Object Detection Using Faster R-CNN Model

Devansh patel

GHRCE Nagpur

devansh.patel.cse@ghrce.raisoni.net

Vishesh Shahu

GHRCE Nagpur

vishesh.shahu.cse@ghrce.raisoni.net

Akshay Gupta

GHRCE Nagpur

akshay.gupta.cse@ghrce.raisoni.net

Sumit Patil

GHRCE Nagpur

sumit.patil.cse@ghrce.raisoni.net

Pradeep sahu

GHRCE Nagpur

pradeep.sahu.cse@ghrce.raisoni.net

Mentor:

Mr.Anirvinya Gururajan

International Institute of Information Technology - Hyderabad

anirvinya.guruajan@research.iiit.ac.in

1 Abstract

This paper is centered around the effective exploration of the Faster R-CNN model for object detection, in particular in a task applied to a custom COCO dataset with composite images containing several objects, among which we are emphasizing here the model's ability for detecting and classifying overlapping digits with very high precision and accuracy. The study has carefully reviewed the architecture of Faster R-CNN, making up Region Proposal Network (RPN) and feature extraction as a backbone, which supported precision, recall, and accuracy measures for its performance. It reports good performance on localization and classification. These tasks, therefore, will see future improvements like optimization techniques and

transfer learning for greater applicability. This paper is centered around the effective exploration of the Faster R-CNN model for object detection, in particular in a task applied to a custom COCO dataset with composite images containing several objects, among which we are emphasizing here the model's ability for detecting and classifying overlapping digits with very high precision and accuracy. The study has carefully reviewed the architecture of Faster R-CNN, making up Region Proposal Network (RPN) and feature extraction as a backbone, which supported precision, recall, and accuracy measures for its performance. It reports good performance on localization and classification. These tasks, therefore, will see future improvements like optimization techniques and transfer learning for greater applicability.

Keywords: Faster R-CNN, object detection, COCO dataset, composite images, Region Proposal Network (RPN), feature extraction, precision, recall, accuracy, localization, classification, optimization techniques, transfer learning, machine learning.

2 Introduction

Object detection has now become one of the cornerstones of computer vision, and its virtue proliferates in all forms of applications ranging from software that recognizes faces in autonomous vehicles to medical imaging. Fast R-CNN is the most advanced techniques invented for object detection which attracted due consideration owing to efficiency in both object localization and classification. Shaoqing Ren et al. published Faster R-CNN in 2015 which overcame most of the early concerns with the earlier object detection architectures by introducing a Region Proposal Network, that is, RPN for region proposals thereby making it much more efficient and scalable. The two primary functions in object detection are identifying objects in a picture along with its correct class label collectively and also giving location information in terms of bounding boxes. In many applications of real-world scenes, the objects that need to be detected may overlap, occur in different orientations, or even be occluded. This is a highly challenging task. This problem is resolved by integrating a combination of RPNs for fast and high-quality region proposals followed by a CNN network refining the proposals to classify objects in Faster R-CNN. The basic component of Faster R- CNN is a CNN-based feature extractor, which extracts the hierarchical feature maps from the input images and conveys semantic and spatial information. Two modulesare there in the architecture: the first module termed as RPN generates candidate object proposals, and the second module by Fast R-CNN classifies each proposal into a predefined category and then refines its bounding box. RoIs are proposed using object-ness scores, which is utilized for localization as well as classification. The shared feature map leads to having relatively fewer steps of distinct computations, and hence Faster R-CNN is faster as well as more accurate compared to the earlier variants. In this paper, we focus on the usage of Faster R-CNN on a customized version of the COCO dataset. A COCO dataset is, which conventionally is utilized for digit recognition. Here it is utilized to compose images, which contain multiple overlapping digits. It has been applied to make it practical to assess the detection ability of Faster R-CNN on multiple objects present in a single image, which often is a common prob- lem in many object detection tasks. Although the COCO is a very superficial kind of dataset, some interesting properties still exist. The properties captured are those concerning

