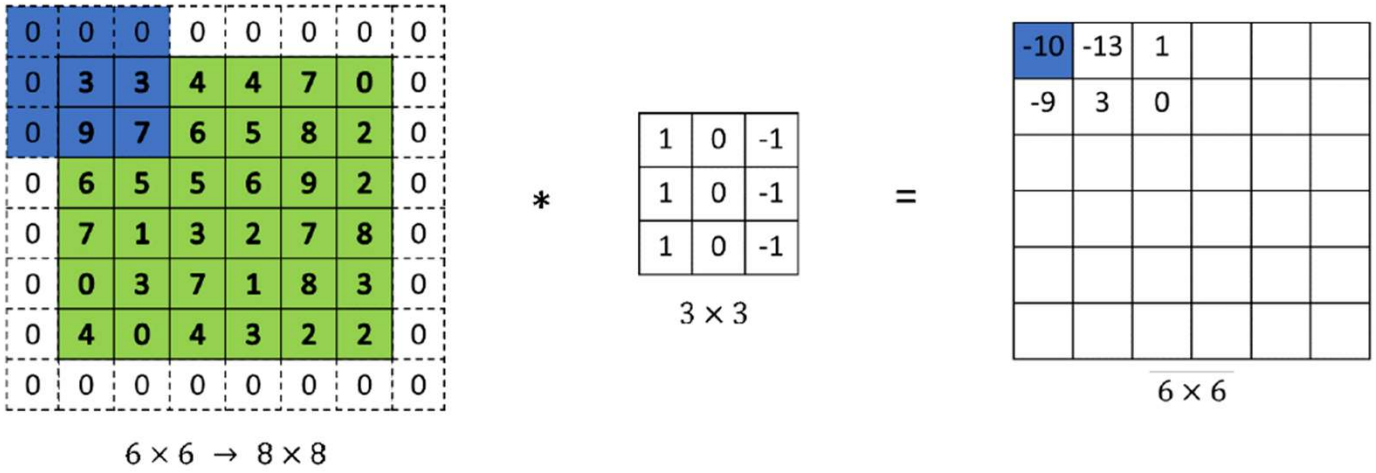
Padding

1. Borders don't get enough attention.
2. Outputs shrink!



Padding

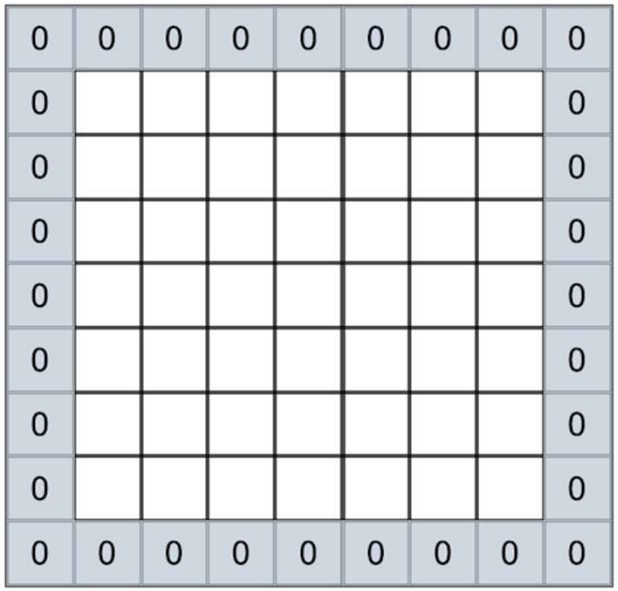
- We can use Padding to preserve the dimensionality
- It ensures that all pixels are used equally frequently



Padding

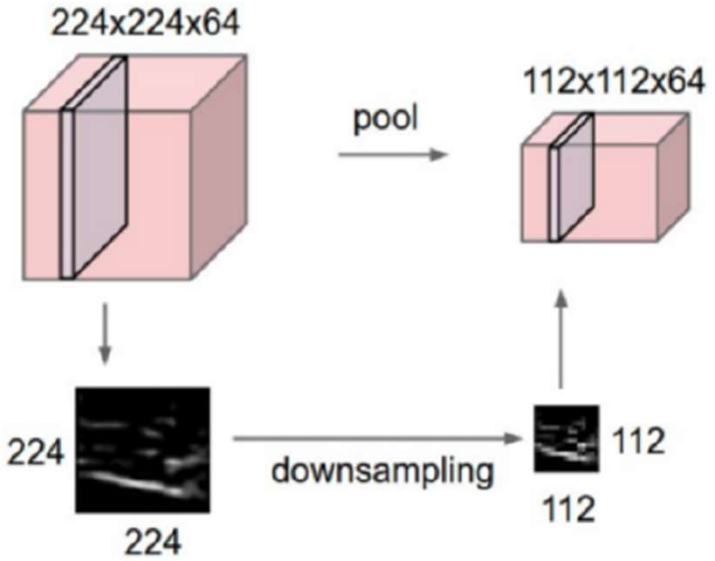
$$OutputSize = (N + 2P - F)/Stride + 1$$

It is common to use $P = (F - 1)/2$ with stride 1 to preserve the input size.

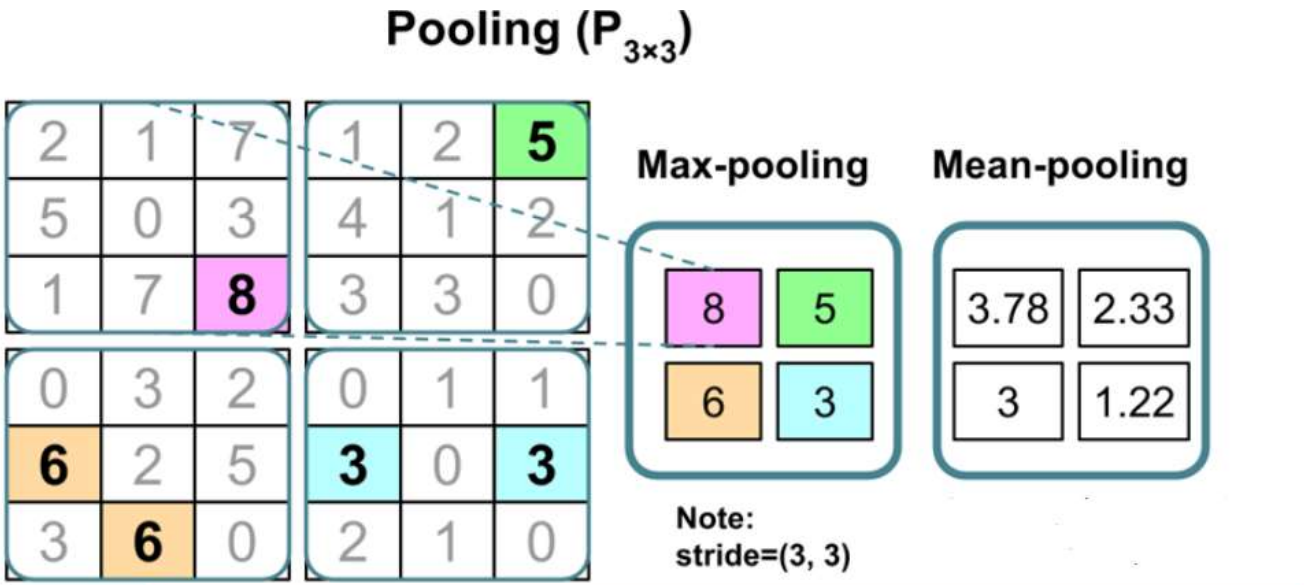


Pooling

Pooling is performed in neural networks to reduce variance and computation complexity



Pooling Layers Can Help With Local Invariance



Note that typical pooling layers do not have any learnable parameters

Downside: Information is lost.
May not matter for classification, but applications where relative position is important (like face recognition)

In practice for CNNs: some image preprocessing still recommended

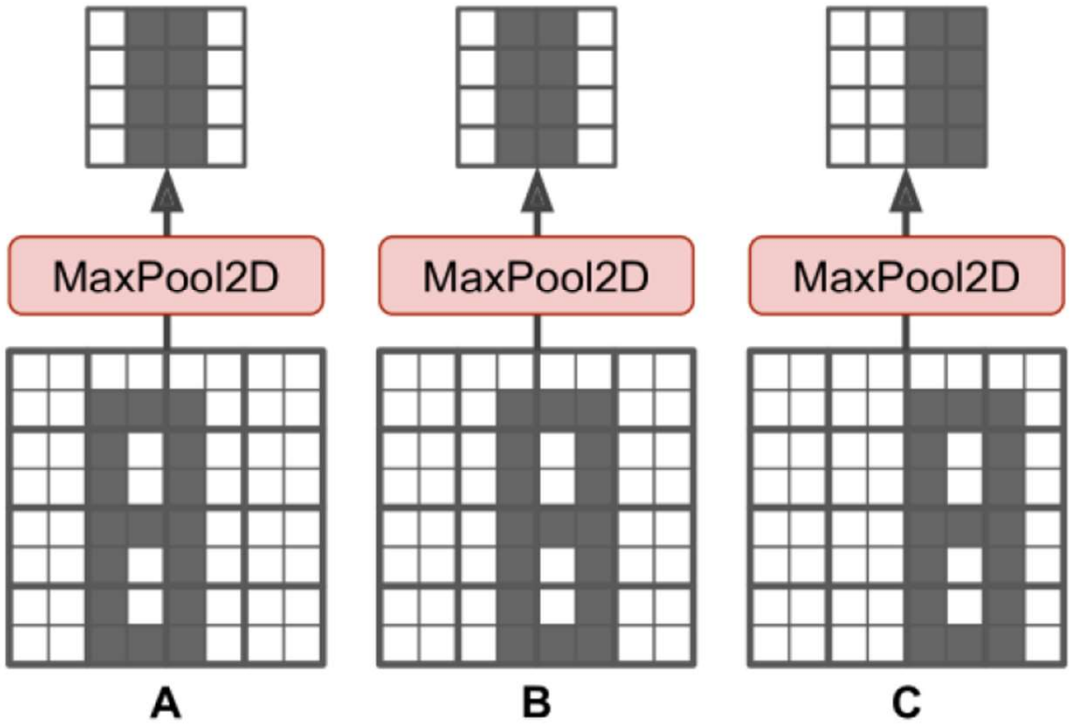
Pooling benefits

A Pooling layer's goal is to sub-sample the input in order to reduce:

- The computational load
- The memory usage
- The number of parameters
- Limiting the risk of overfitting

Max Pooling

Most common type of pooling layer
Invariance to small translations



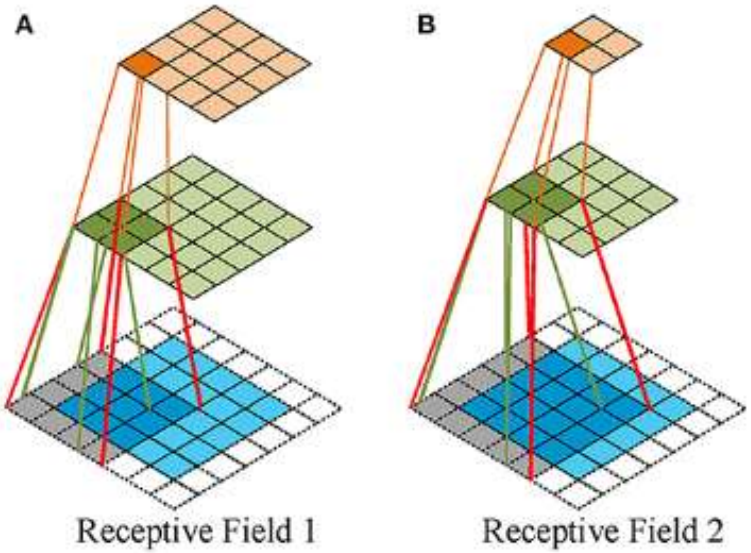
Smaller filter size or larger ?

