

Computer Vision

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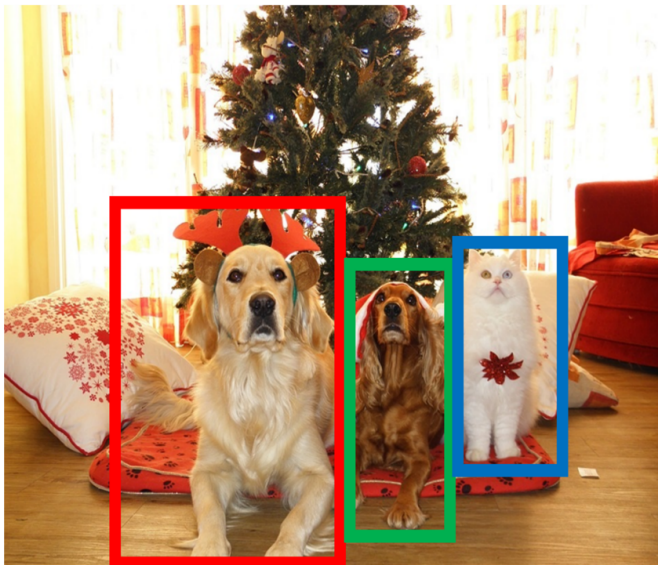
January 28, 2026

1. Object Detection
2. Region Proposal and R-CNN
3. YOLO and Single Shot Detection
4. Instance Segmentation
5. Mask R-CNN
6. Panoptic Segmentation

- ▶ Understand the fundamentals of object detection and its challenges.
- ▶ Learn different region proposal techniques such as R-CNN and Faster R-CNN.
- ▶ Explore one-stage object detection approaches like YOLO.
- ▶ Understand the concepts of instance segmentation and Mask R-CNN.
- ▶ Differentiate between semantic, instance and panoptic segmentation.

- ▶ **Input:** Single RGB Image
- ▶ **Output:** A set of detected objects. For each object predict:
 - Category label (from fixed, known set of categories)
 - Bounding box (four numbers: x , y , width, height)

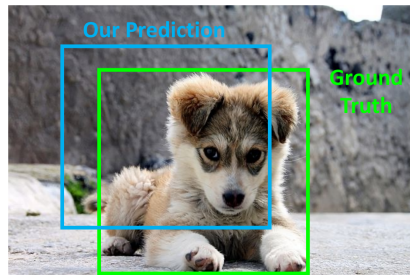
Object Detection (cont.)



- ▶ **Multiple outputs:** Need to output variable numbers of objects per image
- ▶ **Multiple types of output:** Need to predict "what" (category label) as well as "where" (bounding box)
- ▶ **Large images:** Classification works at 224x224; need higher resolution for detection, often $\sim 800 \times 600$

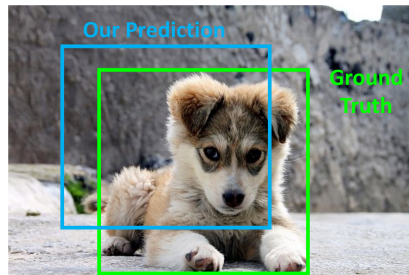
Comparing Boxes: Intersection over Union (IoU)

- ▶ How can we compare our prediction to the ground-truth box?



- ▶ How can we compare our prediction to the ground-truth box?
- ▶ **Intersection over Union (IoU)**
(Also called "Jaccard similarity" or "Jaccard index"):

$$\frac{\text{Area of Intersection}}{\text{Area of Union}}$$

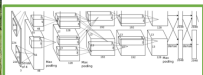


Detecting a Single Object

Often pretrained
on ImageNet
(Transfer learning)



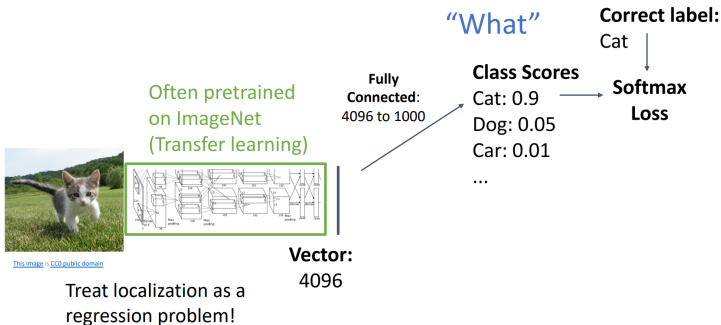
[This image](#) is CC0 public domain



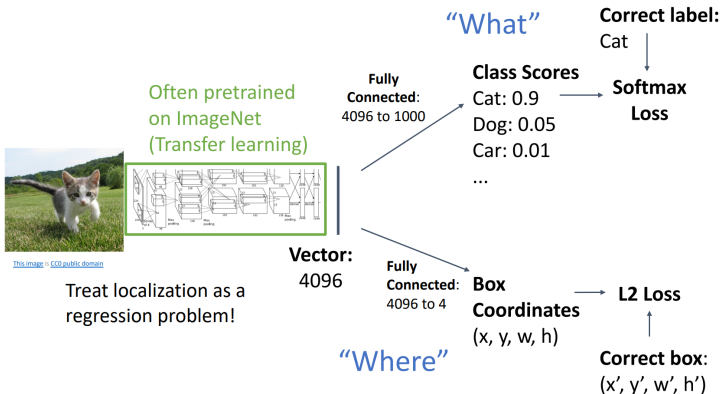
Vector:
4096

Treat localization as a
regression problem!