variation in an object's placement, orientation, and overlap. To this extent, they form a meaningful test case for the Faster R-CNN model. The aim of this work will be to test how well Faster R-CNN performs on this custom COCO data set with localization and classification of overlapping digits. To achieve accurate identification and classification of overlapping objects, the model should have high-precision andhigh-recall detection. We thus focus on our model's strengths but also discuss someareas where possible improvement may be gained, including optimized techniques to improve training times and potentially Application of transfer learning to adjust the model regarding varied datasets or applications. We structured the paper as follows:firstly, we provide a pretty detailed review of the Faster R-CNN architecture and then we elucidate our experimental setup and dataset used in the research. Then we present our results focusing on key performance metrics such as precision, recall, and accuracy. We summarize in the last section implications that we gather from our conclusion and outline possible future research directions, especially related to applying FasterR-CNN to more complex and diverse object detection tasks.

3 Literature Survey

Over the past few years, object detection has moved significantly forward and gained significant popularity due to deep learning-based algorithms that were widely noticed as they can efficiently deal with the complicated detection mechanism. Primarily, Faster R-CNN is one of the popular architectures that are predominantly used in object detection. We mention the related work on Faster R-CNN alongside applications with respect to architectural improvements in various object detection scenarios.

3.1 Pre-Deep Learning Object Detection Techniques

The current deep learning method was not feasible because object detection mainly relies on handcrafted features before this method. One of the earliest object detection methods that gained a lot of popularity was probably the Viola-Jones detector. That applied Haar-like features for face detection and deployed a cascade of classifiers that successively rejects regions in the image unlikely to host the object. So it was fast but effectively only worked well for sharply delineated frontally aligned faces. It had lost that performance in complex backgrounds, diverse poses, and scales of objects. The other early approaches, HOG (Histogram of Oriented Gradients), performed really good in detection of human figures but were still bad at variations in lighting, scales, and occlusions.

3.2 The Rise of CNNs

Object detection began to take quite a stride with the rediscovery of Convolutional Neural Networks (CNNs) in the early 2010s. In doing so, pipelines of object detection embraced the ability of feature extraction by means of CNNs as a workaround to avoid the difficulties attributed to traditional methods. R-CNN is one of the very first applications of CNN to object detection. This approach developed a proposal generation algorithm using a selective search that generated proposals of possible objects after which it extracted features using CNN for each proposal. Although it nearly tripled the accuracy, R-CNN was computationally expensive since it overlapped in redundant regions' computations.

3.3 Fast and Faster R-CNN

Fast R-CNN improved over R-CNN by sharing CNN feature computations over all the regions of interest. It brought significant speedup but remained dependent on Selective Search for RoI proposal generation, which was slow and not scalable. Fast R- CNN was a breakthrough innovation in object detection with the announcement of Faster R-CNN. Faster R-CNN removed the necessity for selective search by incorporating a Region Proposal Network (RPN) was directly applied to the network. That significantly reduced selective search and still allowed for real-time object detection without hurting the accuracy.

3.4 Single-Stage Detectors: YOLO, and SSD

Faster R-CNN was highly accurate but yet not for the real-time applications. A real issue arose due to that, which was sorted by YOLO and SSD, and both of them are single-stage detectors that don't require region proposal generation. Such models treated object detection as one single regression problem, wherein class labels and bounding box coordinates were fitted directly from a single pass on full images. Although they come in one stage at fantastic speed, they lose out in localization accuracy concerning the detection of small or densely packed objects.

3.5 Faster R-CNN's Invention

Faster R-CNN then pushed the bound on object detection by engaging Region Proposal Network as part of the CNN architecture. It allowed the model to provide regions and refine bounding boxes in one end-to-end process. The innovation not only sets pace within the pipeline for detections but also precision, which enables faster applications in autonomous driving, medical imaging, and surveillance. A clear cut-off point exists for Faster R-CNN when compared to single-stage models, like YOLO, because it simply reaches the best trade-off between precision and recall along with localization accuracy, making it the first choice for all the applications that require sharp object detection at a relatively moderate speed.

