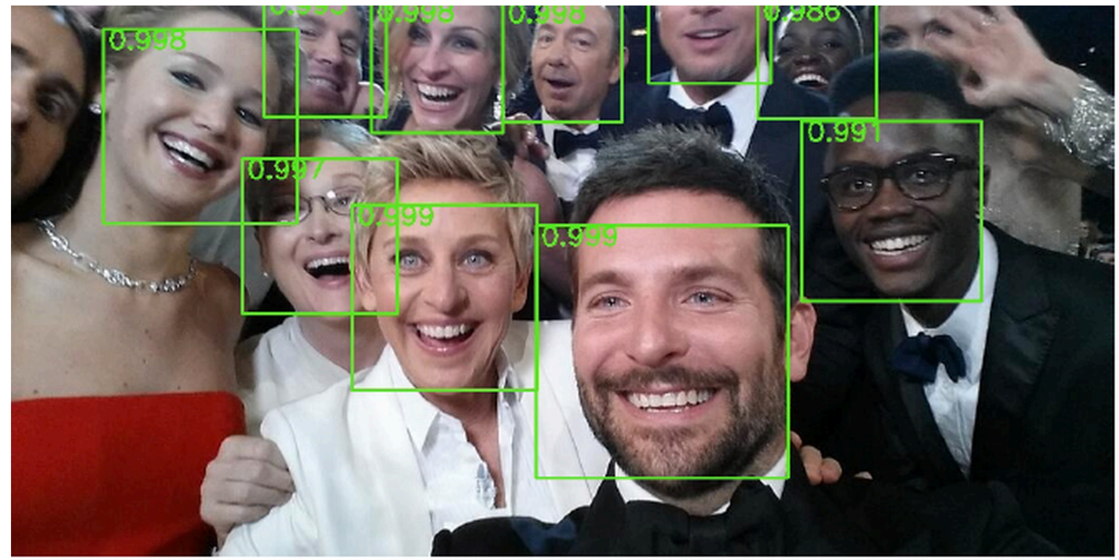
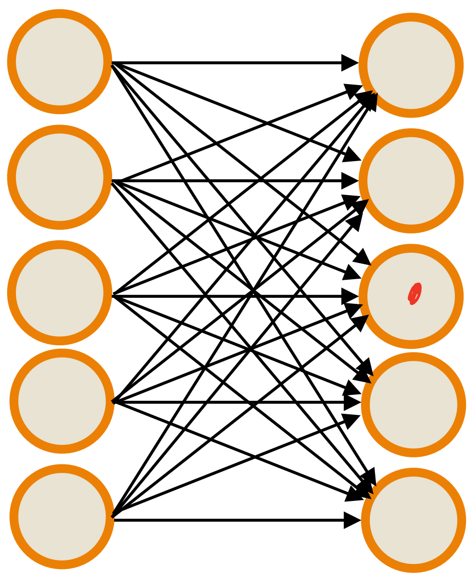
Convolutional Neural Networks

Neural Network Architecture

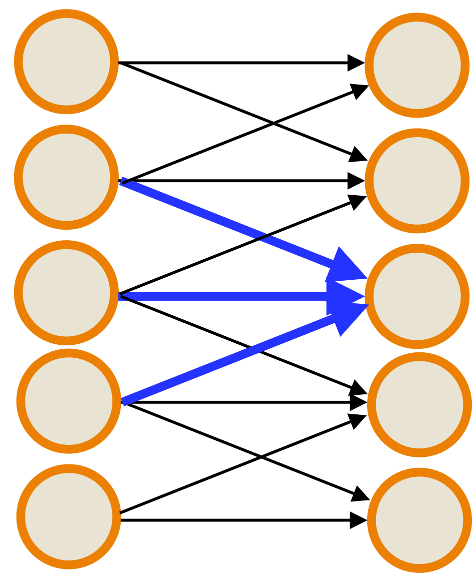
Objects are often **localized in space** so to find the faces in an image, not every pixel is important for classification—makes sense to drag a window across an image.



Similarly, to identify edges or other local structure, it makes sense to only look at **local information**



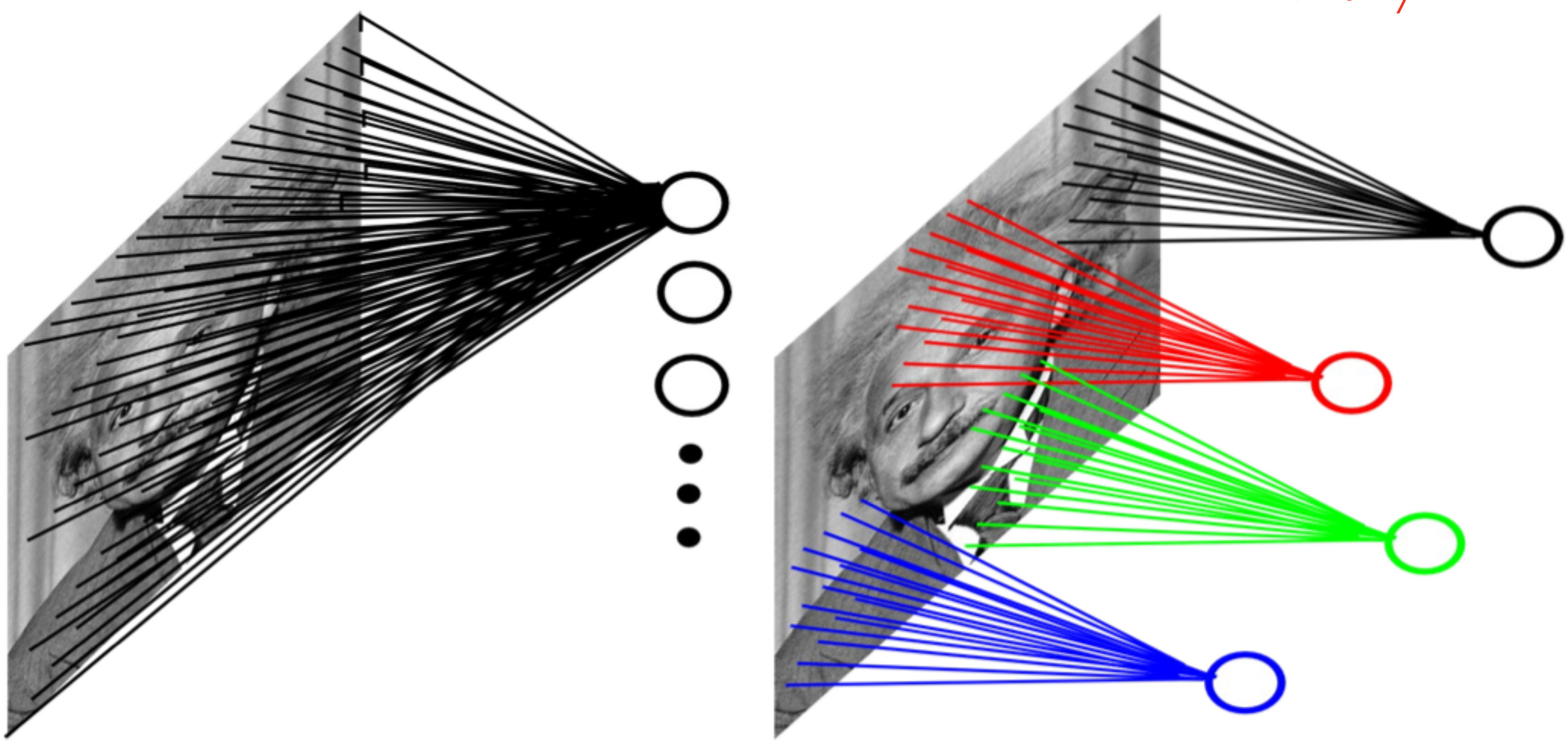
vs.



