



Coarse Semantic Segmentation with Multiscale Dimensionality Reduced Subblocks

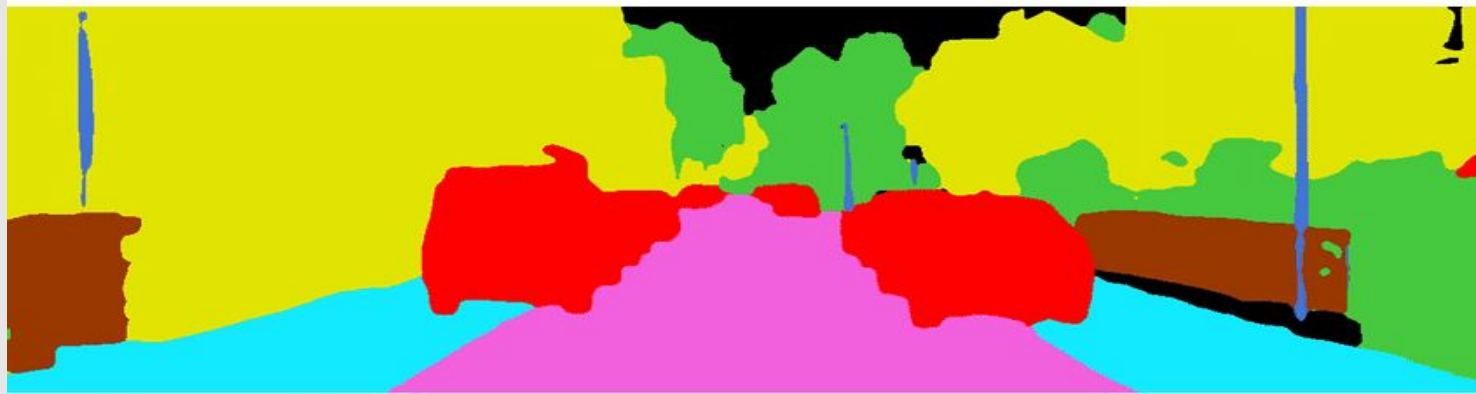
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Semantic Segmentation: Motivation



Task: Assign a semantic class to each pixel in an image



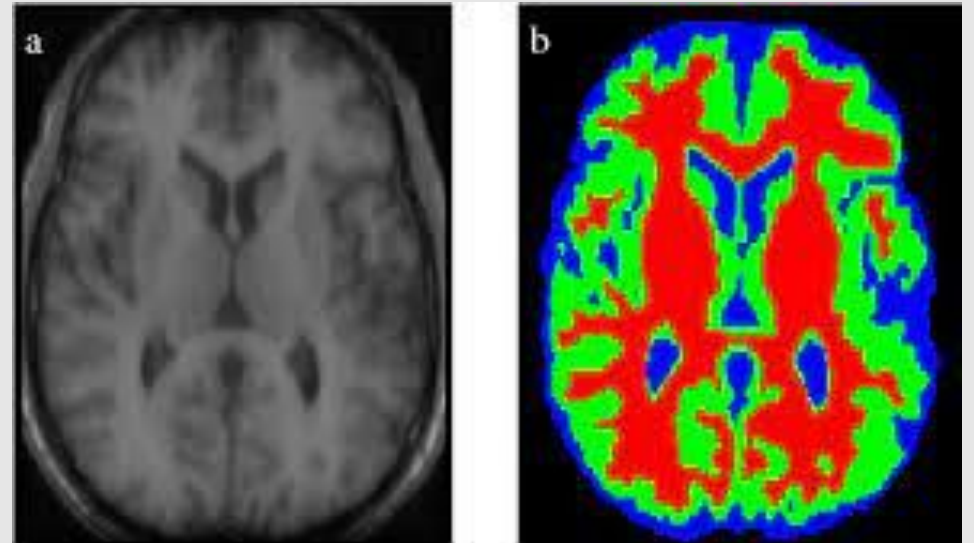
 Road	 Sidewalk	 Building	 Fence
 Pole	 Vegetation	 Vehicle	 Unlabel

