CS7015 (Deep Learning) : Lecture 12

Object Detection: R-CNN, Fast R-CNN, Faster R-CNN, You Only Look Once (YOLO)

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Acknowledgements

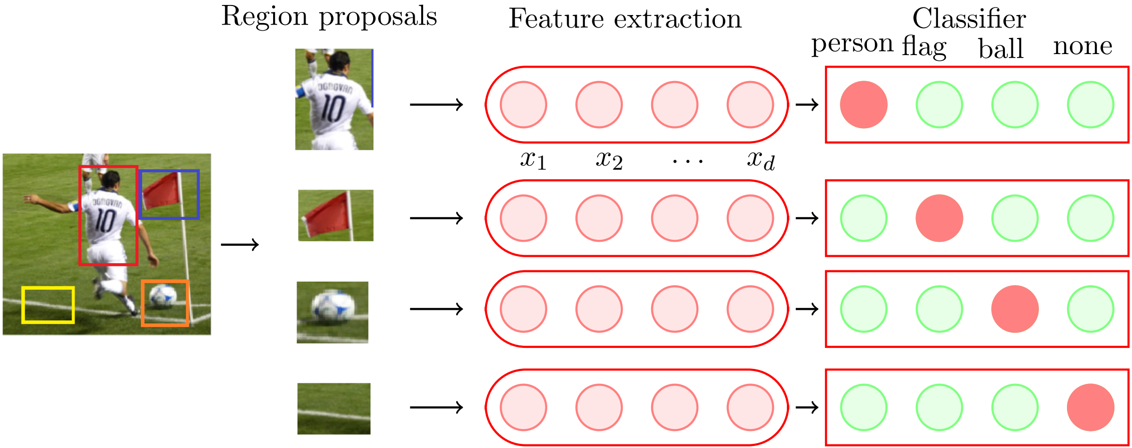
- Some images borrowed from Ross Girshick's original slides on RCNN, Fast RCNN, etc.
- Some ideas borrowed from the presentation of Kaustav Kundu*

* Deep Object Detection

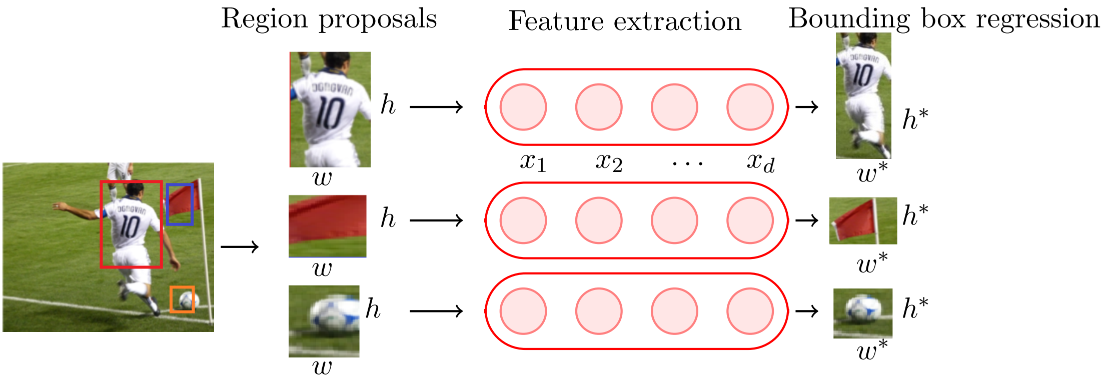
Module 12.1 : Introduction to object detection

- So far we have looked at Image Classification
- We will now move on to another Image Processing Task - *Object Detection*

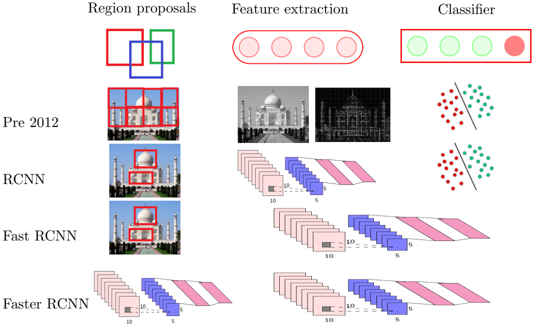
Task	Image classification	Object Detection
Output	Car	Car, exact bounding box containing car



- Let us see a typical pipeline for *object detection*
- It starts with a region proposal stage where we identify potential regions which may contain objects
- We could think of these regions as mini-images