2d Convolution Layer

- **Example: 200x200 image**
  - Fully-connected, 400,000 hidden units = 16 billion parameters
  - Locally-connected, 400,000 hidden units 10x10 fields = 40 million params
  - Local connections capture local dependencies

weight-sharing



Convolution of images (2d convolution)

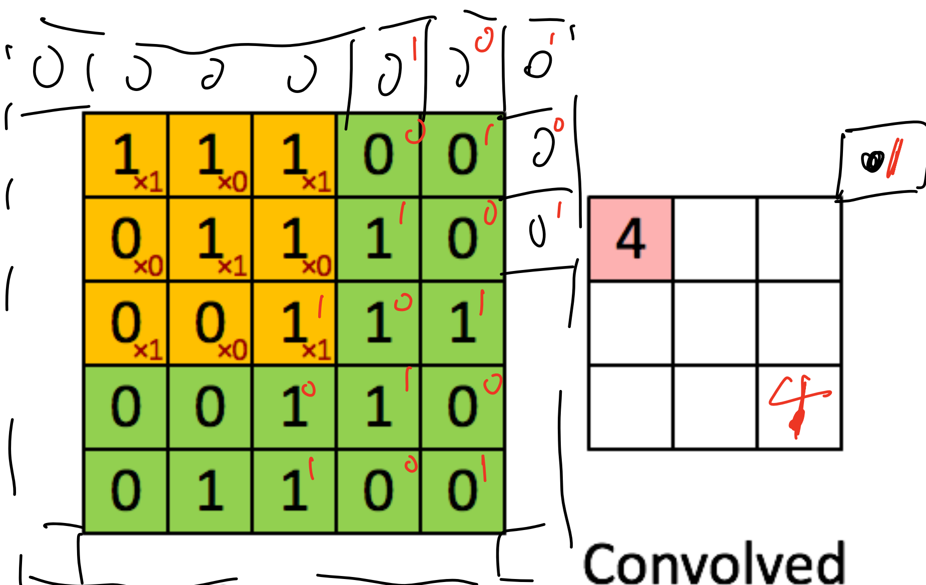
$$(I * K)(i,j) = \sum_m \sum_n I(i+m, j+n)K(m,n)$$

1	1	1	0	0
0	1	1	1	0
0	0	1	1	1
0	0	1	1	0
0	1	1	0	0

Image I

1	0	1
0	1	0
1	0	1

Filter K



Image

Convolved Feature

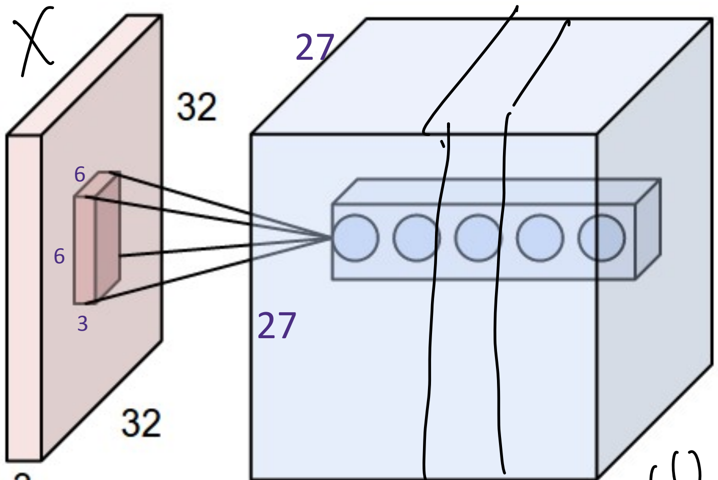
$I * K$

Stacking convolved images

g: activation function

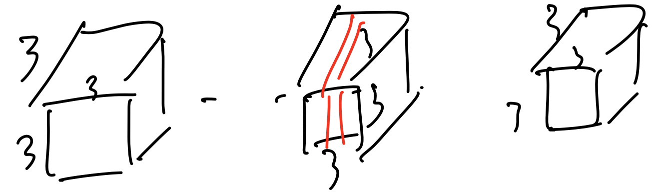
$j = 1, \dots, d$

$a_j^{(1)}$



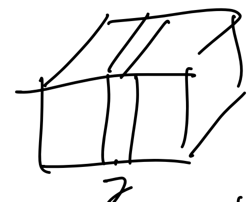
R G B channels

$a^{(1)}$



kernel j

Repeat with d filters!

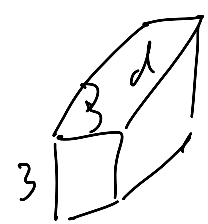


$a^{(2)}$

$$a_j^{(1)} = g\left(\sum_{\alpha=1}^{3} X[:,:,\alpha] * K_j^{(1)}[:,:,\alpha]\right)$$

$$a_j^{(2)} = g\left(\sum_{i=1}^{d} a^{(1)}[:,:,i] * K_j^{(2)}[:,:,i]\right)$$

Second layer filters



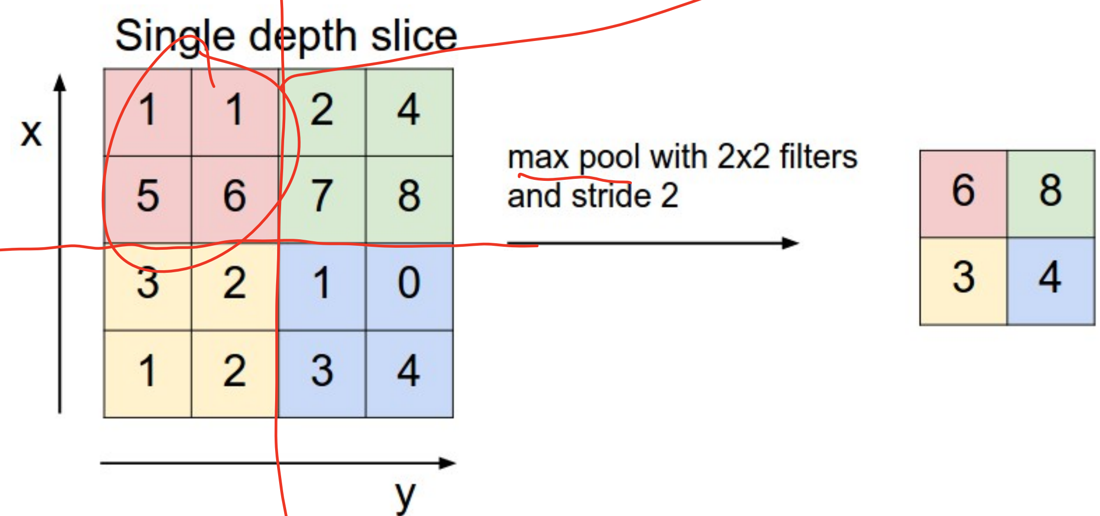
$K_j^{(2)}$

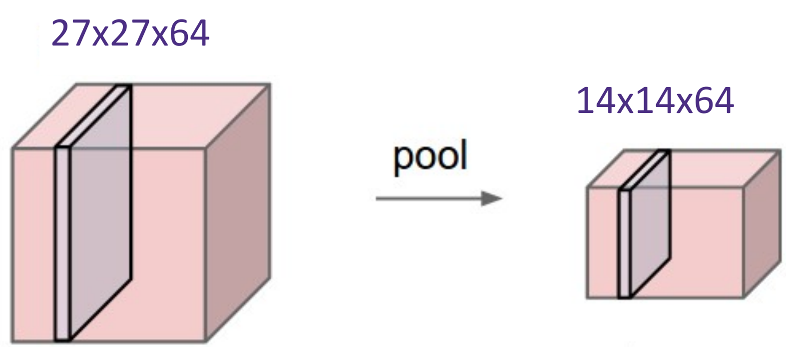
kernel

Pooling

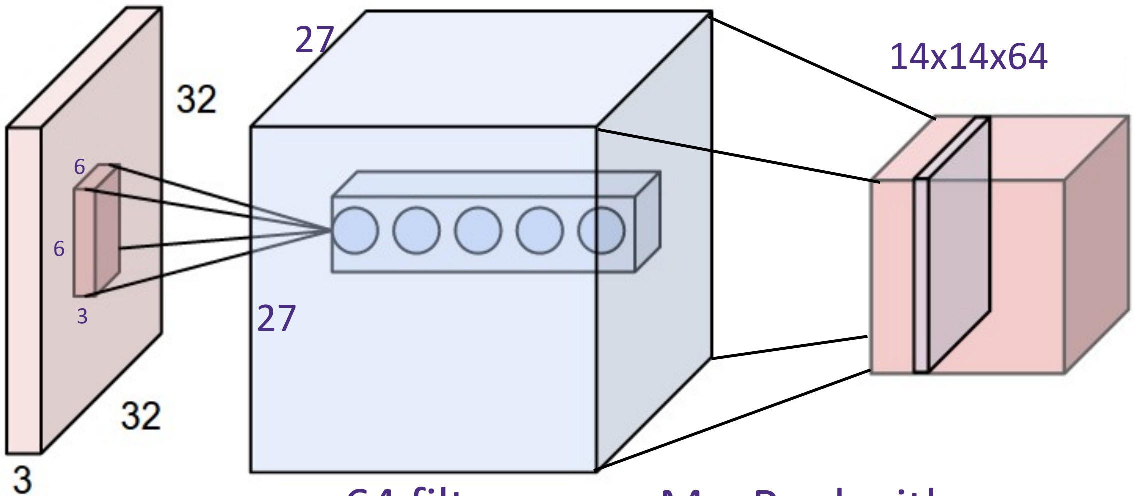
average pooling $\frac{13}{4}$

Pooling reduces the dimension and can be interpreted as “This filter had a high response in this general region”