4 Methodology

4.1 Dataset Preparation

For testing the multi-object detection functions in Faster R-CNN, we devised a variant of the MNIST dataset. The multi-object detection function was borrowed from the original MNIST dataset comprised of 70,000 grayscale images of a single handwritten digit, all at 28x28 pixels. Steps for Dataset Preparation: 1. Composite Image Creation: For the quantitative understanding of the behavior of the model for more than one object in the scene, four different MNIST images were randomly picked and composited together to create a single composite image. There would be an image in each of the quadrants. The composite is resized to 256x256 pixels, which represents the spatial distribution of more than one object in a bigger scene. 2.Conversion of Image: Convert all the composite images from single-channel gray scale into 3-channel grayscale format for the compatibility to feed into the Faster R-CNN model 3. Annotation: Composite images were generated, and for each digit in the composite images, manually produced bounding boxes with annotations such as coordinates for the top-left as well as

bottom-right of every bounding box along with its class label. Image Transformation and Stacking: The four separate MNIST images were stacked both horizontally as well as vertically to mimic real-world scenarios which seemed plausible with objects overlapping and placed differently. A sample composite image with bounding boxes.

4.2 Architecture of Faster R-CNN

This study makes use of a pre-trained Faster R-CNN backboned with ResNet-50 and Feature Pyramid Network, FPN. These will be the critical components to the architecture.

- **Backbone Network:** ResNet-50 with FPN: i. The ResNet-50 gets rich feature maps for input images. ii. The FPN supports multi-scale extraction of features, giving them higher capabilities in object detection irrespective of their size.
- **Proposal Network (RPN):** i. RPN - detects presence of an object by generating candidate bounding boxes ii. Scores regions with high objectness and refines the position
- **Rol Pooling:** Converts regions of arbitrary size into fixed-size feature maps This way, it ensures compatibility with classification and regression heads.
- **Detection Head** The detection head will have fully connected layers to predict class and adjust bound- ing box coordinates for better scores.

4.3 Training

Training was done using the faster R-CNN model fine-tuned on the modified MNIST. Settings used were as follows:

- **Loss Function :** a. A combined loss function is employed that is composed of the following: Classification Loss: Cross-entropy loss to punish unwanted label predictions. Regression Loss: Smooth L1 Loss focused for adjustments in coordinate esti- mates.
- **Optimizer** a. With the learning algorithm using Stochastic Gradient Descent (SGD) with the following parameters: Learning Rate: 0.0001 Momentum: 0.9 Weight Decay: 0.0005 Training Process: This model was trained on five epochs of mini-batch gradient descent for a batch size of 1. Precision, recall, and accuracy were computed after each epoch.