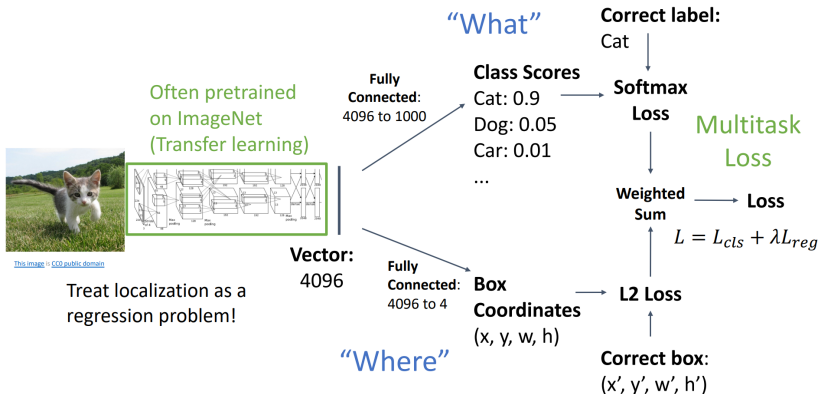
Detecting a Single Object (cont.)



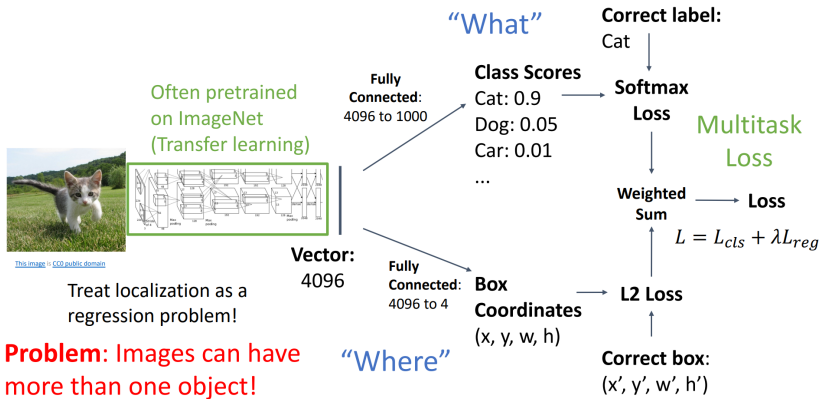
Detecting a Single Object (cont.)

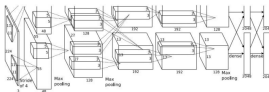


Detecting a Single Object (cont.)

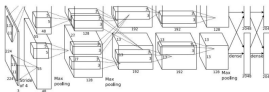


Detecting a Single Object (cont.)





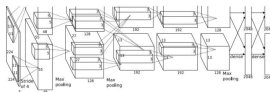
CAT: (x, y, w, h)



DOG: (x, y, w, h)

DOG: (x, y, w, h)

CAT: (x, y, w, h)



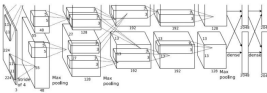
DUCK: (x, y, w, h)

DUCK: (x, y, w, h)

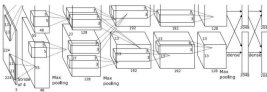
....

Multiple Objects (cont.)

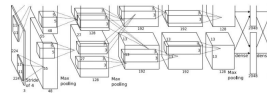
Each image needs a
different number of outputs!



CAT: (x, y, w, h) 4 numbers



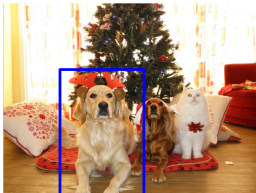
DOG: (x, y, w, h)
DOG: (x, y, w, h) 12 numbers
CAT: (x, y, w, h)



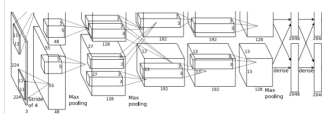
DUCK: (x, y, w, h) Many
DUCK: (x, y, w, h) numbers!

....

Detecting Multiple Objects: Sliding Window (cont.)