Pooling Convolution layer

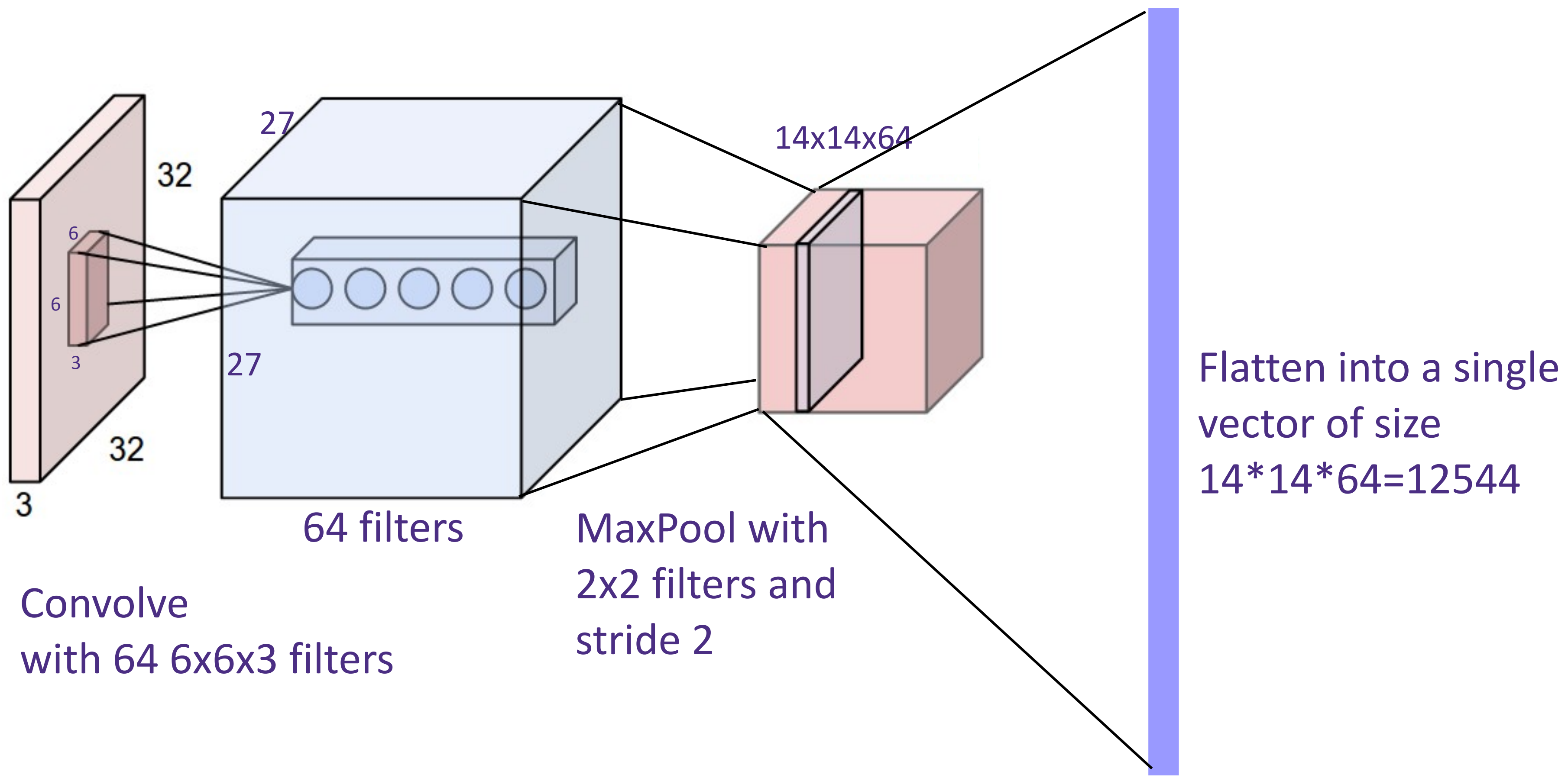


64 filters

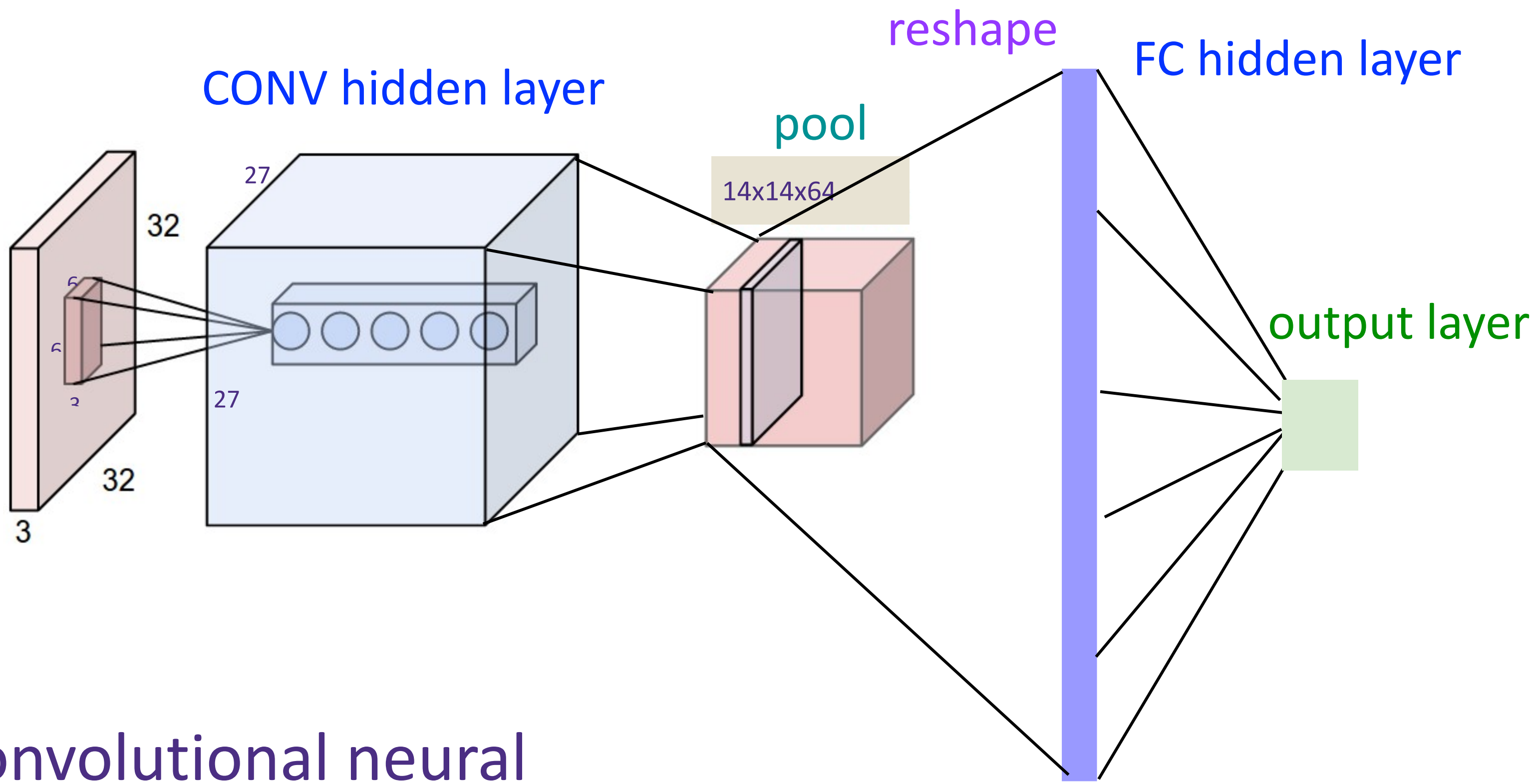
MaxPool with
2x2 filters and
stride 2

Convolve
with 64 6x6x3 filters

Flattening

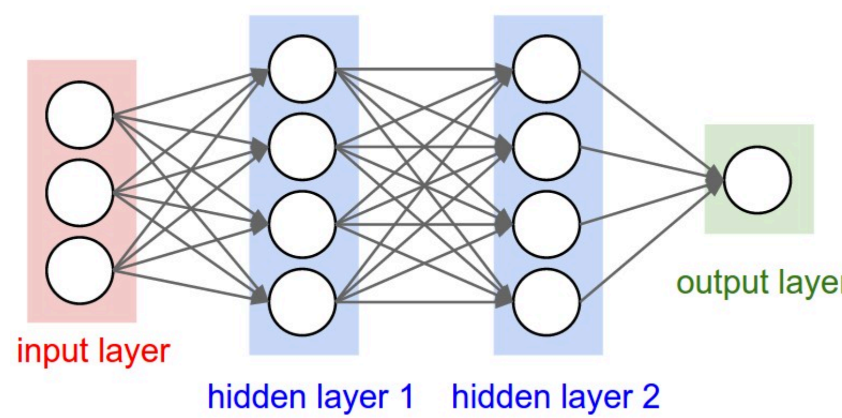

27
32
6
6
3
27
32
3
14x14x64
64 filters
Convolve
with 64 6x6x3 filters
MaxPool with
2x2 filters and
stride 2
Flatten into a single
vector of size
14*14*64=12544