- Using smaller filter size is better or larger?

Distributing the scan

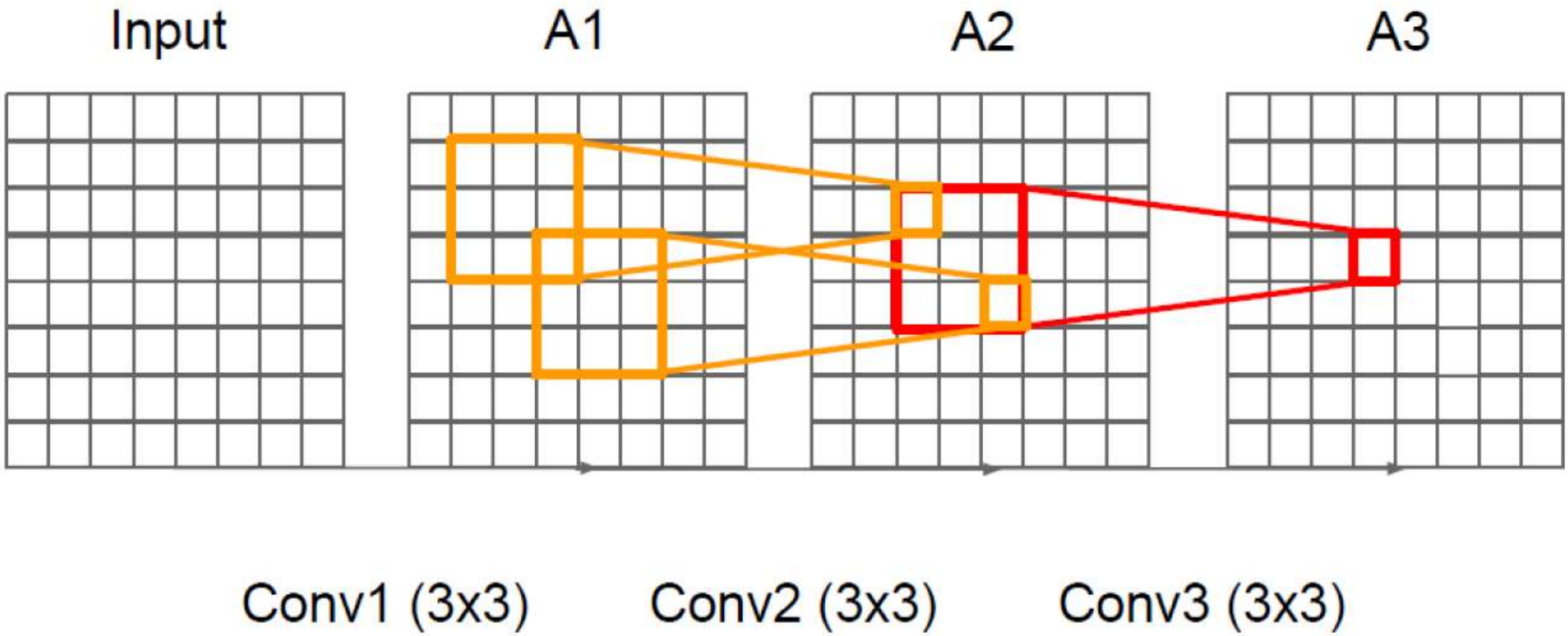
- We can distribute the pattern matching over two layers and still achieve the same block analysis at the second layer
  - The first layer evaluates smaller blocks of pixels
  - The next layer evaluates blocks of outputs from the first layer

Receptive field

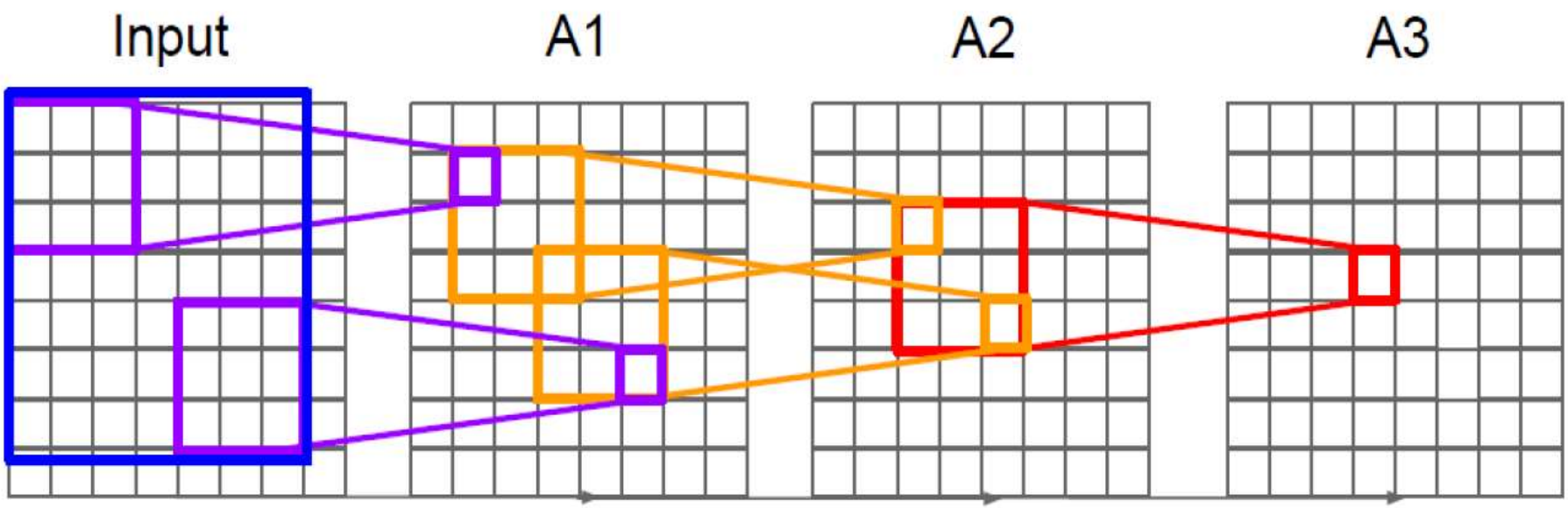


Receptive field a deep CNN. (A) The first convolving: a 3 × 3 kernel over a 5 × 5 input padded with a 1 × 1 border of zeros using unit strides. The second convolving: a 2 × 2 kernel using unit strides. (B) The first convolving: a 4 × 4 kernel over a 5 × 5 input padded with a 1 × 1 border of zeros using unit strides. The second convolving: a 2 × 2 kernel using 2 × 2 strides.

What is the effective receptive field of three 3×3 conv (stride 1) layers?



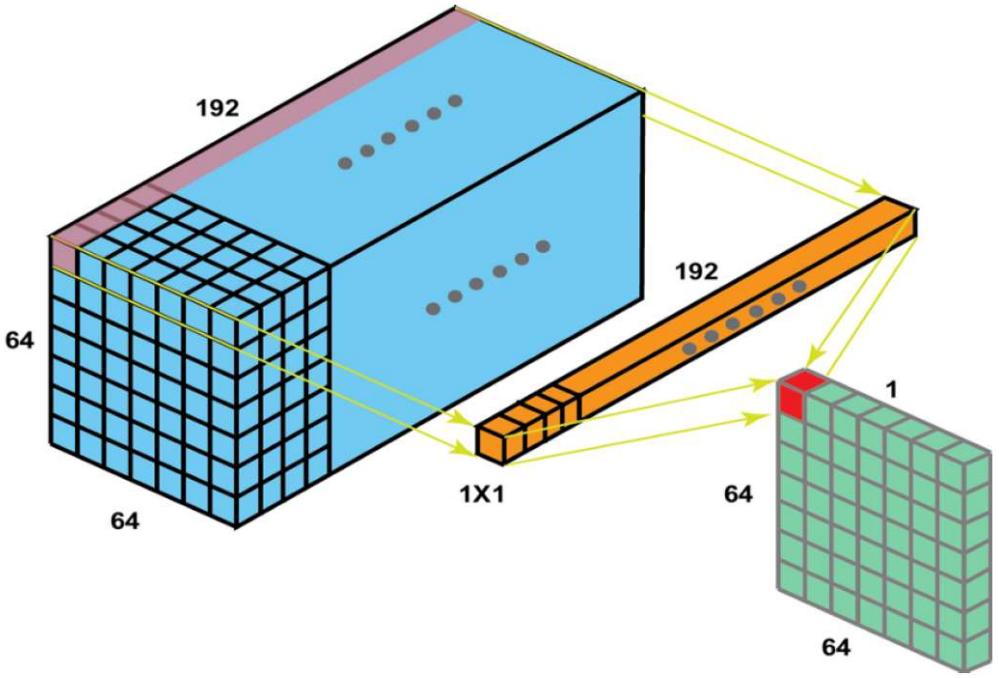
What is the effective receptive field of three 3×3 conv (stride 1) layers?



