



UNIVERSITY OF TECHNOLOGY
IN THE EUROPEAN CAPITAL OF CULTURE
CHEMNITZ

Neurocomputing

Convolutional neural networks

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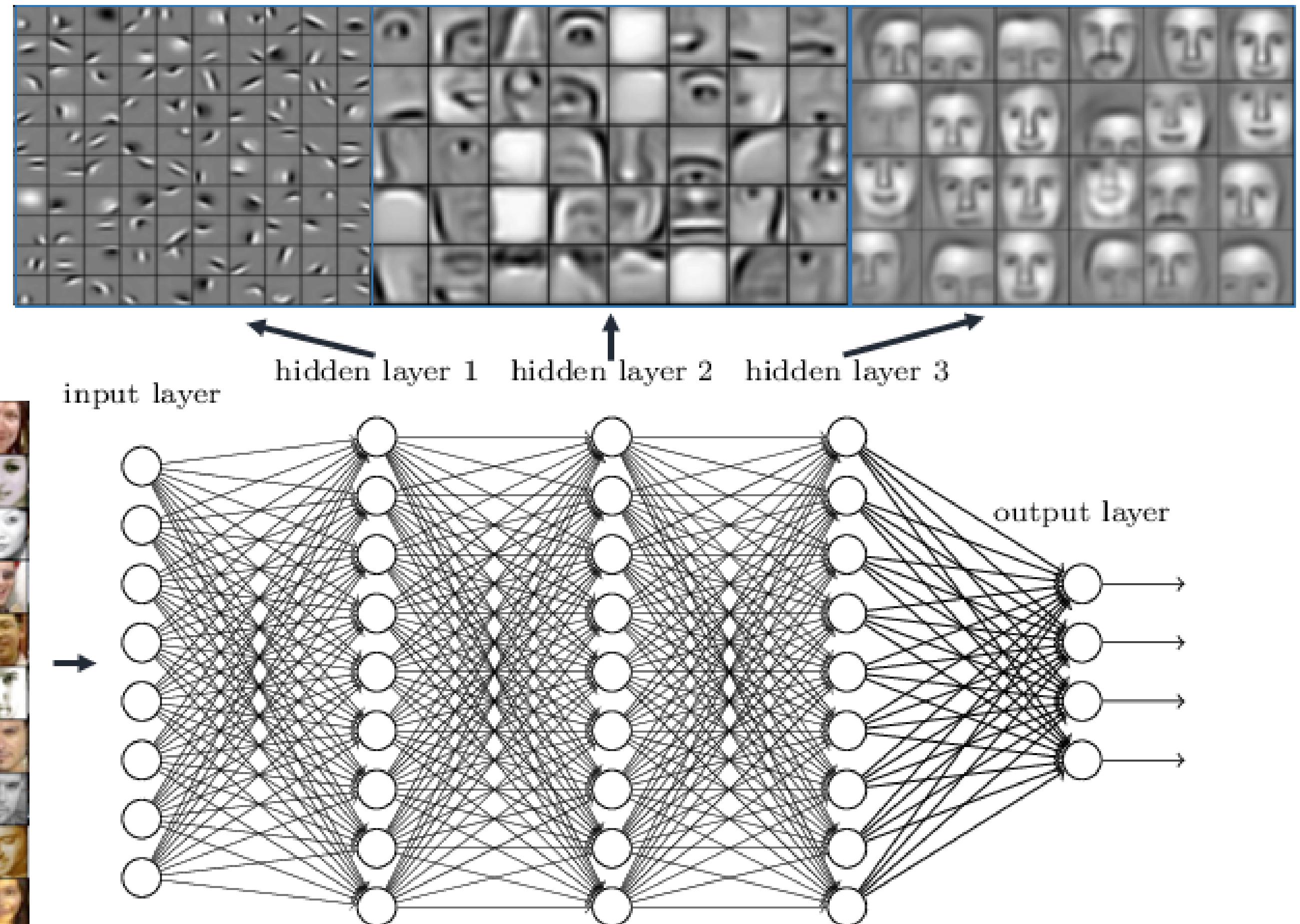
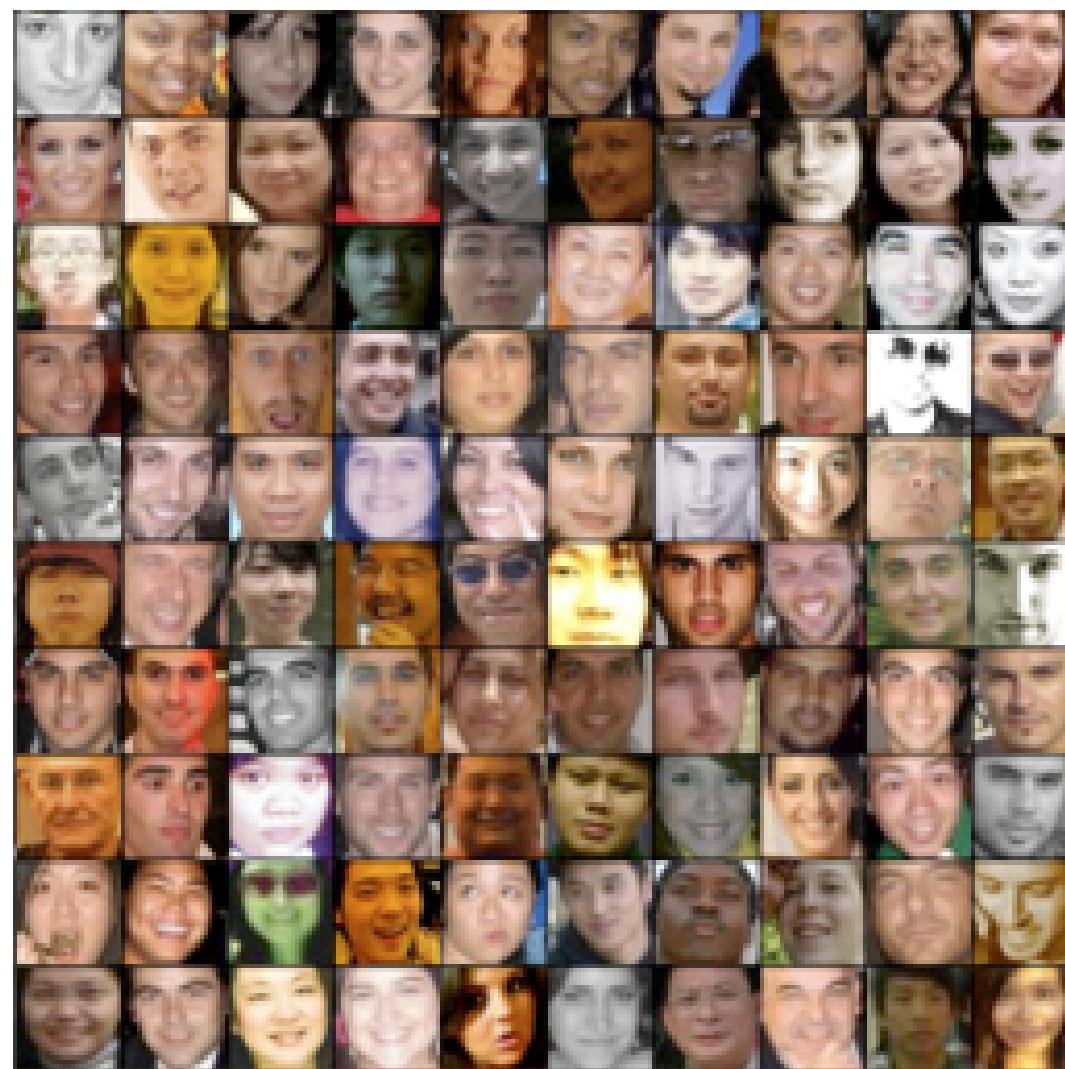
<https://tu-chemnitz.de/informatik/KI/edu/neurocomputing>

1 - Convolutional neural networks

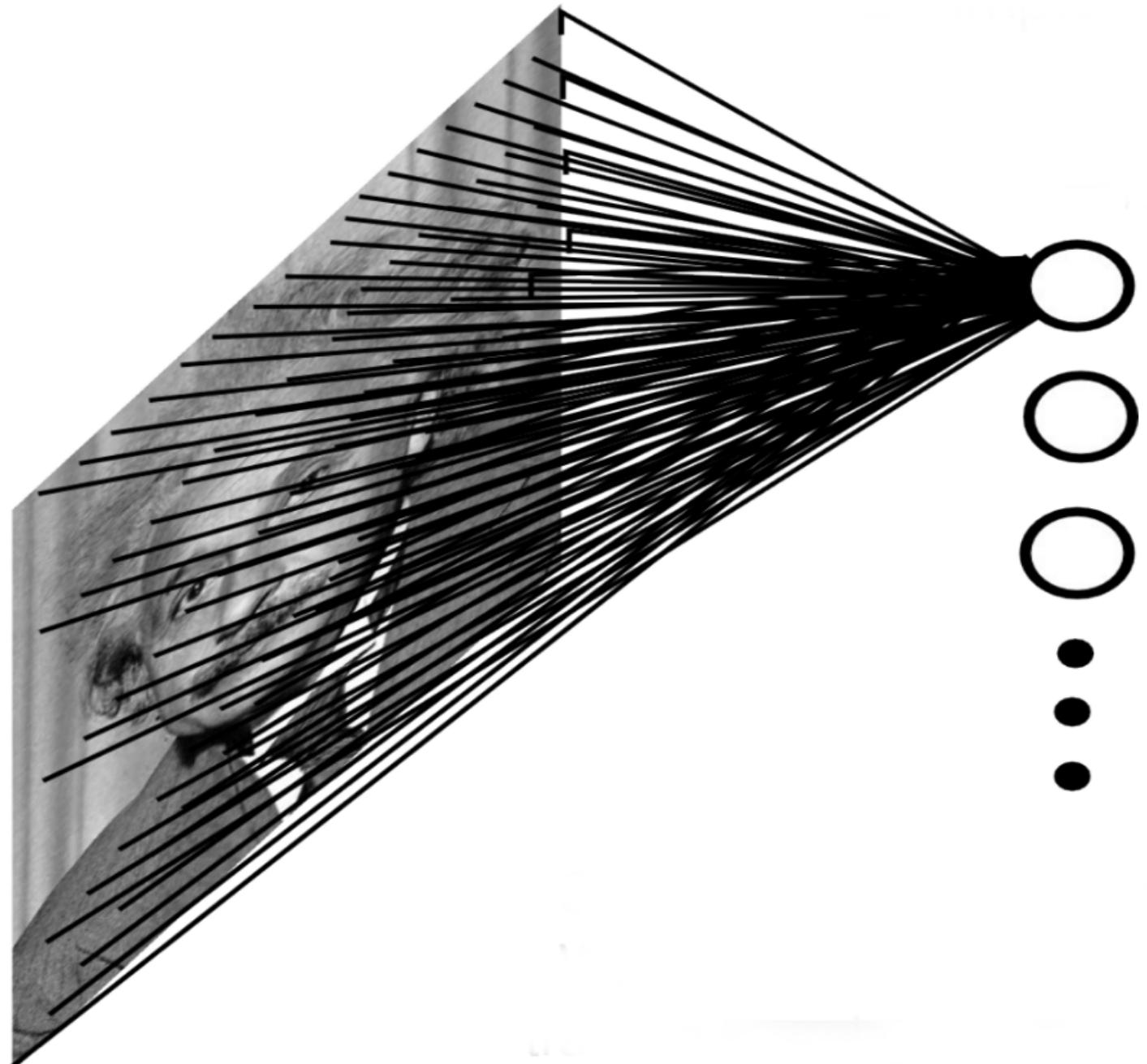
Deep Neural Network

- The different layers of a deep network extract increasingly complex features.
 - edges → contours → shapes → objects

Deep neural networks learn hierarchical feature representations



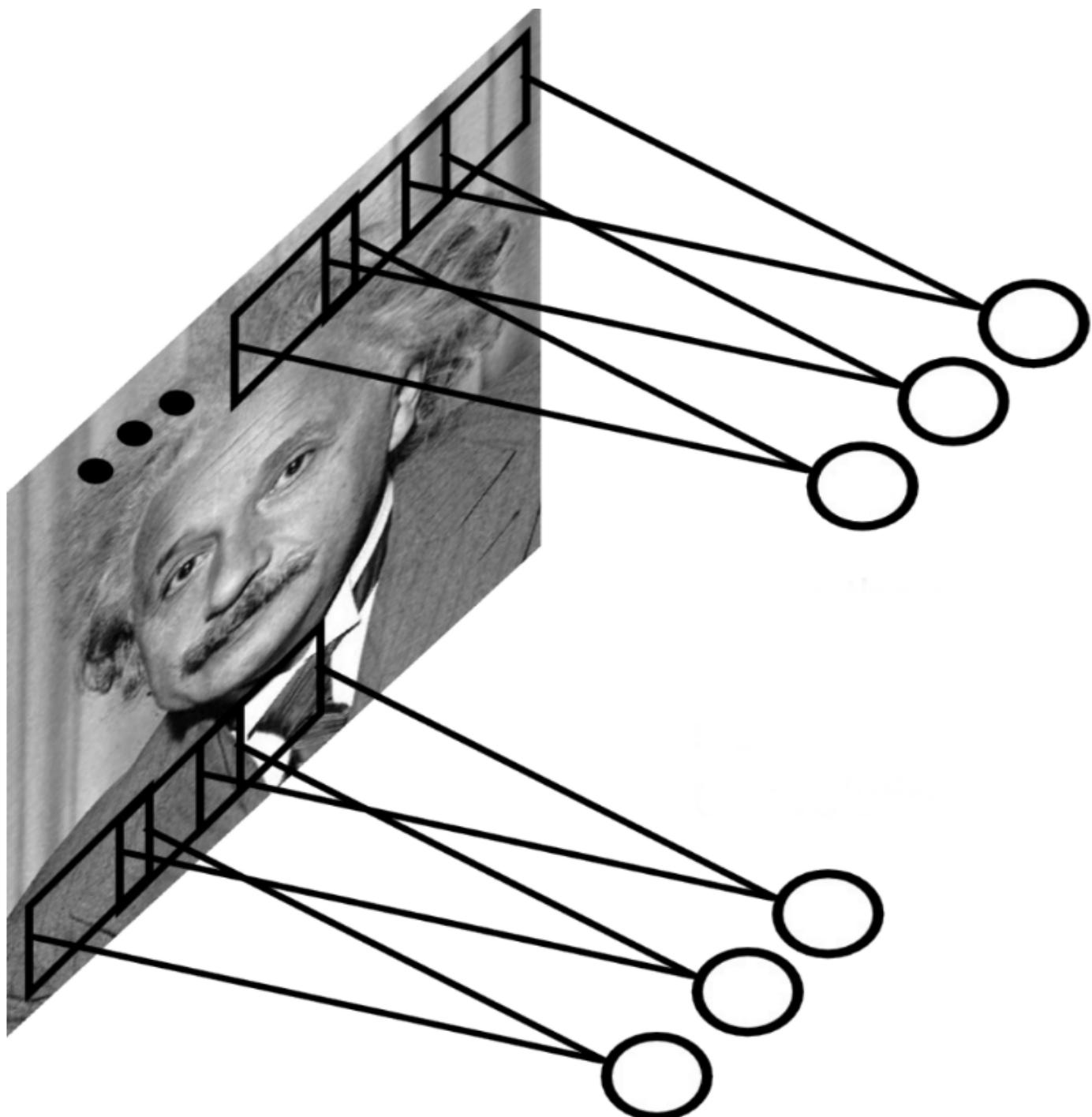
Problem with fully connected networks



- Using full images as inputs leads to an explosion of the number of weights to be learned:
 - A moderately big $800 * 600$ image has 480,000 pixels with RGB values.
 - The number of dimensions of the input space is $800 * 600 * 3 = 1.44$ million.
 - Even if you take only 1000 neurons in the first hidden layer, you get 1.44 **billion** weights to learn, just for the first layer.
- To obtain a generalization error in the range of 10%, you would need at least 14 billion training examples...

$$\epsilon \approx \frac{VC_{dim}}{N}$$

Problem with fully connected networks



- Early features (edges) are usually local, there is no need to learn weights from the whole image.
- Natural images are stationary: the statistics of the pixel in a small patch are the same, regardless the position on the image.
- **Idea:** One only needs to extract features locally and **share the weights** between the different locations.
- This is a **convolution operation**: a filter/kernel is applied on small patches and滑过 the whole image.
- Note: implemented as a cross-correlation, but it does not matter...

The convolutional layer

0	0	0	0	0	0	...
0	156	155	156	158	158	...
0	153	154	157	159	159	...
0	149	151	155	158	159	...
0	146	146	149	153	158	...
0	145	143	143	148	158	...
...

Input Channel #1 (Red)

0	0	0	0	0	0	...
0	167	166	167	169	169	...
0	164	165	168	170	170	...
0	160	162	166	169	170	...
0	156	156	159	163	168	...
0	155	153	153	158	168	...
...

Input Channel #2 (Green)

0	0	0	0	0	0	...
0	163	162	163	165	165	...
0	160	161	164	166	166	...
0	156	158	162	165	166	...
0	155	155	158	162	167	...
0	154	152	152	157	167	...
...

Input Channel #3 (Blue)