Training Convolutional Networks

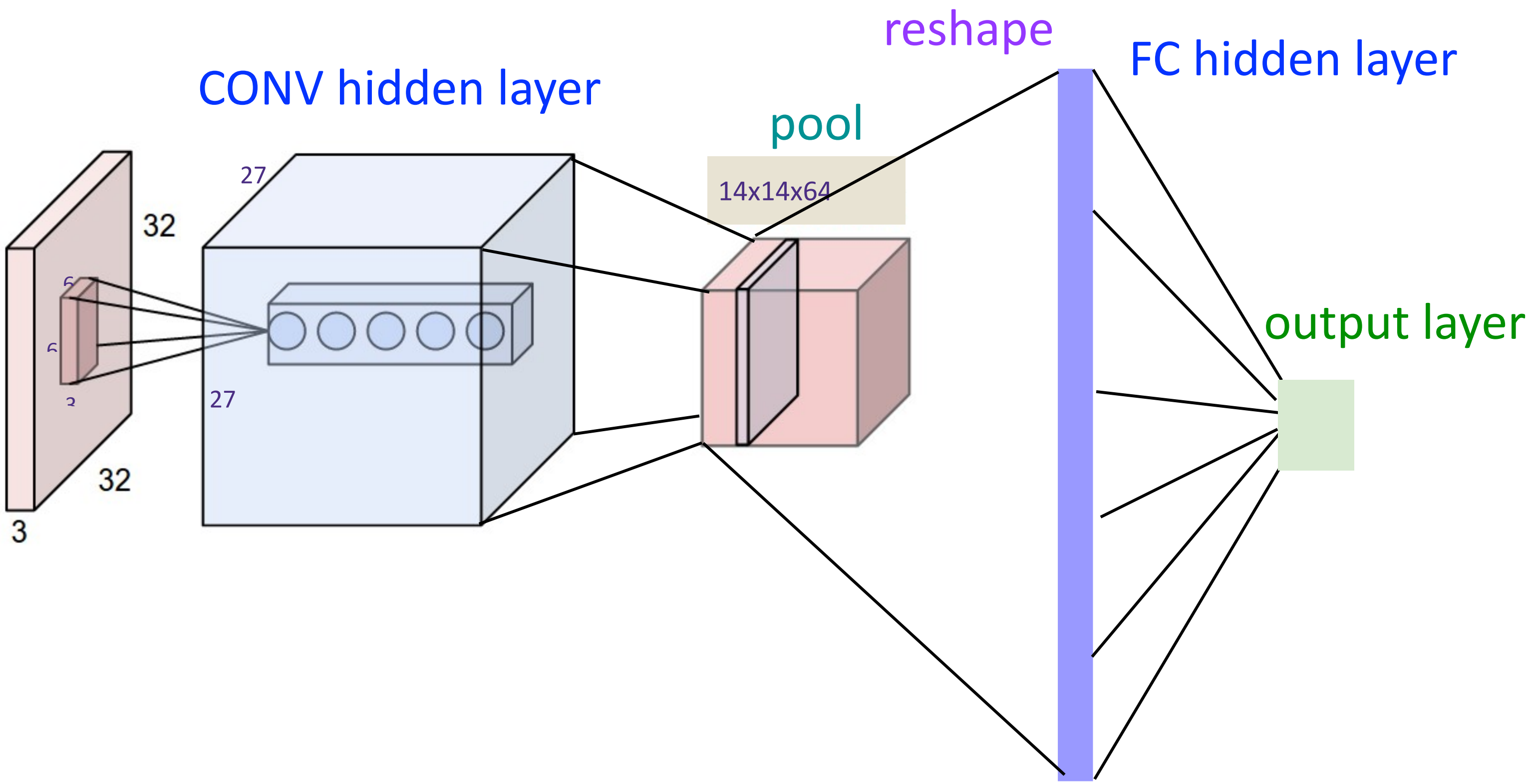


Recall: Convolutional neural networks (CNN) are just regular fully connected (FC) neural networks with some connections removed.

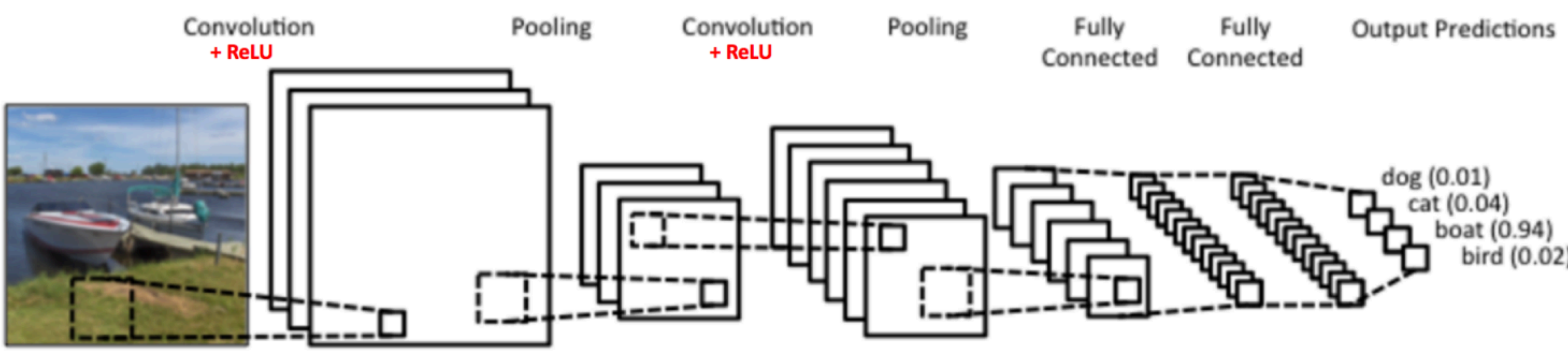
Train with SGD!