Power of small filter

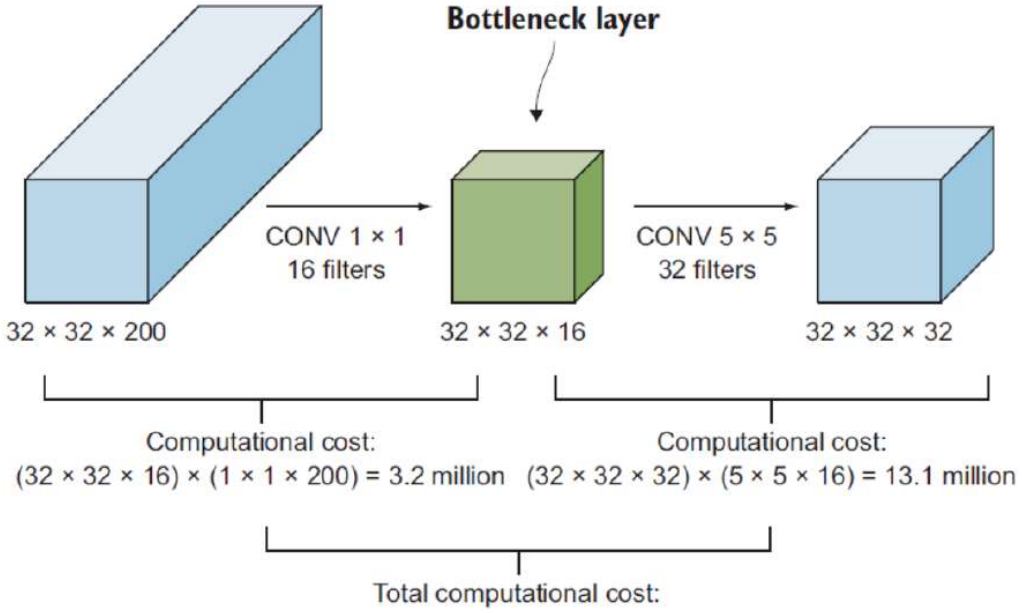
- Suppose input is H*W*C and we use convolutions of C filters
- Stride 1 and Padding to preserve H , W
- One convolution with 7*7 filters
  - Number of weights : (7*7*C) *C(for the number of filter) = 49 C^2
- 3 convolution with 3*3 filters
  - Number of weights: (3*3*C) *C + (3*3)C*C + (3*3*C)*C = 27 C^2

1*1 Convolution



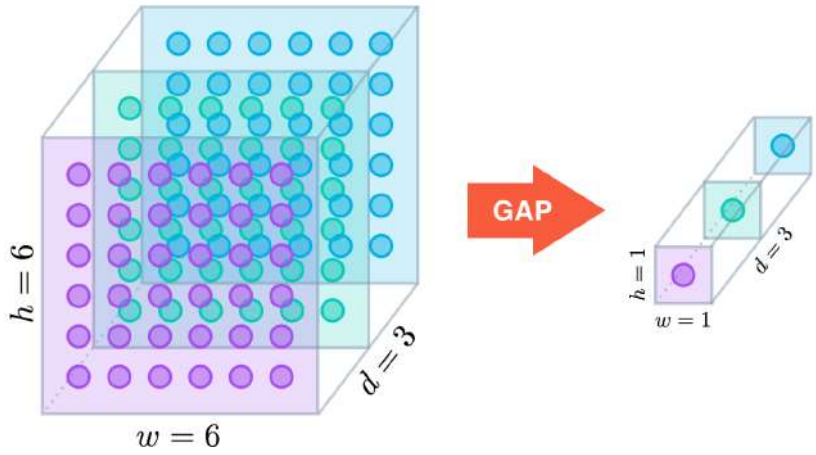
1*1 Convolution use case

- Assume we want to transform a $32 \times 32 \times 200$ tensor to a $32 \times 32 \times 32$ one using 32 5×5 filters. Thus, we need $(32 \times 32 \times 200) \times (5 \times 5 \times 32) \approx 163M$ operations!
- Instead we can use 1×1 convolution:



Global Average Pooling

Similar to max pooling layers, GAP layers are used to reduce the spatial dimensions of a three-dimensional tensor. However, GAP layers perform a more extreme type of dimensionality reduction, where a tensor with dimensions $h \times w \times d$ is reduced in size to have dimensions $1 \times 1 \times d$. GAP layers reduce each $h \times w$ feature map to a single number by simply taking the average of all hw values.



Why Gap

- GAP is used to replace the traditional fully connected layers in CNN.
- There is no parameter to optimize in the GAP thus overfitting is avoided at this layer
- GAP sums out the spatial information, thus it is more robust to spatial translations of the input.

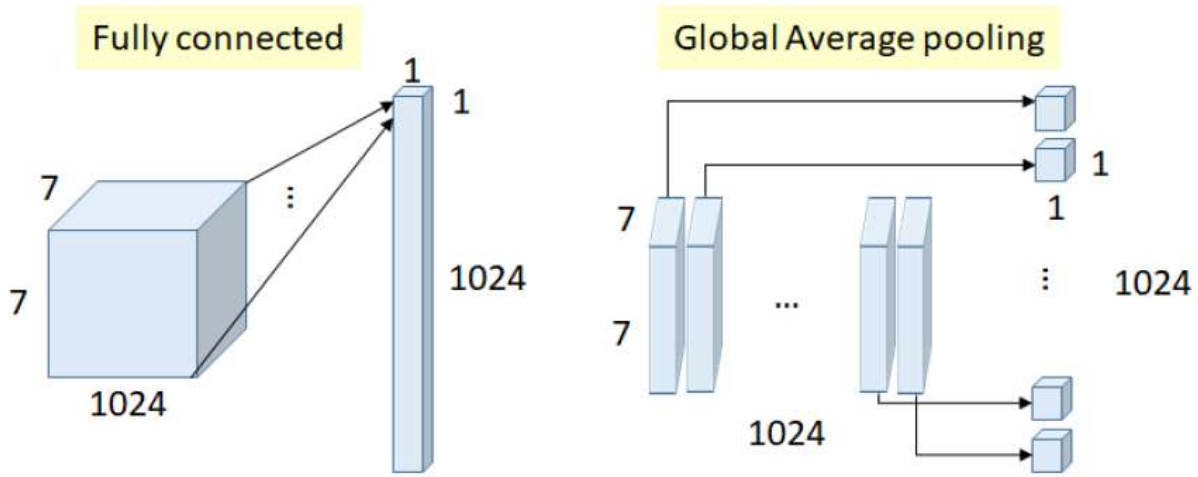
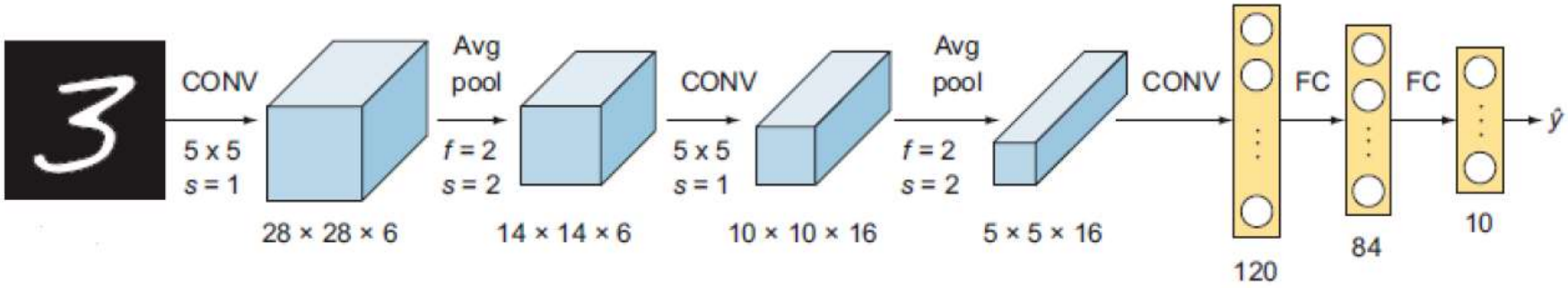