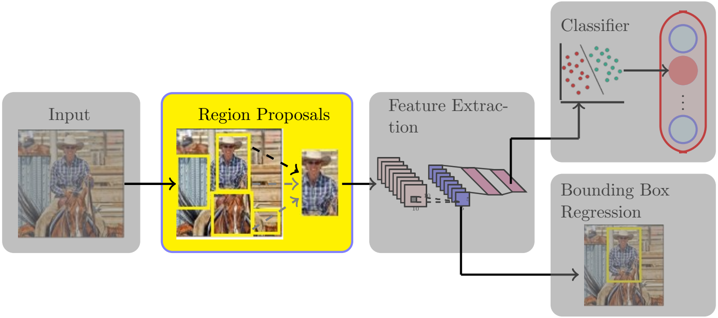


- In addition we would also like to correct the proposed bounding boxes
- This is posed as a regression problem (for example, we would like to predict w^*, h^* from the proposed w and h)

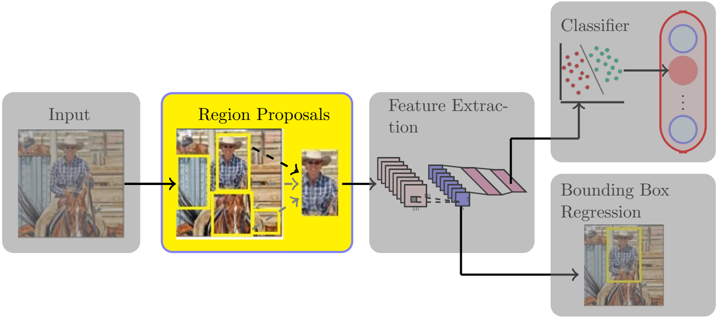


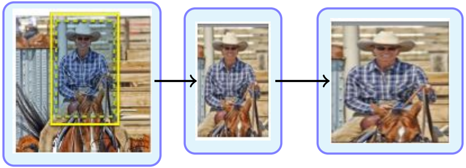
- Let us see how these three components have evolved over time
- Propose all possible regions in the image of varying sizes (almost brute force)
- Use handcrafted features (SIFT, HOG)
- Train a linear classifier using these features
- We will now see three algorithms that progressively improve these components

Module 12.2 : RCNN model for object detection

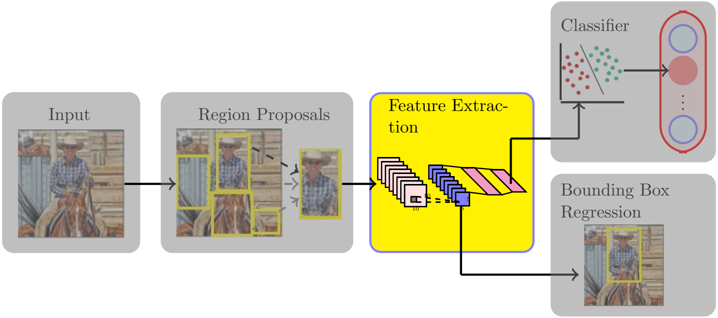


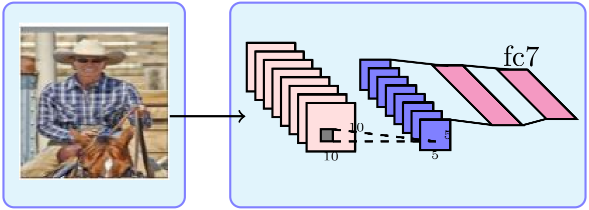
- **Selective Search** for region proposals
- Does hierarchical clustering at different scales
- For example the figures from left to right show clusters of increasing sizes
- Such a hierarchical clustering is important as we may find different objects at different scales



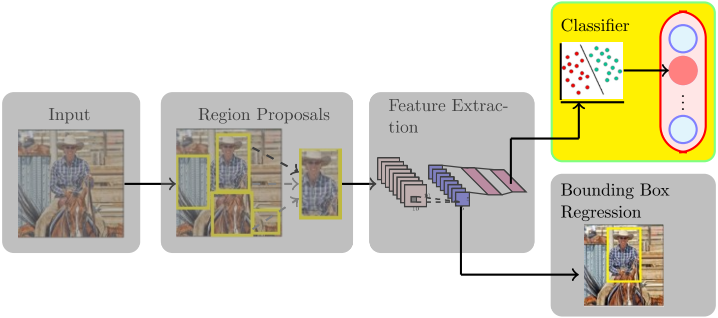


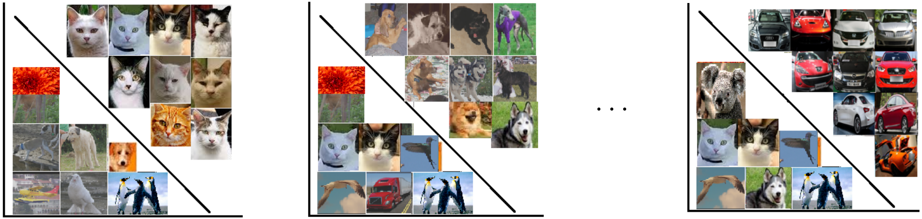
- Proposed regions are cropped to form mini images
- Each mini image is scaled to match the CNN's (feature extractor) input size