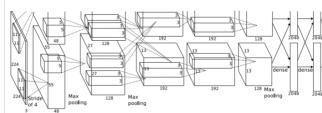
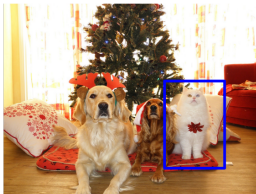
Apply a CNN to many different crops of the image, CNN classifies each crop as object or background



Dog? **YES**
Cat? **NO**
Background? **NO**

Detecting Multiple Objects: Sliding Window (cont.)

Apply a CNN to many different crops of the image, CNN classifies each crop as object or background



Dog? **NO**
Cat? **YES**
Background? **NO**

Apply a CNN to many different crops of the image, CNN classifies each crop as object or background

Question: How many possible boxes are there in an image of size $H \times W$?





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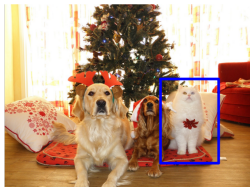
Consider a box of size $h \times w$:

Possible x positions: $W - w + 1$

Possible y positions: $H - h + 1$

Possible positions:

$(W - w + 1) * (H - h + 1)$



Apply a CNN to many different crops of the image, CNN classifies each crop as object or background

Question: How many possible boxes are there in an image of size $H \times W$?

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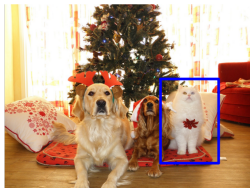
Possible positions:

$(W - w + 1) * (H - h + 1)$

Total possible boxes:

$$\sum_{h=1}^H \sum_{w=1}^W (W - w + 1)(H - h + 1)$$
$$= \frac{H(H+1)}{2} \frac{W(W+1)}{2}$$

Detecting Multiple Objects: Sliding Window (cont.)



Apply a CNN to many different crops of the image, CNN classifies each crop as object or background

800 x 600 image
has ~58M boxes!
No way we can
evaluate them all

Question: How many possible boxes are there in an image of size $H \times W$?

Consider a box of size $h \times w$:

Possible x positions: $W - w + 1$

Possible y positions: $H - h + 1$

Possible positions:

$(W - w + 1) * (H - h + 1)$

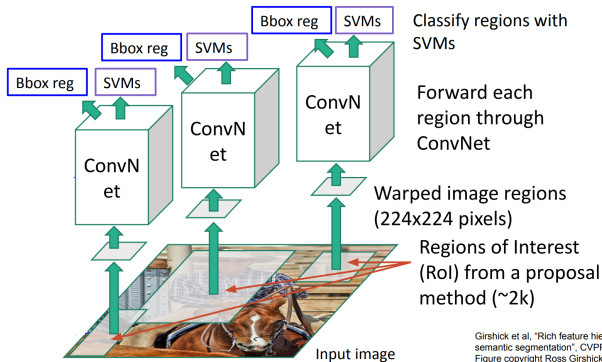
Total possible boxes:

$$\sum_{h=1}^H \sum_{w=1}^W (W - w + 1)(H - h + 1)$$
$$= \frac{H(H+1)}{2} \frac{W(W+1)}{2}$$

- ▶ Find a small set of boxes that are likely to cover all objects
- ▶ Often based on heuristics: e.g. look for “blob-like” image regions
- ▶ Relatively fast to run; e.g. Selective Search gives 2000 region proposals in a few seconds on CPU

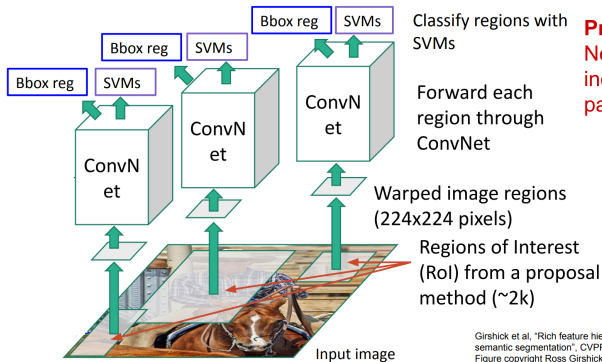


Predict “corrections” to the RoI: 4 numbers: (dx, dy, dw, dh)



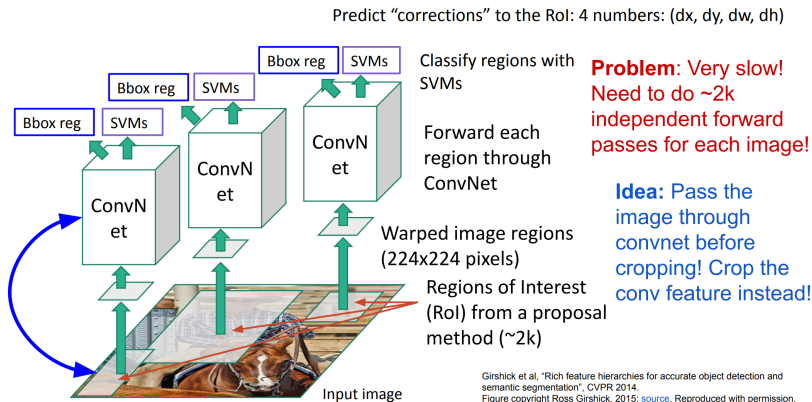
Girshick et al, “Rich feature hierarchies for accurate object detection and semantic segmentation”, CVPR 2014.
Figure copyright Ross Girshick, 2015; [source](#). Reproduced with permission.