-1	-1	1
0	1	-1
0	1	1

Kernel Channel #1



308

1	0	0
1	-1	-1
1	0	-1

Kernel Channel #2



-498

0	1	1
0	1	0
1	-1	1

Kernel Channel #3



164 + 1 = -25

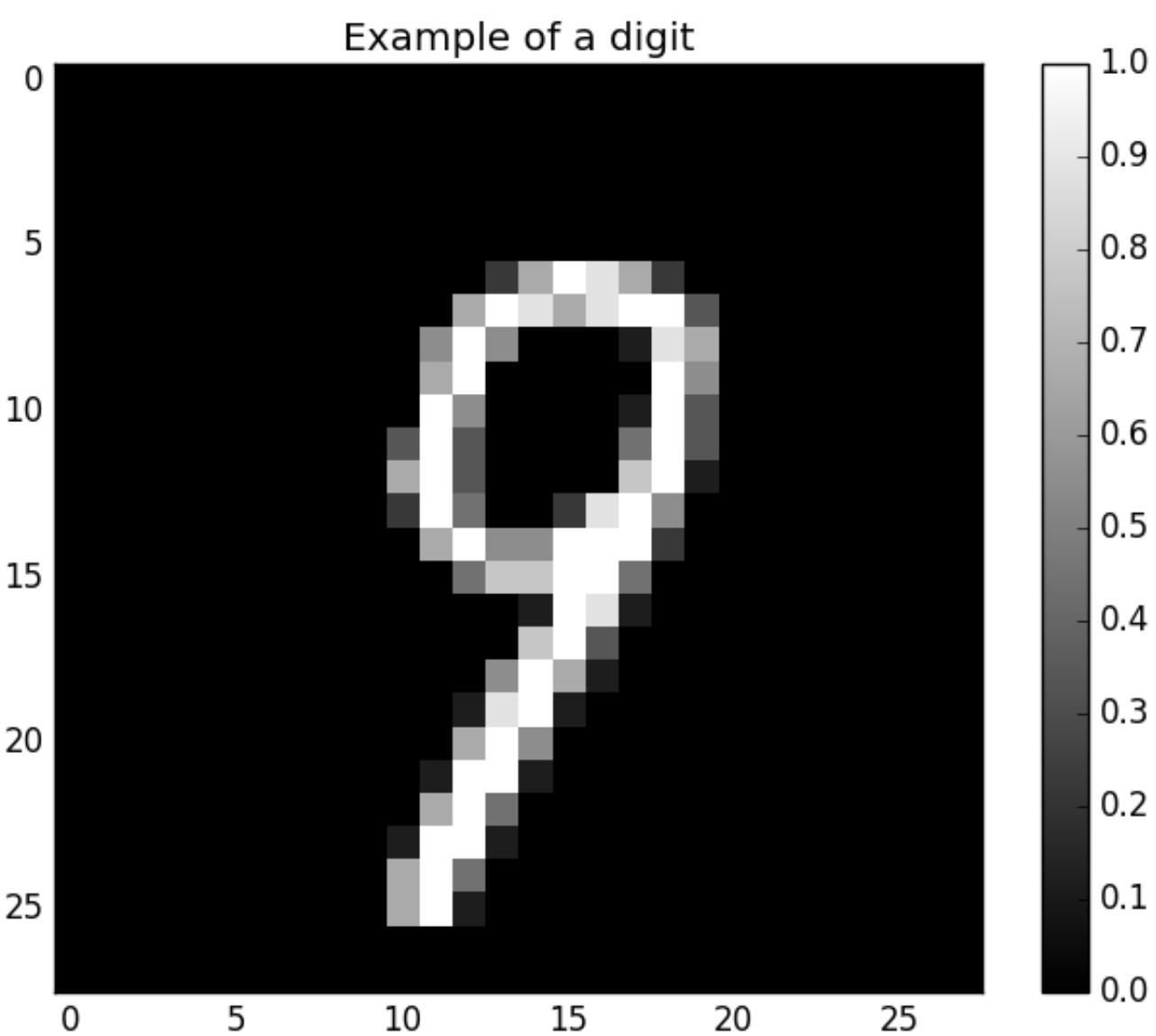
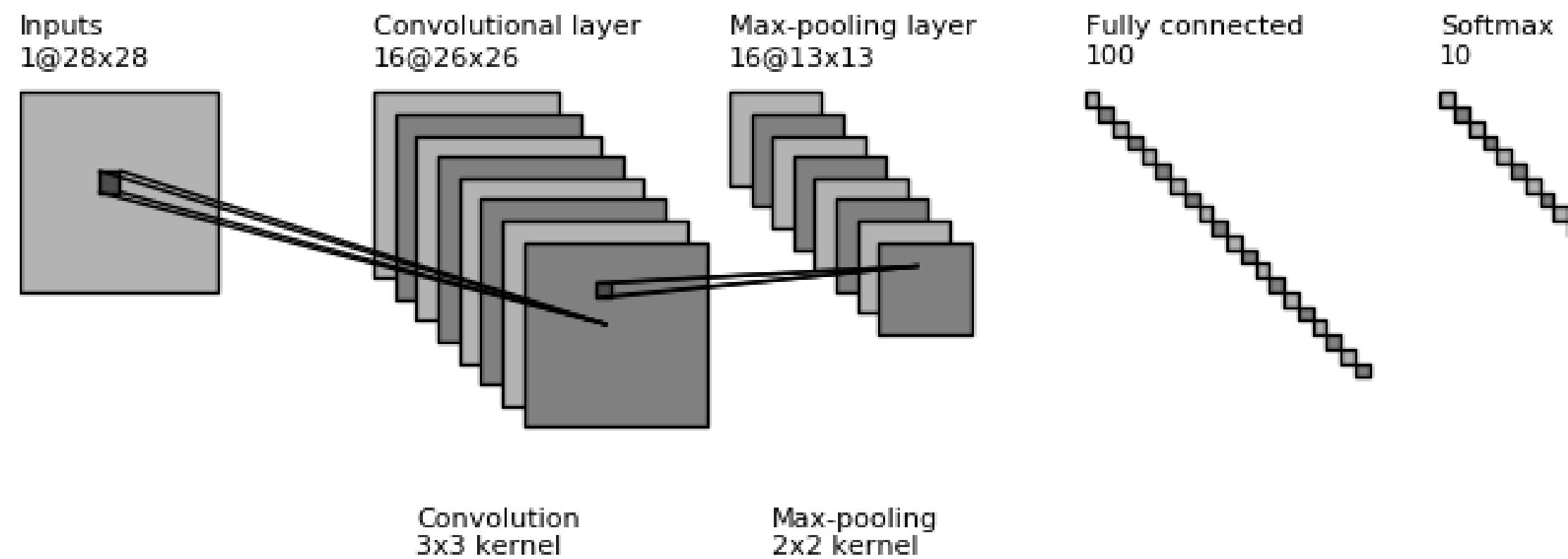
Bias = 1

-25					...
					...
					...
					...
...

Source: <https://towardsdatascience.com/a-comprehensive-guide-to-convolutional-neural-networks-the-eli5-way-3bd2b1164a53>

The convolutional layer

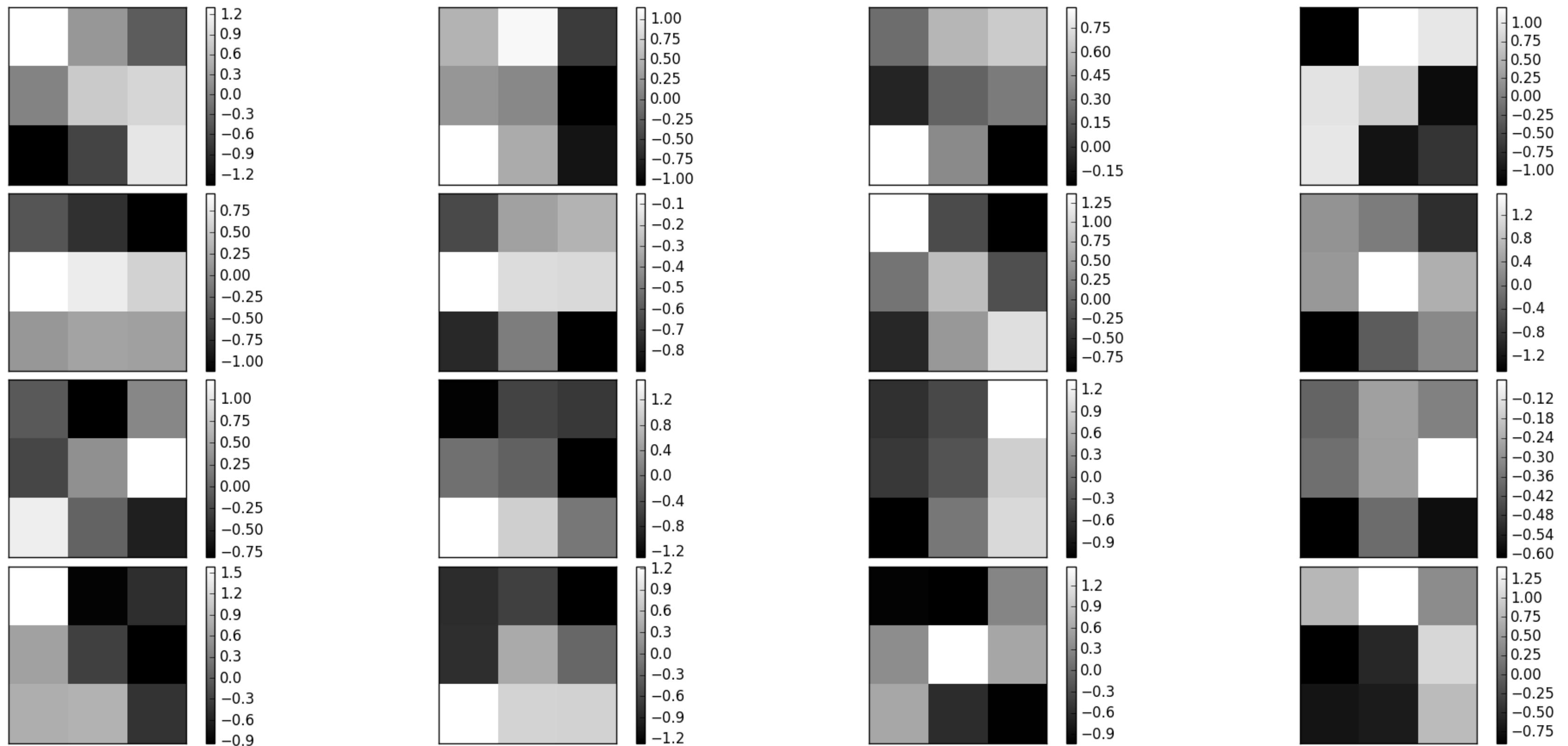
Convolutional layer on MNIST



- Let's see what happens when a convolutional layer is applied on the MNIST dataset (see the exercises).
- The input is a 28x28 black&white image.
- The first convolutional layer extracts 16 features, using 3x3 kernels.

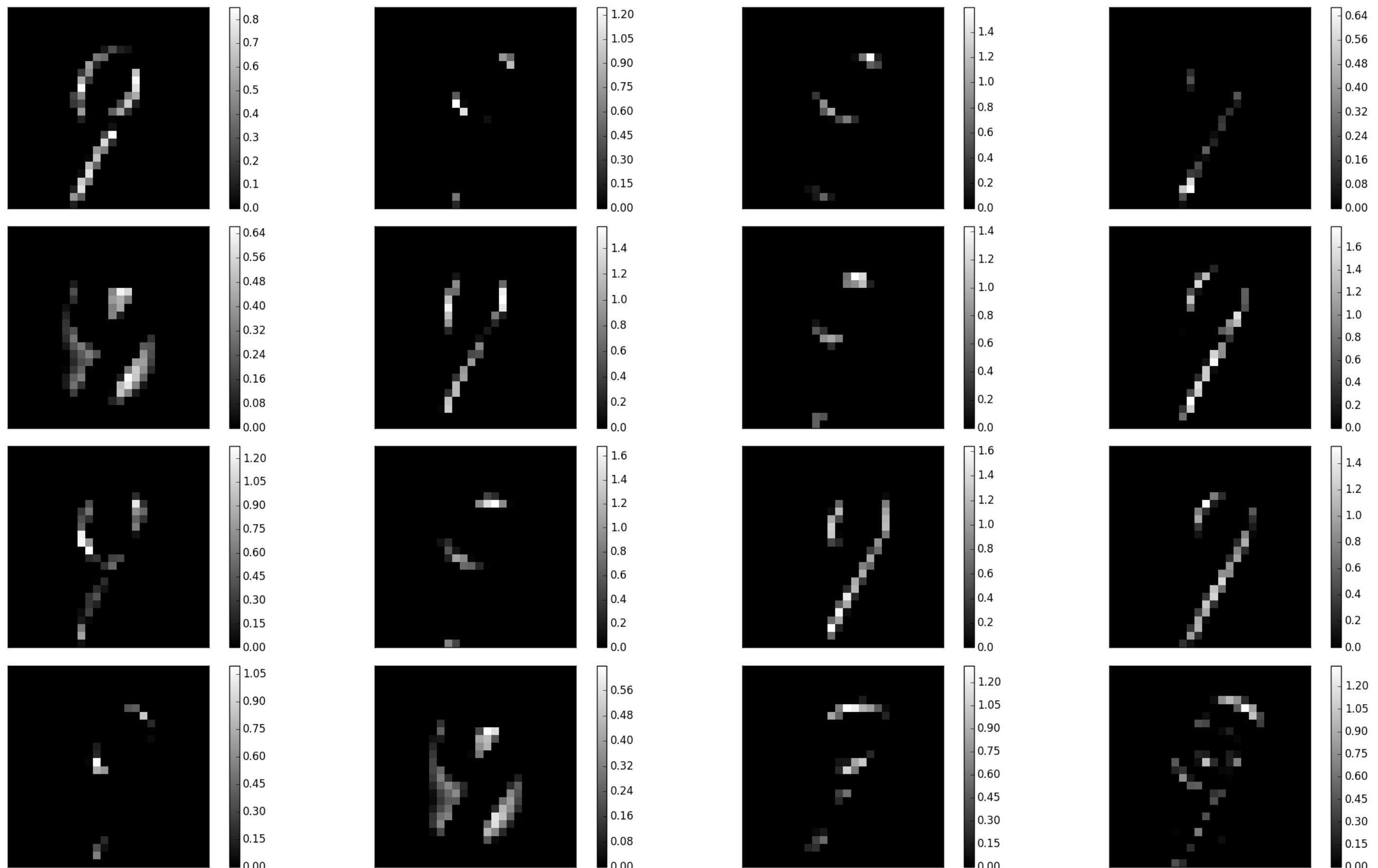
Convolutional layer on MNIST

- Each feature map extracts **edges** of different orientations.
- Here are the weights learned in the convolutional layer:

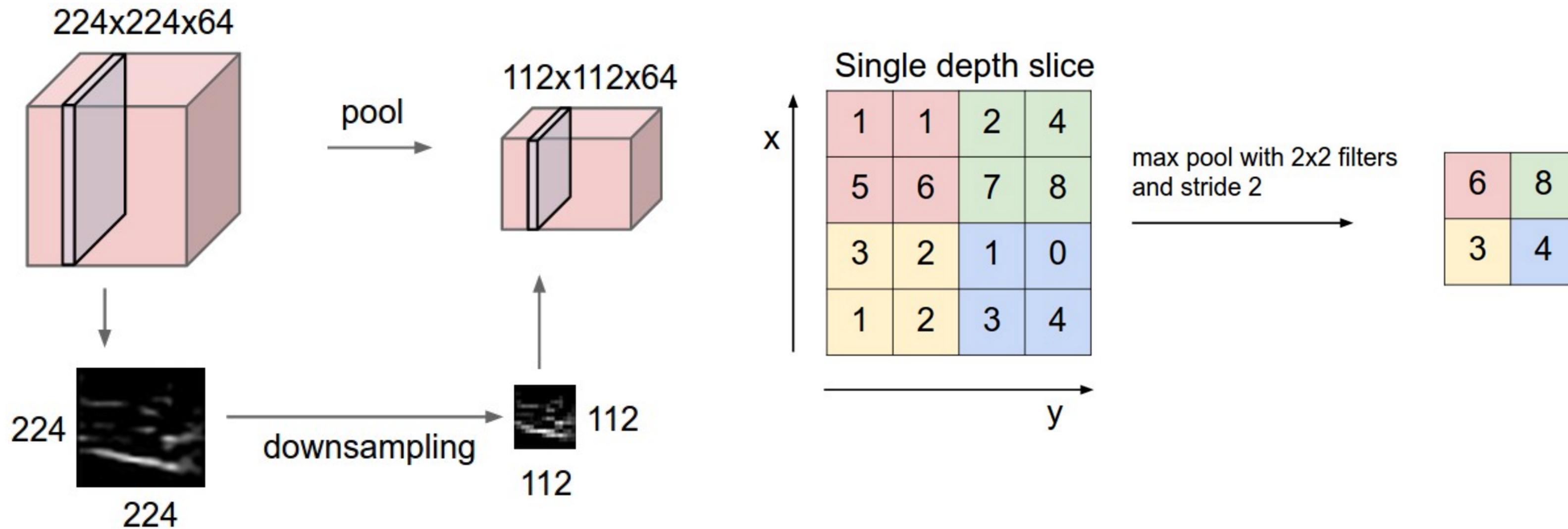


Convolutional layer on MNIST

- A convolutional layer is like a bank of (adaptive) filters applied on the image.
- **Feature maps** are the results of the convolution of these weights with the input image:



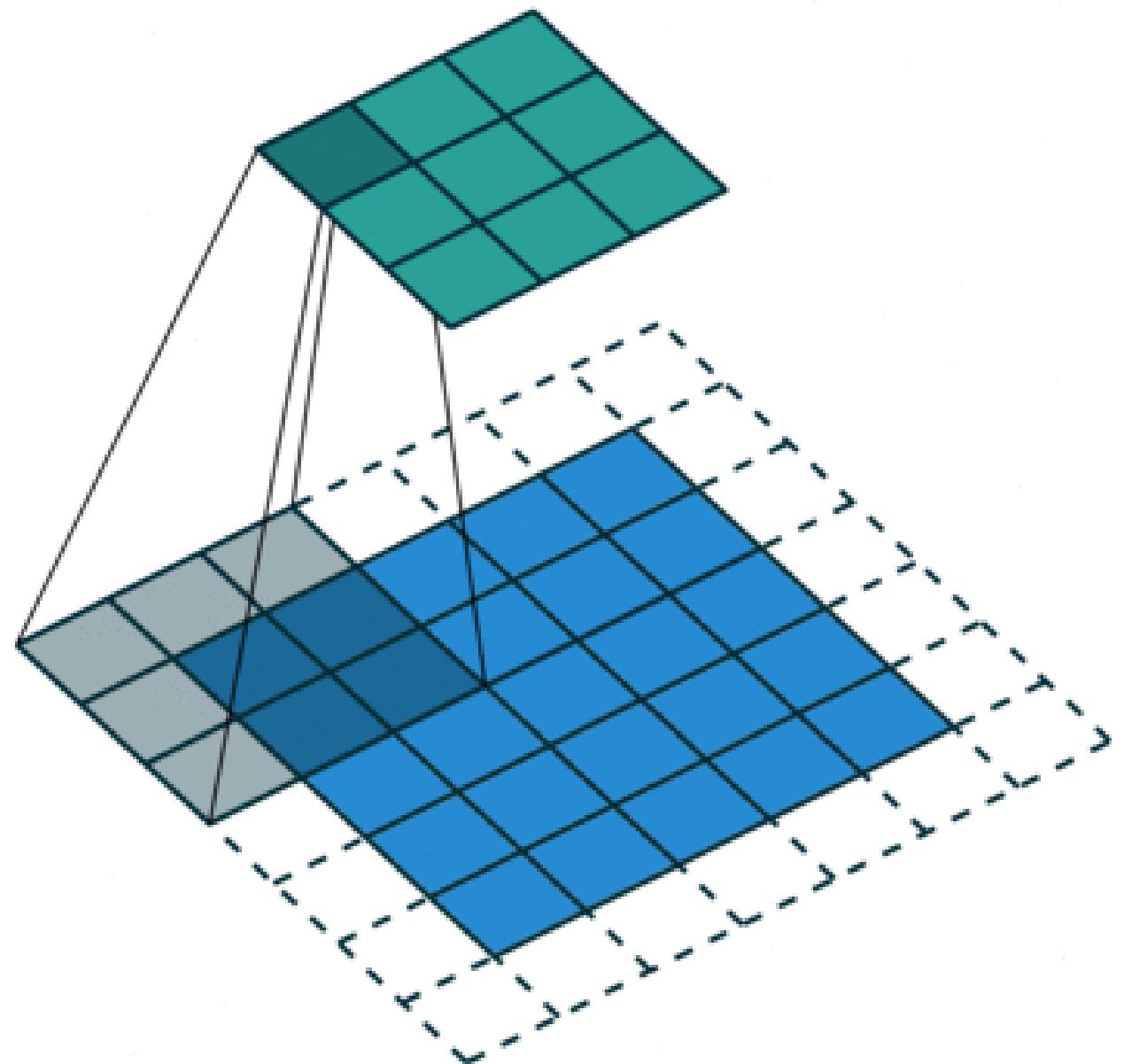
Max-pooling



Source: <http://cs231n.github.io/convolutional-networks/>

- The number of elements in a convolutional layer is still too high. We need to reduce the spatial dimension of a convolutional layer by **downsampling** it.
- For each feature, a **max-pooling** layer takes the maximum value of a feature for each subregion of the image (generally 2x2).
- Mean-pooling layers are also possible, but they are not used anymore.
- Pooling allows translation invariance: the same input pattern will be detected whatever its position in the input image.

Convolution with strides

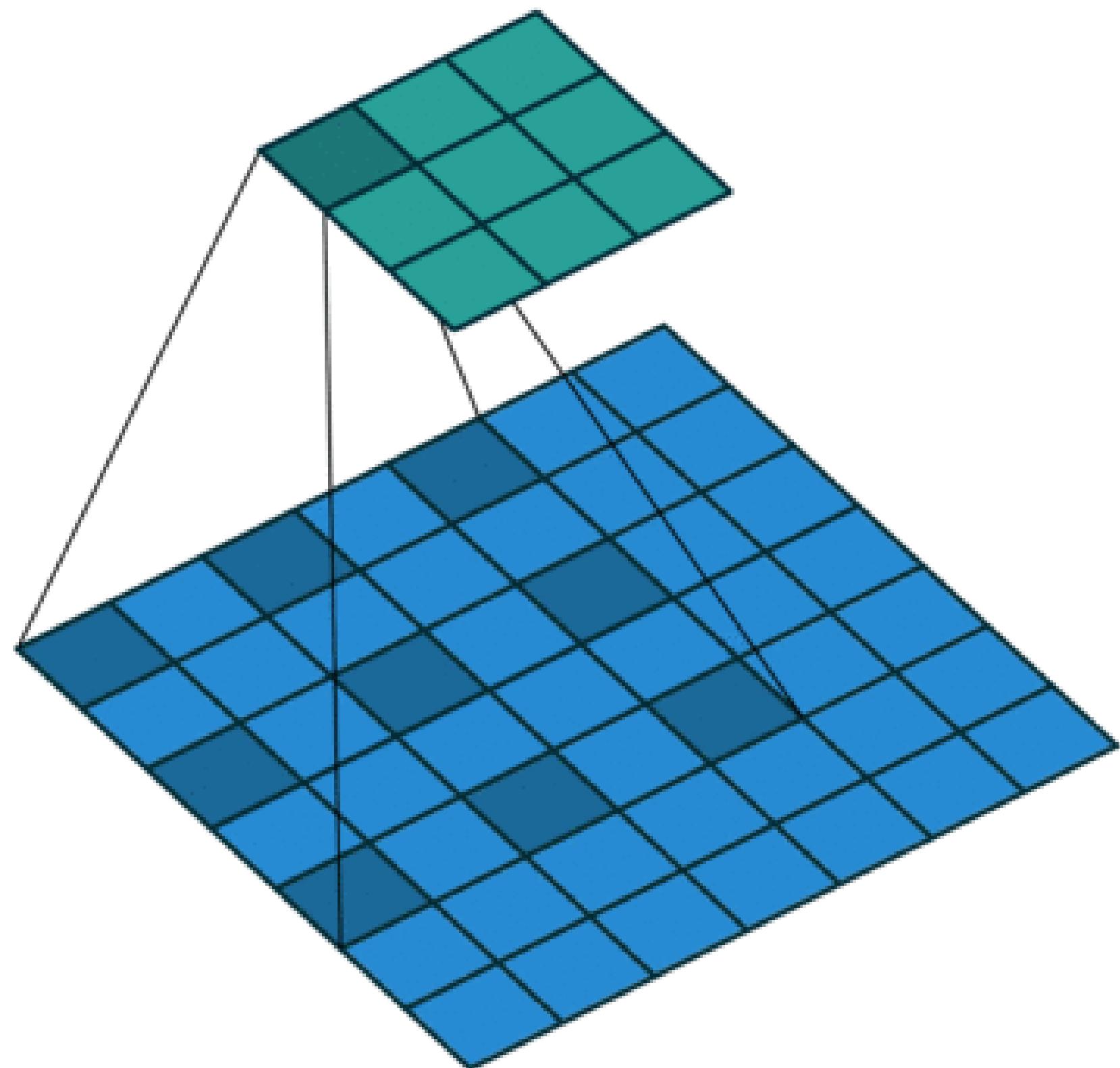


- Convolution with strides is an alternative to max-pooling layers.
- The convolution simply “jumps” one pixel when sliding over the image (stride 2).
- This results in a smaller feature map.
- Much less operations to do than convolution with stride 1 followed by max-pooling, for the same performance.
- Particularly useful for generative models (VAE, GAN, etc).