Semantic Segmentation: Motivation



Applications

- autonomous vehicles
- medical analysis
- specific classification tasks

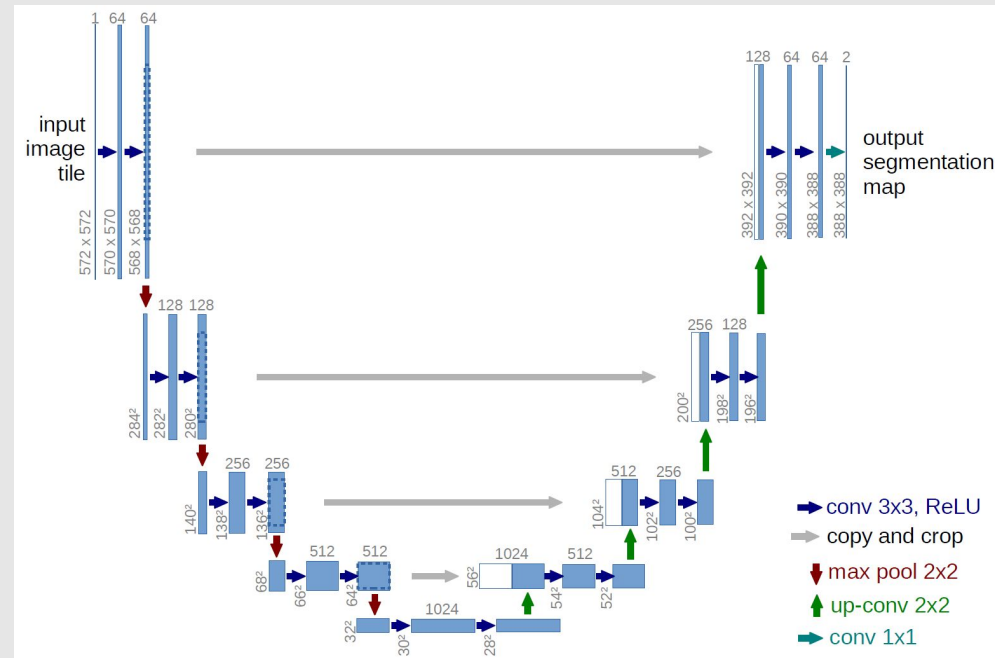


Current State of the Art: UNET



State of the art approach:

- 1) Encoder
 - a) Classification network (convolution)
 - b) Downsampling
- 2) Decoder
 - a) Upsampling
 - b) Concatenation



Our Approach: Motivation



Big Neural Networks & CNNs are Great!

BUT

They are huge, often in the Millions of parameters. Image data is very high-dimensional. Because of this:

- They have very long training time.
- They need lots of training data.
- Inference isn't super fast.