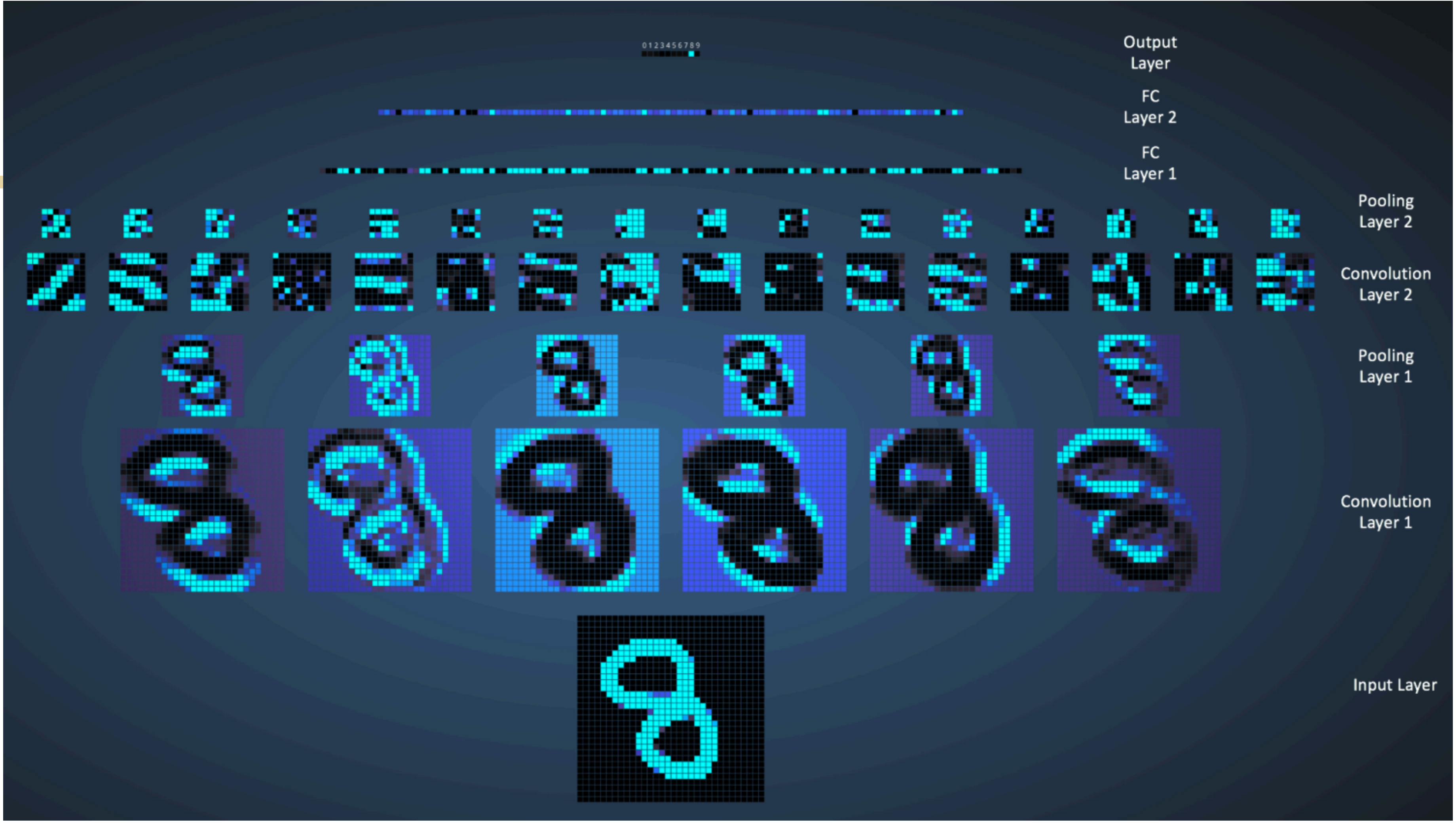


Training Convolutional Networks



Real example network: LeNet





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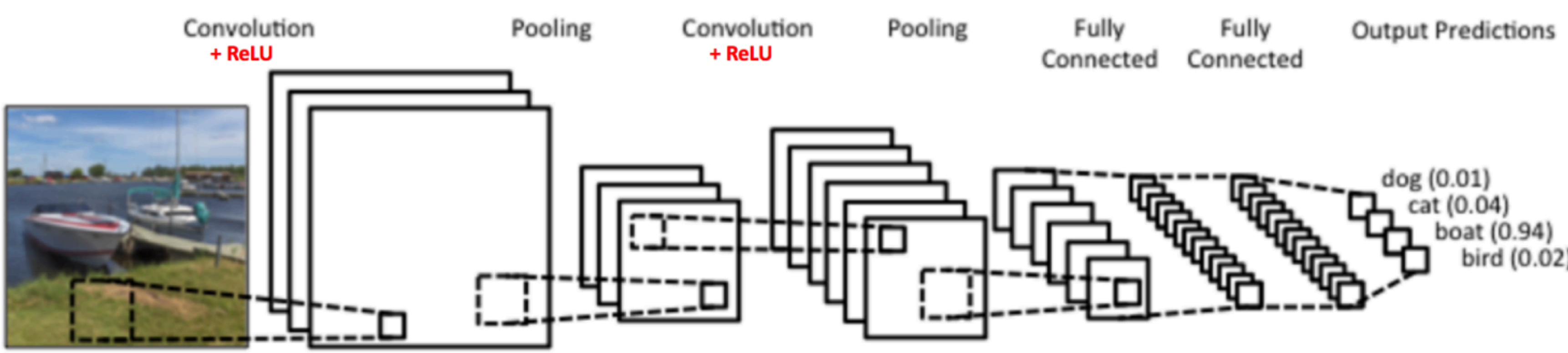


Famous CNNs

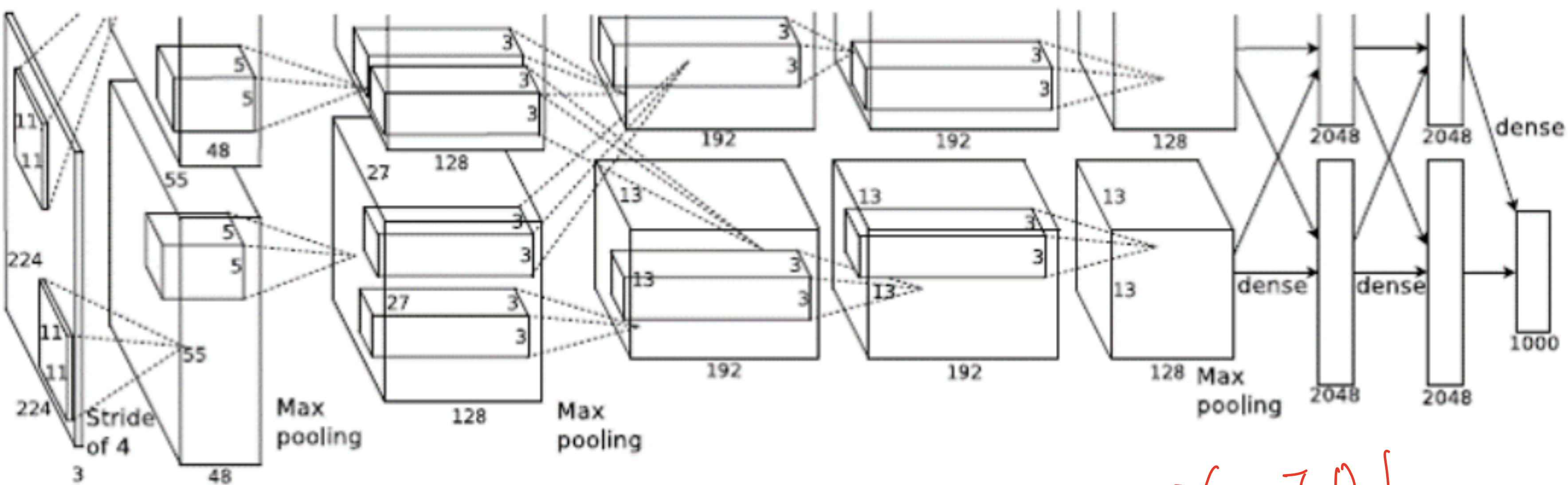
ImageNet Dataset

~14 million images, 20k classes

Deng et al. “Imagenet: a large scale hierarchical image database” ‘09

AlexNet

Breakthrough on ImageNet: ~the beginning of deep learning era



2022 NeurIPS
Test of time

Krizhevsky, Sutskever, Hinton “ImageNet Claasification with Deep Convolutional Neural Networks”, NIPS 2012.

AlexNet

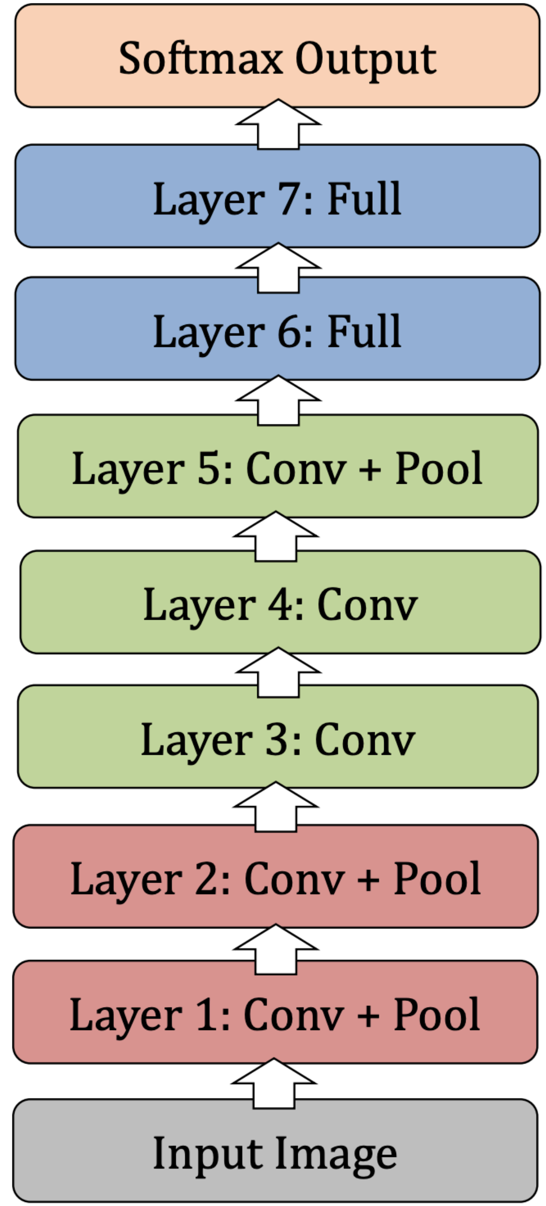
8 layers, ~60M parameters

Top5 error: 18.2%

Top1

Techniques used:

ReLU activation, overlapping pooling, dropout, ensemble (create 10 $\hat{y}_1, \ldots \hat{y}_{10}$ patches by cropping and average the predictions), data-augmentation (intensity of RGB channels)



[From Rob Fergus' CIFAR 2016 tutorial]