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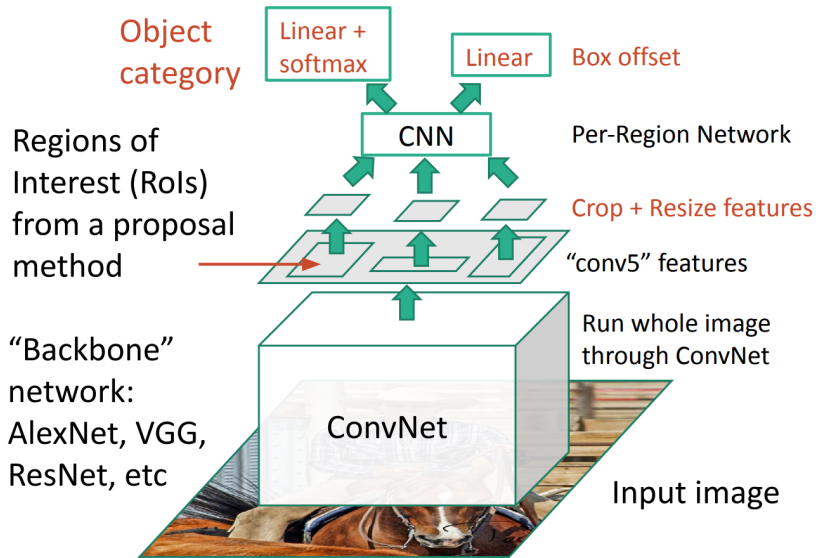


Problem: Very slow!
Need to do ~2k
independent forward
passes for each image!

Girshick et al, “Rich feature hierarchies for accurate object detection and semantic segmentation”, CVPR 2014.
Figure copyright Ross Girshick, 2015; [source](#). Reproduced with permission.

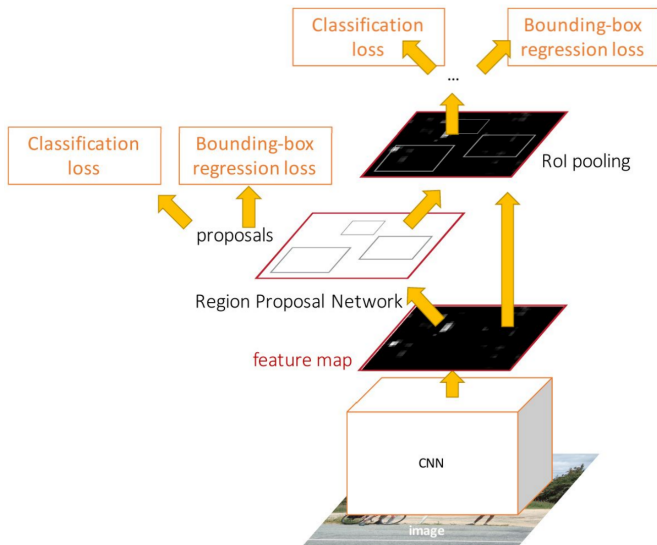


Girshick et al, "Rich feature hierarchies for accurate object detection and semantic segmentation", CVPR 2014.
Figure copyright Ross Girshick, 2015; [source](#). Reproduced with permission.



- ▶ Make CNN do proposals!
- ▶ Insert Region Proposal Network (RPN) to predict proposals from features

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- ▶ Insert Region Proposal Network (RPN) to predict proposals from features
- ▶ Jointly train on 4 losses:
 - **RPN classification:** anchor box is object / not an object
 - **RPN regression:** predict transform from anchor box to proposal box
 - **Object classification:** classify proposals as background / object class
 - **Object regression:** predict transform from proposal box to object box



Faster R-CNN:

Make CNN do proposals!