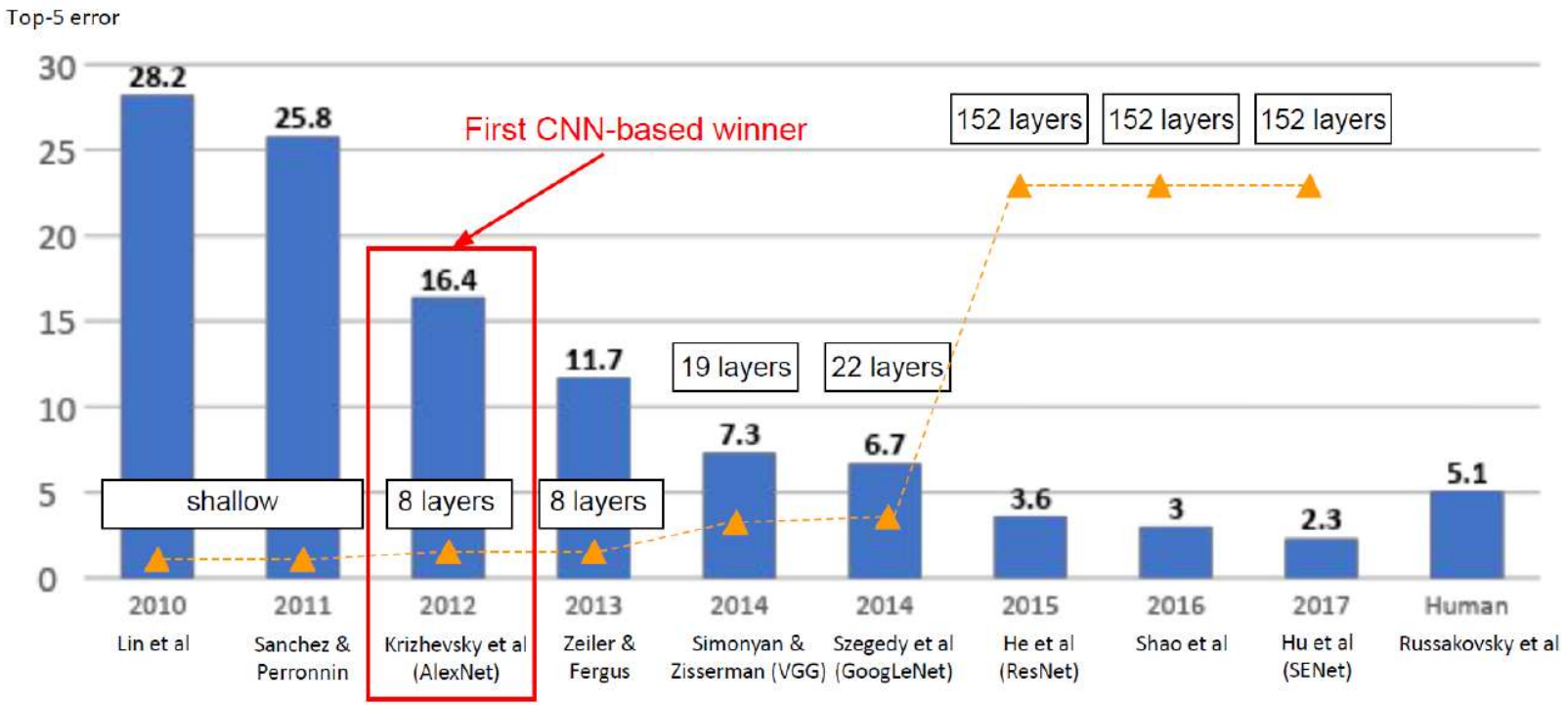
Figure: FC Layer vs GAP Layer

LeNet



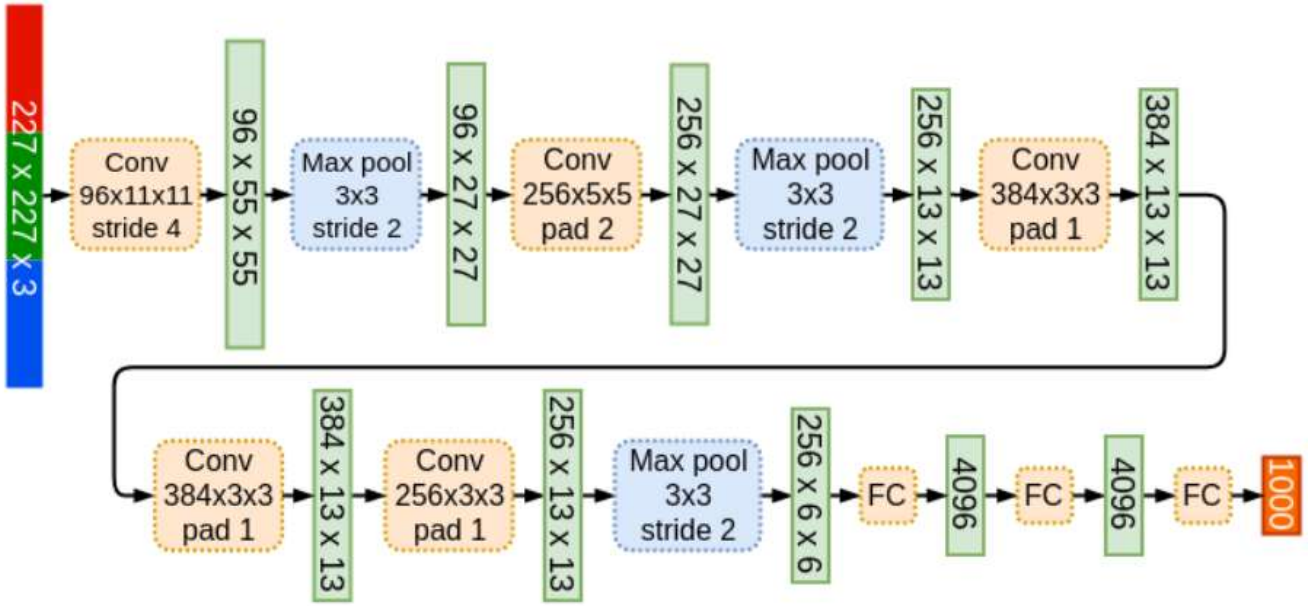
- Conv filters were 5x5 , applied at stride 1
- Subsampling (Pooling) layers were 2x2 applied at stride 2

AlexNet



ImageNet Large Scale Visual Recognition Challenge (ILSVRC) winners

AlexNet

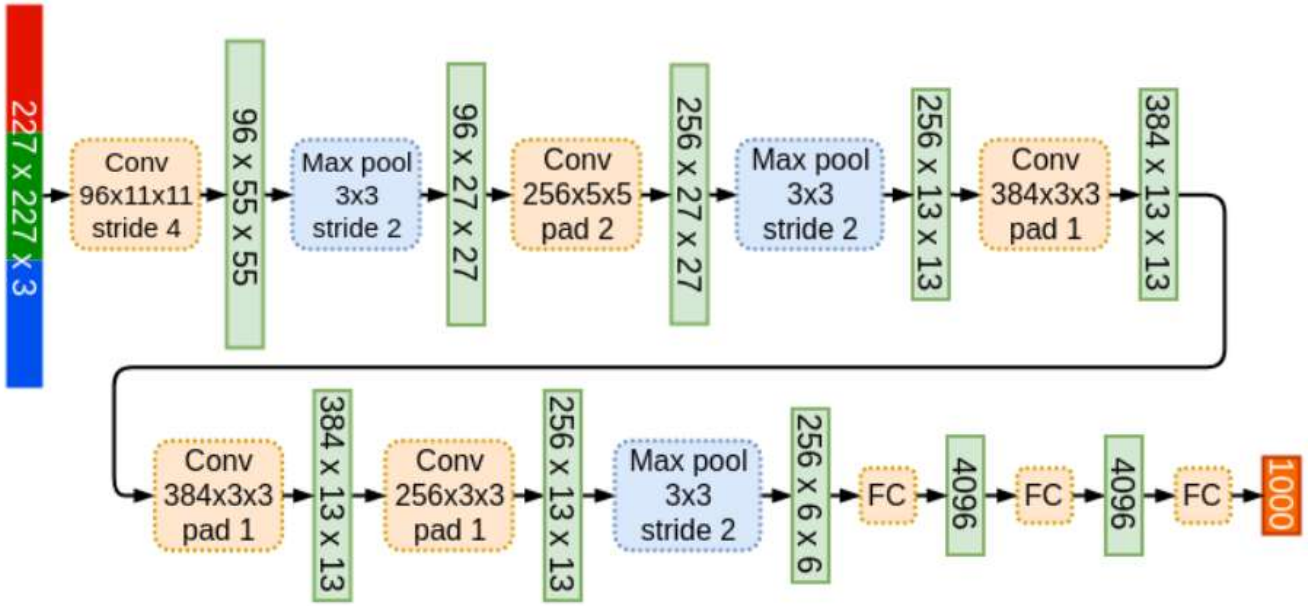


(CONV1): 96 11x11 filters applied at stride 4

Why is the output volume size 55?

What is the total number of parameters in the first layer?

AlexNet



(POOL1): 3×3 filters applied at stride 2

Why is the output volume size 27?

What is the number of parameters?

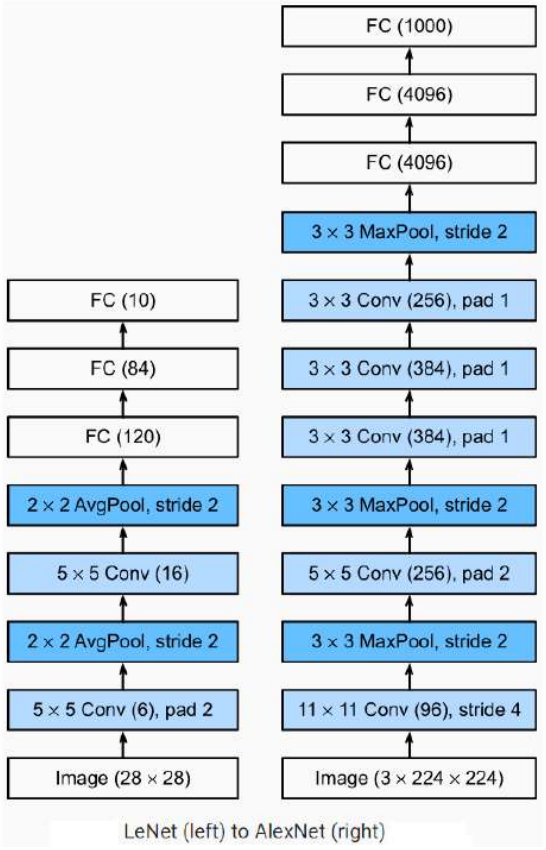
How is AlexNet Different from LeNet?

62M parameters vs 61K parameters

ReLU vs Sigmoid (why?)

Use of Regularization Techniques (Dropout, Weight Decay) (why?)

Use of Normalization (why?)



LeNet (left) to AlexNet (right)

VGG Net

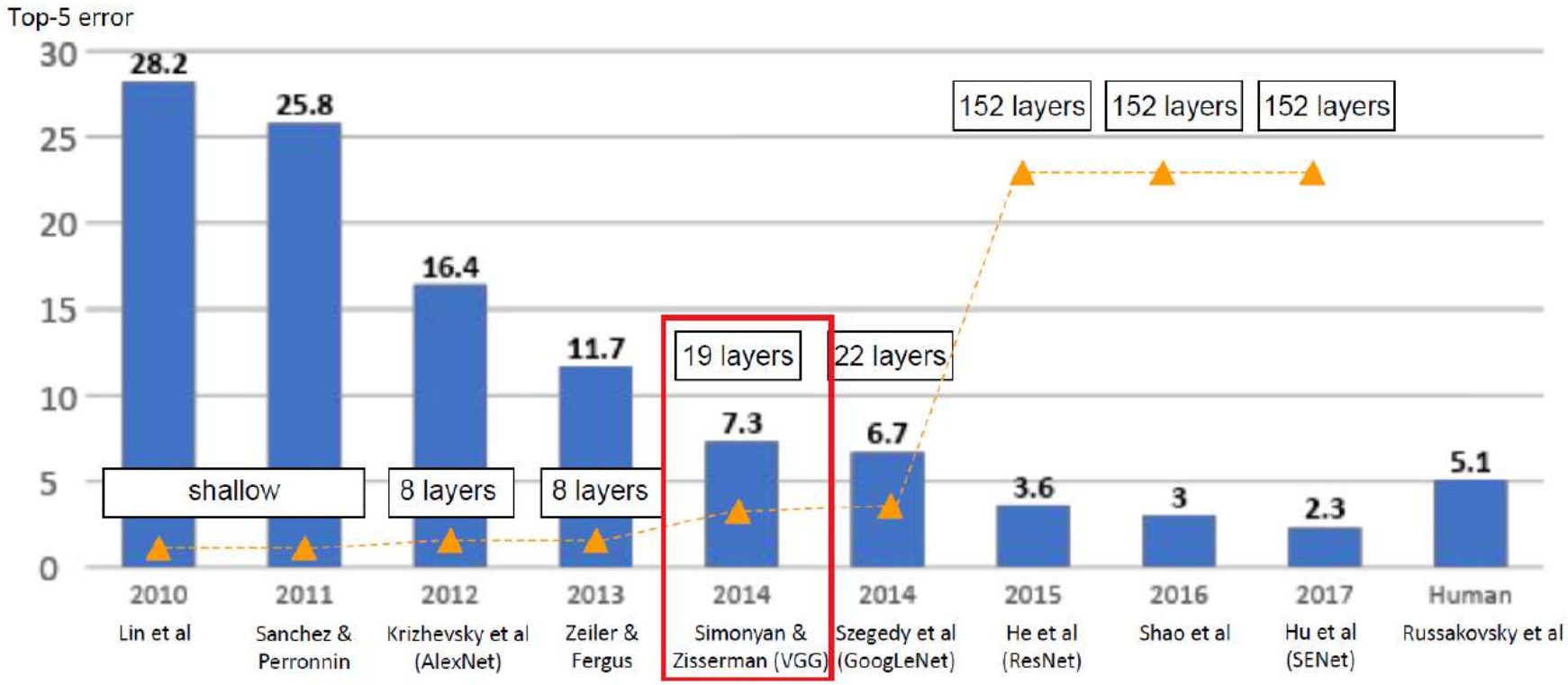


Figure: ImageNet Large Scale Visual Recognition Challenge (ILSVRC) winners

VGGNet

Do you see any difference?