Our Approach: Goal

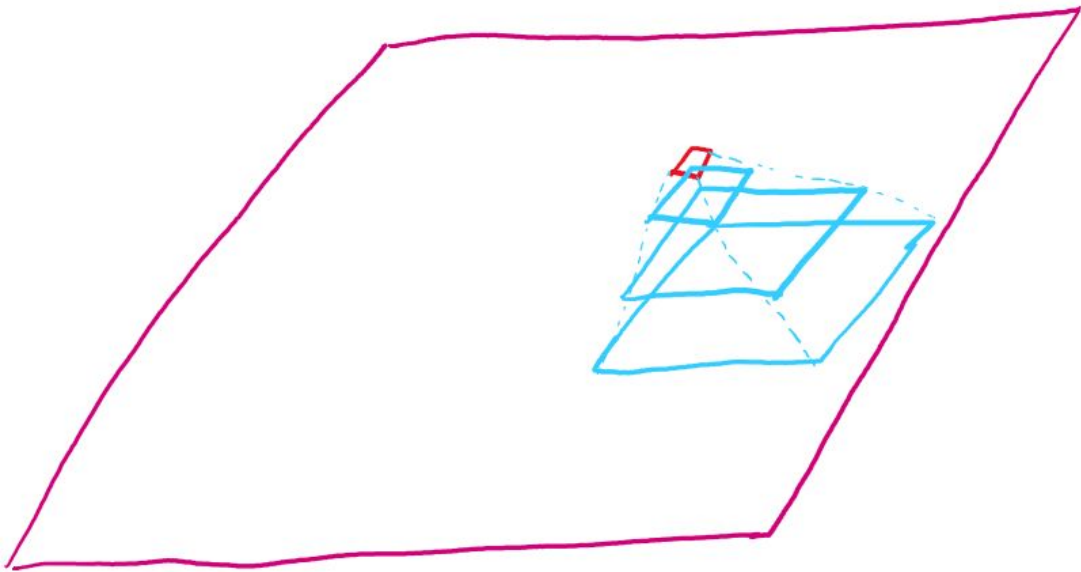


Create a smaller, simpler semantic segmentation algorithm that trains faster.

BY

Simplifying the semantic segmentation task.
Applying MASSIVE dimensionality reduction.