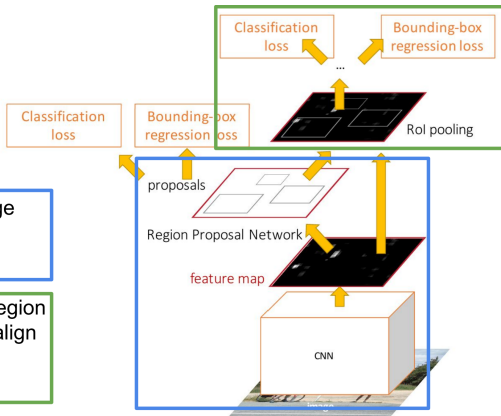
Faster R-CNN is a
Two-stage object detector

First stage: Run once per image

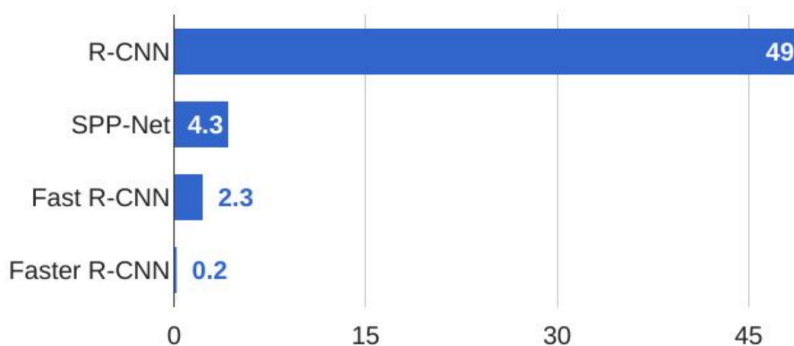
- Backbone network
- Region proposal network

Second stage: Run once per region

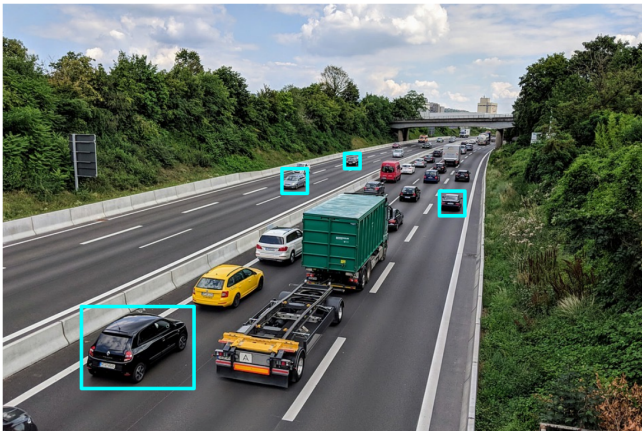
- Crop features: RoI pool / align
- Predict object class
- Prediction bbox offset



R-CNN Test-Time Speed

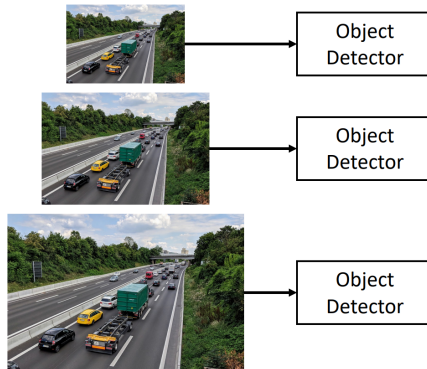


- ▶ We need to detect objects of many different scales.
- ▶ How to improve scale invariance of the detector



Dealing with Scale: Image Pyramid

Classic idea: build an *image pyramid* by resizing the image to different scales, then process each image scale independently.



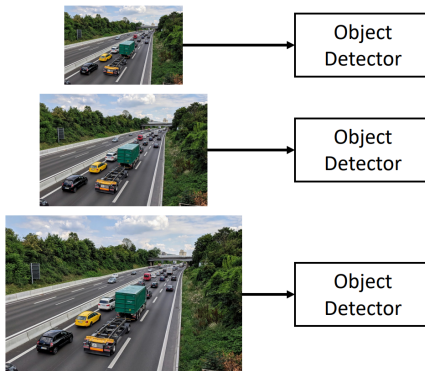
Lin et al, "Feature Pyramid Networks for Object Detection", ICCV 2017

Dealing with Scale: Image Pyramid (cont.)

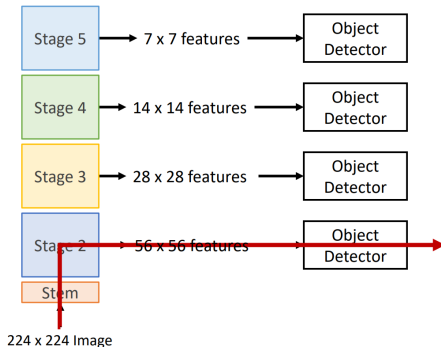
Classic idea: build an *image pyramid* by resizing the image to different scales, then process each image scale independently.

Problem: Expensive! Don't share any computation between scales

Lin et al, "Feature Pyramid Networks for Object Detection", ICCV 2017



CNNs have multiple *stages* that operate at different resolutions. Attach an independent detector to the features at each level



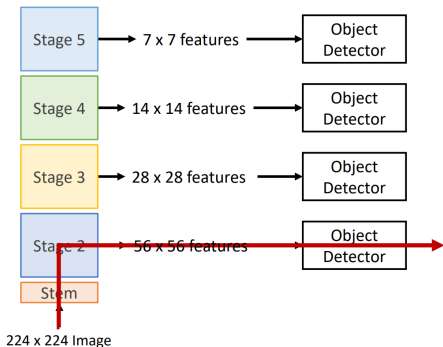
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Dealing with Scale: Image Pyramid (cont.)