- Smaller filters
- Deeper networks
- Only 3×3 CONV with stride 1, pad 1 and 2×2 MAX POOL with stride 2

VGGNet

Why use smaller filters? (3×3 conv)

- Stack of three 3×3 conv (stride 1) layers has same effective receptive field as one 7×7 conv layer
- Deeper network means more non-linearities which leads to more capacity

GoogLeNet

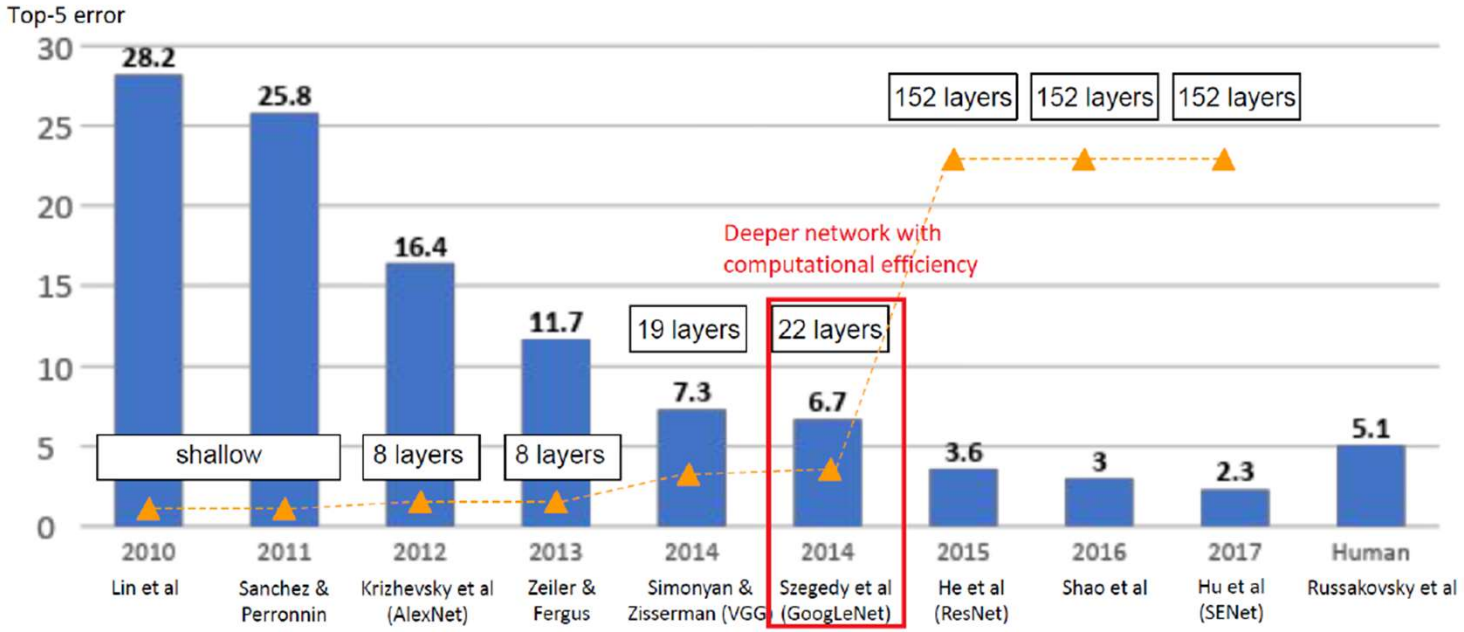
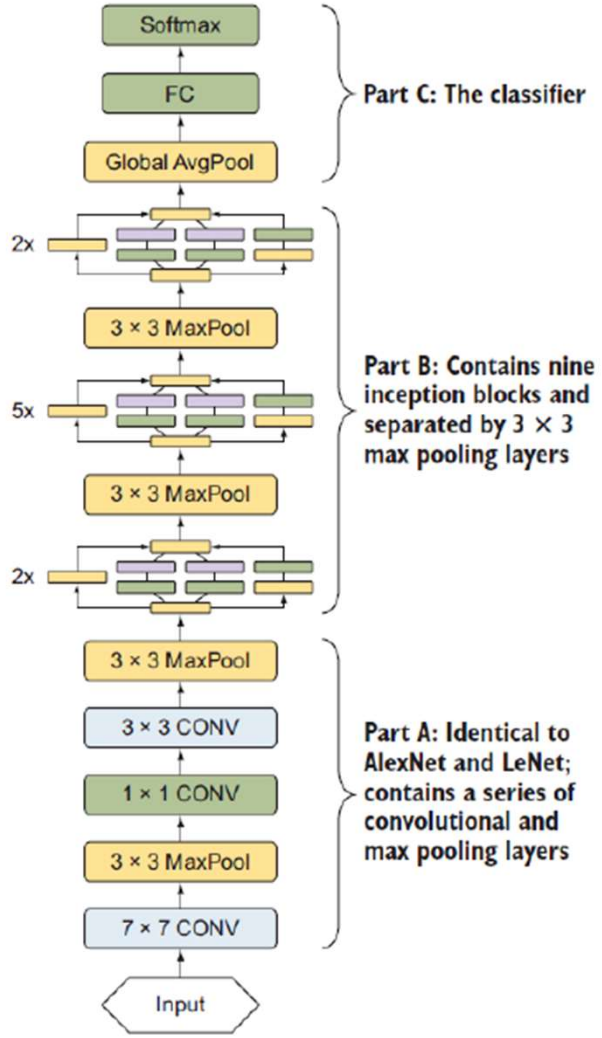


Figure: ImageNet Large Scale Visual Recognition Challenge (ILSVRC) winners

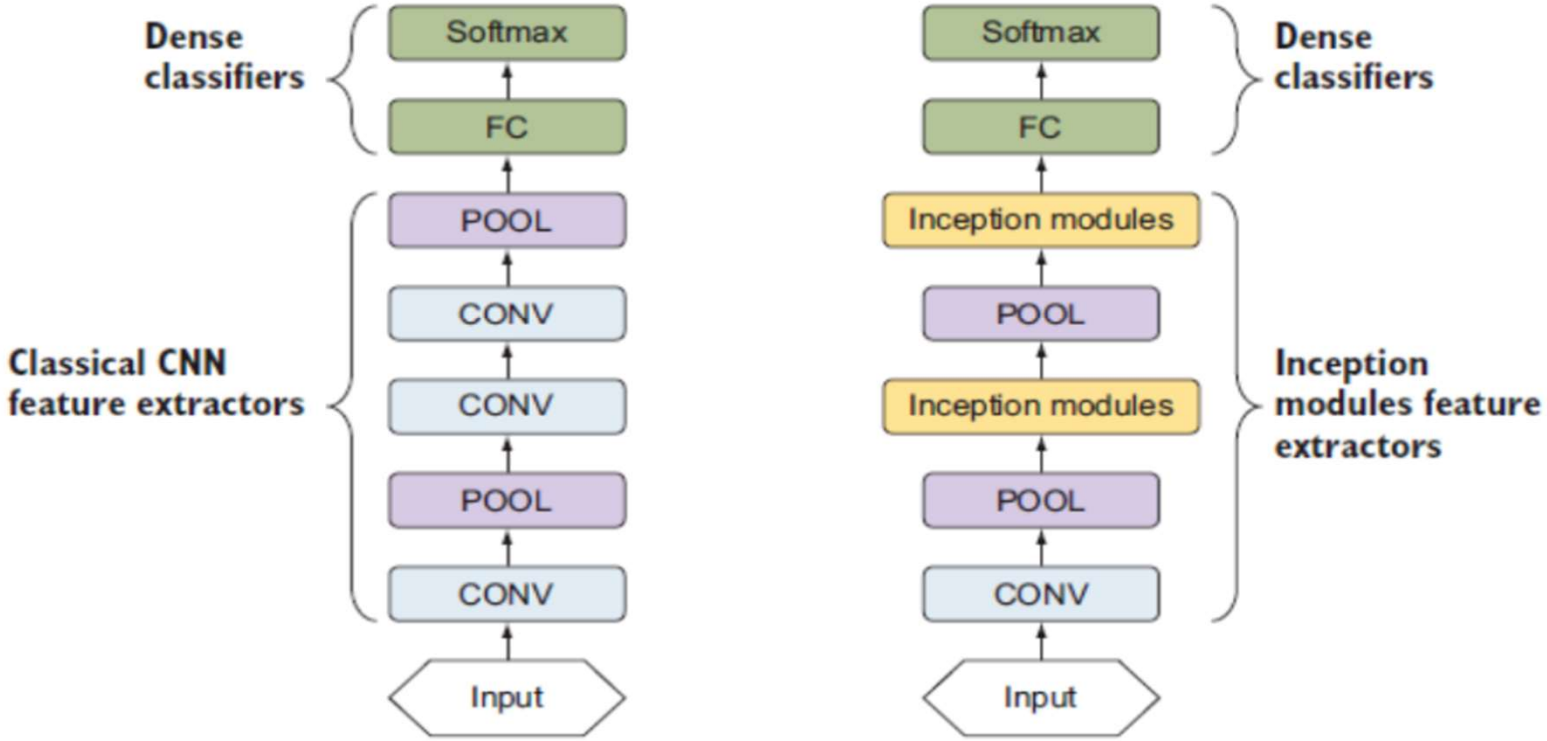
GoogleNet

- Only 5 million parameters! (12x less than AlexNet and 27x less than VGG-16)
- Efficient "Inception" module
- No longer multiple expensive FC layers