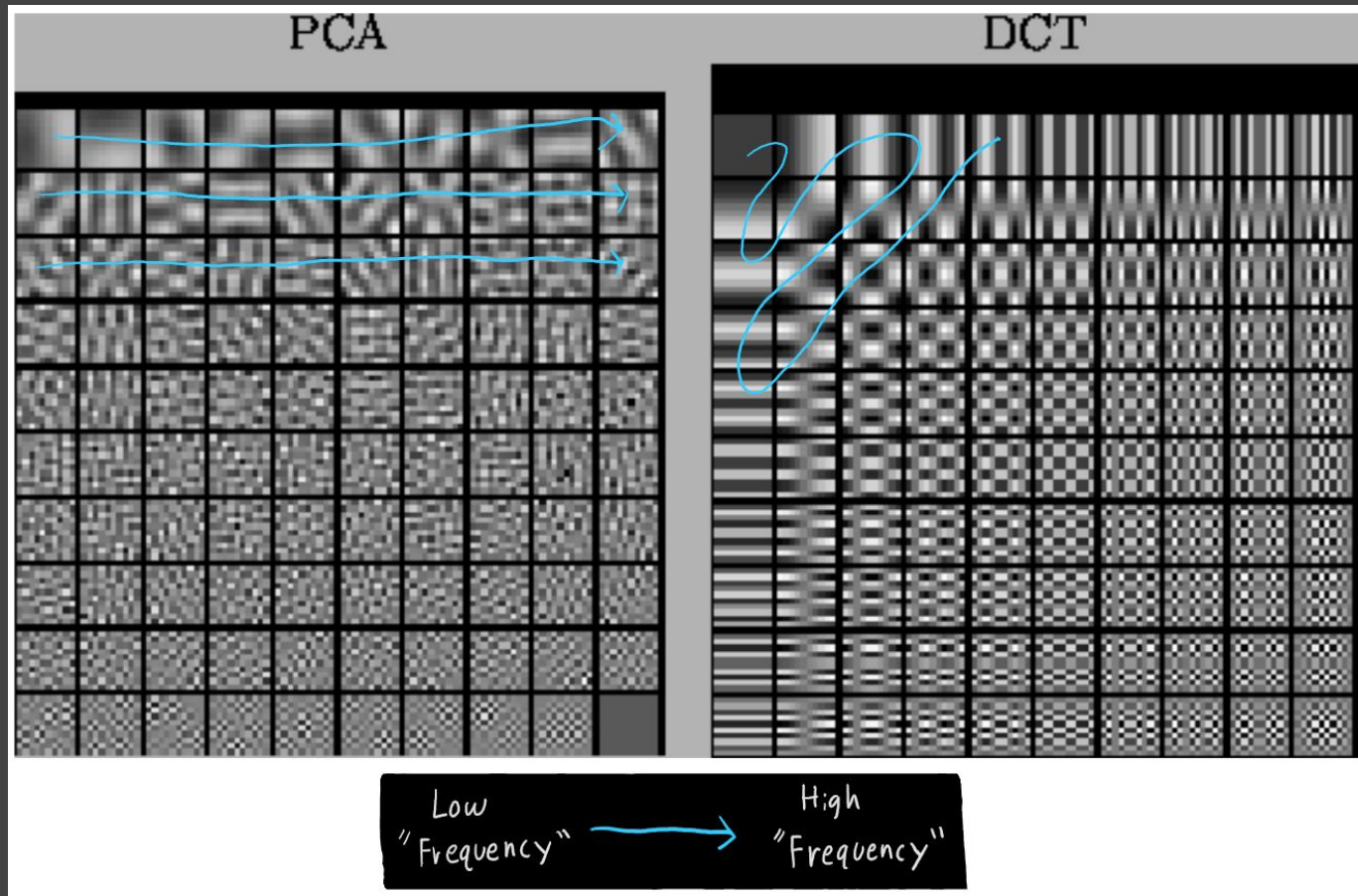
Our Approach: Multiscale Sliding Window



Our Approach: Multiscale Sliding Window



Our Approach: Texture Dimensionality Reduction using PCA

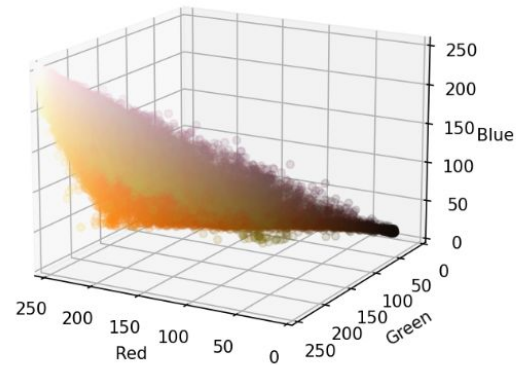


Use PCA Coefficients as input to a predictive model.

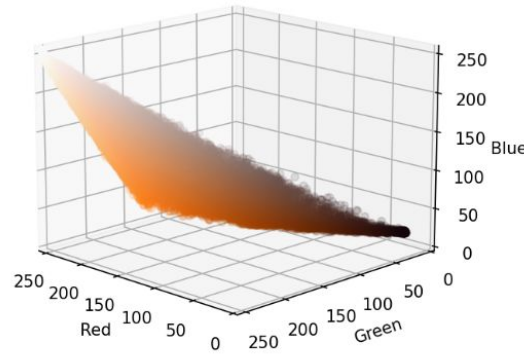
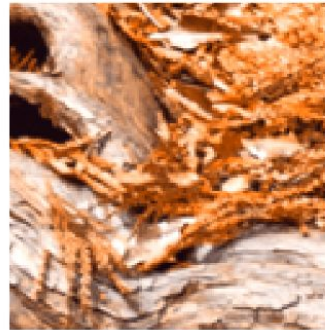
Our Approach: Color Dimensionality Reduction using PCA



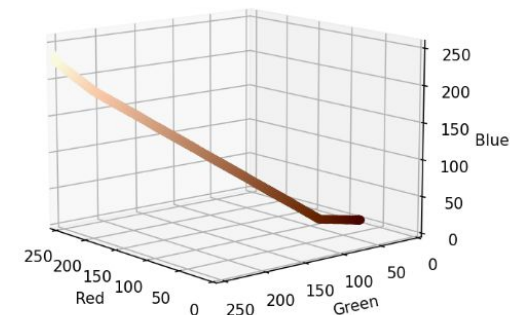
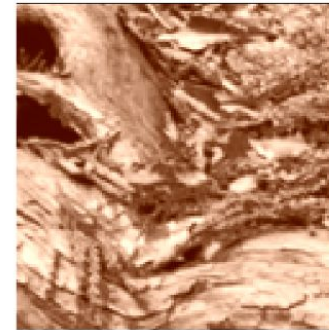
All Channels