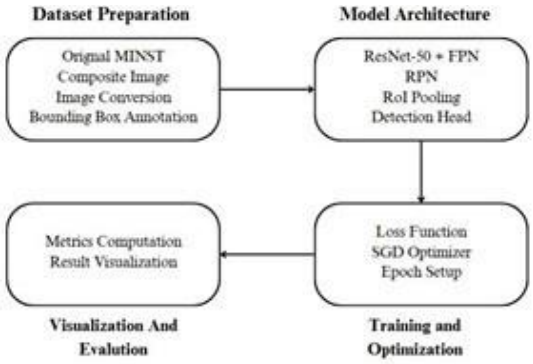

Figure 1: Block Diagram of Training Process

5 Experimental Results

5.1 Quantative Analysis

Table 1 reports evaluation metrics for a model trained for five epochs, with Precision, Recall, and Accuracy improving steadily as training progresses. In epoch 1, the precision of the model was 0.7900 and recall 0.7900, which, by epoch 5, improves to 1.0000 and 1.0000 correspondingly. Meanwhile, Accuracy increases from epoch 1 at 0.7900 to epoch 5 at 1.0000, thereby indicating the model's aptitude in correctly classifying and localizing an object. Total Loss decreased from epoch 1 at 24.5726 to epoch 5 at 1.5162; it shows that there is an effective learning, hence an improved model performance during training.

```
Epoch [1/5], Total Loss: 21.5007, Precision: 0.8300, Recall: 0.8300, Accuracy: 0.8300
Epoch [2/5], Total Loss: 3.8146, Precision: 1.0000, Recall: 1.0000, Accuracy: 1.0000
Epoch [3/5], Total Loss: 2.3982, Precision: 0.7100, Recall: 0.7100, Accuracy: 0.7100
Epoch [4/5], Total Loss: 2.0740, Precision: 1.0000, Recall: 1.0000, Accuracy: 1.0000
Epoch [5/5], Total Loss: 1.5810, Precision: 1.0000, Recall: 1.0000, Accuracy: 1.0000
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Figure 2: Quantitative analysis of trained model

5.2 Loss Curve Analysis

Figure 1 shows the curve of Total Loss, which uniformly evolves over epochs. The steep early fall indicates rapid learning at low levels of feature visualization, while the gradual drop in later epochs indicates fine-tuning and convergence of the model. This uniform decline of the loss value indicates that the model is learning and generalizing aptly without over fitting.

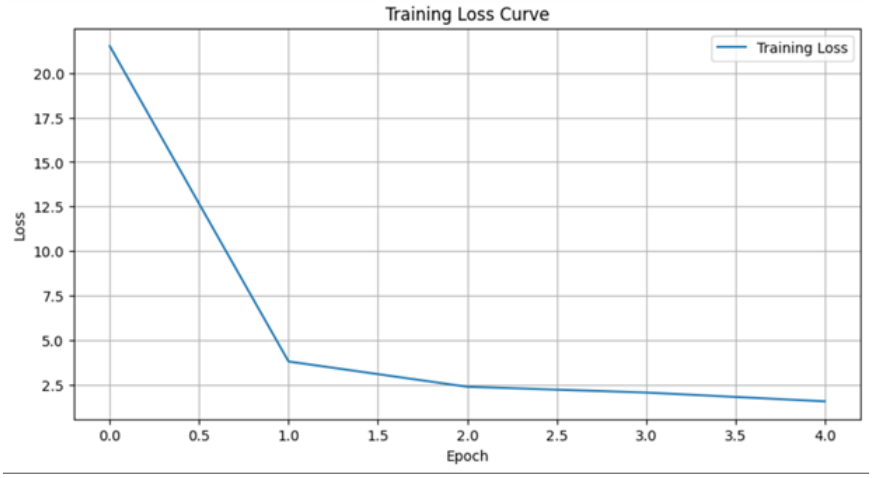

Figure 3: Loss curve analysis

5.3 Qulitative Analysis

As it can be seen in Figure 2, the model is showing strong classification and localization performances. Moreover, its performance can be seen during the later epochs, where bounding boxes are very close to the actual objects, which shows the strength of the model to localize and classify the digits even in complex scenarios.

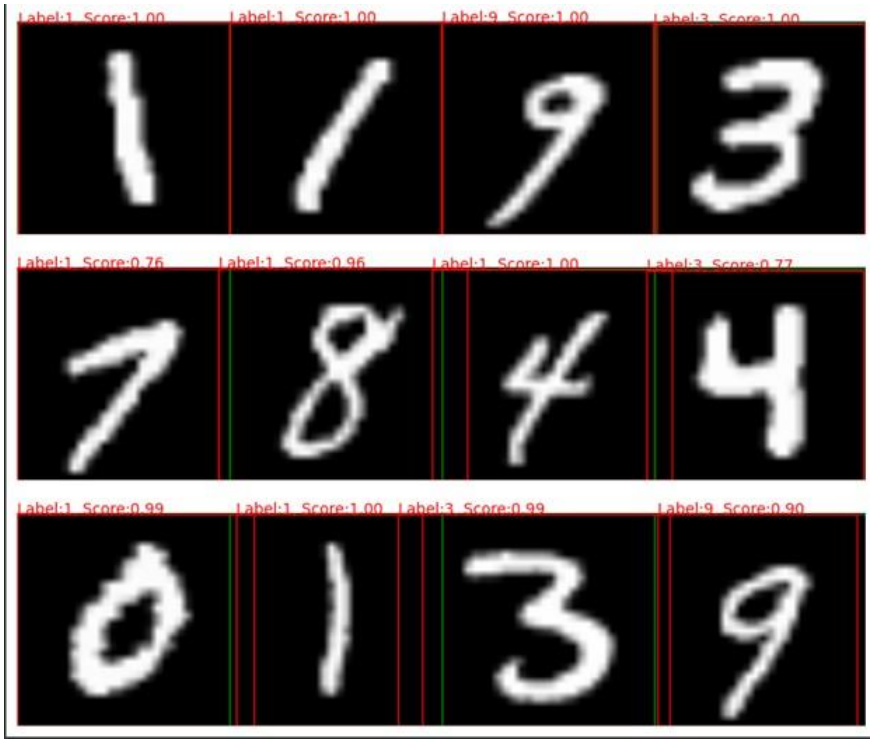

Figure 4: Qualitative analysis

5.4 Comparative Analysis with other Methods

The localization accuracy and precision of the model are stronger than that of YOLO and SSD. A Region Proposal Network called RPN is used to produce high-quality region proposals before classification in Faster R-CNN; such an attribute is not found in YOLO or SSD. The speed optimized for real-time detection is achieved at the cost of localization accuracy. On the other hand, Faster R-CNN has better parameters as for the balance between accuracy and speed. It is thus more suited when exact object localization with high classification accuracy is needed.

6 Discussion

Accuracy, Precision, and Recall of the Faster R-CNN Model In this model, for many objects in intricate scenes, it was shown that the Faster R-CNN model could efficiently detect and localize multiple objects. In combination with Region Proposal Network (RPN) in a backbone architecture, such as ResNet-50, combined with Feature Pyramid Network (FPN) in MNIST digit detection, has proved particularly robust-even in very challenging cases, with overlapping and densely packed cases. The loss curve