Source: https://github.com/vdumoulin/conv_arithmetic

Dilated convolutions

- A **dilated convolution** is a convolution with holes (à trous).
- The filter has a bigger spatial extent than its number of values.



Source: https://github.com/vdumoulin/conv_arithmetic

Backpropagation through a convolutional layer

- But how can we do backpropagation through a convolutional layer?

$x_{00}f_{00}$	$x_{01}f_{01}$	$x_{02}f_{02}$	x_{03}	x_{04}
$x_{10}f_{10}$	$x_{11}f_{11}$	$x_{12}f_{12}$	x_{13}	x_{14}
$x_{20}f_{20}$	$x_{21}f_{21}$	$x_{22}f_{22}$	x_{23}	x_{24}
x_{30}	x_{31}	x_{32}	x_{33}	x_{34}
x_{40}	x_{41}	x_{42}	x_{43}	x_{44}

y_{00}	y_{01}
y_{10}	y_{11}

$$y_{00} = x_{00}f_{00} + x_{01}f_{01} + x_{02}f_{02} + x_{10}f_{10} + x_{11}f_{11} + x_{12}f_{12} + x_{20}f_{20} + x_{21}f_{21} + x_{22}f_{22}$$

Source: <https://medium.com/@mayank.utexas/backpropagation-for-convolution-with-strides-8137e4fc2710>

- In the example above, the four neurons of the feature map will receive a gradient from the upper layers.
- How can we use it to learn the filter values and pass the gradient to the lower layers?

Backpropagation through a convolutional layer

- Answer: simply by convolving the output gradients with the flipped filter!

$$\frac{\partial L}{\partial x_{00}} = \frac{\partial L}{\partial y_{00}} f_{00}$$

$\frac{\partial L}{\partial x_{00}}$	$\frac{\partial L}{\partial x_{01}}$	$\frac{\partial L}{\partial x_{02}}$	$\frac{\partial L}{\partial x_{03}}$	$\frac{\partial L}{\partial x_{04}}$
$\frac{\partial L}{\partial x_{10}}$	$\frac{\partial L}{\partial x_{11}}$	$\frac{\partial L}{\partial x_{12}}$	$\frac{\partial L}{\partial x_{13}}$	$\frac{\partial L}{\partial x_{14}}$
$\frac{\partial L}{\partial x_{20}}$	$\frac{\partial L}{\partial x_{21}}$	$\frac{\partial L}{\partial x_{22}}$	$\frac{\partial L}{\partial x_{23}}$	$\frac{\partial L}{\partial x_{24}}$
$\frac{\partial L}{\partial x_{30}}$	$\frac{\partial L}{\partial x_{31}}$	$\frac{\partial L}{\partial x_{32}}$	$\frac{\partial L}{\partial x_{33}}$	$\frac{\partial L}{\partial x_{34}}$
$\frac{\partial L}{\partial x_{40}}$	$\frac{\partial L}{\partial x_{41}}$	$\frac{\partial L}{\partial x_{42}}$	$\frac{\partial L}{\partial x_{43}}$	$\frac{\partial L}{\partial x_{44}}$

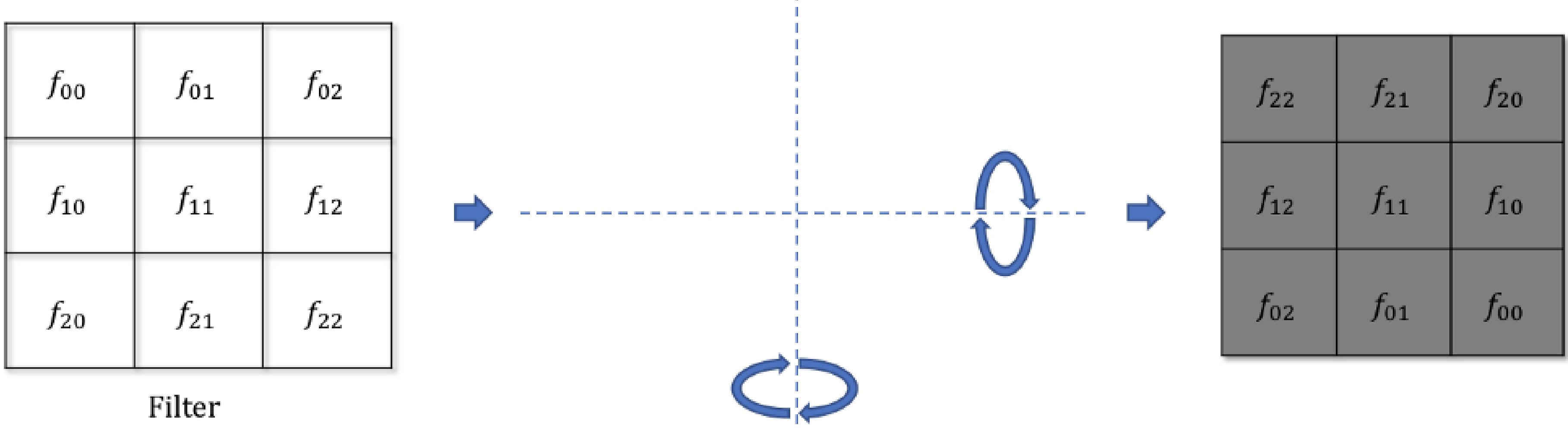


0 * f_{22}	0 * f_{21}	0 * f_{20}	0	0	0	0
0 * f_{12}	0 * f_{11}	0 * f_{10}	0	0	0	0
0 * f_{02}	0 * f_{01}	$\frac{\partial L}{\partial y_{00}} f_{00}$	0	$\frac{\partial L}{\partial y_{01}}$	0	0
0	0	0	0	0	0	0
0	0	$\frac{\partial L}{\partial y_{10}}$	0	$\frac{\partial L}{\partial y_{11}}$	0	0
0	0	0	0	0	0	0
0	0	0	0	0	0	0

Source: <https://medium.com/@mayank.utexas/backpropagation-for-convolution-with-strides-8137e4fc2710>

Backpropagation through a convolutional layer

- The filter just has to be flipped (180° symmetry) before the convolution.



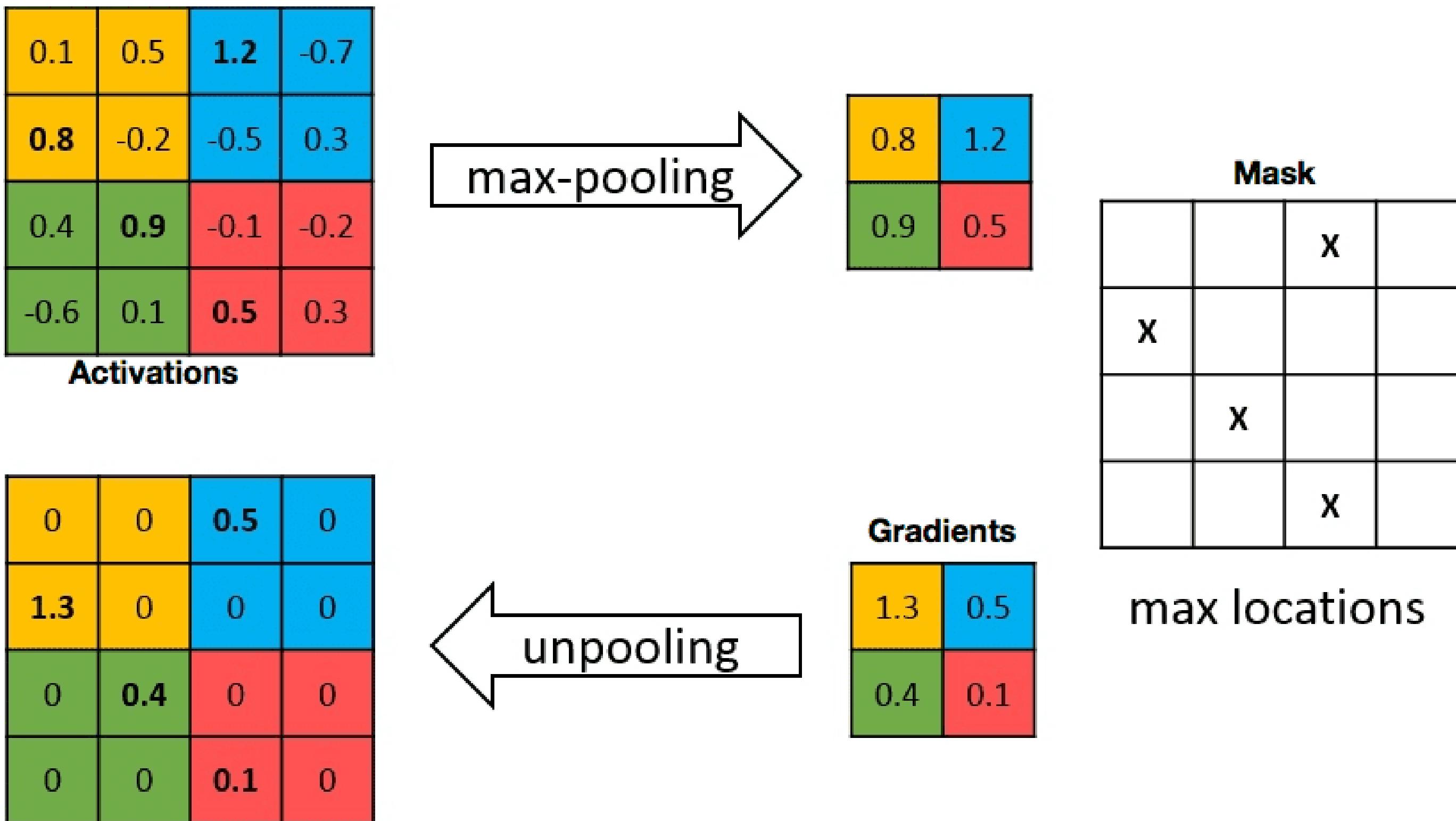
Source: <https://medium.com/@mayank.utexas/backpropagation-for-convolution-with-strides-8137e4fc2710>

- The convolution operation is differentiable, so we can apply backpropagation and learn the filters.

$$\mathbf{h}_k = W_k * \mathbf{h}_{k-1} + \mathbf{b}_k$$

$$\frac{\partial \mathcal{L}(\theta)}{\partial \mathbf{h}_{k-1}} = W_k^F * \frac{\partial \mathcal{L}(\theta)}{\partial \mathbf{h}_k}$$

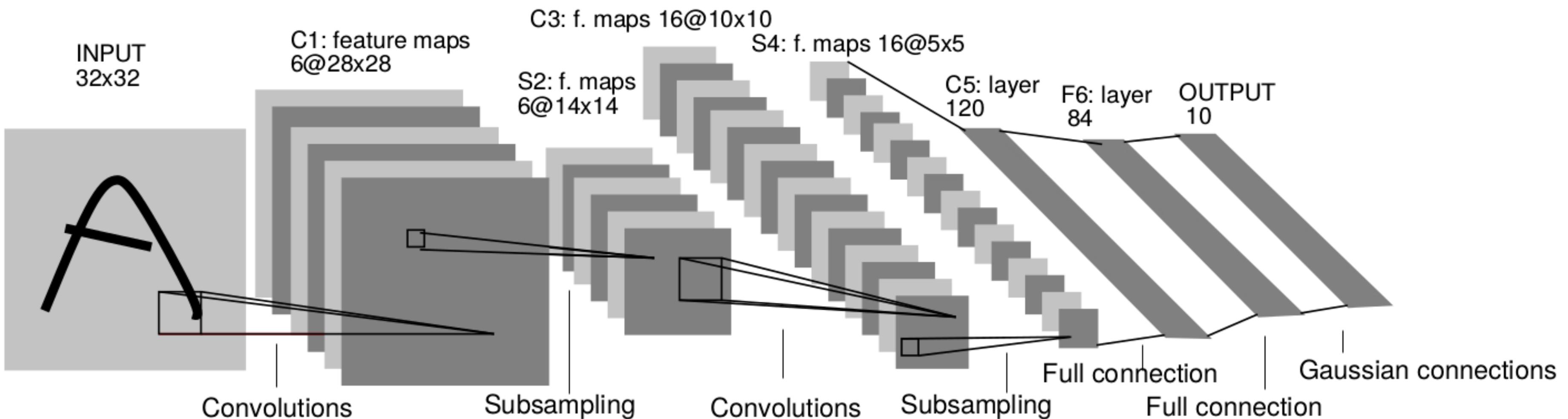
Backpropagation through a max-pooling layer



Source: <https://mukulrathi.com/demystifying-deep-learning/conv-net-backpropagation-maths-intuition-derivation/>

- We can also use backpropagation through a max-pooling layer.
- We need to remember which location was the winning location in order to backpropagate the gradient.
- A max-pooling layer has no parameter, we do not need to learn anything, just to pass the gradient backwards.

Convolutional Neural Networks



- A **convolutional neural network** (CNN) is a cascade of convolution and pooling operations, extracting layer by layer increasingly complex features.
- The spatial dimensions decrease after each pooling operation, but the number of extracted features increases after each convolution.
- One usually stops when the spatial dimensions are around 7×7 .
- The last layers are fully connected (classical MLP).
- Training a CNN uses backpropagation all along: the convolution and pooling operations are differentiable.

Implementing a CNN in keras

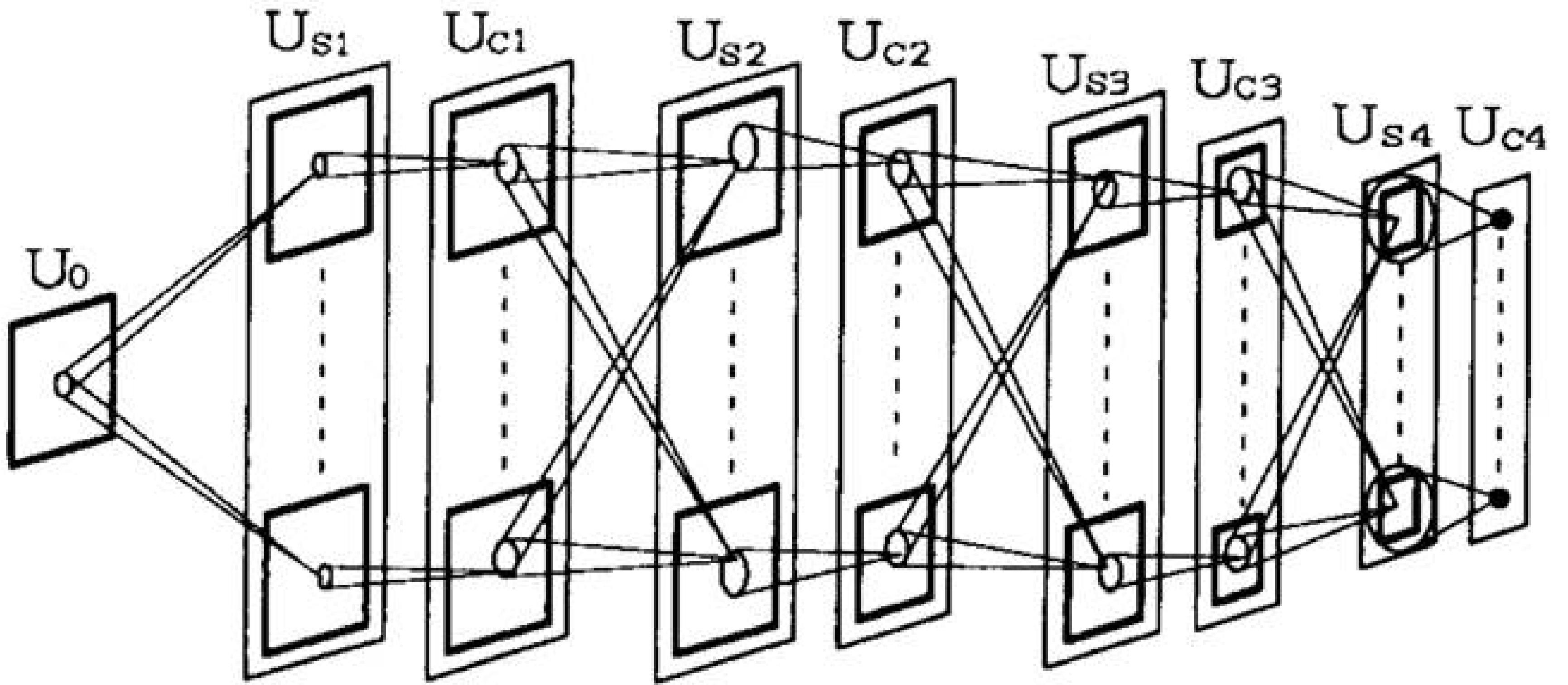
- Convolutional and max-pooling layers are regular objects in keras/tensorflow/pytorch/etc.
- You do not need to care about their implementation, they are designed to run fast on GPUs.
- You have to apply to the CNN all the usual tricks: optimizers, dropout, batch normalization, etc.

```
1 model = Sequential()
2 model.add(Input(X_train.shape[1:]))
3
4 model.add(Conv2D(32, (3, 3), padding='same'))
5 model.add(Activation('relu'))
6 model.add(Conv2D(32, (3, 3)))
7 model.add(Activation('relu'))
8 model.add(MaxPooling2D(pool_size=(2, 2)))
9 model.add(Dropout(0.25))
10
11 model.add(Conv2D(64, (3, 3), padding='same'))
12 model.add(Activation('relu'))
13 model.add(Conv2D(64, (3, 3)))
14 model.add(Activation('relu'))
15 model.add(MaxPooling2D(pool_size=(2, 2)))
16 model.add(Dropout(0.25))
```

```
1 model.add(Flatten())
2 model.add(Dense(512))
3 model.add(Activation('relu'))
4 model.add(Dropout(0.5))
5 model.add(Dense(num_classes))
6 model.add(Activation('softmax'))
7
8 opt = RMSprop(
9     lr=0.0001,
10    decay=1e-6
11 )
12
13 model.compile(
14     loss='categorical_crossentropy',
15     optimizer=opt,
16     metrics=['accuracy'])
17 )
```

2 - Some famous convolutional networks

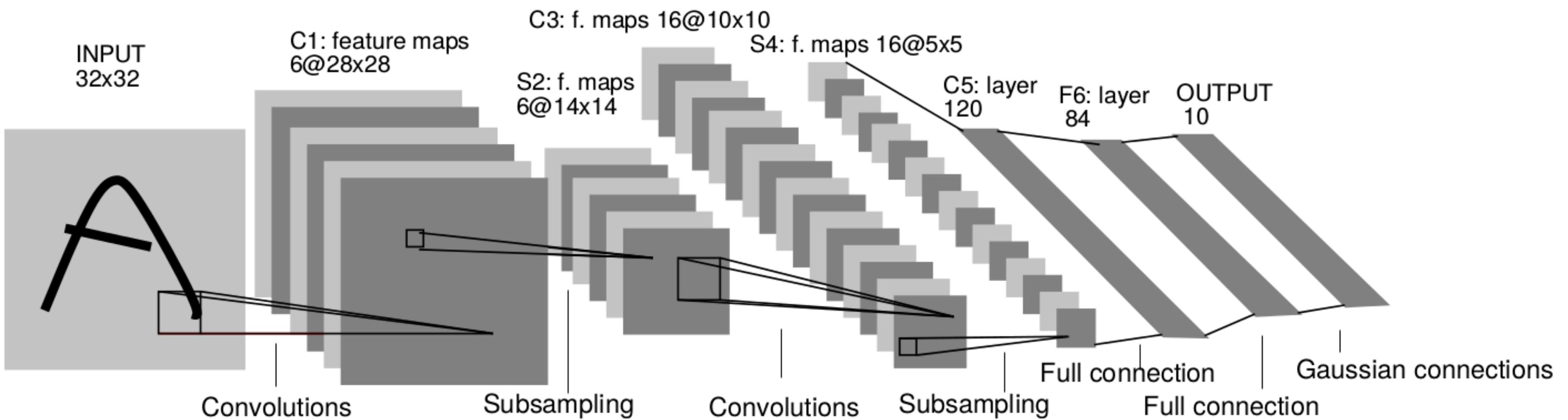
NeoCognitron



Source: <https://upload.wikimedia.org/wikipedia/uk/4/42/Neocognitron.jpg>

- The **Neocognitron** (Fukushima, 1980) was actually the first CNN able to recognize handwritten digits.
- Training is not based on backpropagation, but a set of biologically realistic learning rules (Add-if-silent, margined WTA).
- Inspired by the human visual system.