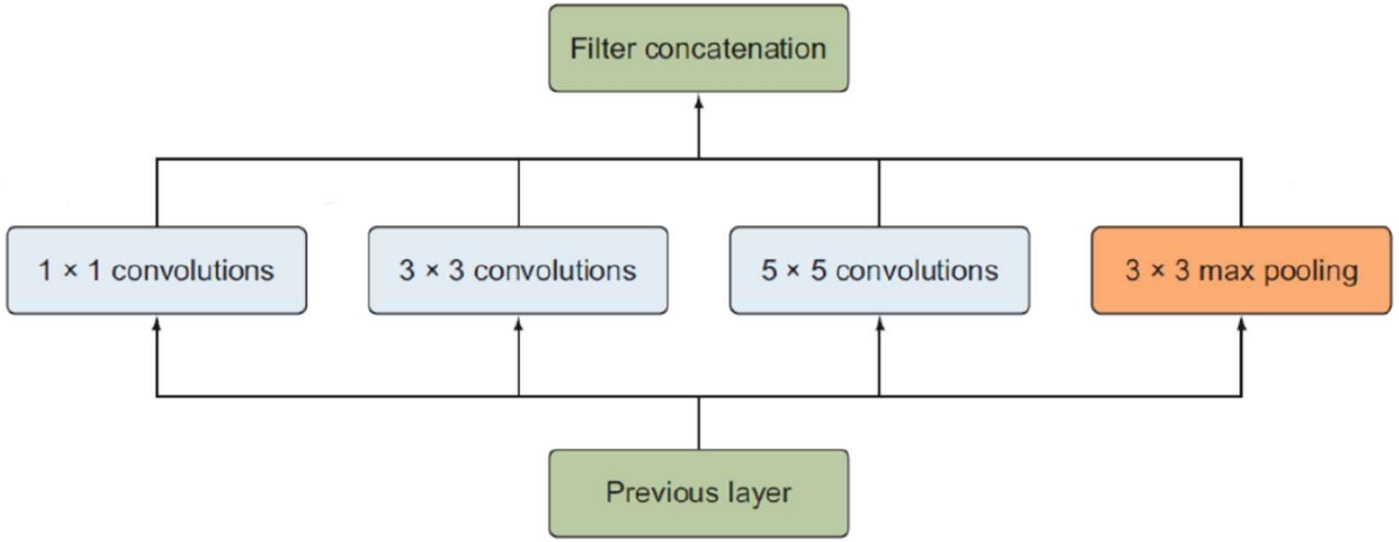
GoogLeNet

Inception modules instead of classical CNNs for feature extraction

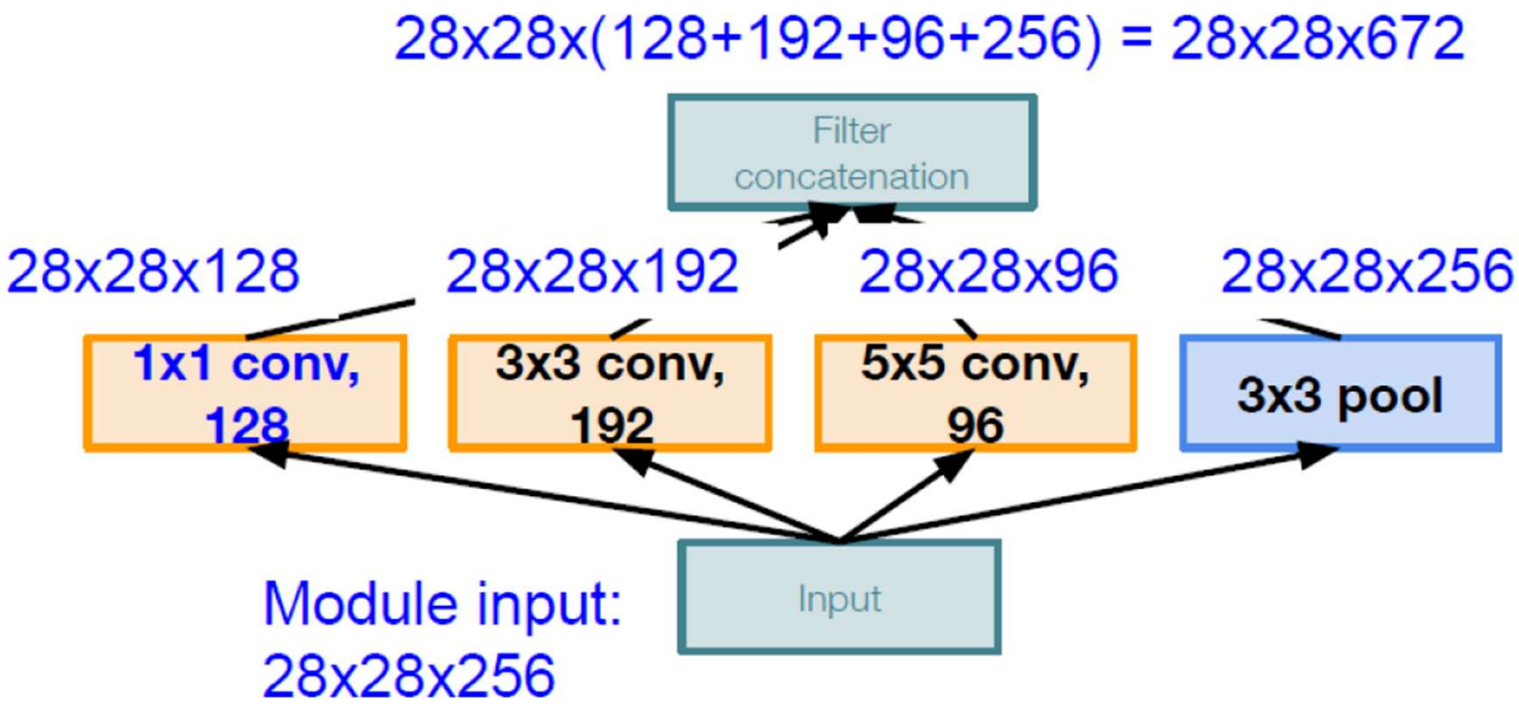


Naïve Inception Module

- Apply parallel filter operations on the input from previous layer
- Multiple receptive field sizes for convolution ($1 \times 1, 3 \times 3, 5 \times 5$)
- Pooling operation (3×3)
- Concatenate all filter outputs together channel-wise

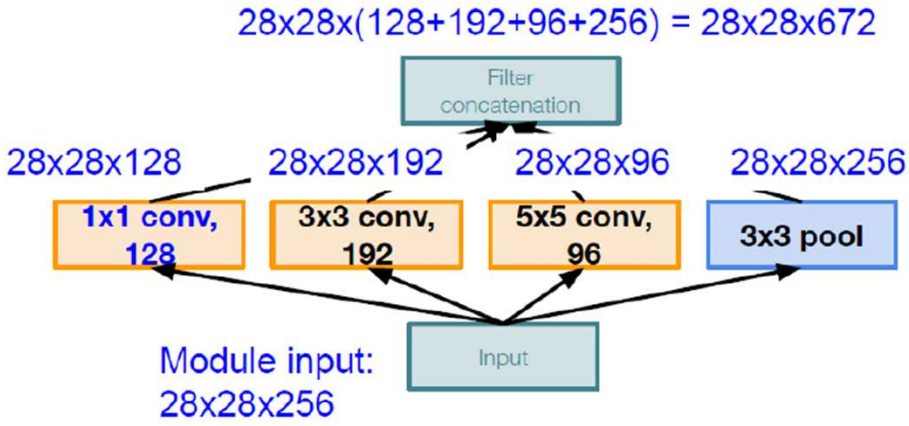


Naïve inception module



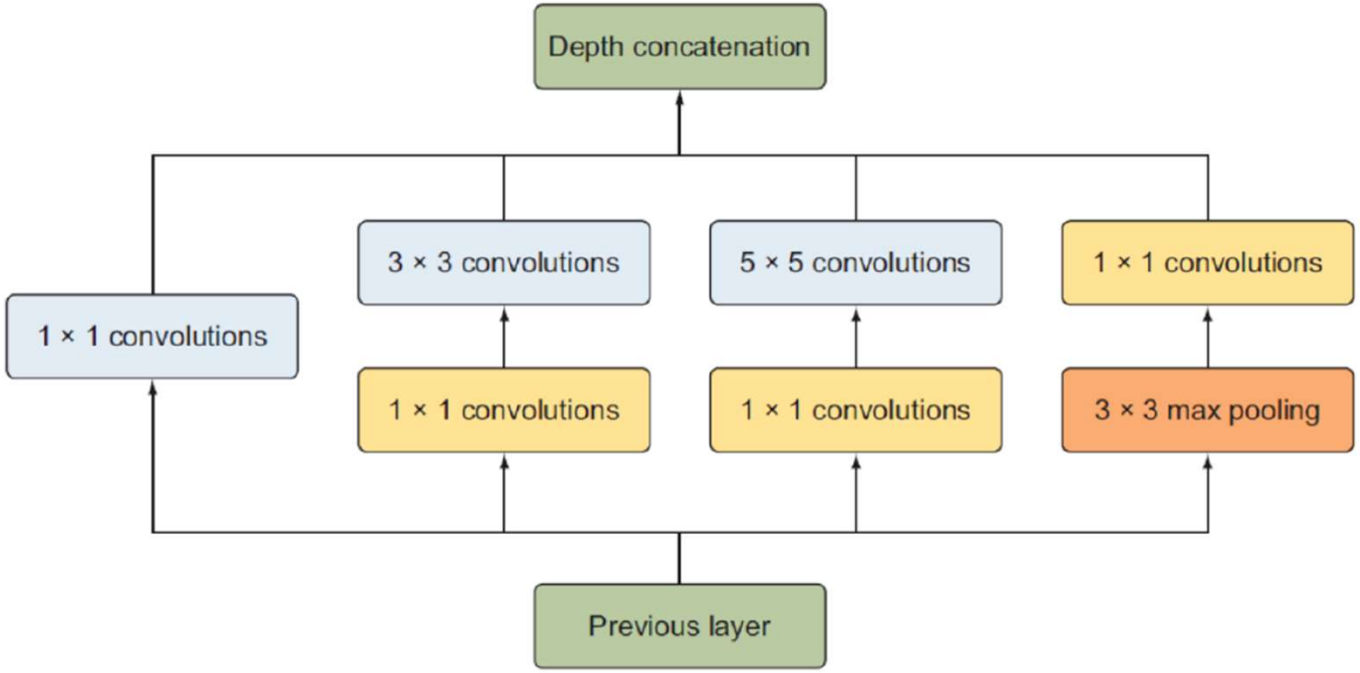
Naïve inception module

- What is the problem with this?
- Computational complexity!
  - Conv Ops:
  - $[1 \times 1 \text{ conv}, 128]\ 28 \times 28 \times 128 \times 1 \times 1 \times 256$
  - $[3 \times 3 \text{ conv}, 192]\ 28 \times 28 \times 192 \times 3 \times 3 \times 256$
  - $[5 \times 5 \text{ conv}, 96]\ \ 28 \times 28 \times 96 \times 5 \times 5 \times 256$
  - Total: 854M ops



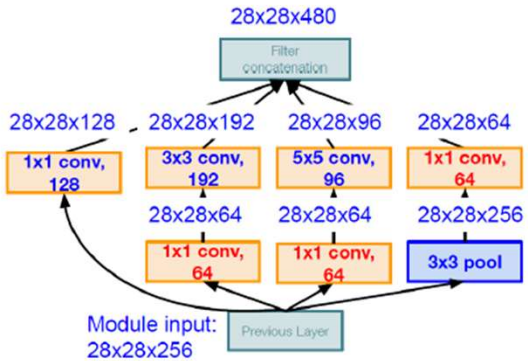
Inception module

- Any Solution?
- "bottleneck" layers that use 1×1 convolutions to reduce feature channel size



Dimension reduction in inception module

- Using same parallel layers as naive example, and adding "1×1 conv, 64 filter" bottlenecks
  - $[1 \times 1 \text{ conv}, 64]\ 28 \times 28 \times 64 \times 1 \times 1 \times 256$
  - $[1 \times 1 \text{ conv}, 64]\ 28 \times 28 \times 64 \times 1 \times 1 \times 256$
  - $[1 \times 1 \text{ conv}, 128]\ 28 \times 28 \times 128 \times 1 \times 1 \times 256$
  - $[3 \times 3 \text{ conv}, 192]\ 28 \times 28 \times 192 \times 3 \times 3 \times 64$
  - $[5 \times 5 \text{ conv}, 96]\ 28 \times 28 \times 96 \times 5 \times 5 \times 64$
  - $[1 \times 1 \text{ conv}, 64]\ 28 \times 28 \times 64 \times 1 \times 1 \times 256$
  - Total: 358M ops
- Compared to 854M ops for naive version Bottleneck can also reduce depth after pooling layer