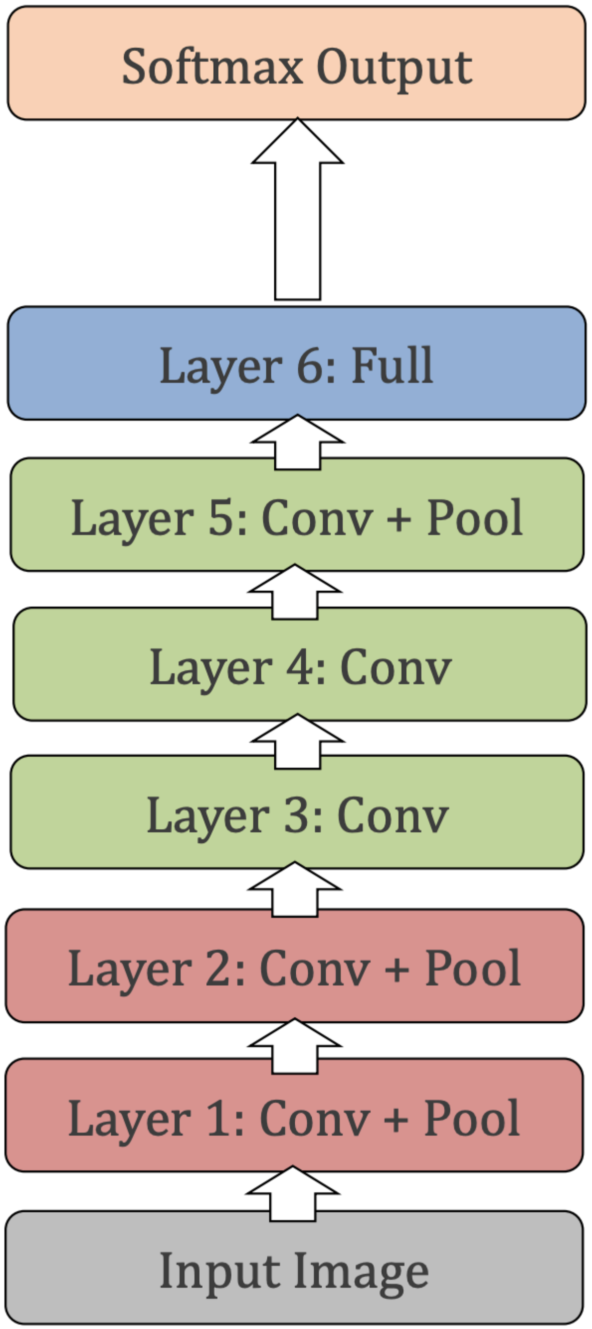
AlexNet

Remove top fully-connected layer 7

Drop ~16 million parameters

1.1% drop in performance

[From Rob Fergus' CIFAR 2016 tutorial]

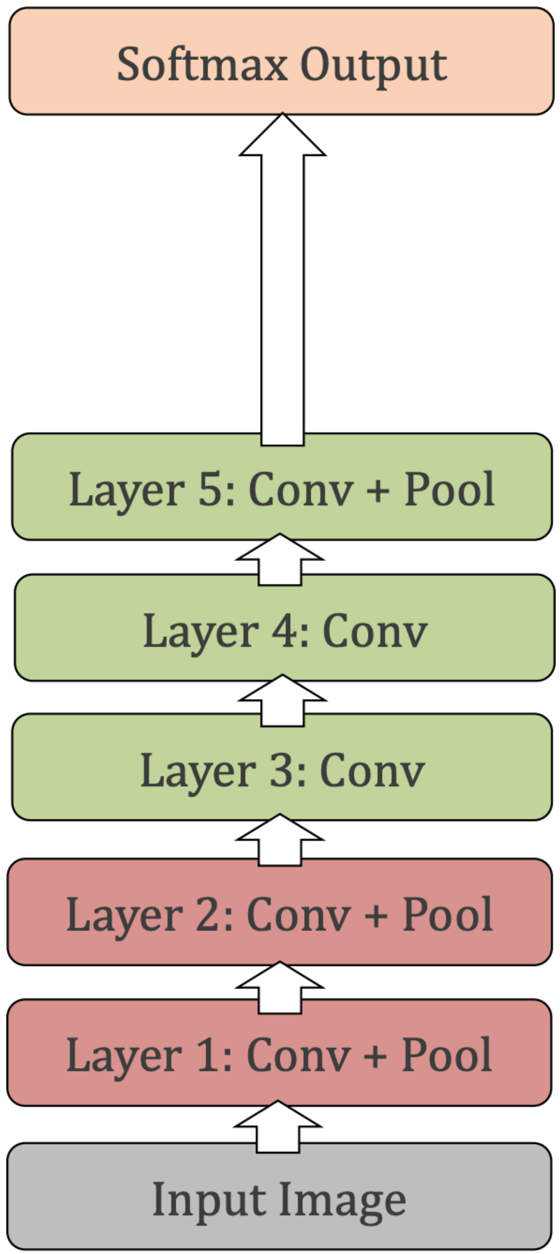


AlexNet

Remove both fully connected layers 6 and 7

Drop ~50 million parameters

5.7% drop in performance



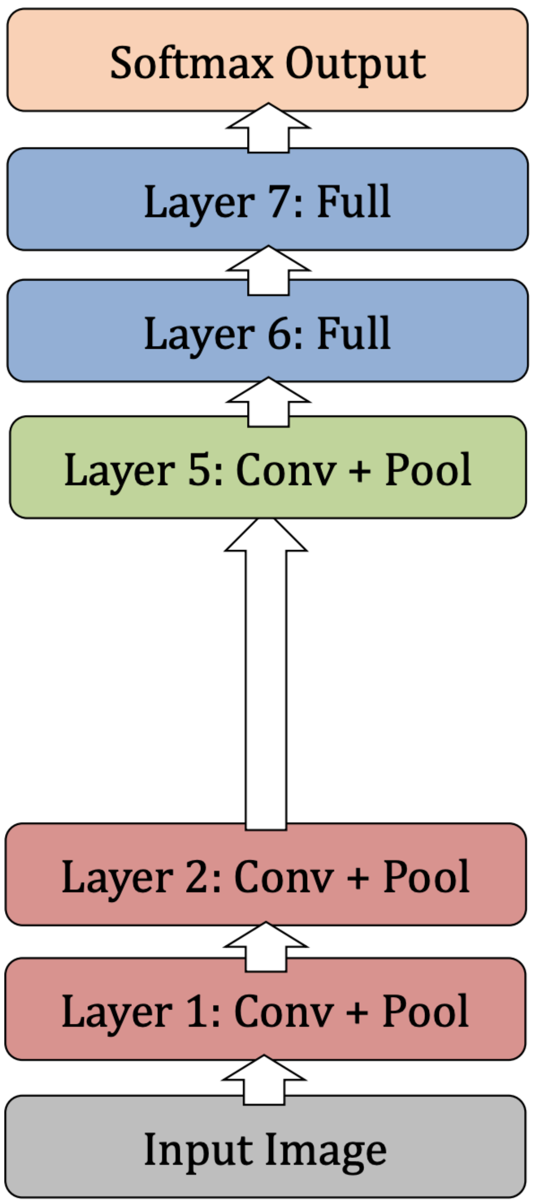
[From Rob Fergus' CIFAR 2016 tutorial]

AlexNet

Remove upper convolutio / feature extractor layers (layer 3 and 4)

Drop ~1 million parameters

3% drop in performance



[From Rob Fergus' CIFAR 2016 tutorial]

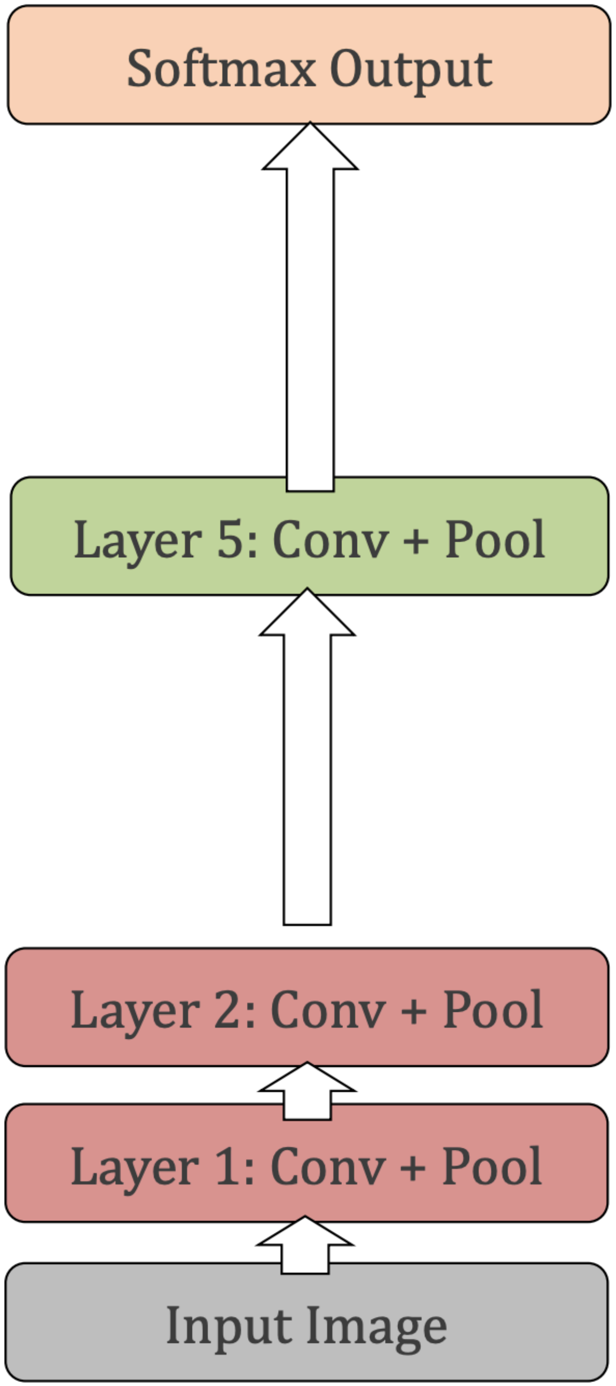
AlexNet

Remove top fully connected layer 6,7 and upper convolution layers 3,4.

33.5% drop in performance.

Depth of the network is the key.