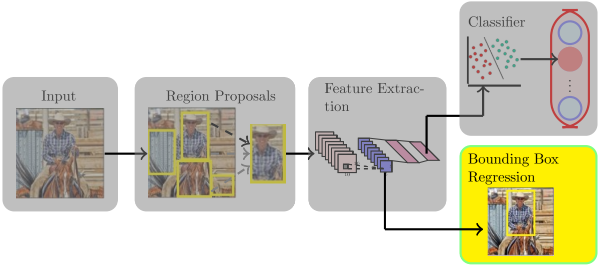


- For feature extraction any CNN trained for Image Classification can be used (AlexNet/ VGGNet etc.)
- Outputs from fc7 layer are taken as features
- CNN is fine tuned using ground truth (cropped) object images





- Linear models (SVMs) are used for classification (1 model per class)

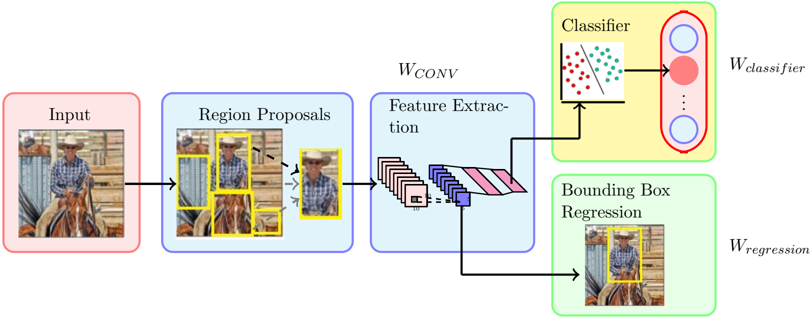


Proposed Box

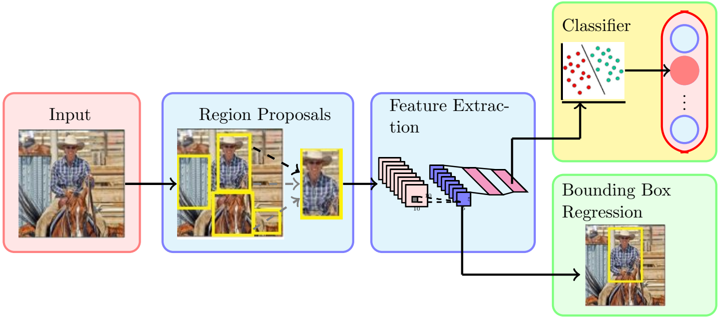
True Box

z : features from pool5 layer of the network

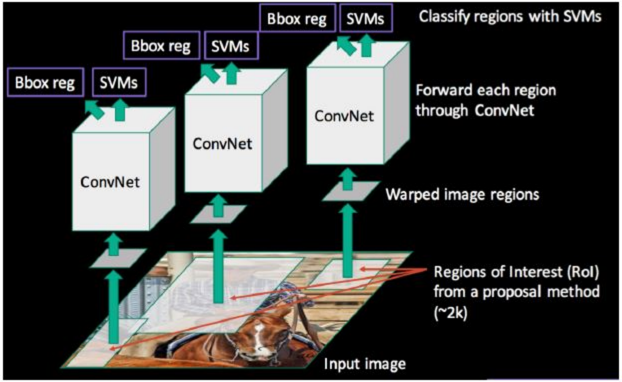
- The proposed regions may not be perfect
- We want to learn four regression models which will learn to predict x^*, y^*, w^*, h^*
- We will see their respective objective functions



- What are the parameters of this model?
- W_{CONV} is taken as it is from a CNN trained for Image classification (say on ImageNet)
- W_{CONV} is then fine tuned using ground truth (cropped) object images
- $W_{classifier}$ is learned using ground truth (cropped) object images
- $W_{regression}$ is learned using ground truth bounding boxes