2/3 PCA Channels



1/3 PCA Channels



Our Approach: Color Dimensionality Reduction using PCA



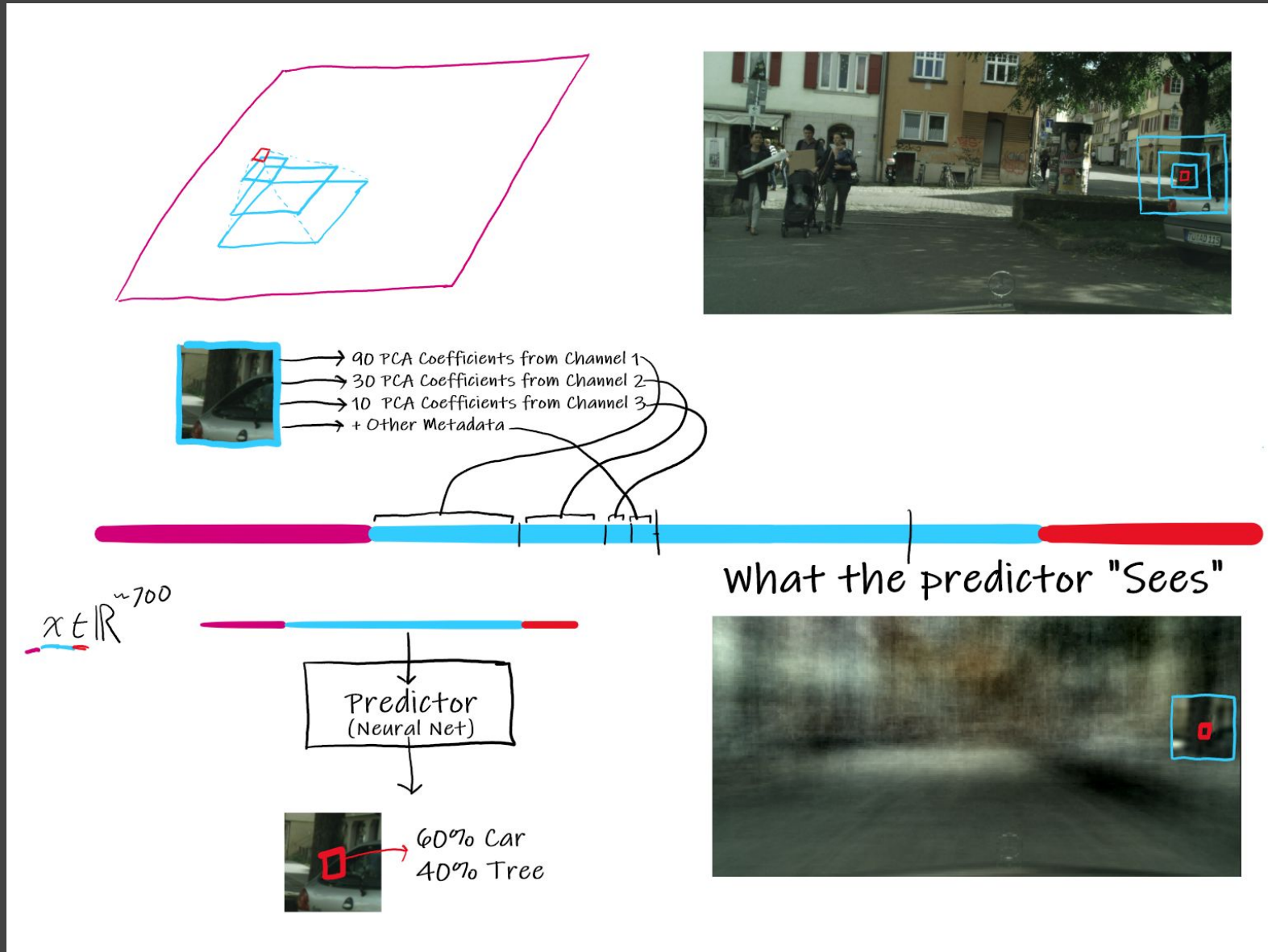
Original



25% Coefficients Channel 1
10% Coefficients Channel 2
5 % Coefficients Channel 3



Our Approach: Encoding



Our Approach: Encoding





NN Architecture

- 3 Dense layers
- Mean Squared Logarithmic Error loss function
- Adam optimizer with a learning rate of 0.0001
- Judged in terms of Accuracy metrics.
- Trained for 20 minutes.

Our Approach: Limitations & Constraints



- We use the Full-Resolution 2048 x 1024 images
- Coarse Segmentation
- No Corners

Task: Cityscapes



Goal: classify objects within the city

Inspiration: Self-driving cars





Results: Model Size

Our Model Size vs UNET

- Our model contains a total of 47,998 parameters.
- UNET's model contains a total of 2,060,424 parameters.

Model: "sequential"

Layer (type)	Output Shape	Param #
dense (Dense)	(None, 64)	44928
dense_1 (Dense)	(None, 32)	2080
dense_2 (Dense)	(None, 30)	990