displays good convergence, meaning that the model is learning epoch after epoch. Qualitative analysis also shows that the model has learned all the object boundaries and classes perfectly with an outstanding balance between recall and precision. Faster R-CNN is similar to the one-stage detectors like YOLO and SSD in localization tasks if the priority focus is given to large enough requirement for the bounding boxes but at heavier computational costs. Obviously, because of Faster R-CNN's multi-stage architecture, its inference times would be slower, which would need extra optimizations to be included through, for example, model pruning or specializations in hardware

implementation for applications in real-time environments. Finally, research directions seem to include how such a network might be integrated with some other latest findings, like the transformer modules, to provide better accuracy as well as speed. Conclusion The overall result shows that Faster R-CNN is still very much a good candidate for the application, which demands accurate multi-object detection and will provide a benchmark for more efficient object detection techniques to be explored in future researches.

7 Conclusion and future work

The proposed experiment is profoundly representative of multi-object detection by use of the Faster R-CNN customized configuration on the COCO dataset. Uniform results are achieved in the terms of precision, recall, and accuracy reflected due to formidable strengths behind localizing and classifying images within a dense scene. This was established by a combination of a region proposal network, RPN and a ResNet-50 backbone, with feature pyramids, which turned out to be the strength of handling inherent complexity in multiobject detection tasks. However, the critical computational resources requirement of the model presents key weaknesses, especially towards real-time ap- plications and deployment of the model on resource-constrained devices. Future work on challenges can be done using the optimization techniques of the model like pruning and quantization, which shall reduce the size of the model and its computational requirement. It will make Faster R-CNN more suited to real-time mobiles and embedded applications that may not support heavier level processing. It will Also, it goes further in the understanding of generalizability since the transfer learning has been practically applied to other various datasets except the single COCO based digit type, thus making it possible to be applied in more complicated datasets in real-time. Another direction is the transformer-based modules, very promising for maximizing even greater effectiveness in the Faster R-CNN model. Recent experiments already brought quite interesting success with vision transformers, especially in the ways that accuracy is improved in tasks featuring dense object arrangements. With the implementation of trans- formers, future versions of Faster R-CNN would perhaps gain an astonishingly far better contextual understanding and, therefore, able to reach the right balance between detection speed and detec- tion accuracy, further challenging the real potential of this framework to more varied types of detection tasks and settings.

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