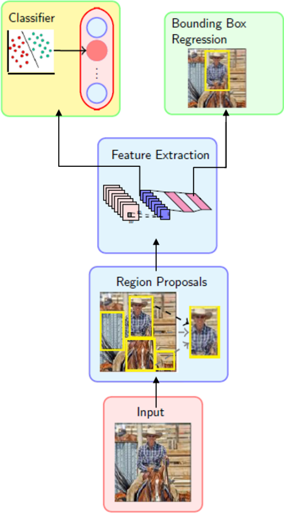


- What is the computational cost for processing one image at test time?
- Inference Time = Proposal Time + # Proposals × Convolution Time + # Proposals × classification + # Proposals × regression



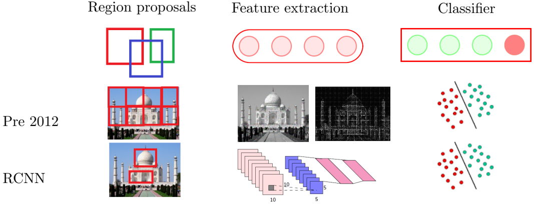
Source: *Ross Girshick*

- On average selective search gives 2K region proposal
- Each of these pass through the CNN for feature extraction
- Followed by classification and regression



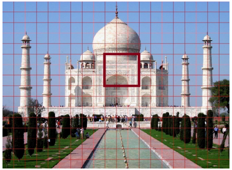
- No joint learning
- Use ad hoc training objectives
  - Fine tune network with softmax classifier (log loss)
  - Train post-hoc linear SVMs (hinge loss)
  - Train post-hoc bounding-box regressors (squared loss)
- Training ($\approx$ 3 days) and testing (47s per image) is slow[1].
- Takes a lot of disk space

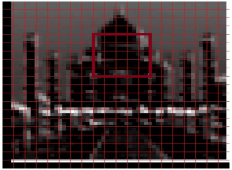
[1] Source: *Ross Girshick*
[1] Using VGG-Net

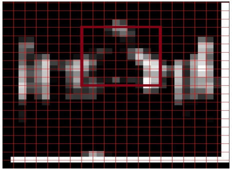


- **Region Proposals:** Selective Search
- **Feature Extraction:** CNNs
- **Classifier:** Linear

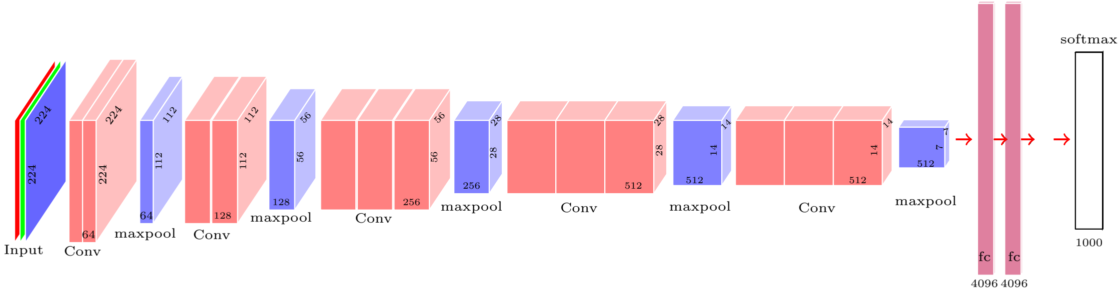
Module 12.3 : Fast RCNN model for object detection



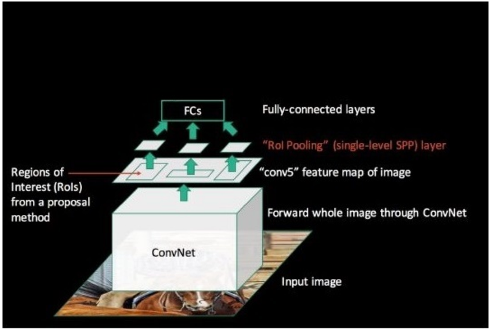




- Suppose we apply a 3×3 kernel on an image
- What is the region of influence of each pixel in the resulting output ?
- Each pixel contributes to a 5×5 region
- Suppose we again apply a 3×3 kernel on this output?
- What is the region of influence of the original pixel from the input ? (a 7×7 region)

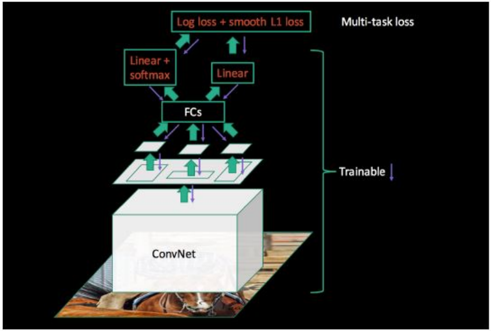


Input
224
224
Conv
224
224
64
maxpool
112
112
64
Conv
112
112
128
maxpool
56
56
128
Conv
56
56
256
maxpool
28
28
256
Conv
28
28
512
maxpool
14
14
512
Conv
14
14
512
maxpool
7
7
512
fc
4096
fc
4096
softmax
1000