[From Rob Fergus' CIFAR 2016 tutorial]



GoogLeNet

7x7, 5x5, 3x3, 1x1

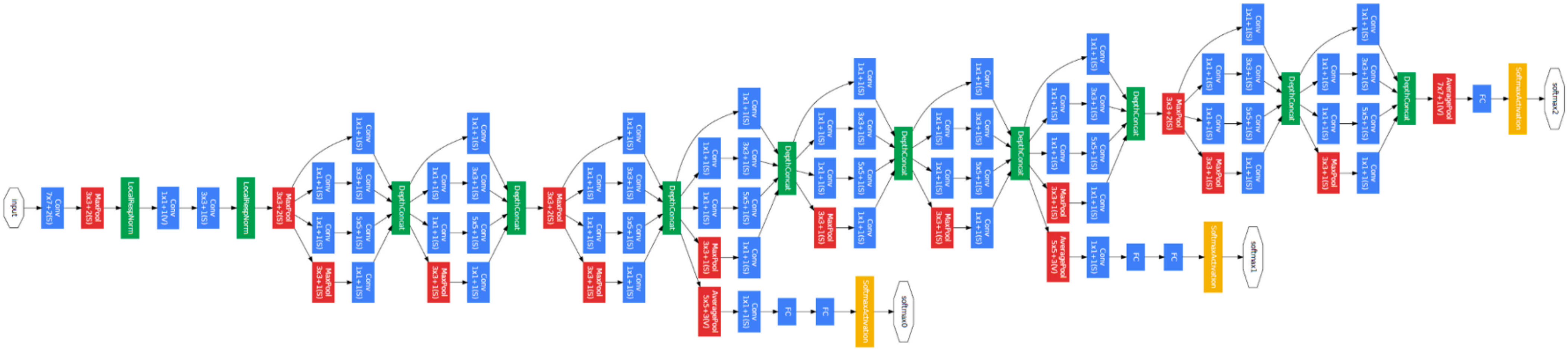
Motivation: multiscale nature of images

Large kernel for global features, and **smaller kernel** for local features.

Idea: have multiple different-size kernels at any layer.

[Going Deep with Convolutions, Szegedy et al. '14]

GoogLeNet



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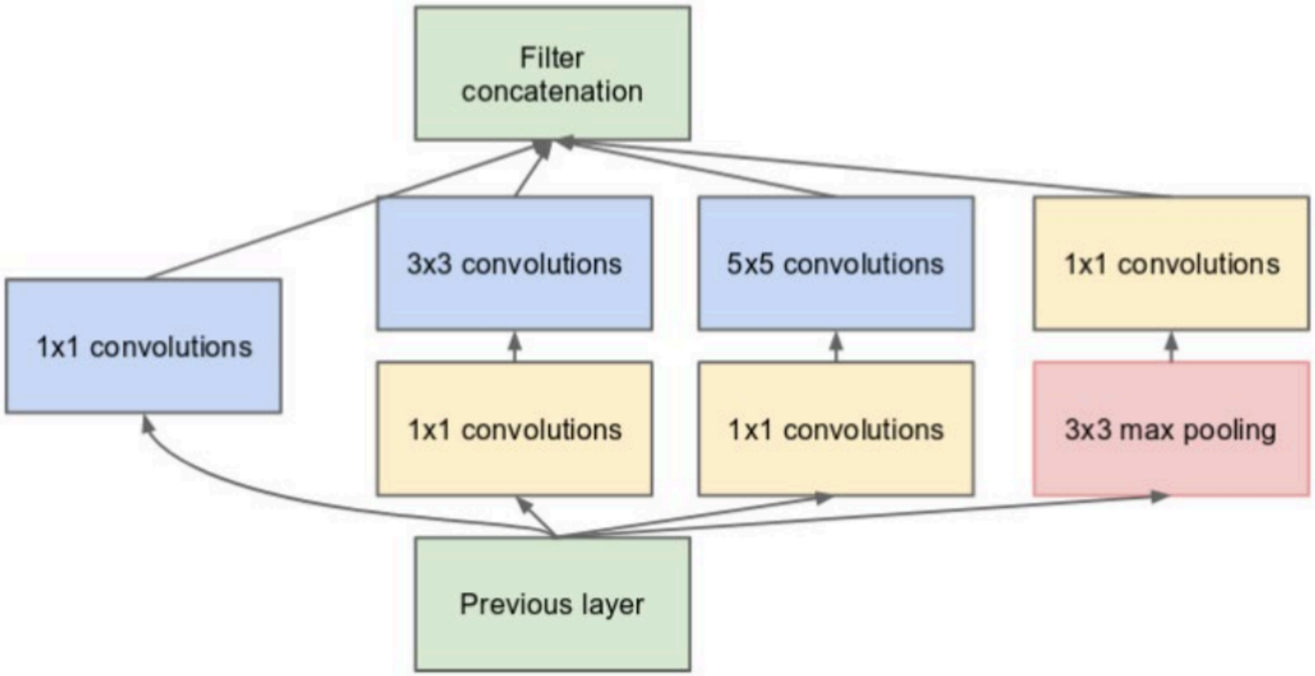
Inception Module



Multiple filter scales at each layer

Dimensionality reduction to keep computational requirements down

[Going Deep with Convolutions, Szegedy et al. ’14]

Residual Networks

Motivation: extremely deep nets are hard to train (gradient explosion/ vanishing)

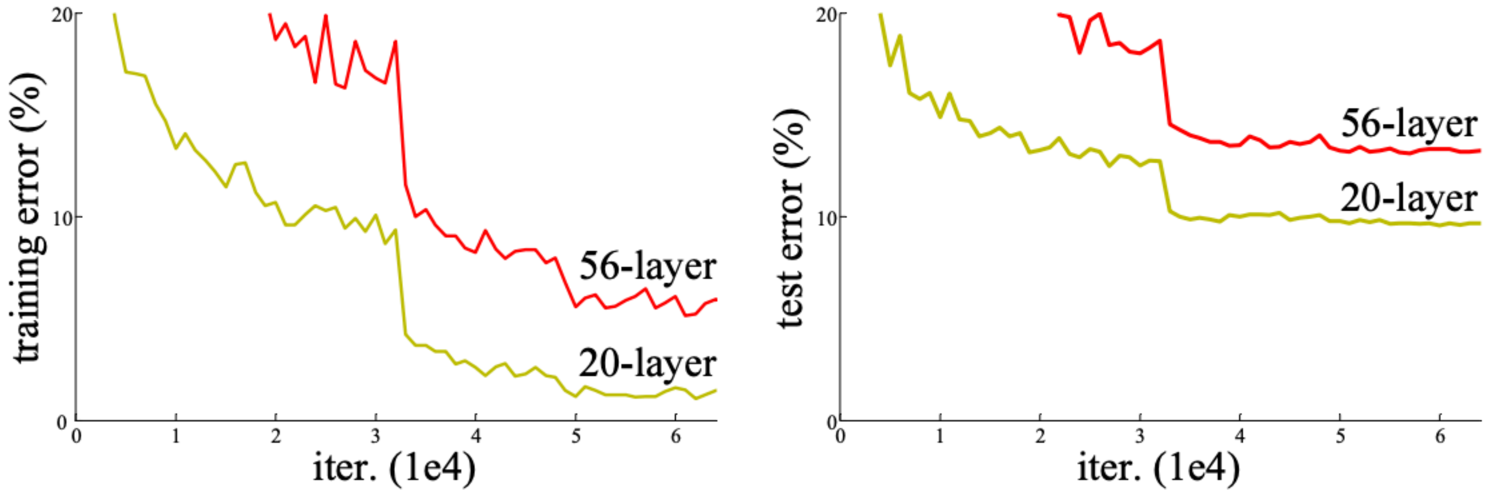


Figure 1. Training error (left) and test error (right) on CIFAR-10 with 20-layer and 56-layer "plain" networks. The deeper network has higher training error, and thus test error. Similar phenomena on ImageNet is presented in Fig. 4.

[He, Zhang, Ren, Sun, '16]

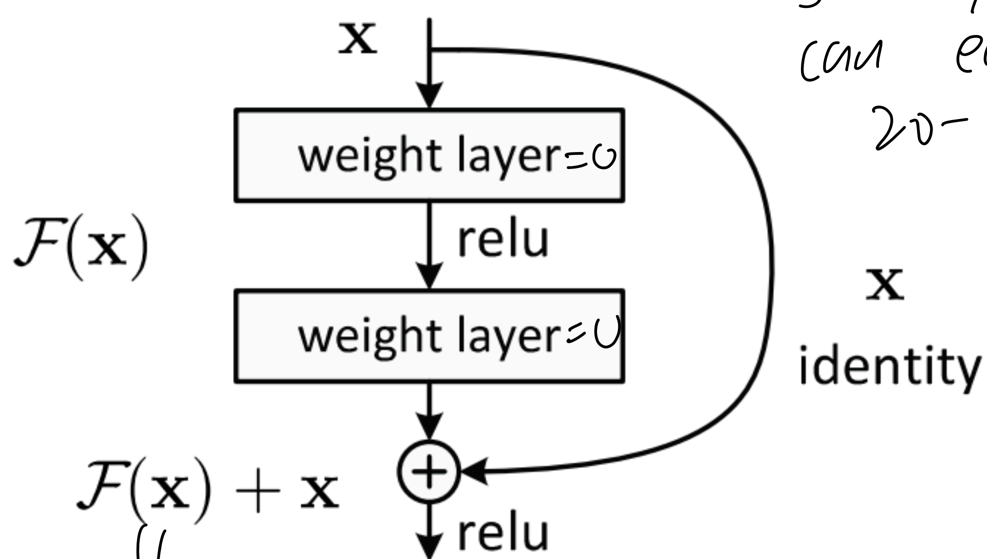
Residual Networks

Idea: identity shortcut, skip one or more layers.