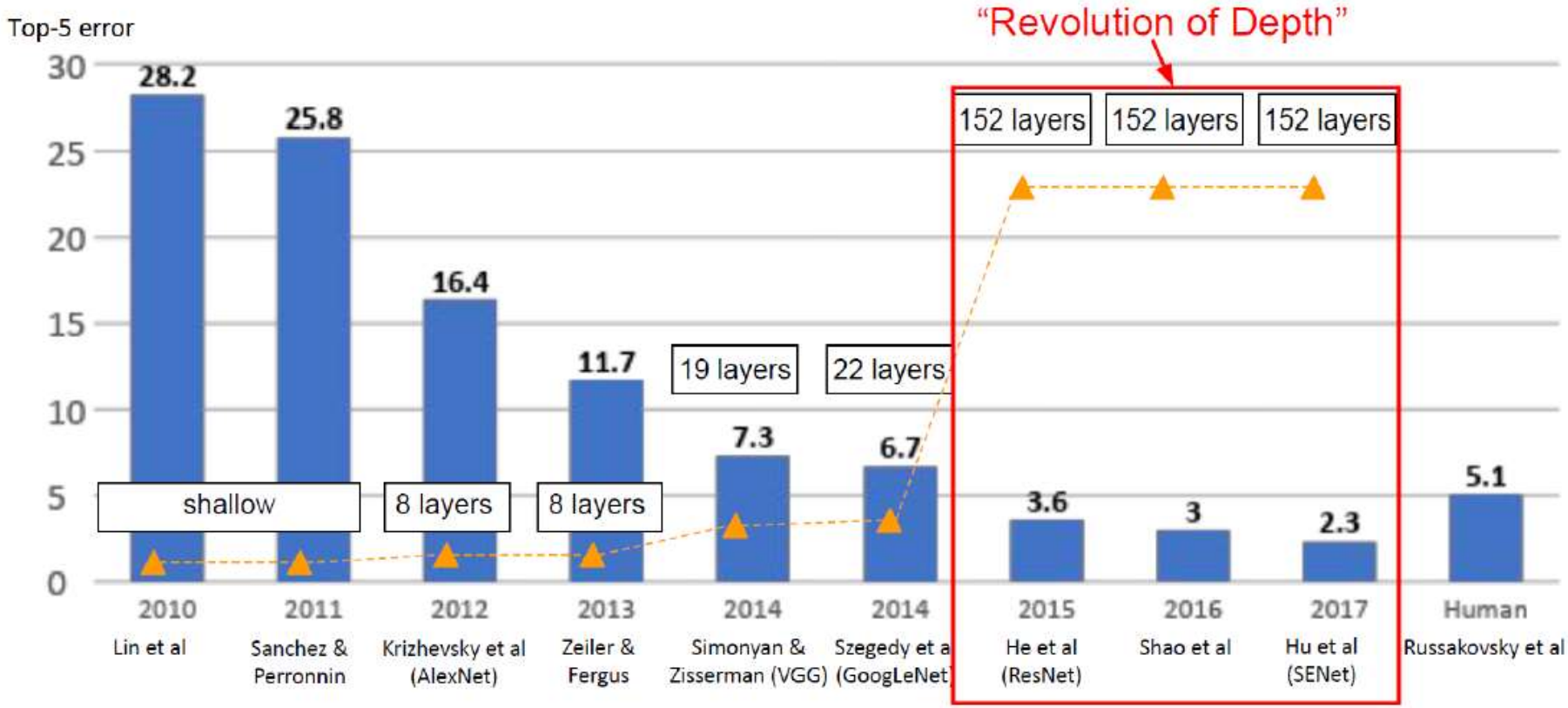
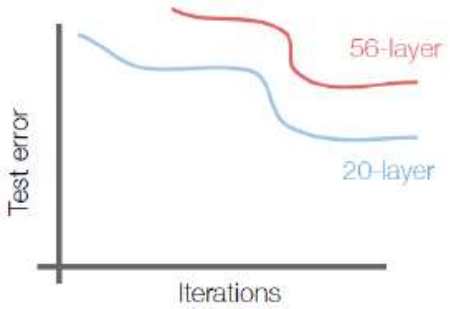
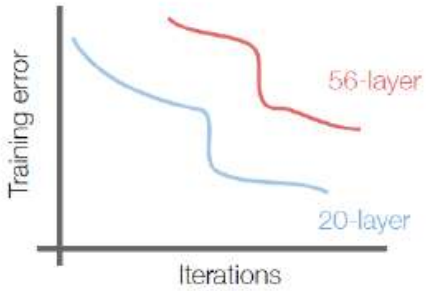


Figure: ImageNet Large Scale Visual Recognition Challenge (ILSVRC) winners

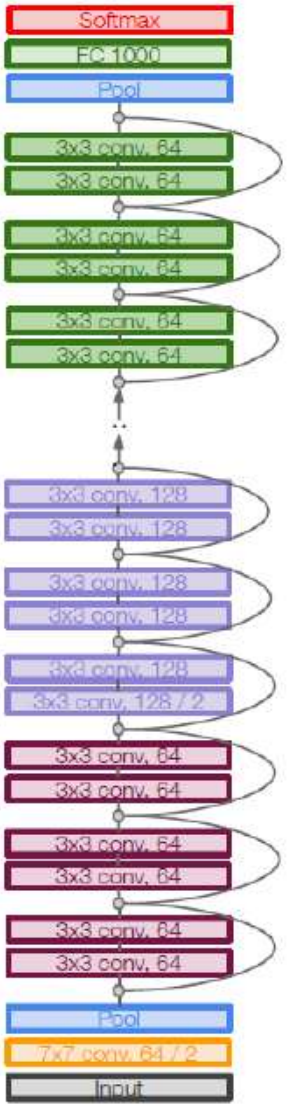
ResNet

- A very deep network using residual connections
- What happens when we continue stacking deeper layers on a "plain" convolutional



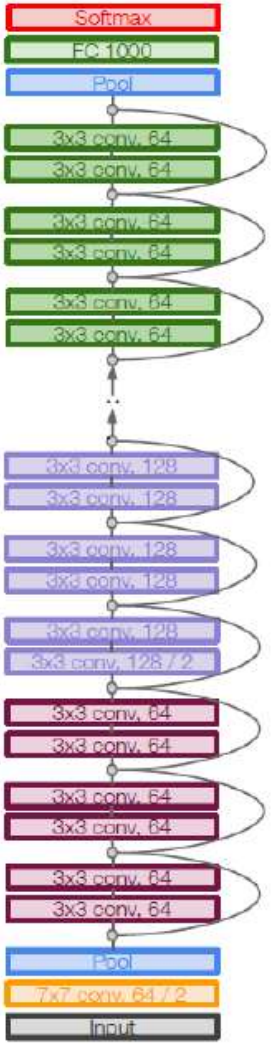


- The deeper model performs worse, but it's not caused by overfitting!



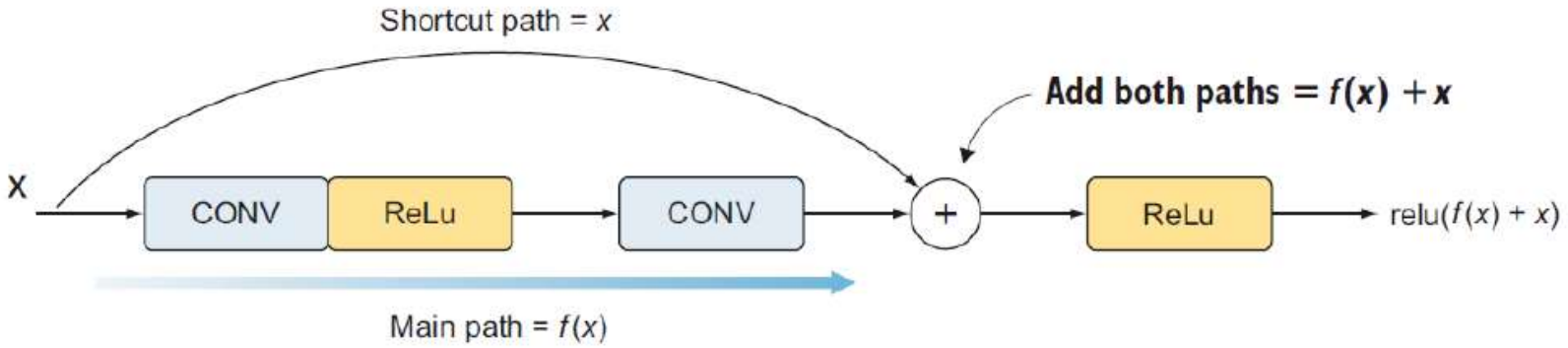
Res Net

- Fact: Deep models have more representation power (more parameters) than shallower models.
- Hypothesis: the problem is an optimization problem, deeper models are harder to optimize



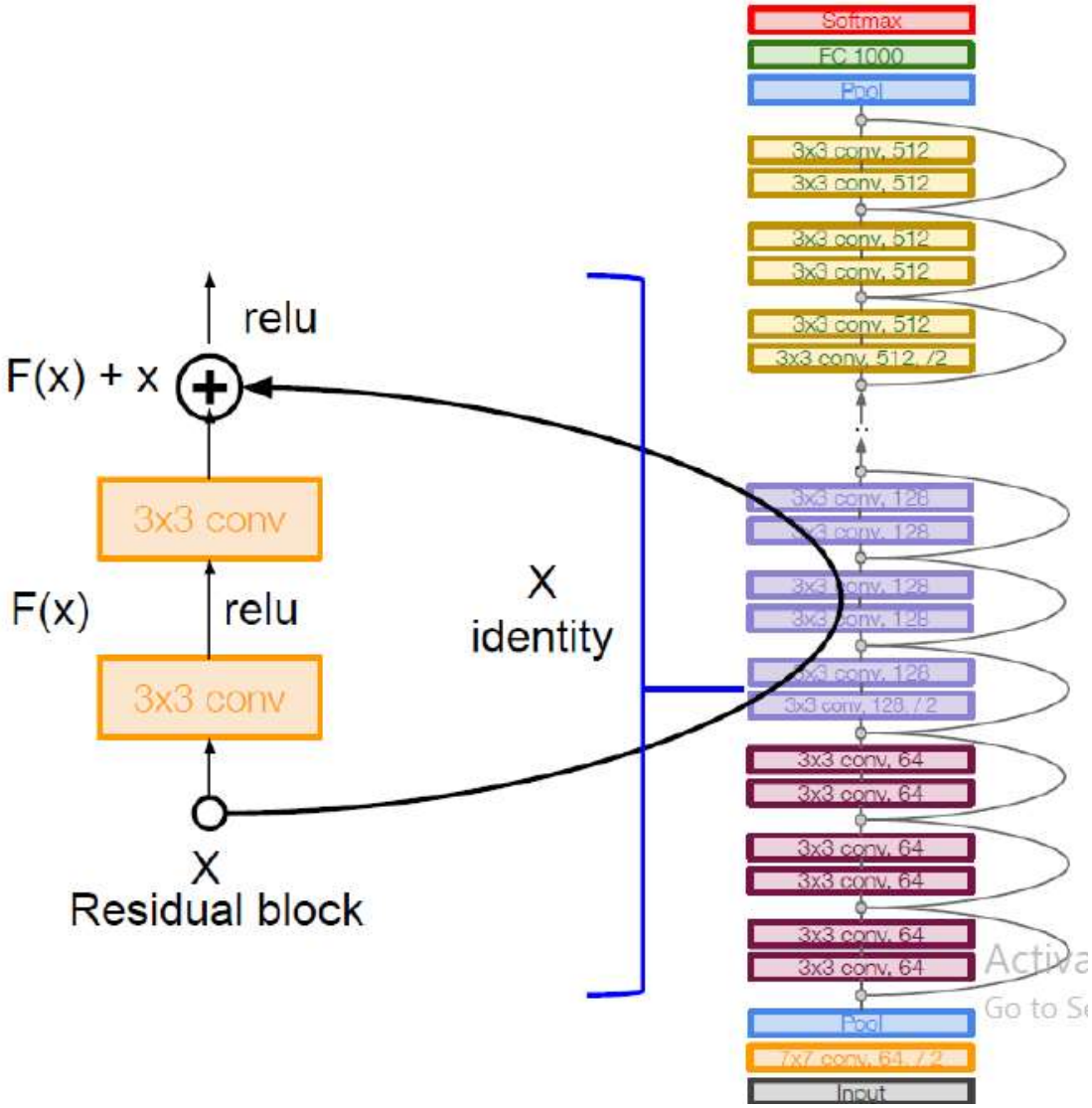
Skip Connection

Use network layers to fit a residual mapping instead of directly trying to fit a desired underlying mapping