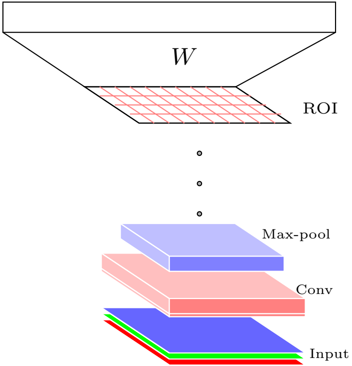
Source: *Ross Girshick*

- Using this idea we could get a bounding box's region of influence on any layer in the CNN
- The projected Region of Interest (RoI) may be of different sizes
- Divide them into k equally sized regions of dimension $H \times W$ and do max pooling in each of those regions to construct a k dimensional vector
- Connect the k dimensional vector to a fully connected layer
- This max pooling operation is call RoI pooling

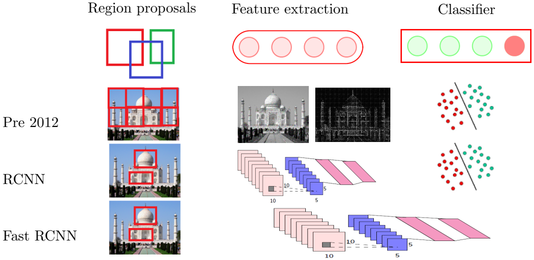


Source: *Ross Girshick*

- Once we have the FC layer it gives us the representation of this region proposal
- We can then add a softmax layer on top of it to compute a probability distribution over the possible object classes
- Similarly we can add a regression layer on top of it to predict the new bounding box (w^*, h^*, x^*, y^*)

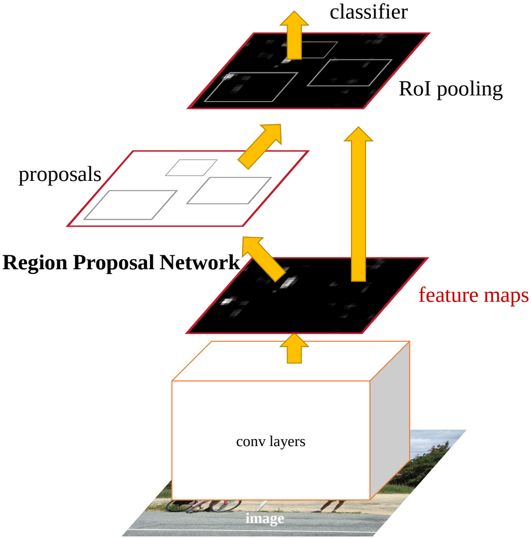


- Recall that the last pooling layer of VGGNet-16 results in an output of size $512 \times 7 \times 7$
- We replace the last max pooling layer by a RoI pooling layer
- We set $H = W = 7$ and divide each of these RoIs into $(k = 49)$ regions
- We do this for every feature map resulting in an ouput of size 512×49
- This output is of the same size as the output of the original max pooling layer
- It is thus compatible with the dimensions of the weight matrix connecting the original pooling layer to the first

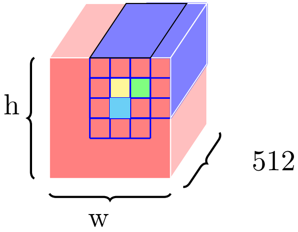


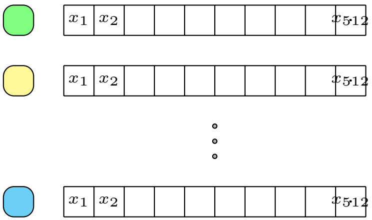
- **Region Proposals:** Selective Search
- **Feature Extraction:** CNN
- **Classifier:** CNN

Module 12.4 : Faster RCNN model for object detection

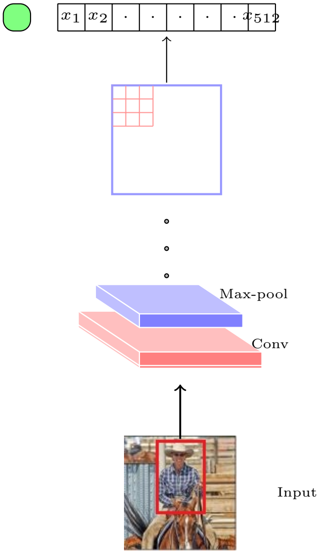


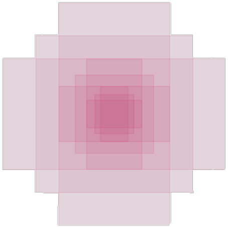
- So far the region proposals were being made using Selective Search algorithm
- **Idea:** Can we use a CNN for making region proposals also?
- How? Well it's slightly tricky
- We will illustrate this using **VGGNet**