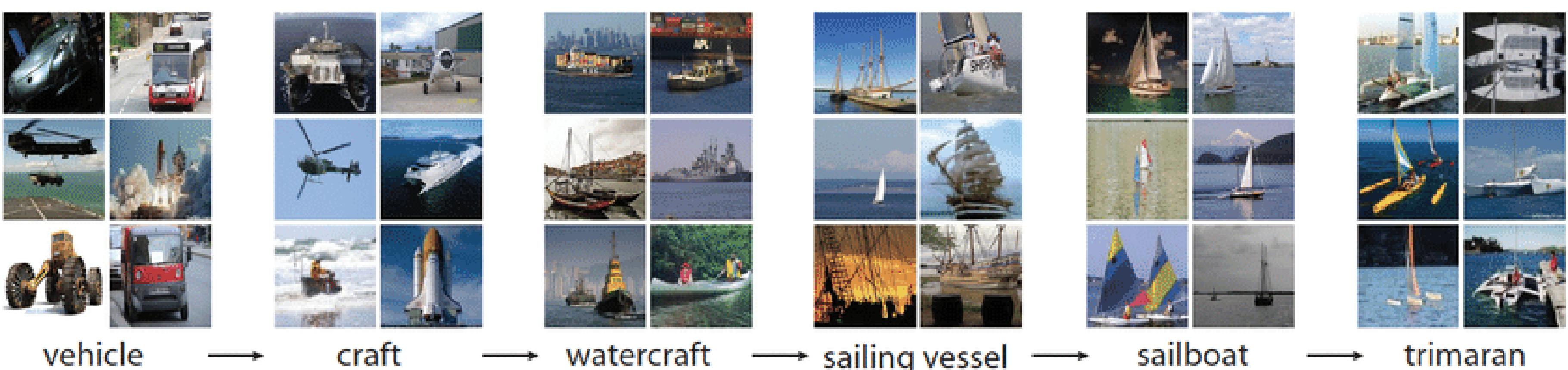
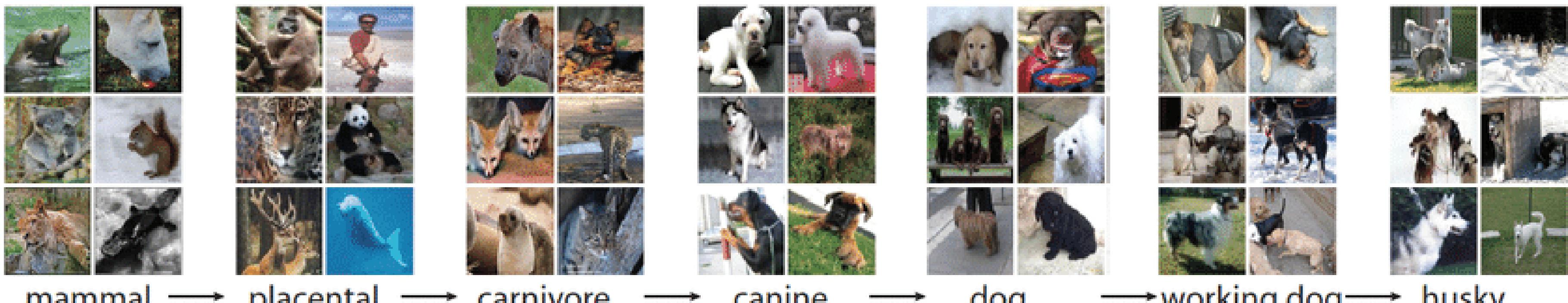
LeNet



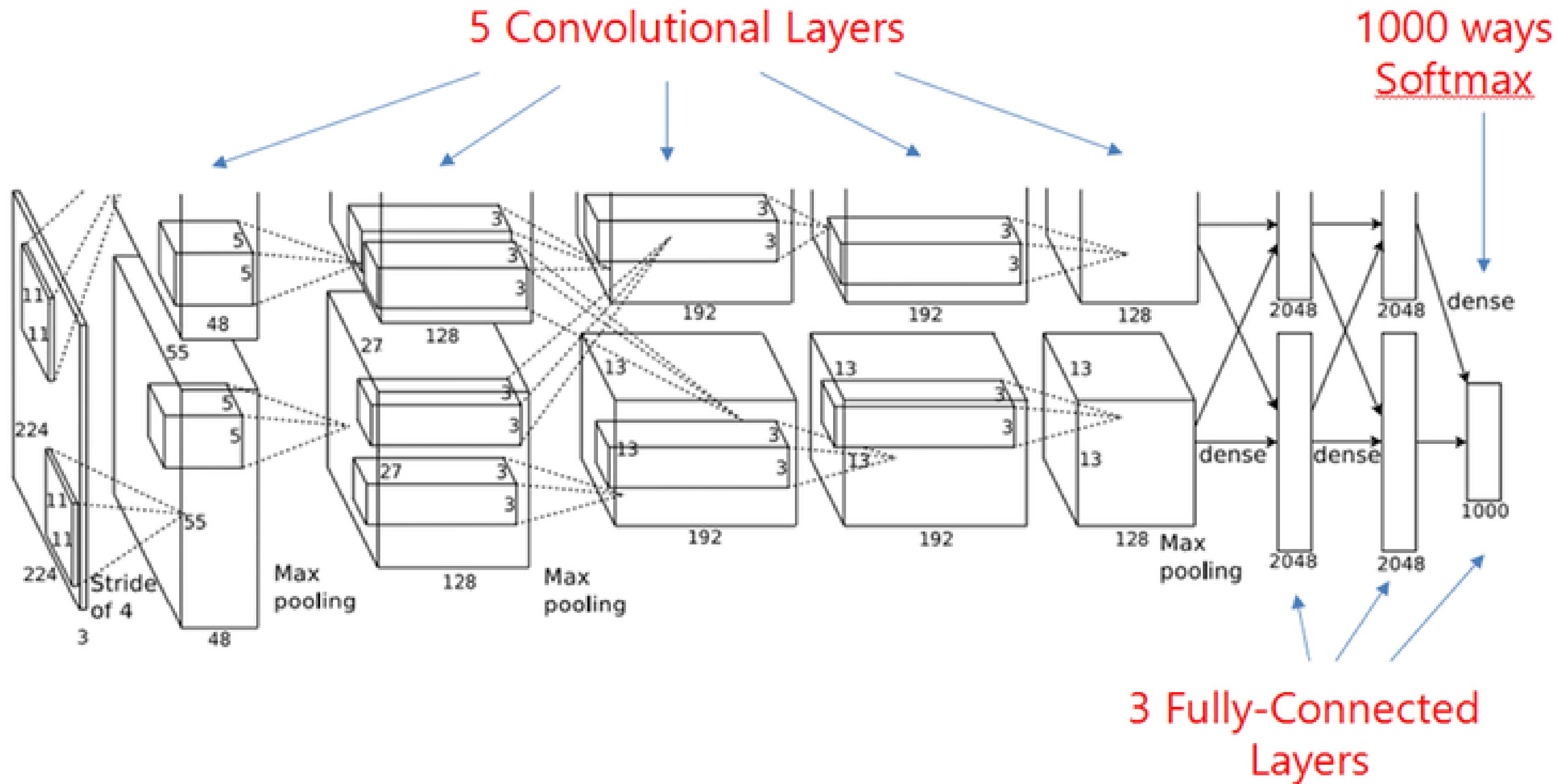
- **1998: LeNet** (AT&T labs) was one of the first CNN able to learn from raw data using backpropagation.
- It has two convolutional layers, two **mean**-pooling layers, two fully-connected layers and an output layer.
- It uses tanh as the activation function and works on CPU only.
- Used for handwriting recognition (for example ZIP codes).

ImageNet object recognition challenge (image-net.org)

- The ImageNet challenge was a benchmark for computer vision algorithms, providing millions of annotated images for object recognition, detection and segmentation.
- 14 millions images (224x224), 1000 classes.

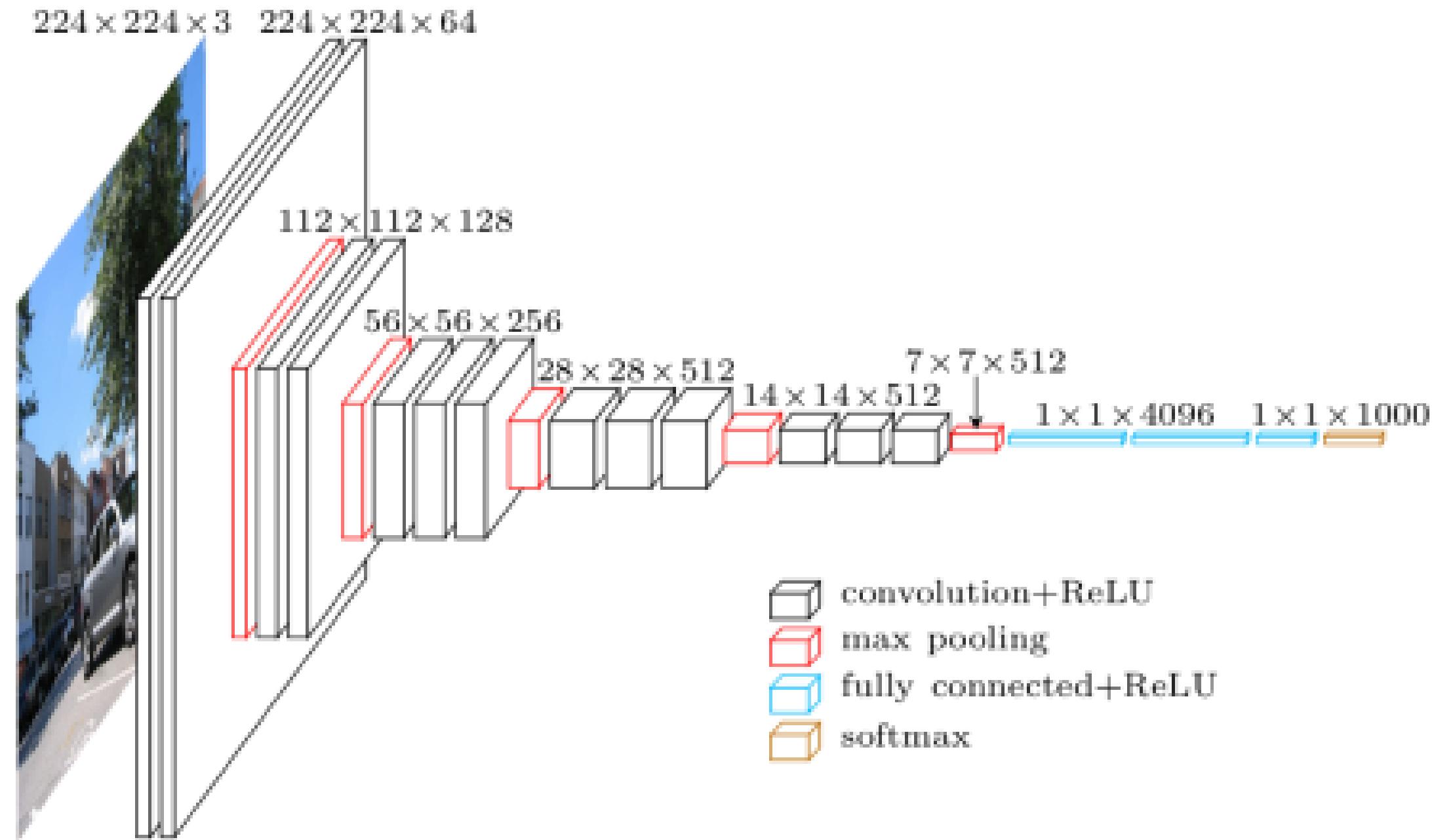


AlexNet

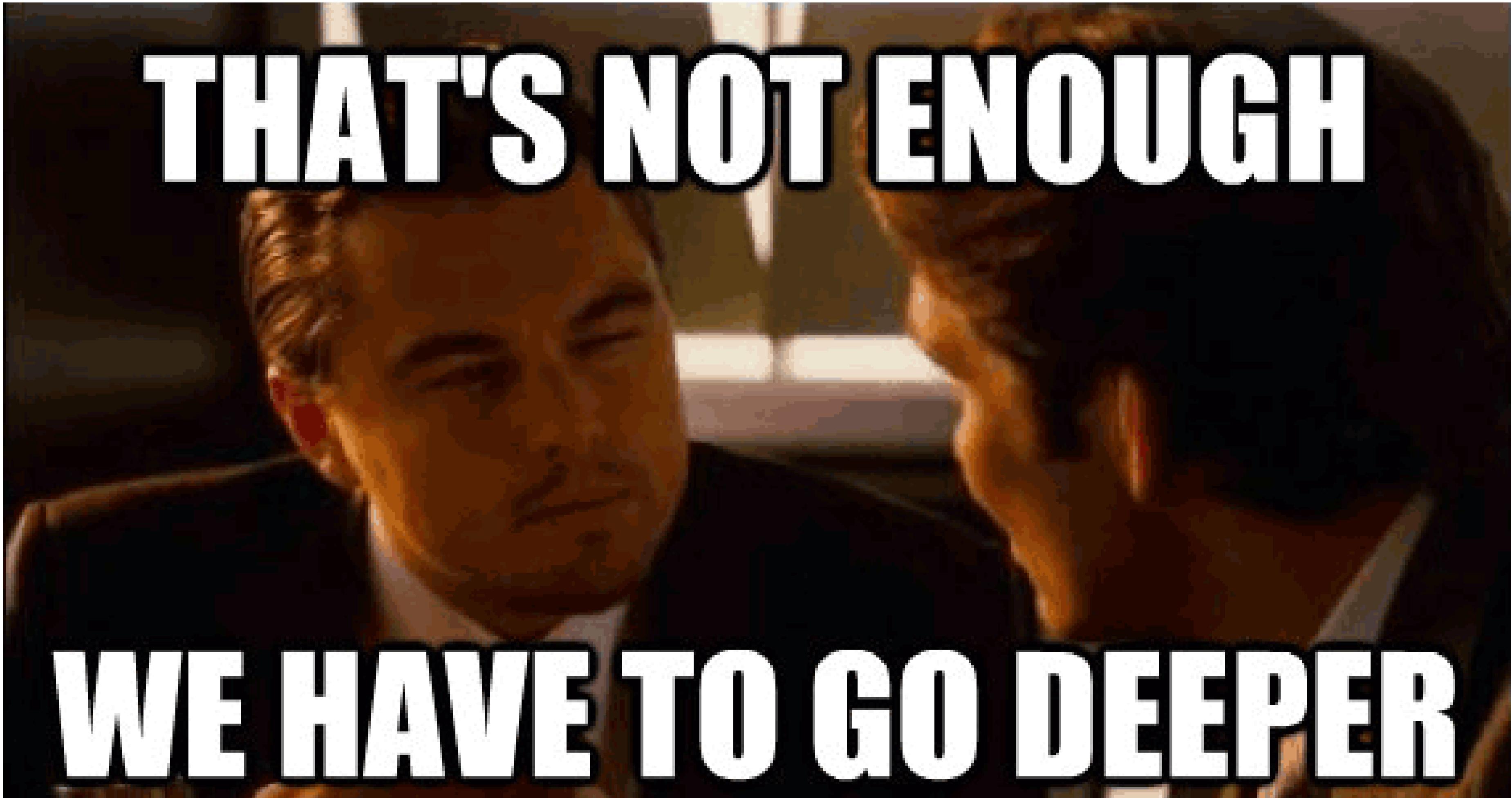


- **2012:** **AlexNet** (Toronto University) started the DL revolution by winning ImageNet 2012.
- Similar architecture to LeNet, but trained on two GPUs using augmented data.
- Uses ReLU, max-pooling, dropout, SGD with momentum, L2 regularization.

VGG-16



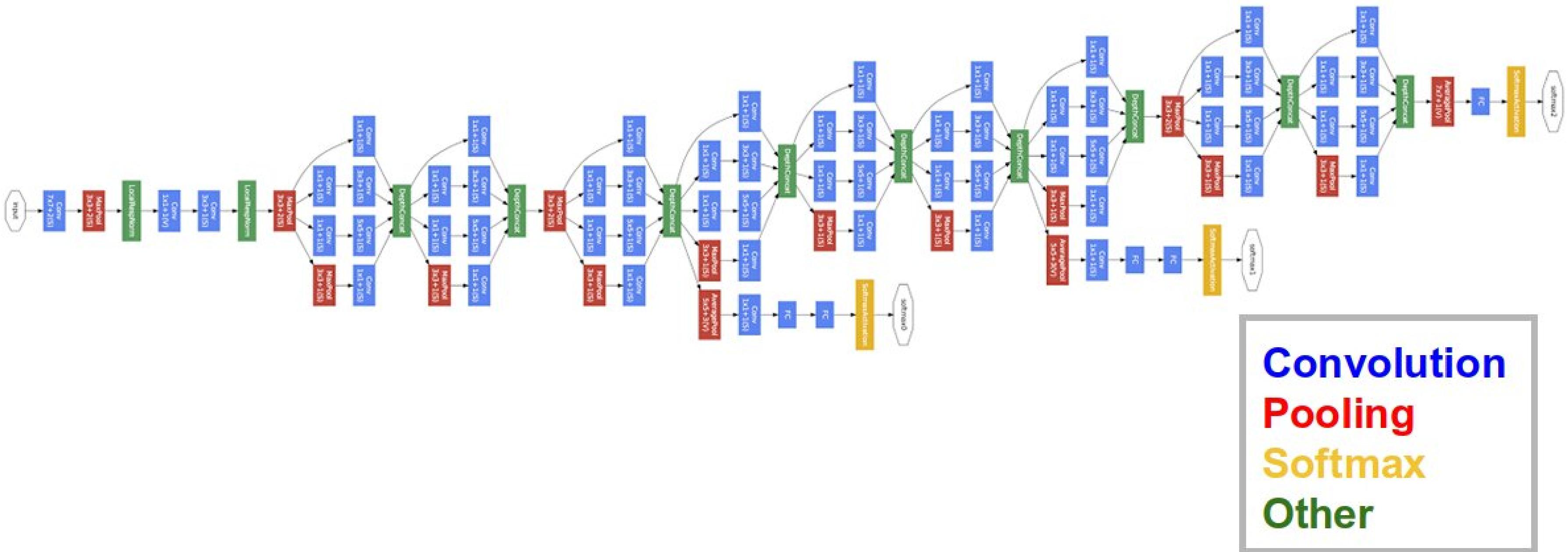
- **2014: VGG-16** (Visual Geometry Group, Oxford) placed second at ImageNet 2014.
- It went much deeper than AlexNet with 16 parameterized layers (a VGG-19 version is also available with 19 layers).
- Its main novelty is that two convolutions are made successively before the max-pooling, implicitly increasing the receptive field (2 consecutive 3×3 filters cover 5×5 pixels).
- Drawback: 140M parameters (mostly from the last convolutional layer to the first fully connected) quickly fill up the memory of the GPU.