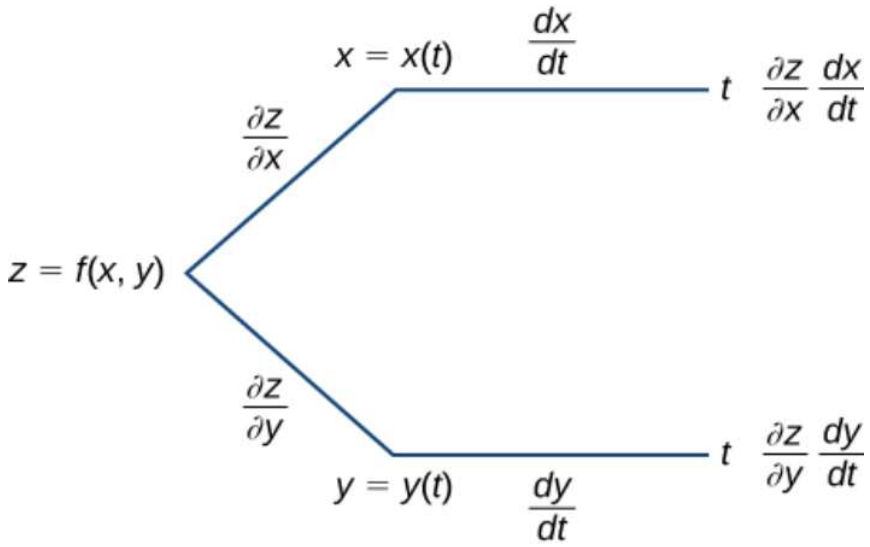


ResNet

- Stack residual blocks
- Every residual block has two 3×3 conv layers
- Periodically, double size of filters and downsample spatially using stride 2 (/2 in each dimension)
- Additional conv layer at the beginning (stem)
- No FC layers besides FC 1000 to output classes
- Global average pooling layer after last conv layer
- Batch Normalization after every CONV layer
- No dropout used

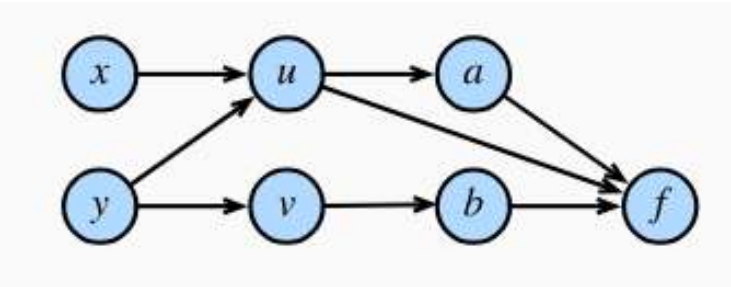


Multivariate Chain Rule



$$\frac{dz}{dt} = \frac{\partial z}{\partial x} \cdot \frac{dx}{dt} + \frac{\partial z}{\partial y} \cdot \frac{dy}{dt}$$

Multivariate chain rule

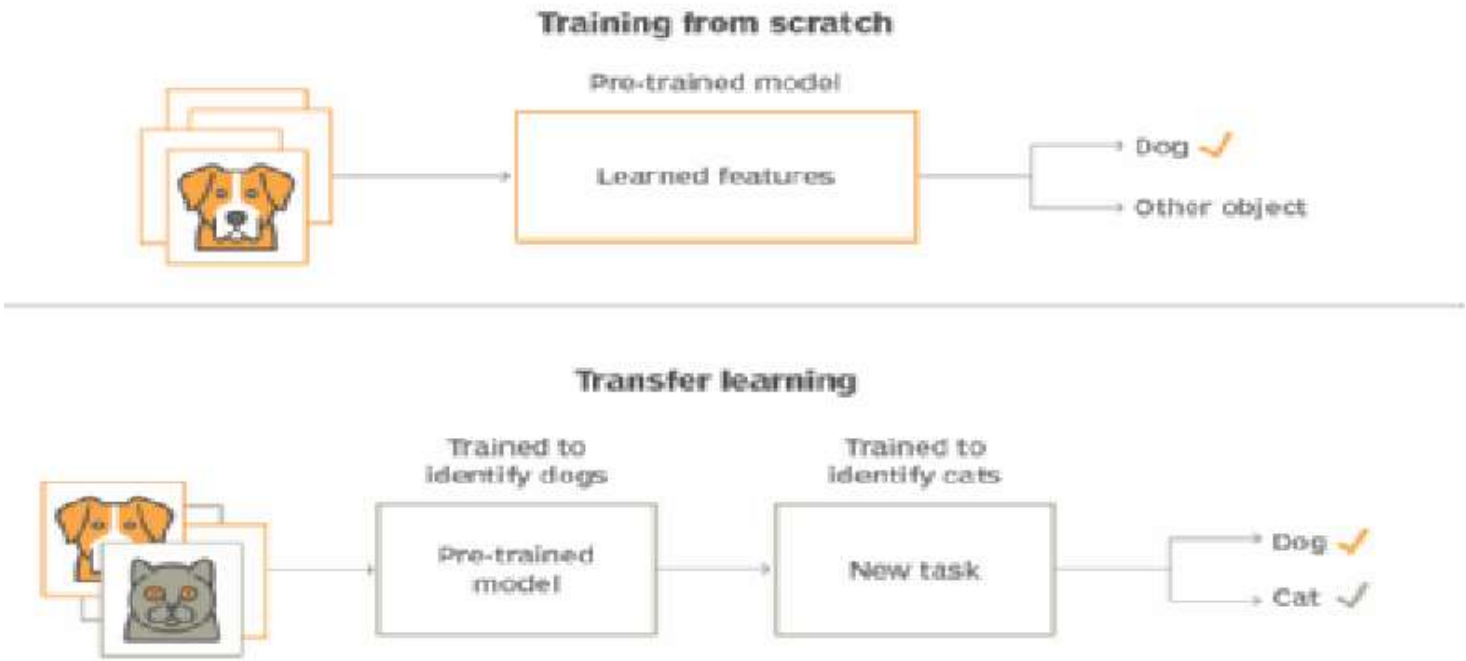


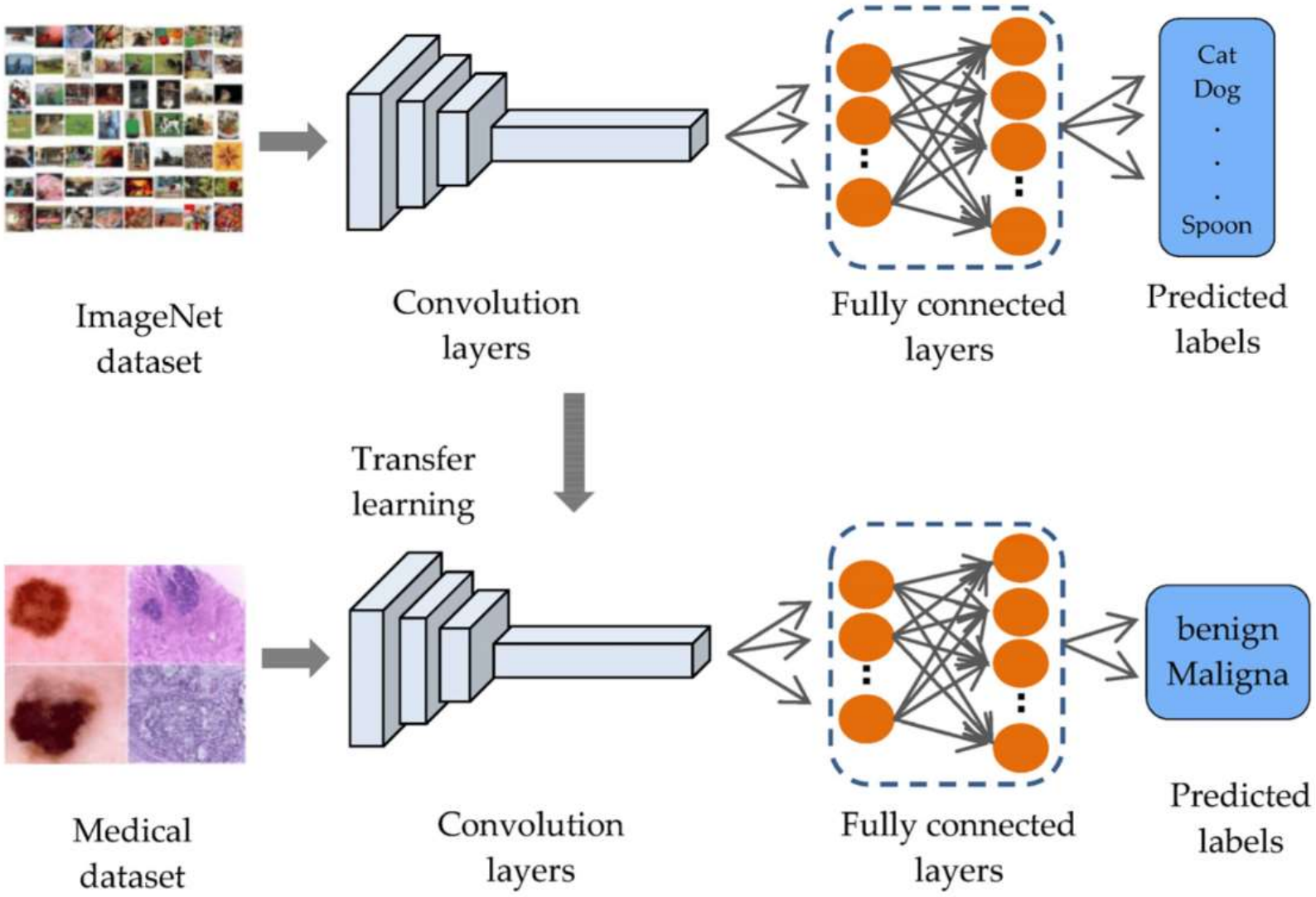
$$\frac{\partial f}{\partial y} = \frac{\partial f}{\partial a}\frac{\partial a}{\partial u}\frac{\partial u}{\partial y} + \frac{\partial f}{\partial u}\frac{\partial u}{\partial y} + \frac{\partial f}{\partial b}\frac{\partial b}{\partial v}\frac{\partial v}{\partial y}.$$

Transfer Learning

- What is Transfer Learning ?

How to transfer learning works




Cat
Dog
Spoon
ImageNet dataset
Convolution layers
Fully connected layers
Predicted labels
Transfer learning
benign
Maligna
Medical dataset
Convolution layers
Fully connected layers
Predicted labels