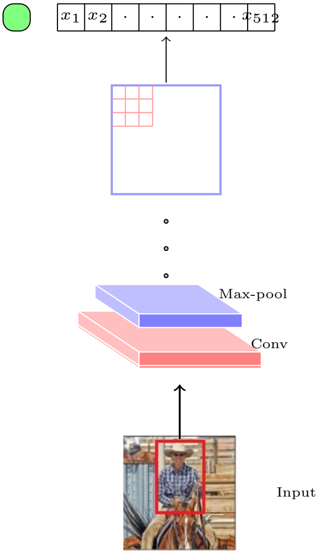


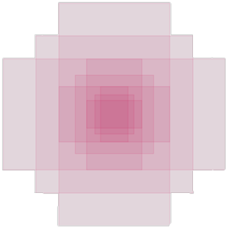
- Consider the output of the last convolutional layer of VGGNet
- Now consider one cell in one of the 512 feature maps
- If we apply a 3×3 kernel around this cell then we will get a 1D representation for this cell
- If we repeat this for all the 512 feature maps then we will get a 512 dimensional representation for this position
- We use this process to get a 512 dimensional representation for each of the $w \times h$ positions



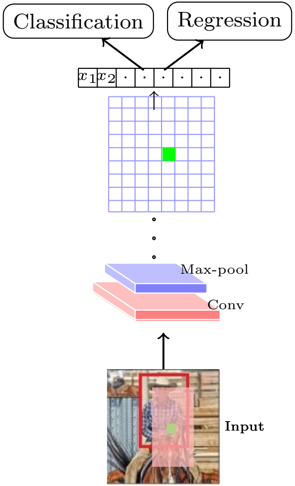


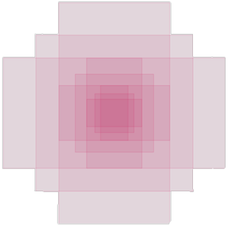
- We now consider k bounding boxes (called anchor boxes) of different sizes & aspect ratio
- We are interested in the following two questions:
- Given the $512d$ representation of a position, what is the probability that a given anchor box centered at this position contains an object? (Classification)
- How do you predict the true bounding box from this anchor box? (Regression)



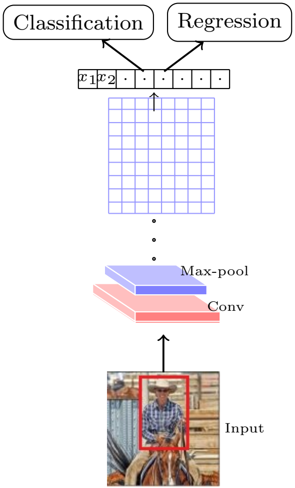


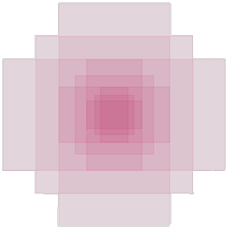
- We train a classification model and a regression model to address these two questions
- How do we get the ground truth data?
- What is the objective function used for training?





- Consider a ground truth object and its corresponding bounding box
- Consider the projection of this image onto the conv5 layer
- Consider one such cell in the output
- This cell corresponds to a patch in the original image
- Consider the center of this patch
- We consider anchor boxes of different sizes
- For each of these anchor boxes, we would want the classifier to predict 1 if this anchor box has a reasonable overlap (IoU > 0.7) with the true grounding box



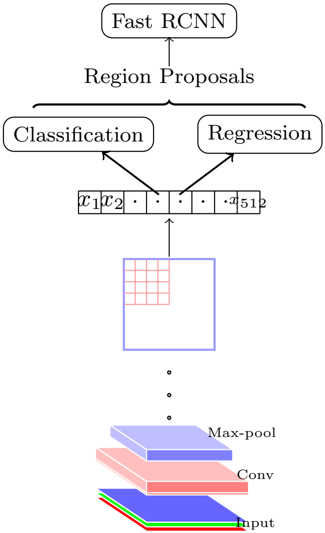


- We train a classification model and a regression model to address these two questions
- How do we get the ground truth data?
- What is the objective function used for training?