THAT'S NOT ENOUGH

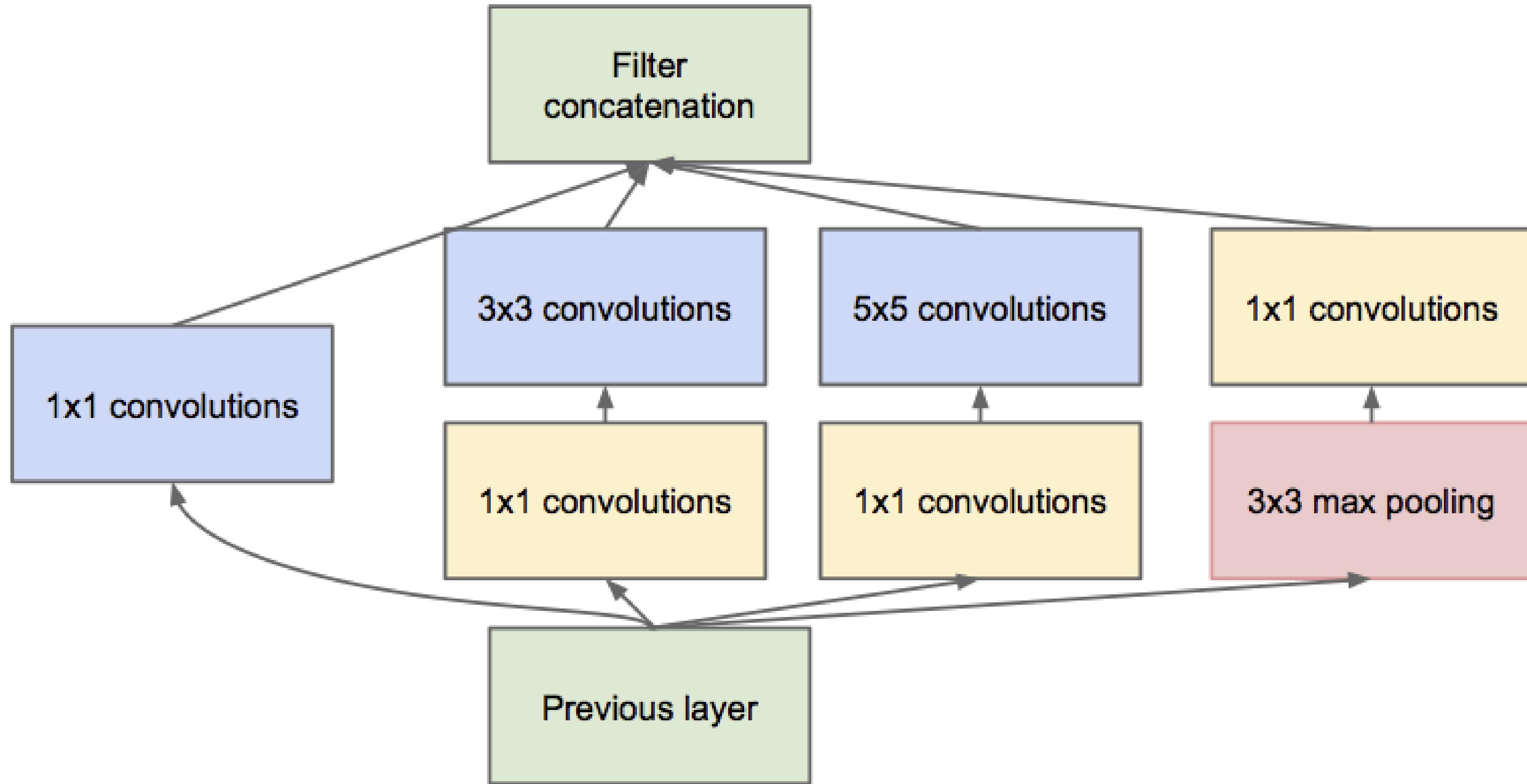
WE HAVE TO GO DEEPER

GoogLeNet - Inception v1



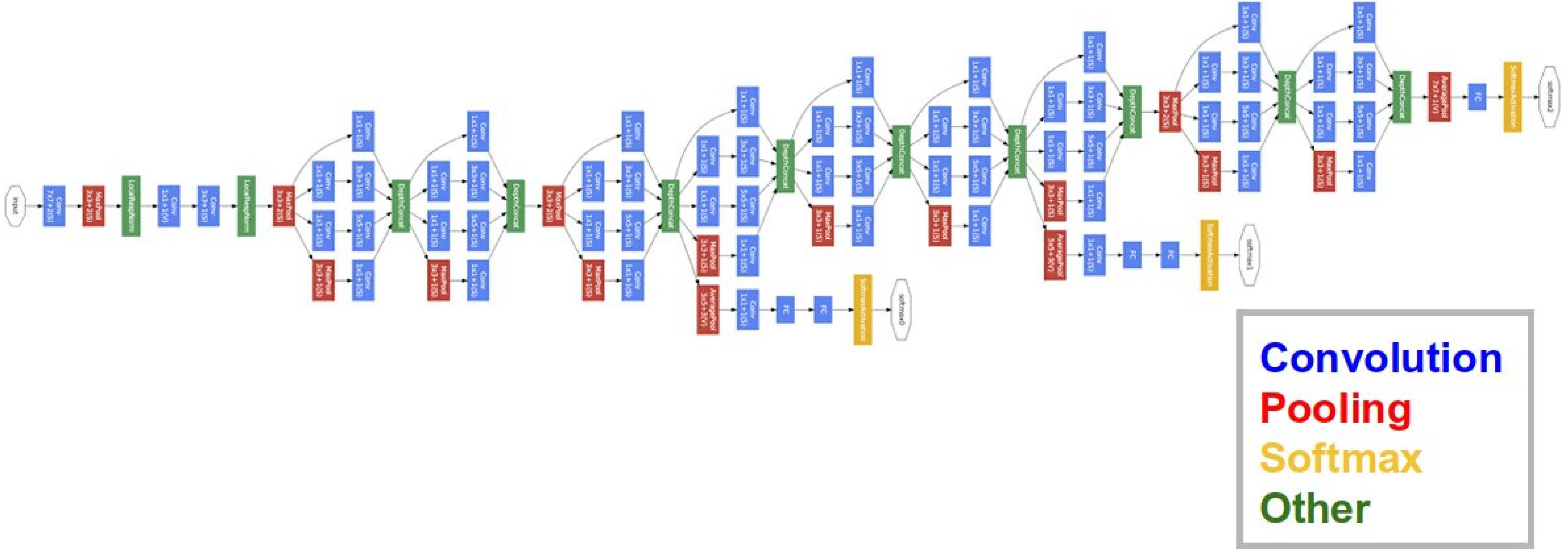
- **2014: GoogLeNet** (Google Brain) used Inception modules (Network-in-Network) to further complexify each stage.
- Won ImageNet 2014 with 22 layers. Dropout, SGD with Nesterov momentum.

Inception module



- Inside GoogleNet, each **Inception** module learns features at different resolutions using convolutions and max poolings of different sizes.
- 1x1 convolutions are **shared MLPs**: they transform a (w, h, d_1) tensor into (w, h, d_2) pixel per pixel.
- The resulting feature maps are concatenated along the feature dimension and passed to the next module.

GoogLeNet - Inception v1

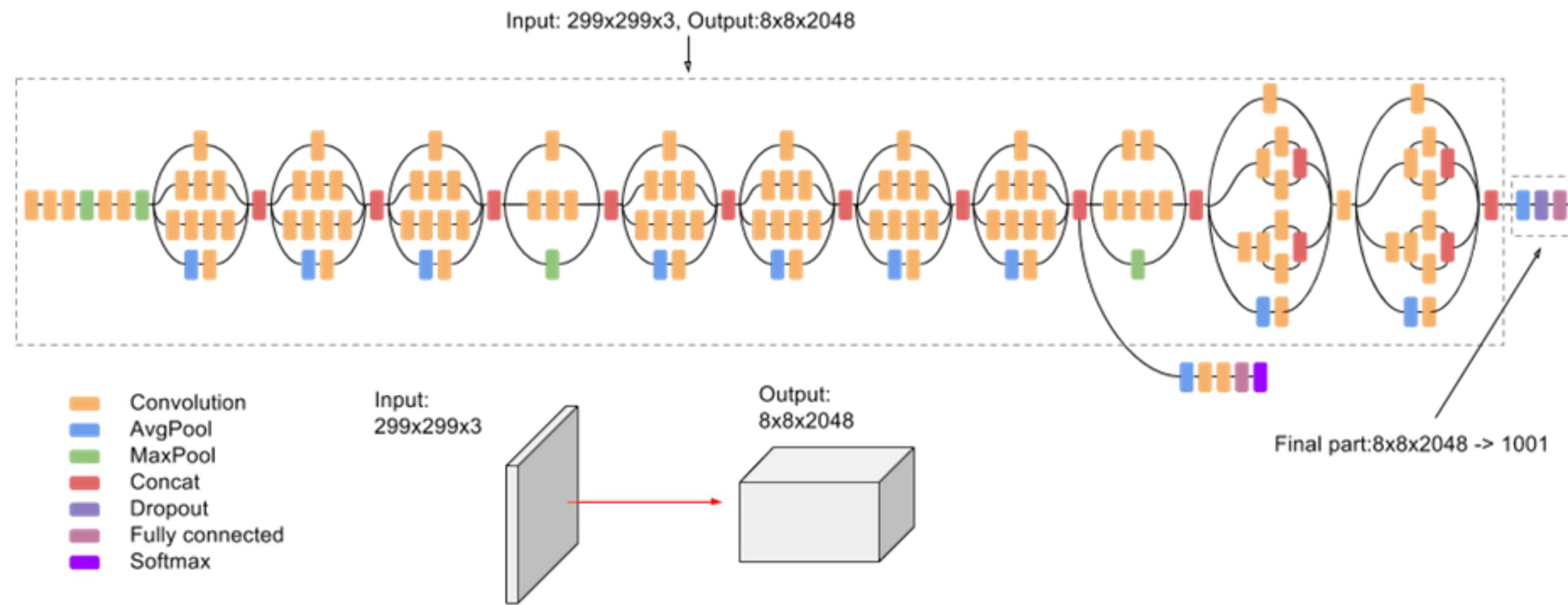


- Three softmax layers predict the classes at different levels of the network. Combined loss:

$$\mathcal{L}(\theta) = \mathbb{E}_{\mathcal{D}}[-\mathbf{t} \log \mathbf{y}_1 - \mathbf{t} \log \mathbf{y}_2 - \mathbf{t} \log \mathbf{y}_3]$$

- Only the deeper softmax layer matters for the prediction.
- The additional losses improve convergence by fight vanishing gradients: the early layers get useful gradients from the lower softmax layers.

Inception networks



Source: <https://cloud.google.com/tpu/docs/inception-v3-advanced>

- Several variants of GoogleNet have been later proposed: Inception v2, v3, InceptionResNet, Xception...
- Xception has currently the best top-1 accuracy on ImageNet: 126 layers, 22M parameters (88 MB).
- Pretrained weights are available in [keras](#):

```
1 tf.keras.applications.Xception(include_top=True, weights="imagenet")
```



References

Szegedy C, Vanhoucke V, Ioffe S, Shlens J, Wojna Z. (2015). Rethinking the Inception Architecture for Computer Vision. arXiv:151200567.

Chollet F. (2017). Xception: Deep Learning with Depthwise Separable Convolutions. arXiv:161002357.

Residual networks : ResNets

Residual networks : ResNets

- Skip connections help overcome the **vanishing gradients** problem, as the contribution of bypassed layers to the backpropagated gradient is 1.

$$\mathbf{h}_n = f_W(\mathbf{h}_{n-1}) + \mathbf{h}_{n-1}$$

$$\frac{\partial \mathbf{h}_n}{\partial \mathbf{h}_{n-1}} = \frac{\partial f_W(\mathbf{h}_{n-1})}{\partial \mathbf{h}_{n-1}} + 1$$

- The norm of the gradient stays roughly around one, limiting vanishing.
- Skip connections can bypass whole blocks of layers.
- ResNet can have many layers without vanishing gradients.
The most popular variants are:
 - ResNet-50.
 - ResNet-101.
 - ResNet-152.
- It was the first network to make an heavy use of **batch normalization**.

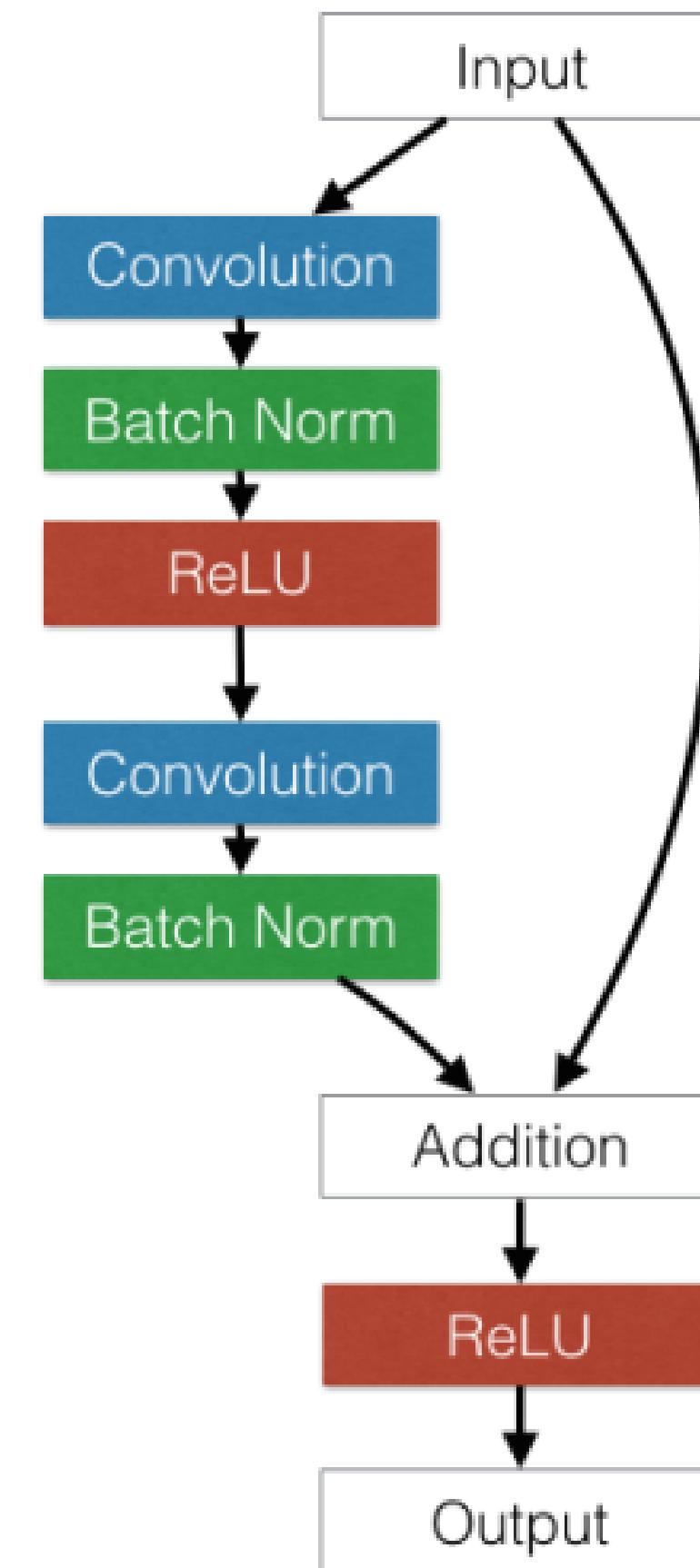


Figure 1. A RestNet basic block

HighNets: Highway networks

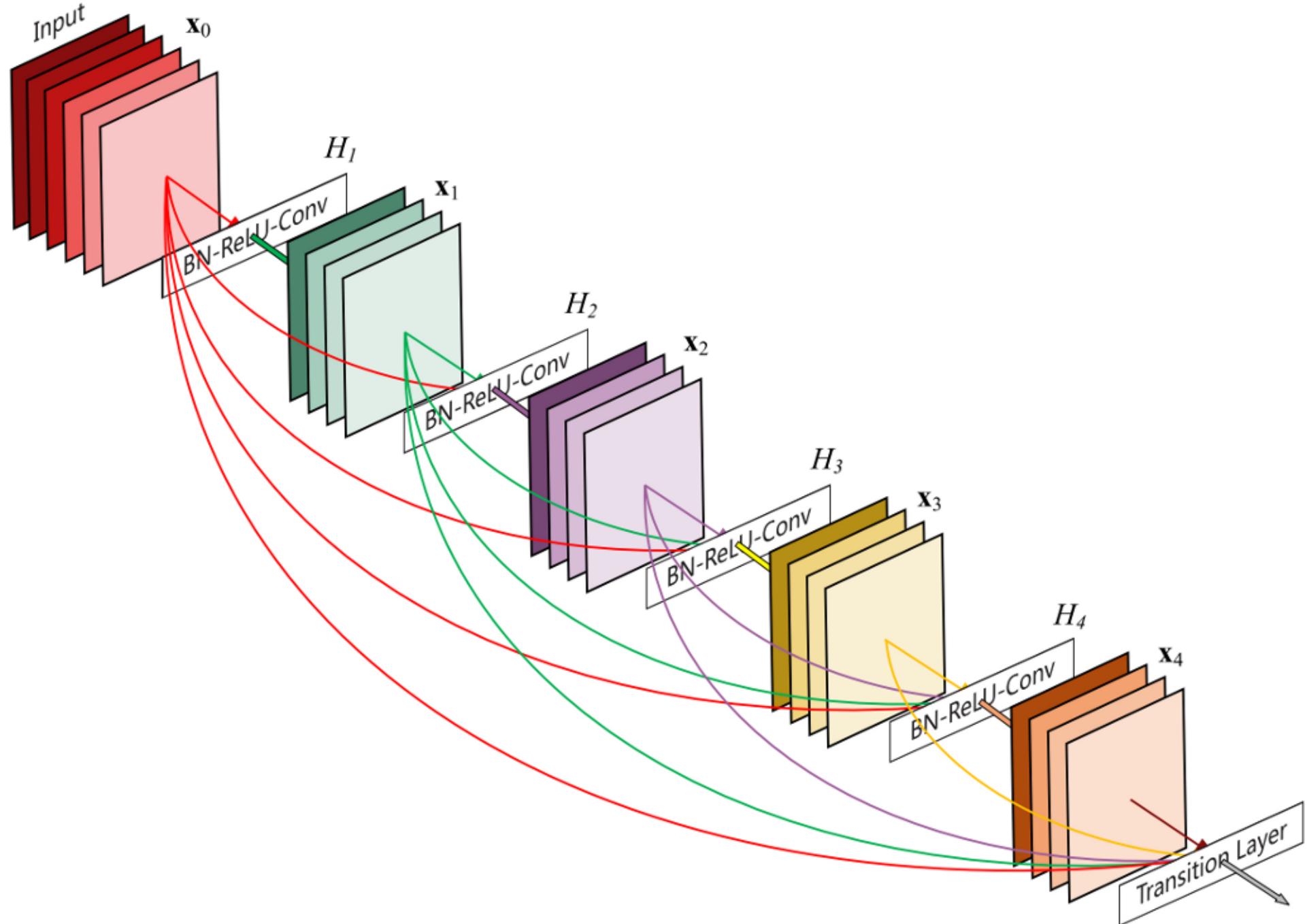


- **Highway networks** (IDSIA) are residual networks which also learn to balance inputs with feature extraction:

$$\mathbf{h}_n = T_{W'} f_W(h_{n-1}) + (1 - T_{W'}) h_{n-1}$$

- The balance between the **primary** pathway and the **skip** pathway adapts to the task.
- Has been used up to 1000 layers.
- Improved state-of-the-art accuracy on MNIST and CIFAR-10.