Total params: 47,998
Trainable params: 47,998
Non-trainable params: 0

```
conv2d_7 (Conv2D) (None, 512, 512, 32) 2080 up_sampling2d_7[0][0]
-----
add_6 (Add) (None, 512, 512, 32) 0 up_sampling2d_6[0][0]
conv2d_7[0][0]
-----
conv2d_8 (Conv2D) (None, 512, 512, 8) 2312 add_6[0][0]
=====
=====
Total params: 2,060,424
Trainable params: 2,056,648
Non-trainable params: 3,776
-----
```

Results: Time to Train



Our Model Training Time vs UNET

- Our model took 20 minutes to train vs UNET's 400 minutes to train.
- Our model trained utilizing 30% of a laptop processor, specifically the i7 8750H.
- UNET's model trained utilizing an unspecified gpu.
- Although we do not know UNET's gpu, it is likely a lot more powerful than a cpu in terms of training neural networks.

Results: Accuracy



Our Model Accuracy vs Ground Truth

Caveat: Coarse

Our Model's accuracy after 20 minutes of training:

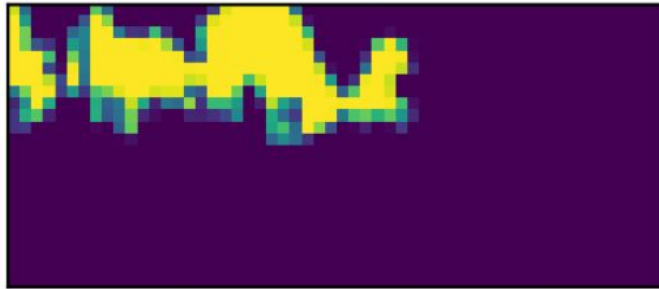
- 47,998 Parameters: 82.79%
- 203,630 Parameters: 90.08%
- 845,982 Parameters: 93.04%