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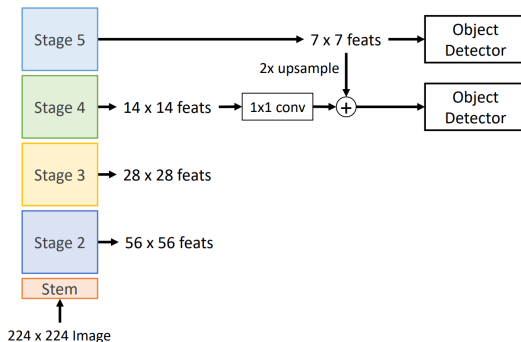
Problem: detector on early features doesn't make use of the entire backbone; doesn't get access to high-level features

Lin et al, "Feature Pyramid Networks for Object Detection", ICCV 2017



Dealing with Scale: Feature Pyramid Network

Add *top down* connections that feed information from high level features back down to lower level features



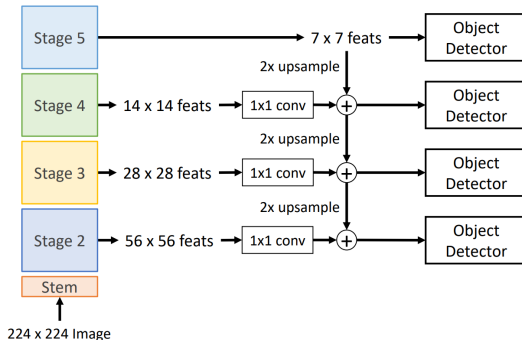
Lin et al, "Feature Pyramid Networks for Object Detection", ICCV 2017

Dealing with Scale: Feature Pyramid Network (cont.)

Add *top down* connections that feed information from high level features back down to lower level features

Efficient multiscale features where all levels benefit from the whole backbone! Widely used in practice

Lin et al, "Feature Pyramid Networks for Object Detection", ICCV 2017

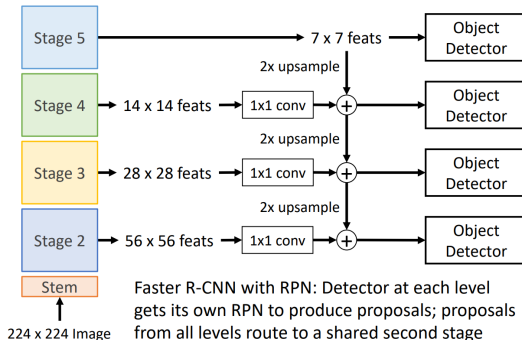


Dealing with Scale: Feature Pyramid Network (cont.)

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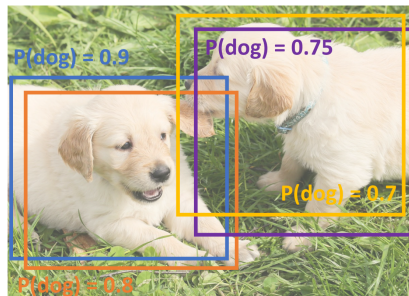
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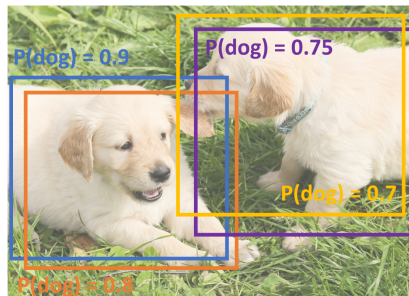
Overlapping Boxes: Non-Max Suppression (NMS)

- **Problem:** Object detectors often output many overlapping detections



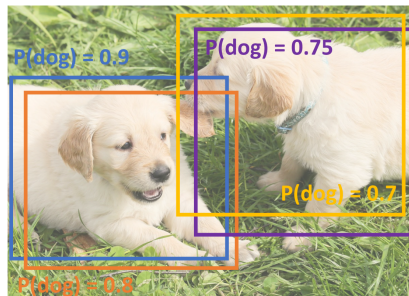
Overlapping Boxes: Non-Max Suppression (NMS)

- **Problem:** Object detectors often output many overlapping detections
- **Solution:** Post-process raw detections using Non-Max Suppression (NMS)

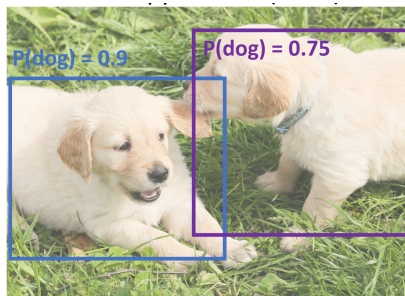


Overlapping Boxes: Non-Max Suppression (NMS)