DenseNets: Dense networks



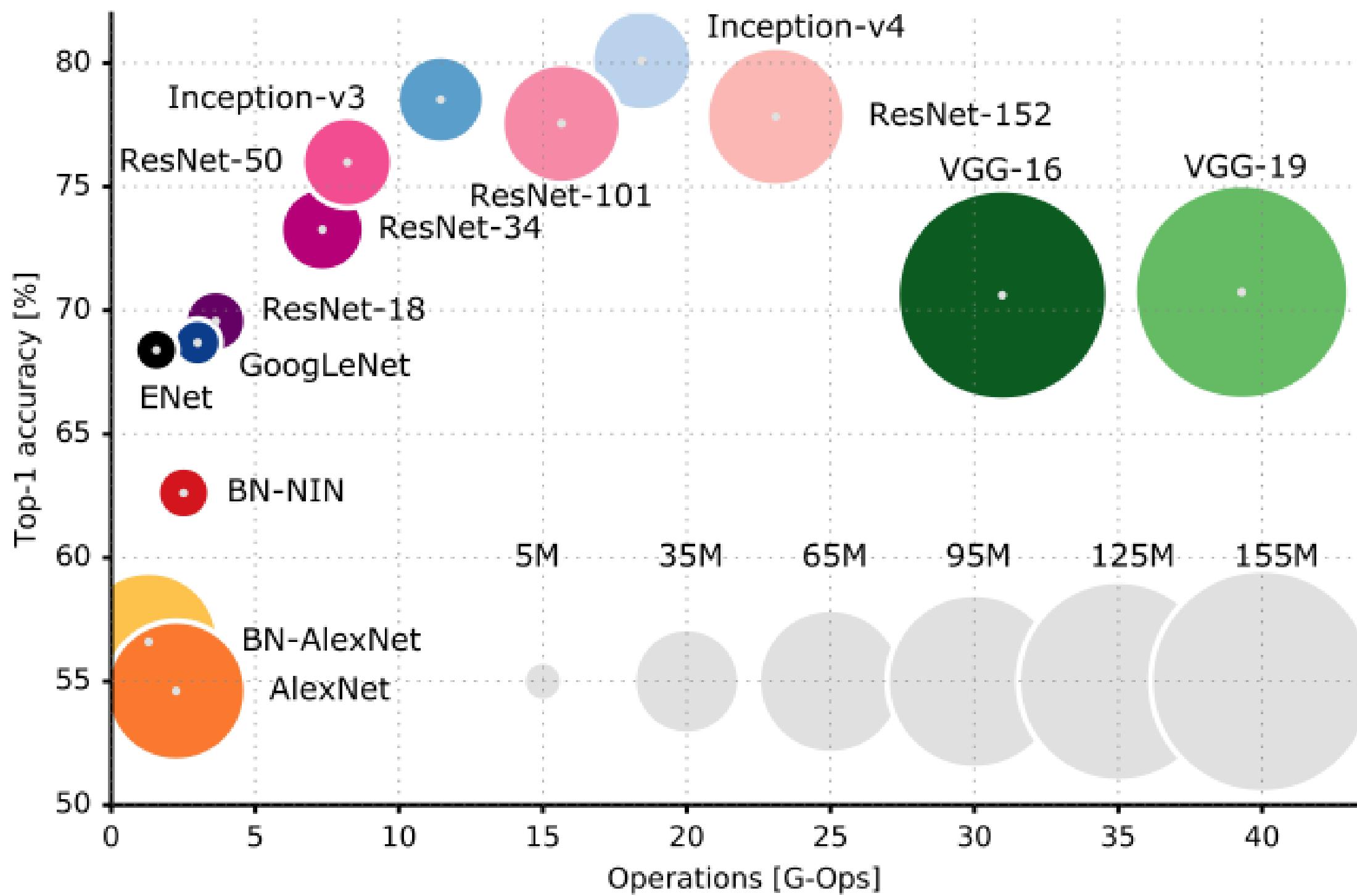
- **Dense networks** (Cornell University & Facebook AI) are residual networks that can learn **bypasses** between any layer of the network (up to 5).
- 100 layers altogether.
- Improved state-of-the-art accuracy on five major benchmarks.

Model zoos

- These famous models are described in their respective papers, you could reimplement them and train them on ImageNet.
 - Fortunately, their code is often released on Github by the authors or reimplemented by others.
 - Most frameworks maintain **model zoos** of the most popular networks.
 - Some models also have **pretrained weights** available, mostly on ImageNet.
 - Very useful for **transfer learning** (see later).
- Overview website:
<https://modelzoo.co>
 - Caffe:
<https://github.com/BVLC/caffe/wiki/Model-Zoo>
 - Tensorflow:
<https://github.com/tensorflow/models>
 - Pytorch:
<https://pytorch.org/docs/stable/torchvision/models.html>
 - Papers with code:
<https://paperswithcode.com/>

Comparison of the most popular networks

- Several criteria have to be considered when choosing an architecture:
 - Accuracy on ImageNet.
 - Number of parameters (RAM consumption).
 - Speed (flops).



Source: <https://dataconomy.com/2017/04/history-neural-networks>

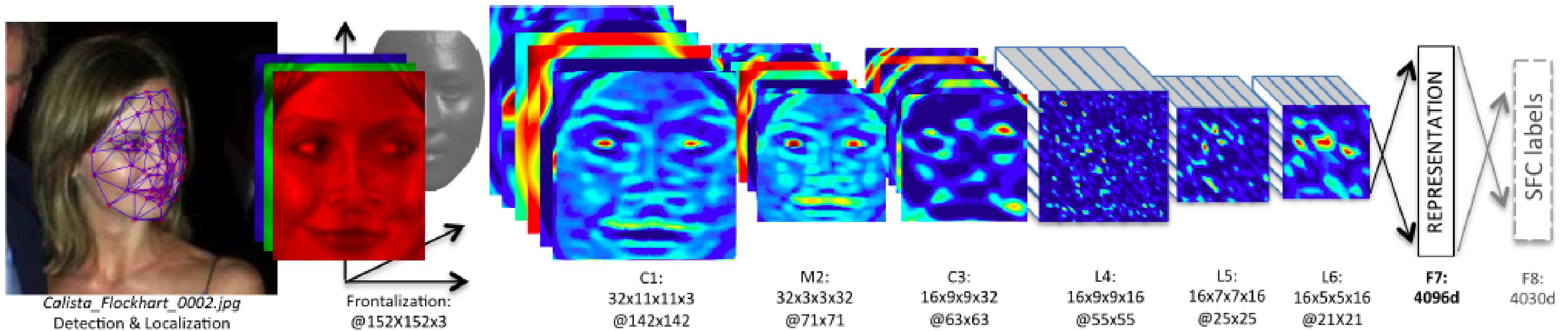
3 - Applications

Object recognition



- **Object recognition** has become very easy, each image is associated to a label.
- With huge datasets like **ImageNet** (14 millions images), a CNN can learn to recognize 1000 classes of objects with a better accuracy than humans.
- Just get enough examples of an object and it can be recognized.

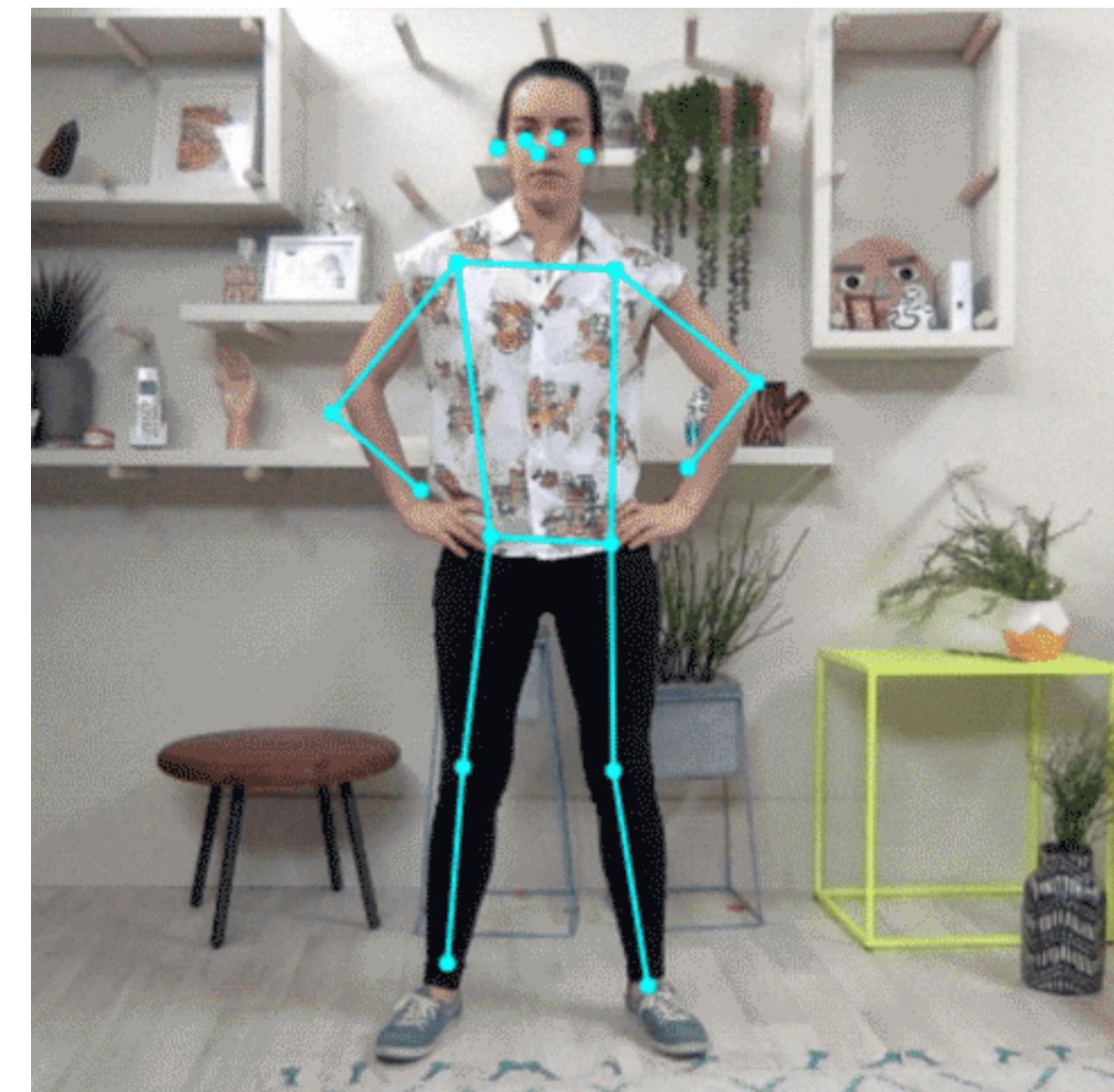
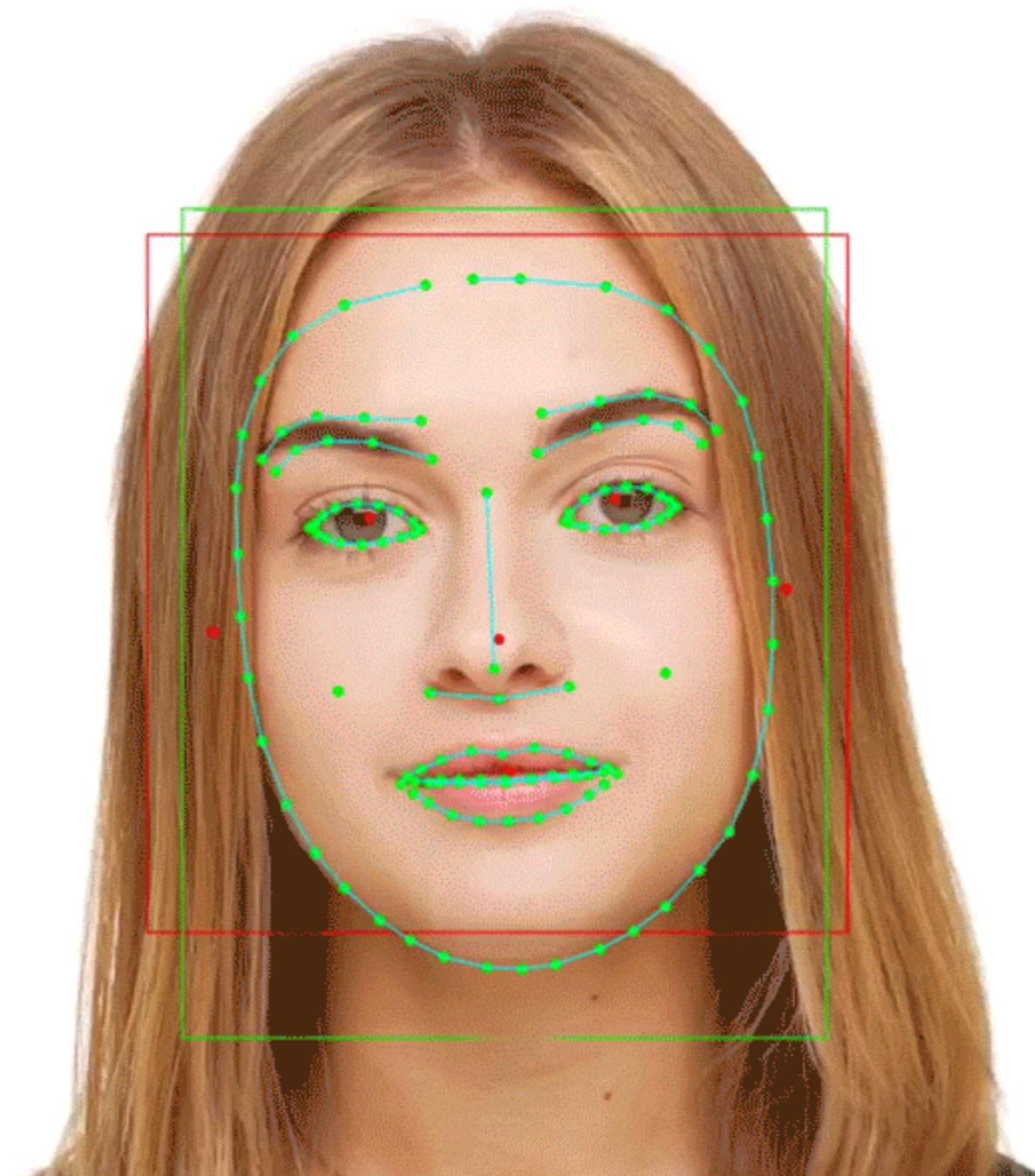
Facial recognition



- Facebook used 4.4 million annotated faces from 4030 users to train **DeepFace**.
- Accuracy of 97.35% for recognizing faces, on par with humans.
- Used now to recognize new faces from single examples (transfer learning, one-shot learning).

Pose estimation

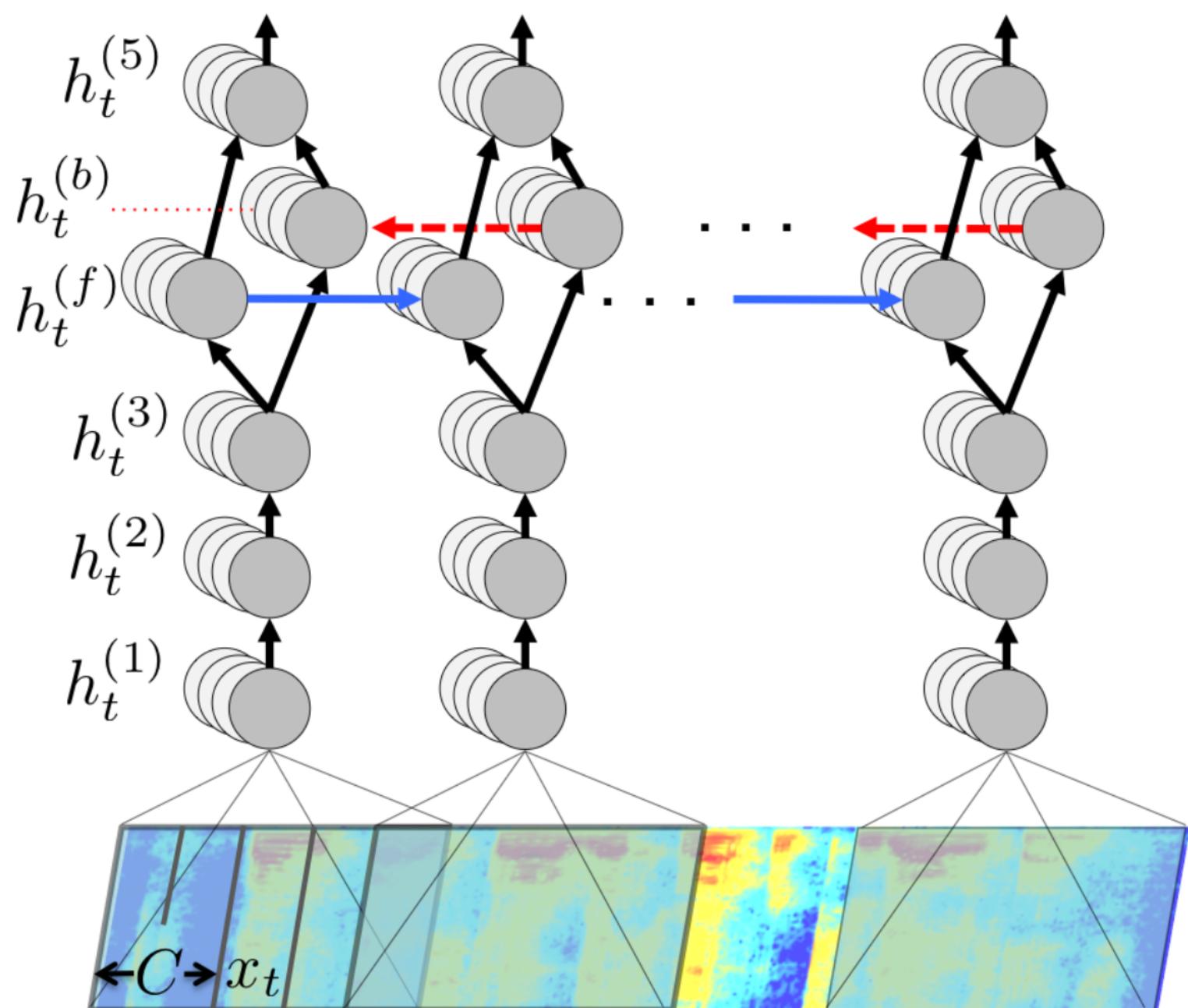
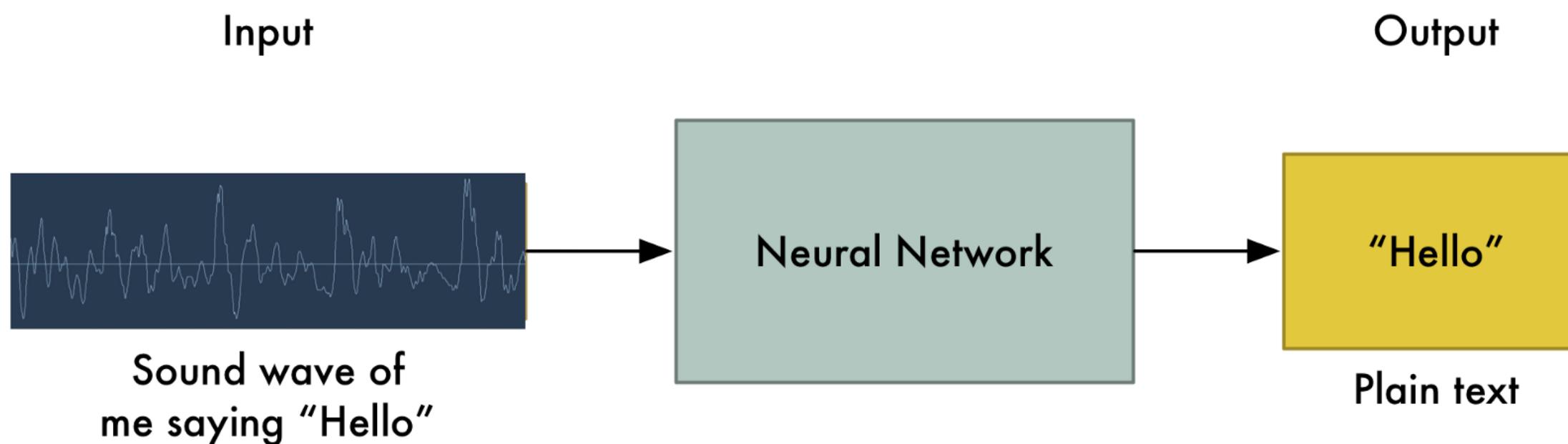
- **PoseNet** is a Inception-based CNN able to predict 3D information from 2D images.
- It can be for example the calibration matrix of a camera, 3D coordinates of joints or facial features.
- There is a free tensorflow.js implementation that can be used in the browser.