Justification: network can easily simulate shallow network ($F \approx 0$), so performance should not degrade by going deeper.

56 layer NN can easily represent 20-layer NN

block



$\parallel$

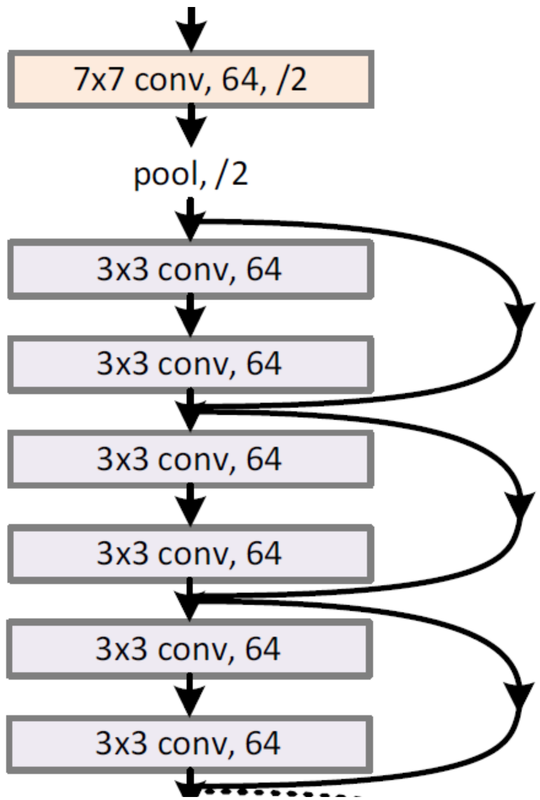
0

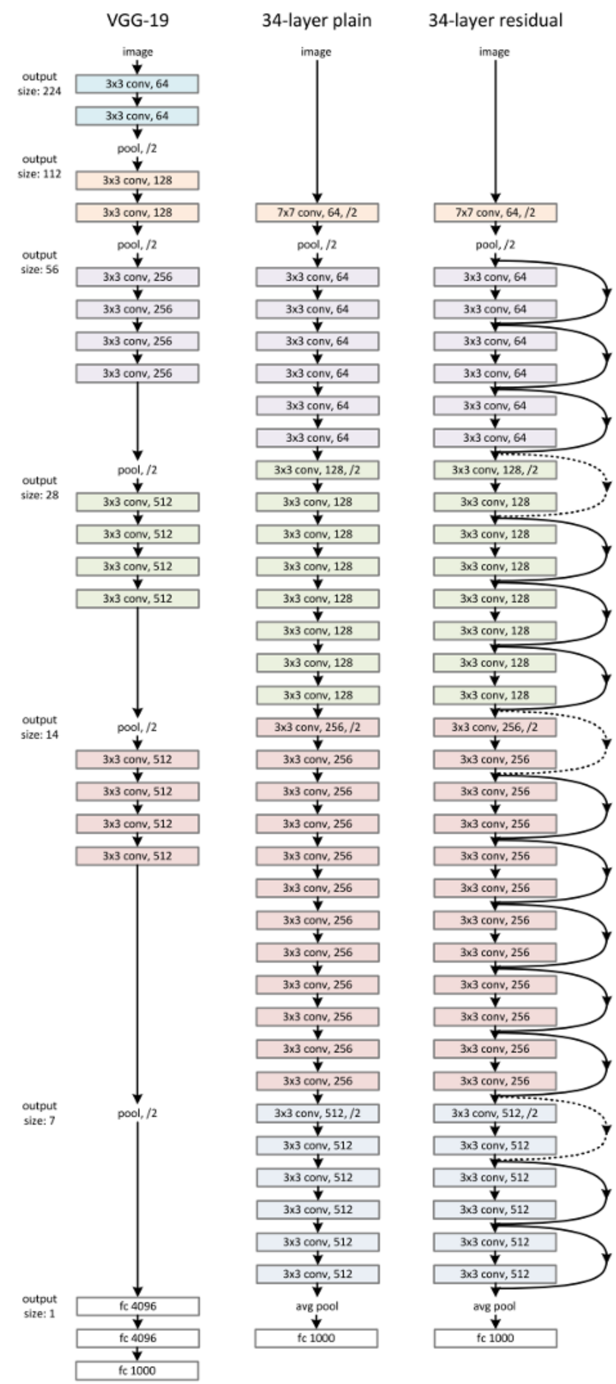
[He, Zhang, Ren, Sun, '16]

Residual Networks

vs. 18%

- 3.57% top-5 error on ImageNet
- First deep network with > 100 layers.
- Widely used in many domains (AlphaGo)





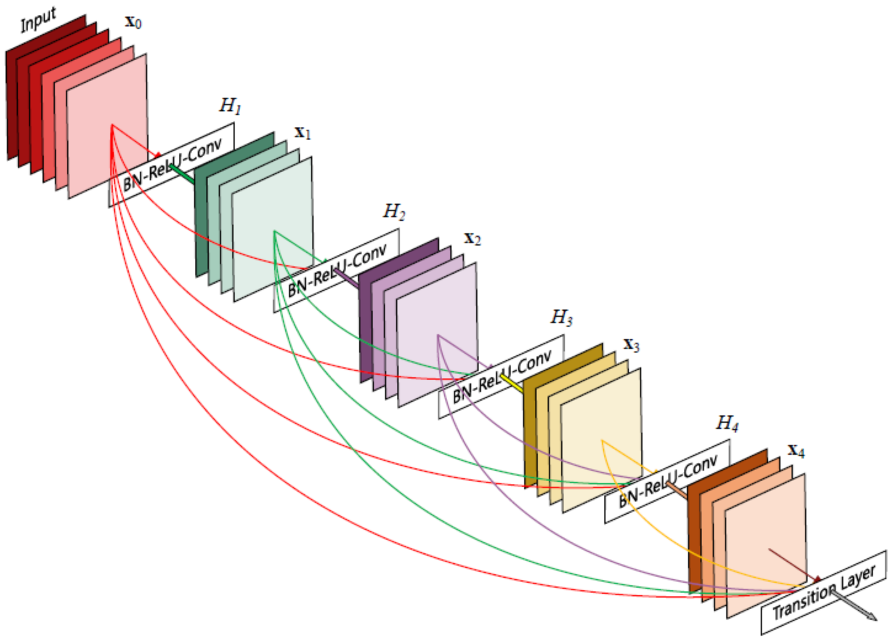
[He, Zhang, Ren, Sun, '16]

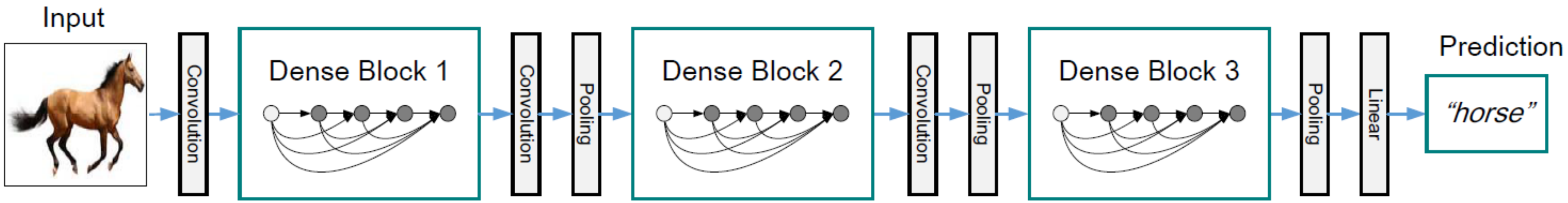
Densely Connected Network

Idea: explicit forward output of layer to all future layers (by concatenation)

Intuition: helps vanishing gradients, encourage reuse features (reduce parameter count)

Issues: network maybe too wide, need to be careful about memory consumption





[He, Zhang, Ren, Sun, '16]

Neural Architecture / Hyper-Parameter Search

Many design choices:
- Number of layers, width, kernel size, pooling, connections, etc.
- Normalization, learning rate, batch size, etc.

Strategies:
- Grid search
- Random search [Bergestra & Bengio '12]
- Bandit-based [Li et al. '16]
- Gradient-based (DARTS) [Liu et al. '19]
- Neural tangent kernel [Xu et al. '21]
- …