- **Problem:** Object detectors often output many overlapping detections
- **Solution:** Post-process raw detections using Non-Max Suppression (NMS)
 1. Select next highest-scoring box
 2. Eliminate lower-scoring boxes
 3. with $\text{IoU} > \text{threshold}$ (e.g. 0.7)
 4. If any boxes remain, GOTO 1



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- ▶ **Solution:** Post-process raw detections using Non-Max Suppression (NMS)
 1. Select next highest-scoring box
 2. Eliminate lower-scoring boxes
 3. with $\text{IoU} > \text{threshold}$ (e.g. 0.7)
 4. If any boxes remain, GOTO 1
- ▶ **Problem:** NMS may eliminate "good" boxes when objects are highly overlapping. . . no good solution =(

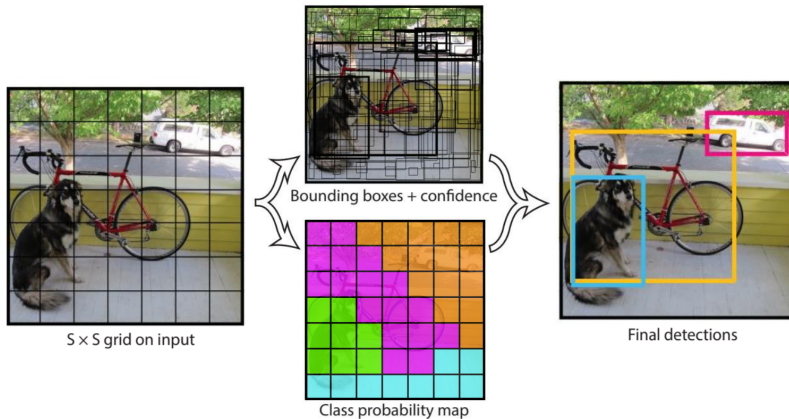


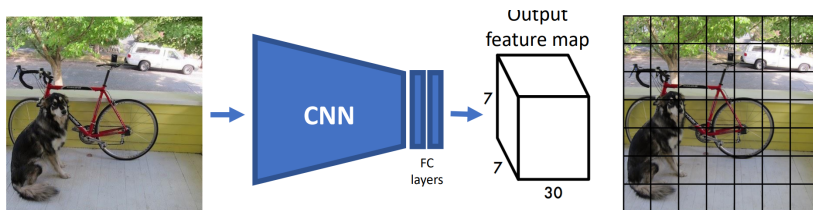


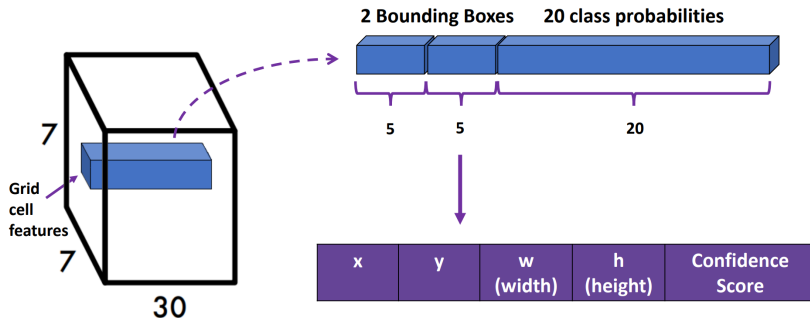
Single Shot:
SSD, **YOLO** ...