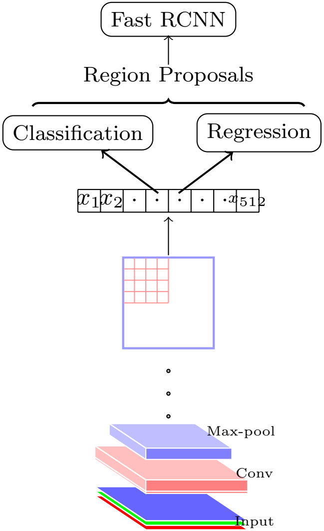
- The full network is trained using the following objective.

$$\mathscr{L}(p_i, t_i) = \frac{1}{N_{cls}} \sum_i \mathscr{L}_{cls}(p_i, p_i^*) + \frac{\lambda}{N_{reg}} \sum_i p_i^* \mathscr{L}_{reg}(t_i, t_i^*)$$

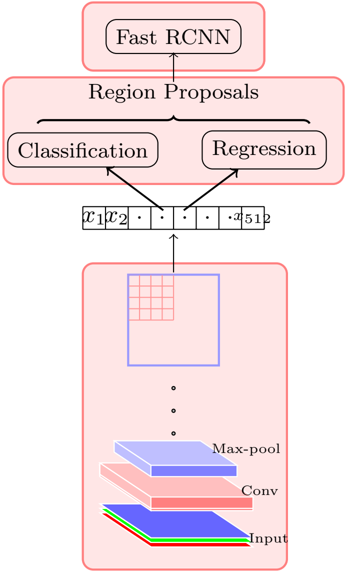
$$\begin{aligned}
p_i^* &= 1 \quad \text{if anchor box contains ground truth object} \\
&= 0 \quad \text{otherwise} \\
p_i &= \text{predicted probability of anchor box containing an object} \\
N_{cls} &= \text{batch-size} \\
N_{reg} &= \text{batch-size} \times k \\
k &= \text{anchor boxes}
\end{aligned}$$



- So far we have seen a CNN based approach for region proposals instead of using selective search
- We can now take these region proposals and then add fast RCNN on top of it to predict the class of the object
- And regress the proposed bounding box



- But the fast RCNN would again use a VGG Net
- Can't we use a single VGG Net and share the parameters of RPN and RCNN
- Yes, we can
- In practice, we use a 4 step alternating training process

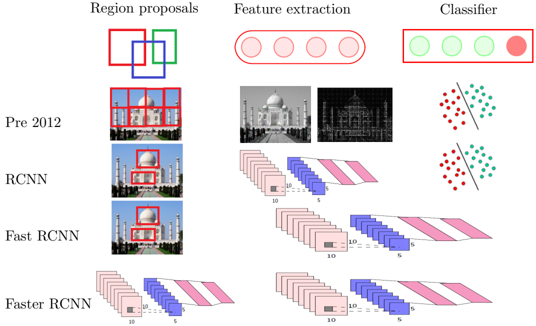


Faster RCNN:Training

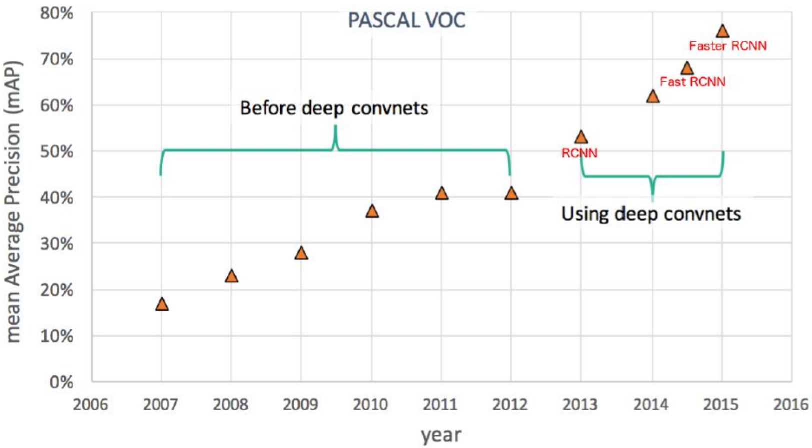
- Fine-tune RPN using a pre-trained ImageNet network
- Fine-tune fast RCNN from a pre-trained ImageNet network using bounding boxes from step 1
- Keeping common convolutional layer parameters fixed from step 2, fine-tune RPN (post conv5 layers)
- Keeping common convolution layer parameters fixed from step 3, fine-tune fc layers of fast RCNN

Faster RCNN and RPN are the basis of several 1st place entries in the ILSVRC and COCO tracks on :