Source: https://www.tensorflow.org/lite/models/pose_estimation/overview

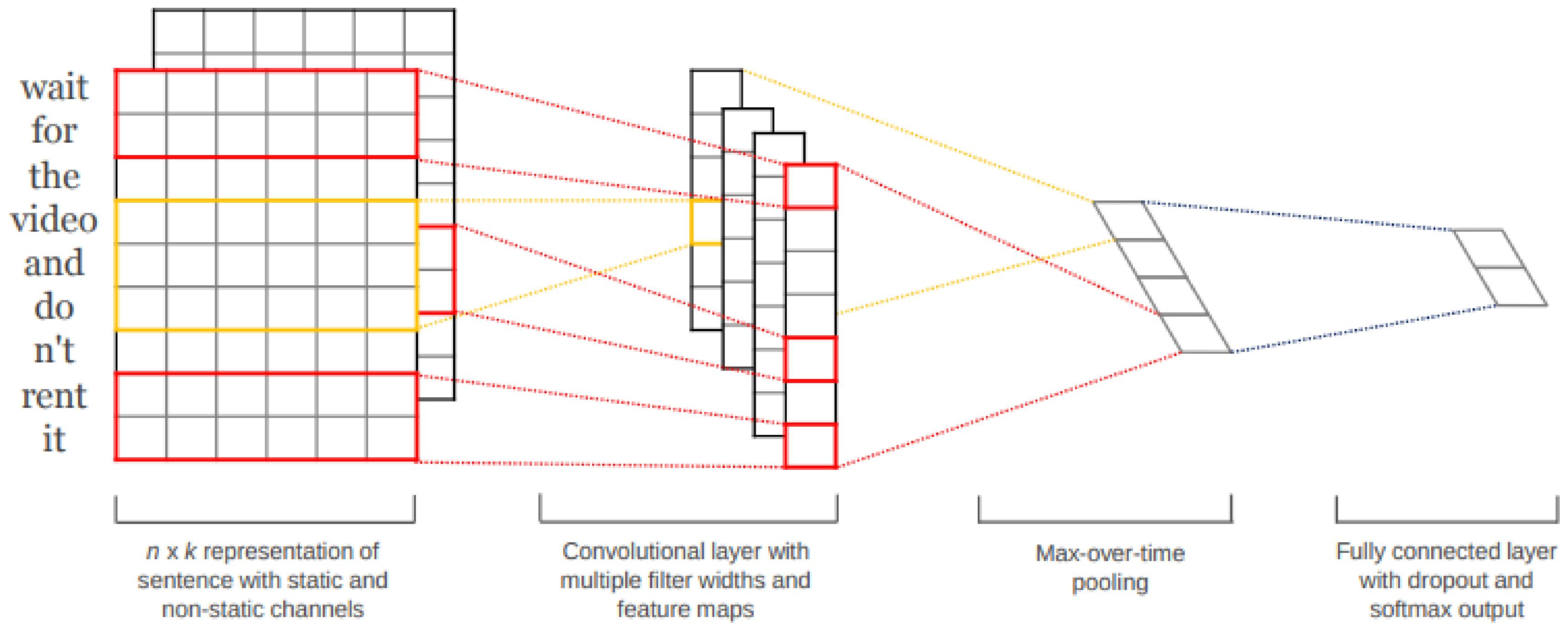
Source: <https://blog.tensorflow.org/2019/01/tensorflow-lite-now-faster-with-mobile.html>

Speech recognition



- To perform speech recognition, one could treat speech signals like images: one direction is time, the other are frequencies (e.g. mel spectrum).
- A CNN can learn to associate phonemes to the corresponding signal.
- **DeepSpeech** from Baidu is one of the state-of-the-art approaches.
- Convolutional networks can be used on any signals where early features are local.
- It uses additionally recurrent networks, which we will see later.

Sentiment analysis

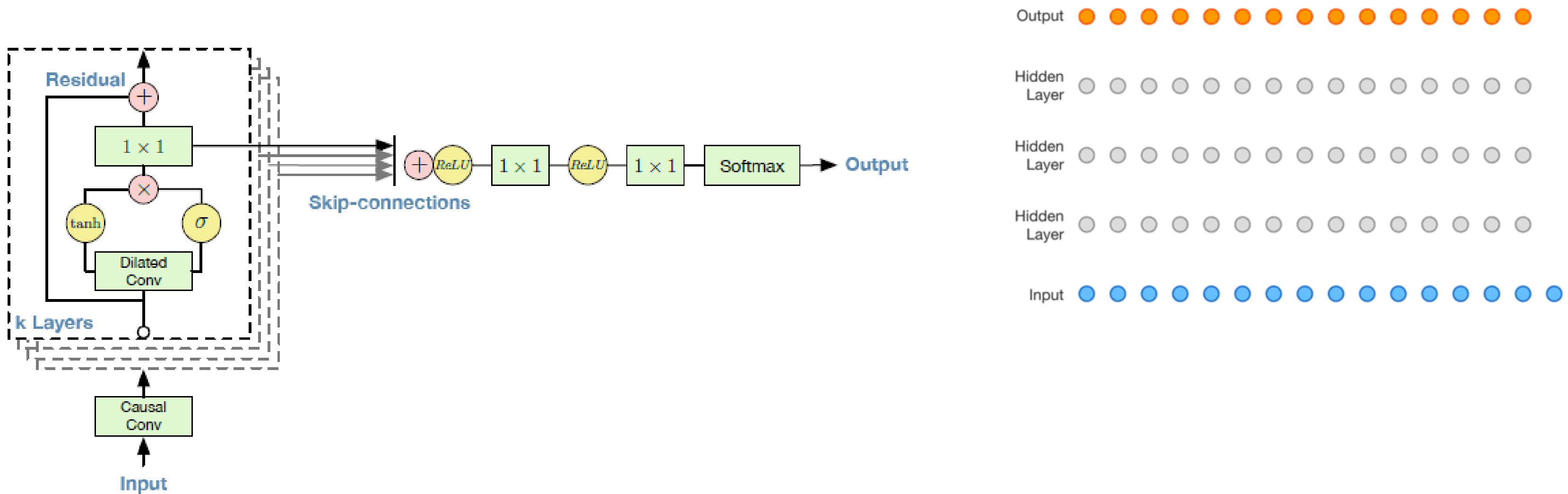


- It is also possible to apply convolutions on text.
- **Sentiment analysis** assigns a positive or negative judgment to sentences.
- Each word is represented by a vector of values (word2vec).
- The convolutional layer can slide over all words to find out the sentiment of the sentence.

Wavenet : text-to-speech synthesis



- **Text-To-Speech (TTS)** is also possible using CNNs.
- Google Home relies on **Wavenet**, a complex CNN using *dilated convolutions* to grasp long-term dependencies.

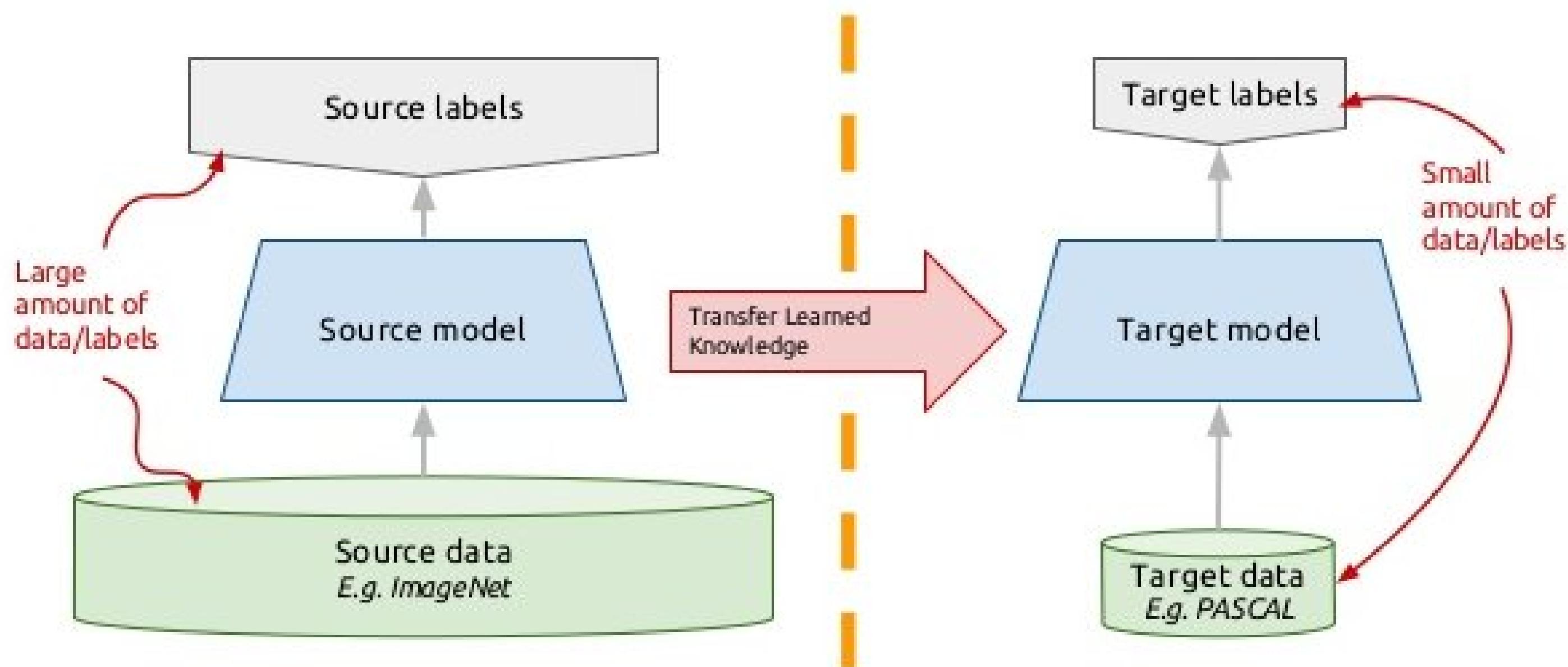


Source: <https://deepmind.com/blog/wavenet-generative-model-raw-audio/>

4 - Transfer learning

Transfer learning / Domain adaptation

- **Myth:** ones needs at least one million labeled examples to use deep learning.
- This is true if you train the CNN **end-to-end** with randomly initialized weights.
- But there are alternatives:
 1. **Unsupervised learning** (autoencoders) may help extract useful representations using only images.
 2. **Transfer learning** allows to re-use weights obtained from a related task/domain.



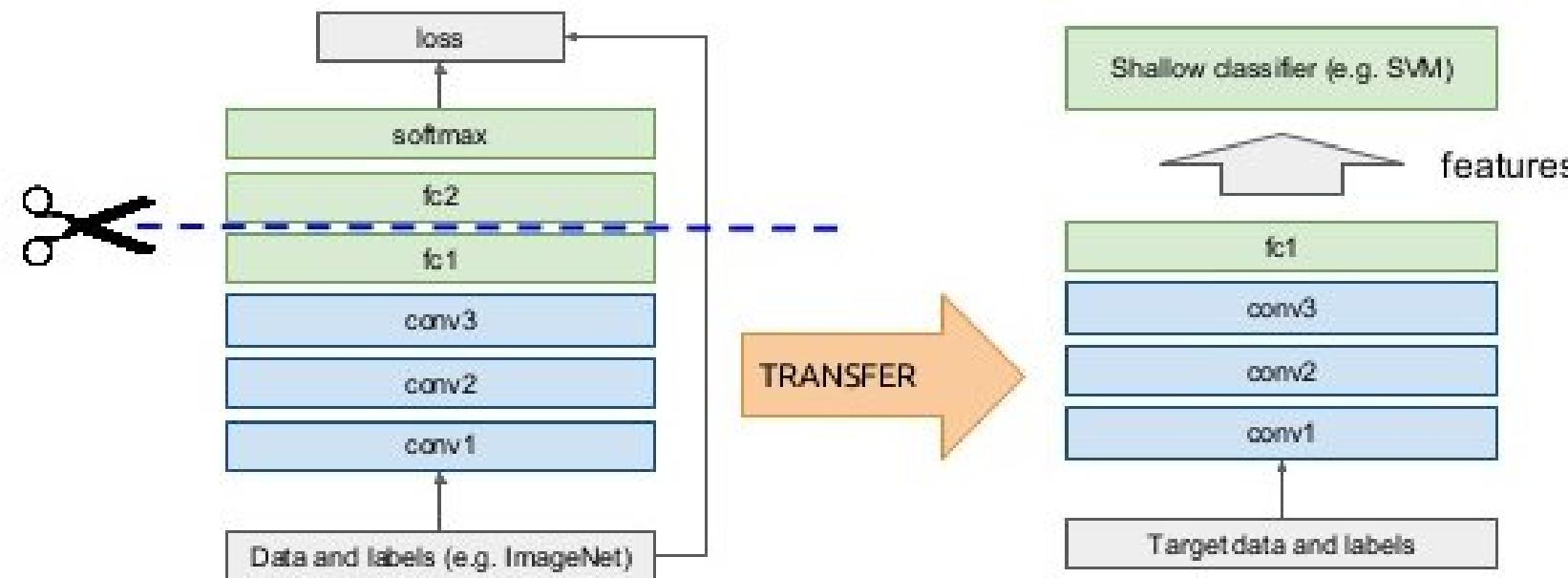
Source: <http://imatge-upc.github.io/telecombcn-2016-dlcv>

Transfer learning / Domain adaptation

- Take a classical network (VGG-16, Inception, ResNet, etc.) trained on ImageNet (if your task is object recognition).

Off-the-shelf

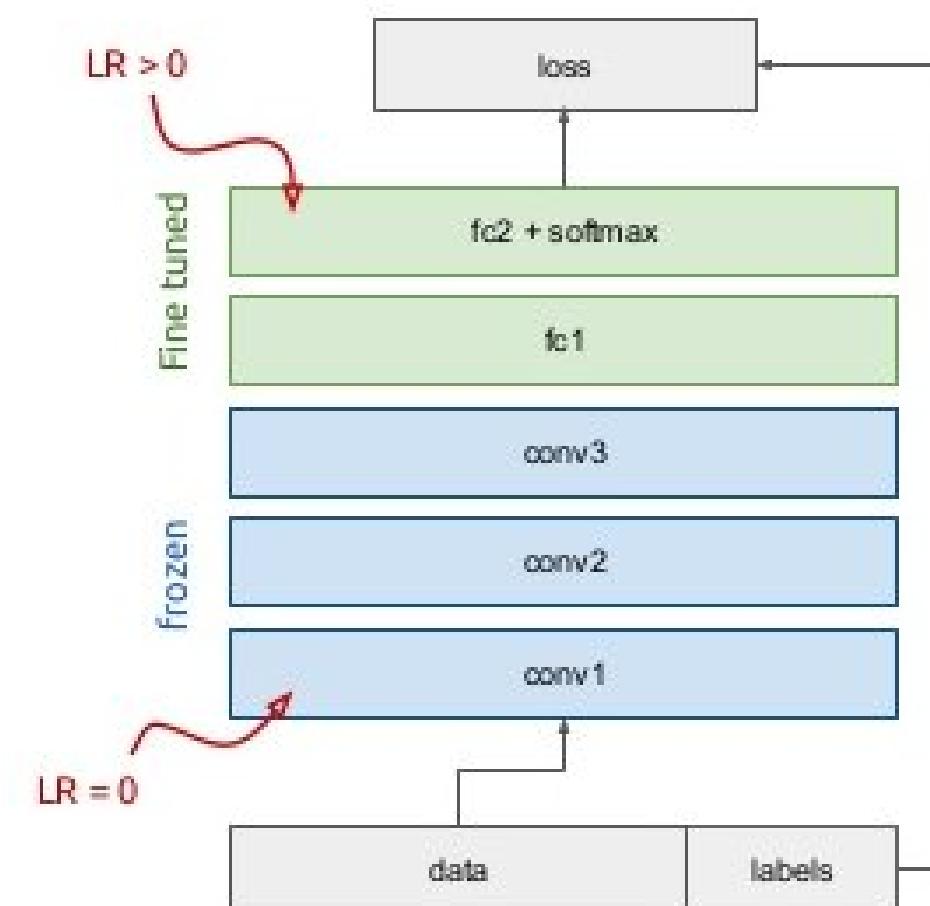
- Cut the network before the last layer and use directly the high-level feature representation.
- Use a shallow classifier directly on these representations (not obligatorily NN).



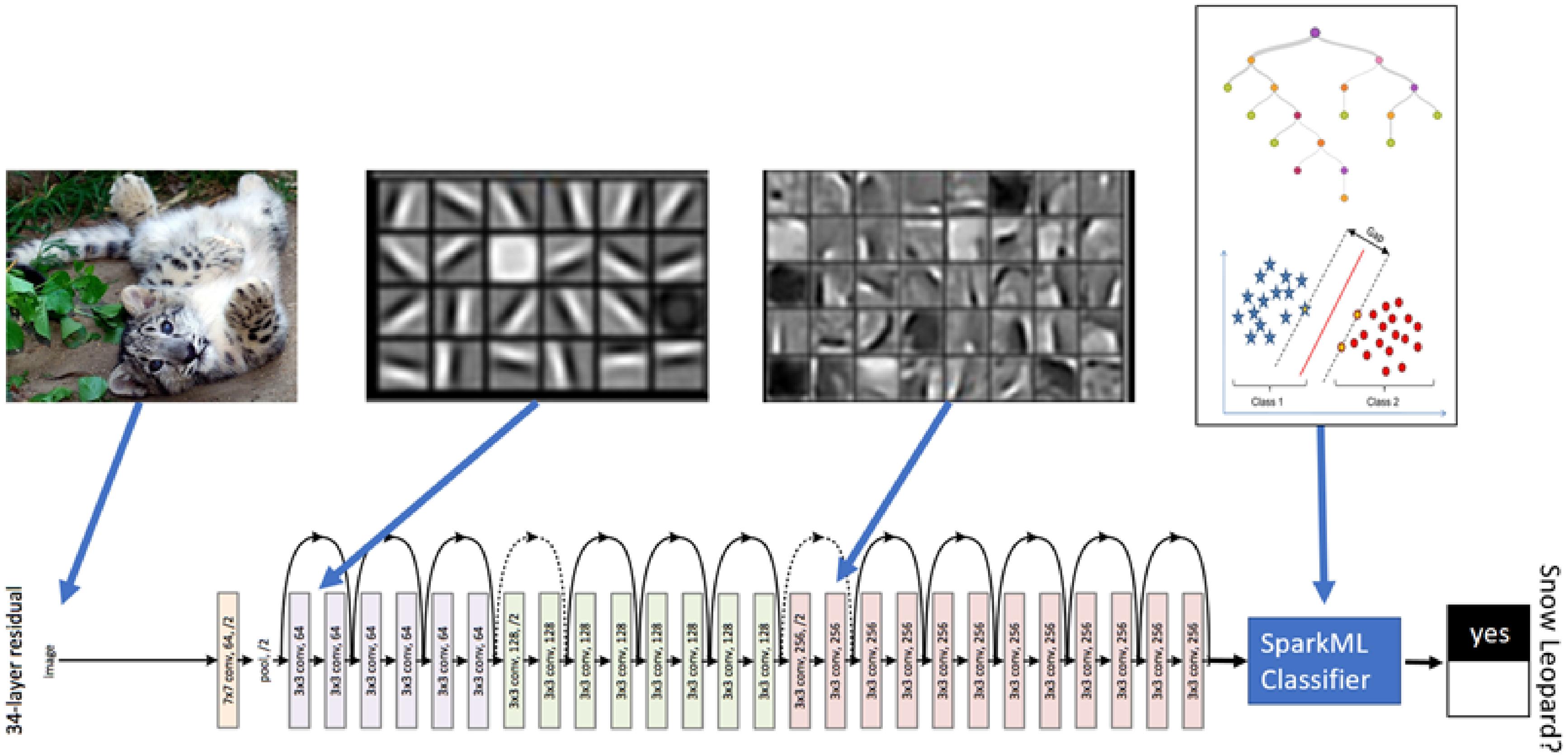
Source: <http://imatge-upc.github.io/telecombcn-2016-dlcv>

Fine-tuning

- Use the trained weights as initial weight values and re-train the network on your data (often only the last layers, the early ones are frozen).