UNET's pixel-wise segmentation model's accuracy: 91.69%

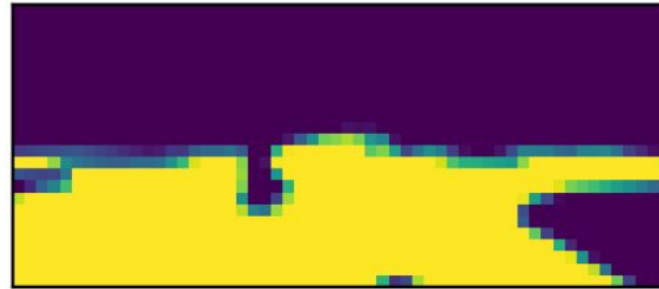
Results: Successes



Foliage



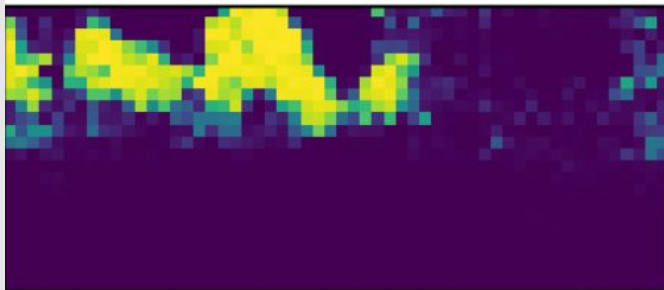
Road



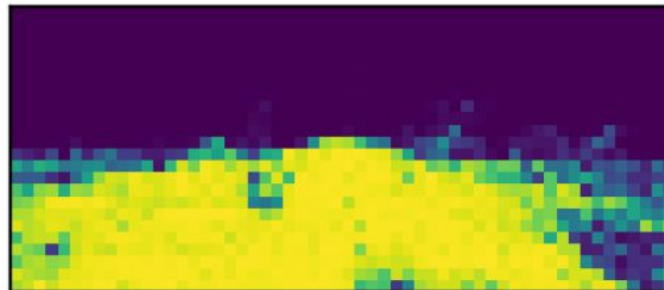
Sidewalk



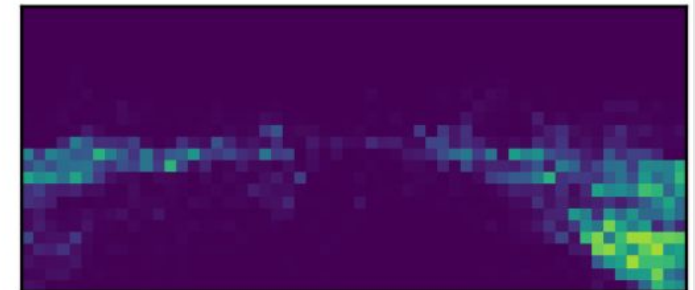
Foliage



Road



Sidewalk



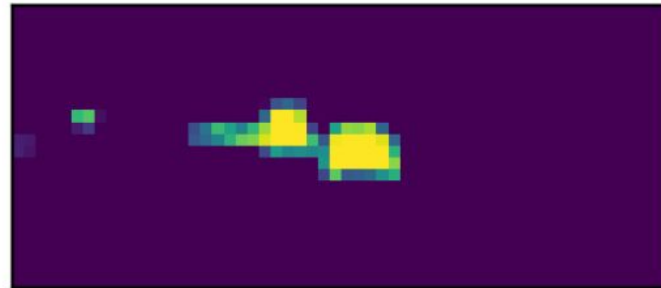
Results: Areas of Improvement



Person



Car



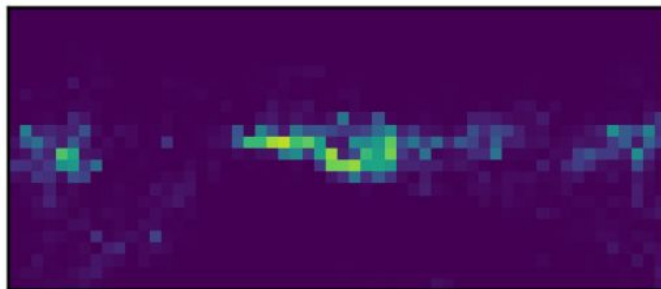
Pole



Person



Car



Pole



Future Work



- Corners
- Pixel-Wise segmentation



Thank You!

References



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