- Imagenet detection
- COCO Segmentation
- Imagenet localization
- COCO detection



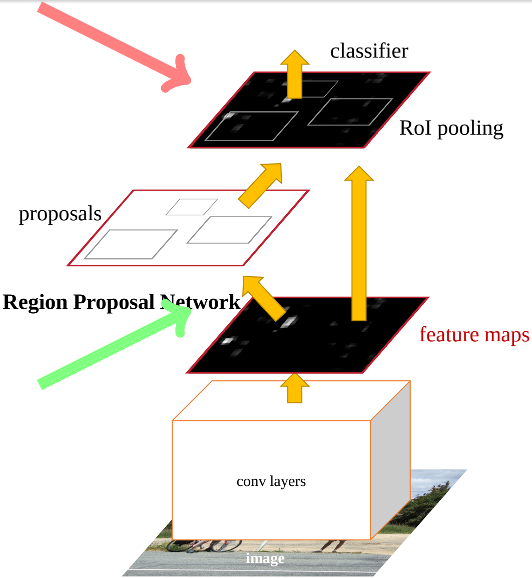
- **Region Proposals:** CNN
- **Feature Extraction:** CNN
- **Classifier:** CNN



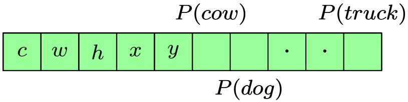
Object Detection Performance

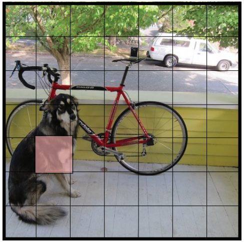
Source: Ross Girshick

Module 12.5 : YOLO model for object detection



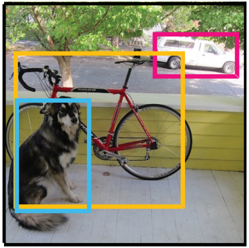
- The approaches that we have seen so far are two stage approaches
- They involve a region proposal stage and then a classification stage
- Can we have an end-to-end architecture which does both proposal and classification simultaneously ?
- This is the idea behind **YOLO**-You Only Look Once.





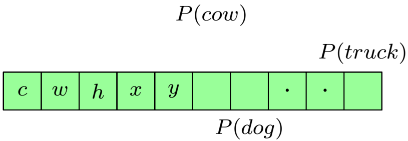
S × S grid on input

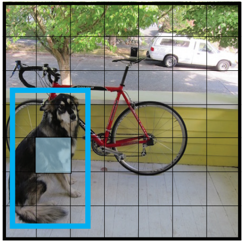
- Divide an image into $S \times S$ grids (S=7)
- For each such cell we are interested in predicting $5 + k$ quantities
- Probability (confidence) that this cell is indeed contained in a true bounding box
- Width of the bounding box
- Height of the bounding box
- Center (x,y) of the bounding box
- Probability of the object in the bounding box belonging to the k^{th} class (k - values)
- The output layer thus contains $S \times S \times (5 + k)$ elements



Bounding Boxes & Confidence

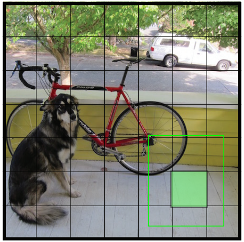
- How do we interpret this $S \times S \times (5+k)$ dimensional output?
- For each cell, we are computing a bounding box, its confidence and the object in it
- We then retain the most confident bounding boxes and the corresponding object label





S × S grid on input

- How do we train this network ?
- Consider a cell such that the center of the true bonding box lies in it
- The network is initialized randomly and it will predict some values for c, w, h, x, y & ℓ
- We can then compute the following losses
- $(x - \hat{x})^2$
- $(y - \hat{y})^2$
- $(\sqrt{w} - \sqrt{\hat{w}})^2$
- $(\sqrt{h} - \sqrt{\hat{h}})^2$
- $(1 - \hat{c})^2$
- $\sum_{i=1}^{k} (\ell_i - \hat{\ell}_i)^2$
- And train the network to minimize


S × S grid on input

- Now consider a grid which does not contain any object
- For this grid we do not care about the predictions w, h, x, y & ℓ
- But we want the confidence to be low
- So we minimize only the following loss

$$(0 - \hat{c})^2$$

Method	Pascal 2007 mAP	Speed
DPM v5	33.7	0.07 FPS — 14 sec/ image
RCNN	66.0	0.05 FPS — 20 sec/ image
Fast RCNN	70.0	0.5 FPS — 2 sec/ image
Faster RCNN	73.2	7 FPS — 140 msec/ image
YOLO	69.0	45 FPS — 22 msec/ image