Example of transfer learning

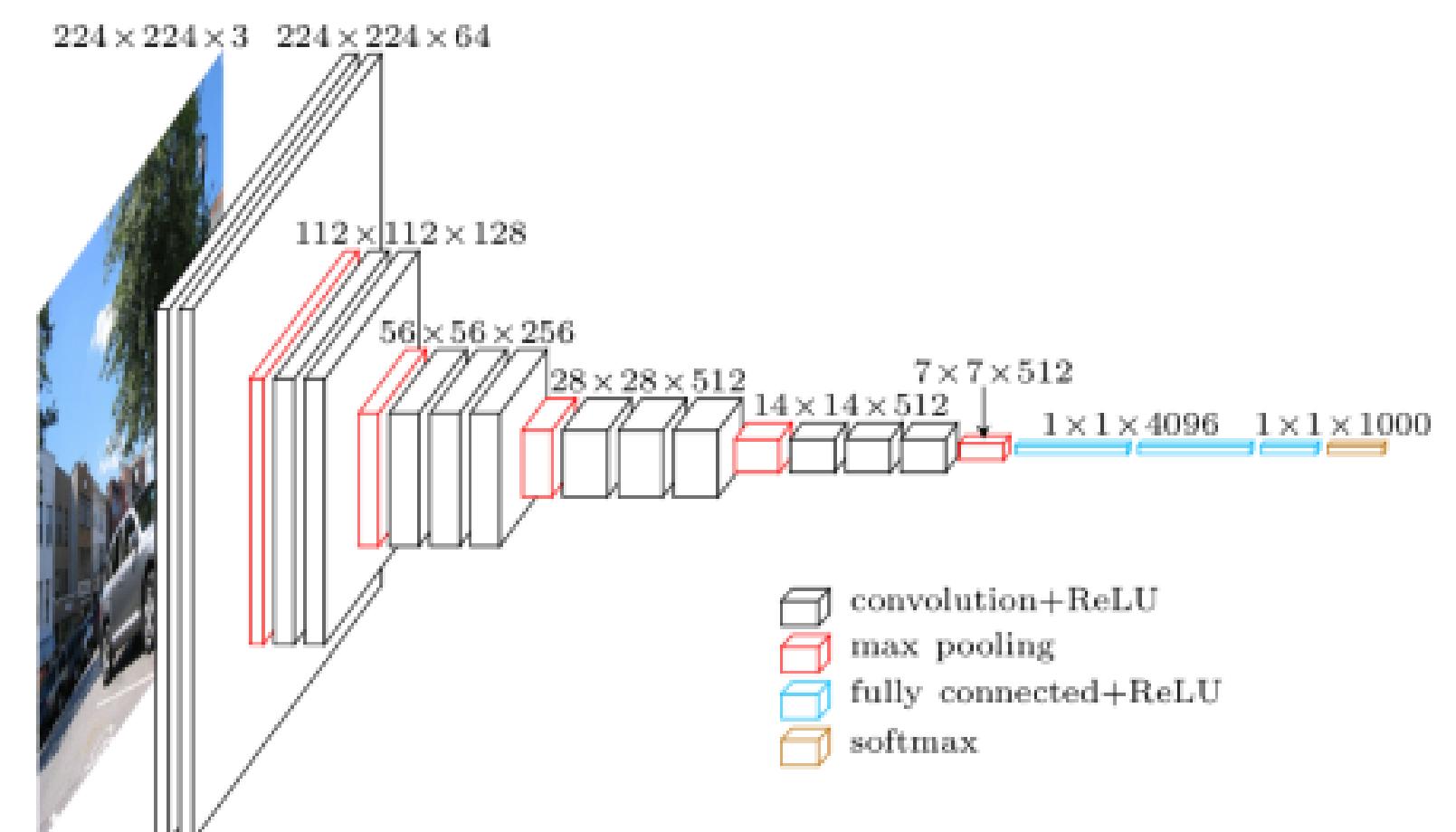


- Microsoft wanted a system to automatically detect **snow leopards** into the wild, but there were not enough labelled images to train a deep network **end-to-end**.
- They used a pretrained **ResNet50** as a feature extractor for a simple **logistic regression** classifier.

Transfer learning in keras

- Keras provides pre-trained CNNs that can be used as feature extractors:

```
1 from tf.keras.applications.vgg16 import VGG16
2
3 # Download VGG without the FC layers
4 model = VGG16(include_top=False,
5                 input_shape=(300, 300, 3))
6
7 # Freeze learning in VGG16
8 for layer in model.layers:
9     layer.trainable = False
10
11 # Add a fresh MLP on top
12 flat1 = Flatten()(model.layers[-1].output)
13 class1 = Dense(1024, activation='relu')(flat1)
14 output = Dense(10, activation='softmax')(class1)
15
16 # New model
17 model = Model(
18     inputs=model.inputs, outputs=output)
```



- See <https://keras.io/api/applications/> for the full list of pretrained networks.

5 - Ensemble learning

ImageNet recognition challenge: object recognition

- Since 2016, only ensembles of existing networks win the competitions.

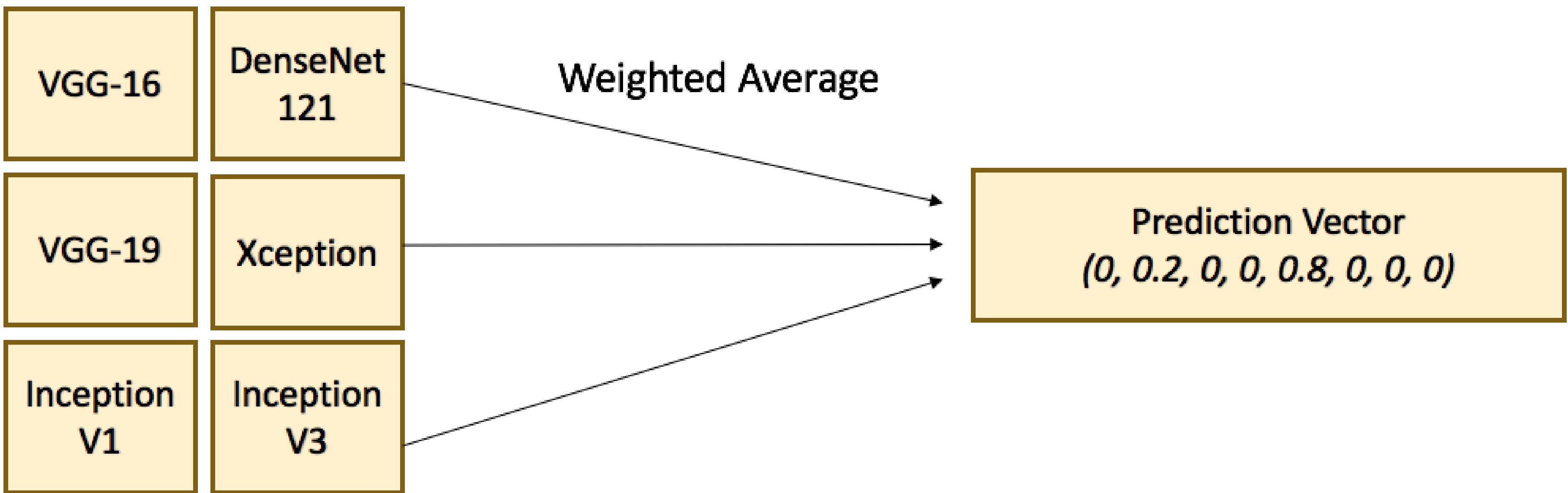
Object detection (DET)^[top]

Task 1a: Object detection with provided training data

Ordered by number of categories won

Team name	Entry description	Number of object categories won	mean AP
CUIimage	Ensemble of 6 models using provided data	109	0.662751
Hikvision	Ensemble A of 3 RPN and 6 FRCN models, mAP is 67 on val2	30	0.652704
Hikvision	Ensemble B of 3 RPN and 5 FRCN models, mean AP is 66.9, median AP is 69.3 on val2	18	0.652003
NUIST	submission_1	15	0.608752
NUIST	submission_2	9	0.607124
Trimps-Soushen	Ensemble 2	8	0.61816
360+MCG-ICT-CAS_DET	9 models ensemble with validation and 2 iterations	4	0.615561
360+MCG-ICT-CAS_DET	Baseline: Faster R-CNN with Res200	4	0.590596
Hikvision	Best single model, mAP is 65.1 on val2	2	0.634003
CIL	Ensemble of 2 Models	1	0.553542
360+MCG-ICT-CAS_DET	9 models ensemble	0	0.613045
360+MCG-ICT-CAS_DET	3 models	0	0.605708

Ensemble of networks



Source <https://flyyufelix.github.io/2017/04/16/kaggle-nature-conservancy.html>

- **Ensemble learning** is the process of combining multiple independent classifiers together, in order to obtain a better performance.
- As long the individual classifiers do not make mistakes for the same examples, a simple majority vote might be enough to get better approximations.

Ensemble learning

- Let's consider we have three **independent** binary classifiers, each with an accuracy of 70% ($P = 0.7$ of being correct). When using a majority vote, we get the following cases:

- all three models are correct:

$$P = 0.7 * 0.7 * 0.7 = 0.3492$$

- two models are correct

$$P = (0.7 * 0.7 * 0.3) + (0.7 * 0.3 * 0.7) + (0.3 * 0.7 * 0.7) = 0.4409$$

- two models are wrong

$$P = (0.3 * 0.3 * 0.7) + (0.3 * 0.7 * 0.3) + (0.7 * 0.3 * 0.3) = 0.189$$

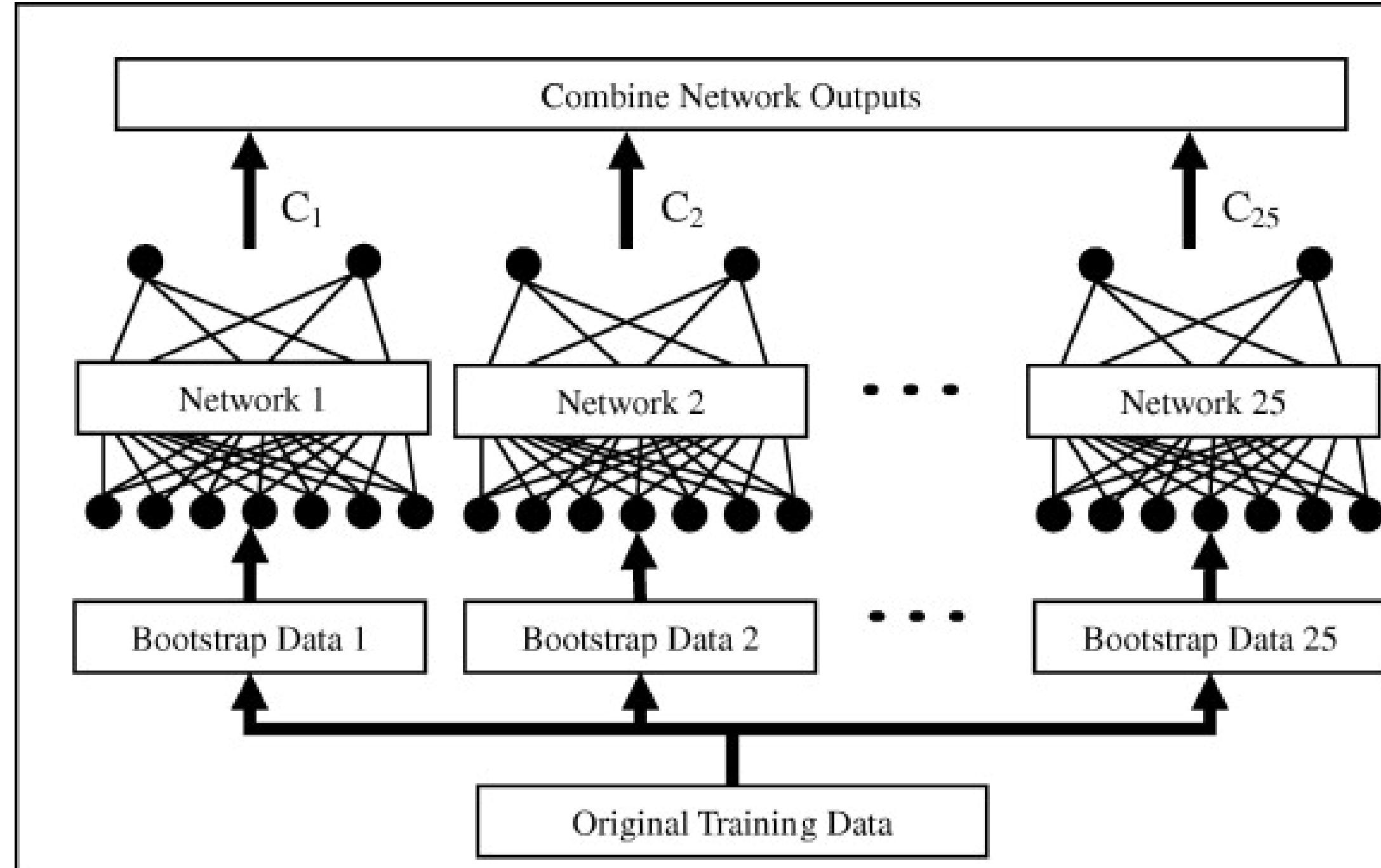
- all three models are wrong

$$P = 0.3 * 0.3 * 0.3 = 0.027$$

- The majority vote is correct with a probability of $P = 0.3492 + 0.4409 = \mathbf{0.78}$!
- The individual learners only have to be slightly better than chance, but they **must** be as independent as possible.

Ensemble learning: bagging

- Bagging methods (bootstrap aggregation) trains multiple classifiers on randomly sampled subsets of the data.

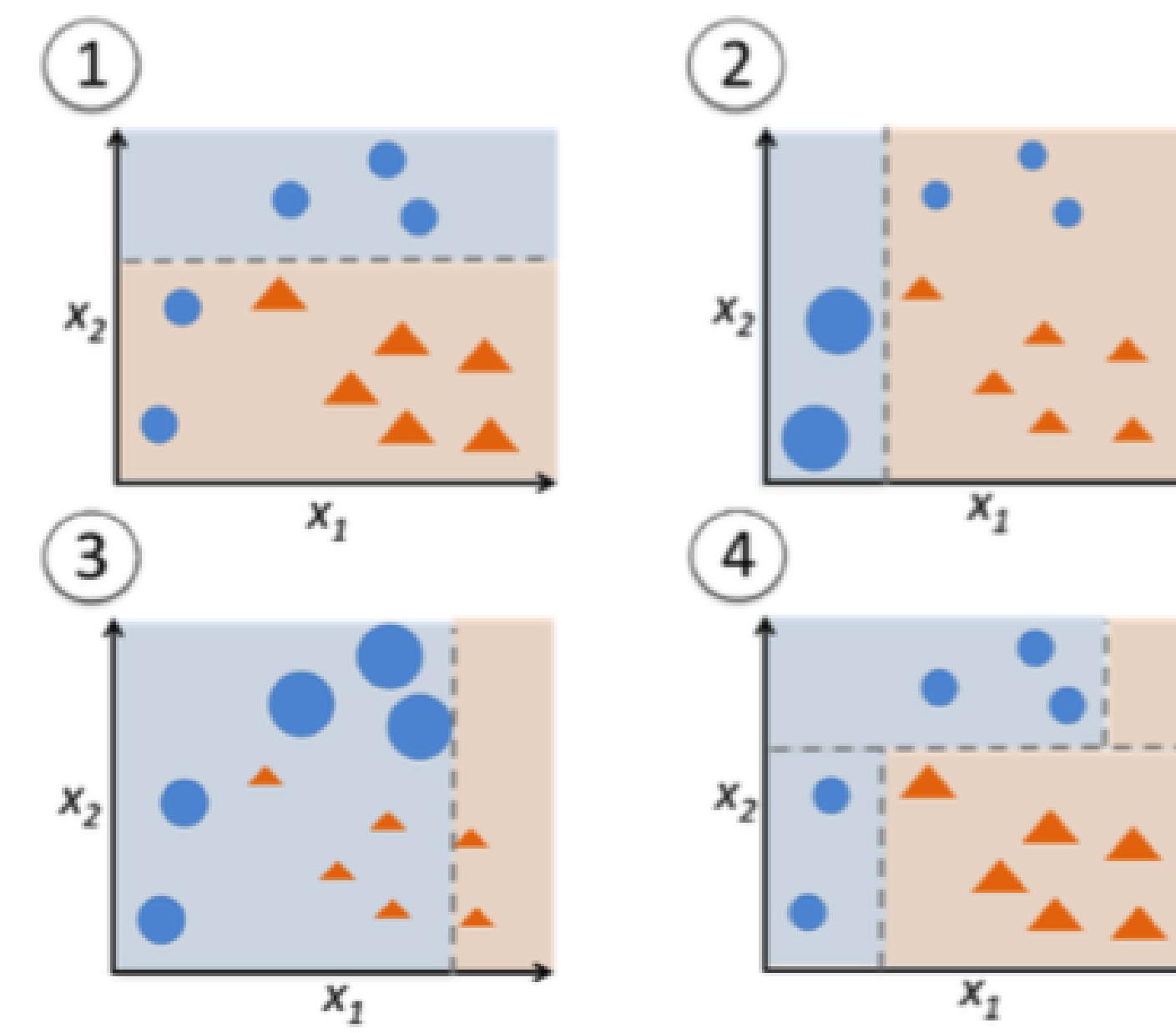


Source: <http://www.sciencedirect.com/science/article/pii/S0957417409008781>

- A **random forest** is a bagging method for decision trees, where the data and features are sampled..
- One can use majority vote, unweighted average, weighted average or even a meta-learner to form the final decision.

Ensemble learning: boosting

- **Bagging** algorithms aim to reduce the complexity of models that overfit the training data.
- **Boosting** is an approach to increase the complexity of models that suffer from high bias, that is, models that underfit the training data.
 - Algorithms: Adaboost, XGBoost (gradient boosting)...

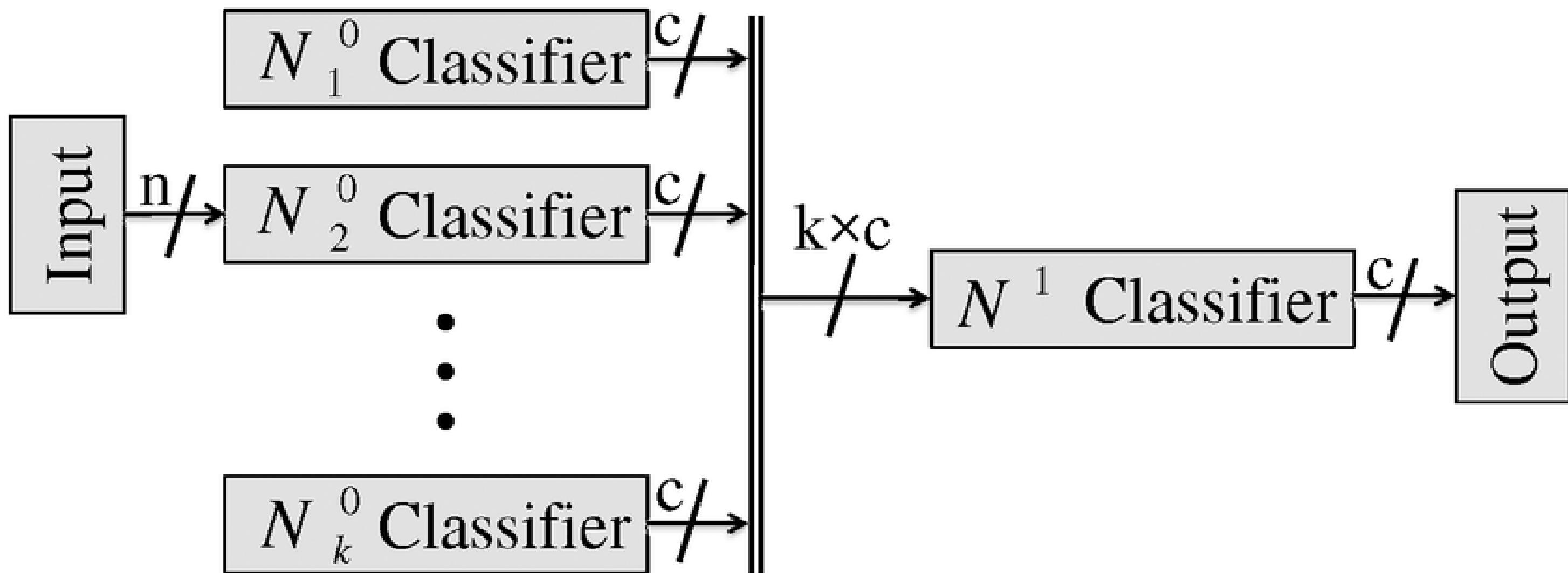


Source: <https://www.analyticsvidhya.com/blog/2015/11/quick-introduction-boosting-algorithms-machine-learning/>

- Not very useful with deep networks (overfitting), but there are some approaches like SelfieBoost (<https://arxiv.org/pdf/1411.3436.pdf>).

Ensemble learning: stacking

- **Stacking** is an ensemble learning technique that combines multiple models via a meta-classifier. The meta-model is trained on the outputs of the basic models as features.



Source: doi:10.1371/journal.pone.0024386.g005

- Winning approach of ImageNet 2016 and 2017.
- See <https://blog.statsbot.co/ensemble-learning-d1dcd548e936>