Pooling Pyramid Network for Object Detection

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Abstract

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1. Introduction

2. Related Work

Multibox [1] SSD [5] Faster-RCNN [8] YOLO [6] YOLO-v2 [7] FPN [3] Survey [2]

RetinaNet [4]

3. Pooling Pyramid Network (PPN)

Our proposed model, called *Pooling Pyramid Network* (*PPN*), is a single-stage convolutional object detector, that is designed to address several issues found in the original Single Shot Detector (SSD) [5]. The network architecture is illustrated in Figure 1. There are two major changes to the original SSD: (1) the box predictor is shared across feature maps with different scales; (2) the convolutions between feature maps are replaced with the max pooling operations. In the following sections, we will discuss the rationales behind them and effects of these changes.

3.1. Sharing Box Predictor

The original SSD uses separate box predictors for feature maps of different scales. While each box predictor is

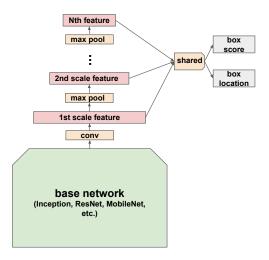


Figure 1. The Pooling Pyramid Network (PPN) architecture.

allocated to spend its full capacity on one specific scale, this design could be vulnerable in some practical situations. One

Because each box predictor only sees a portion of groundtruth boxes whose sizes corresponds to the predictor's scale, the predicted scores can be mis-calibrated across different predictors. corresponding to its own scale, the predicted scores can be mis-calibrated across different scales.

One biggest problem is mis-calibration across different box predictors

this could become this could also become less robust we have found this design may lead to several problems in practice.

focuses on one particular scales

While each box predictor focuses on one specific scales and spends full capacity specializing

In practice,

The original SSD uses separate box predictors for feature maps with different scales.

3.2. Max Pooling Pyramid

Our goal is to build a multi-scale feature pyramid structure, from which we make the predictions using the shared box predictor. We achieve this by shrinking down a base

feature map from the backbone network using a series of max pooling operations. This is different from SSD where feature maps are built by extracting layers from backbone network and shrinking them with additional convolutions, and FPN where feature maps are built by a top-down pathway with skip connections. We choose max pooling mainly for two reasons. Firstly, using the pooling operations ensures feature maps with different scales live in the same embedding space, which makes training the shared box predictor more effective. We choose max pooling over average pooling because average pooling would make the complete pooling process linear, which would lead to the fact that every predictions from the feature map with the smallest scale would have higher scores than predictions from feature maps of larger scales. Applying non-linear activation functions after pooling would be another solution to overcome this problem. Also, since max pooling does not has any convolution weight parameters as in SSD, nor any upsampling opeartions as in FPN, it is very fast for inference, making it suitable for many latency sensitive applications.

4. Experiments

4.1. Comparing with SSD and FPN

Performance on COCO detection
MobileNet-v1-SSD vs MobileNet-v1-PPN vs
MobileNet-v1-FPN
Model Size
Latency

5. Conclusion

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An analysis of the frobnicatable foo filter.

In this paper we present a performance analysis of the paper of Smith *et al.* [1], and show it to be inferior to all previously known methods. Why the previous paper was accepted without this analysis is beyond me.

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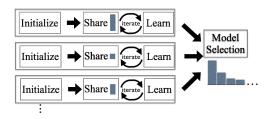


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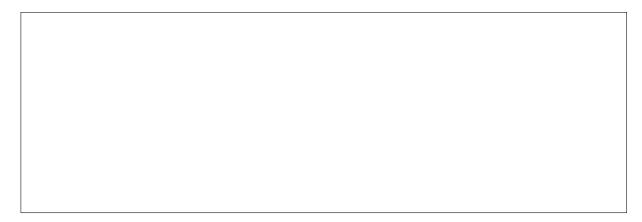


Figure 3. Example of a short caption, which should be centered.

Method	Frobnability
Theirs	Frumpy
Yours	Frobbly
Ours	Makes one's heart Frob

Table 1. Results. Ours is better.

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