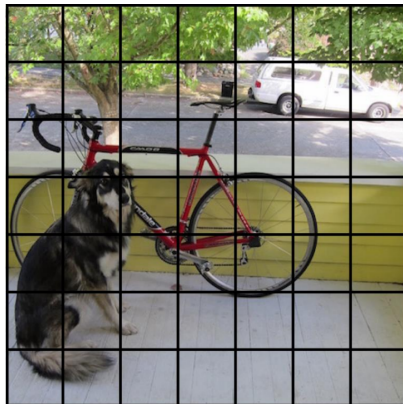
Fast

High false rate

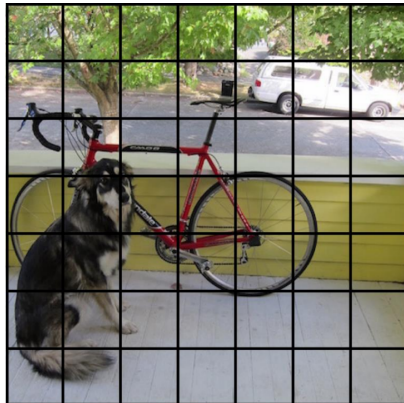






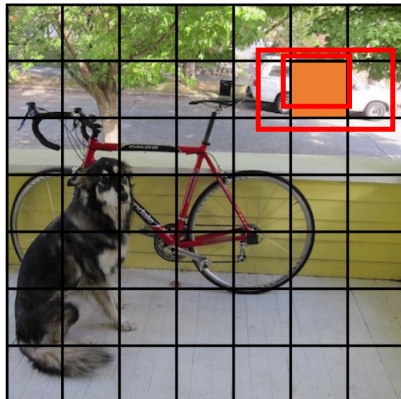


Each cell predicts



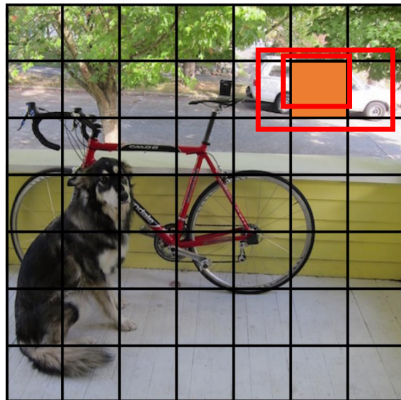
Each cell predicts

- ▶ $B = 2$ bounding boxes
(x, y, w, h) + confidence score



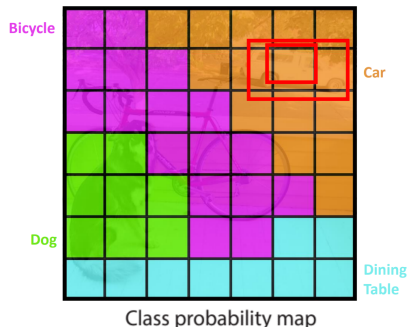
Each cell predicts

- ▶ $B = 2$ bounding boxes
(x, y, w, h) + confidence score
- ▶ $C = 20$ class probabilities



Each cell predicts

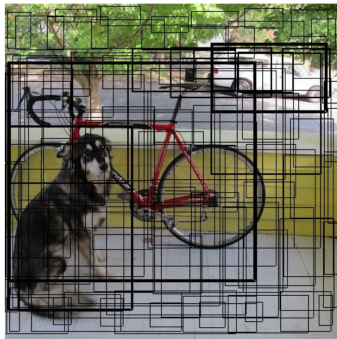
- ▶ $B = 2$ bounding boxes
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- ▶ $C = 20$ class probabilities



Each cell predicts

- ▶ $B = 2$ bounding boxes
(x, y, w, h) + confidence score
- ▶ $C = 20$ class probabilities

$S \times S \times B$ Bounding-Boxes ($S=7, B=2 \rightarrow 98$ Bboxes)



$S \times S$ grid on input

SxSxB Bounding-Boxes ($S=7, B=2 \rightarrow 98$ Bboxes)

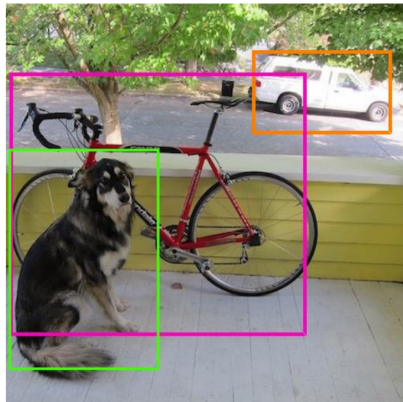
Each cell predicts

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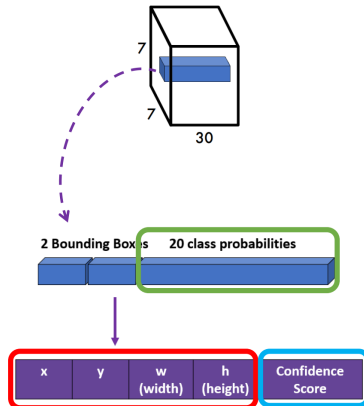
Each cell predicts

- ▶ $B = 2$ bounding boxes
(x, y, w, h) + confidence score
- ▶ $C = 20$ class probabilities
- ▶ Apply Non-Maximum Suppression

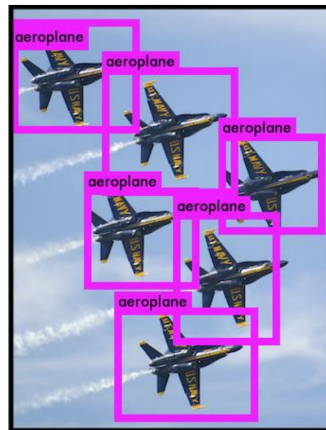
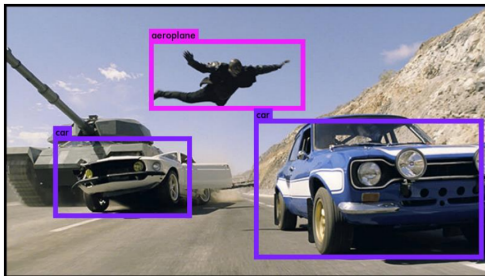


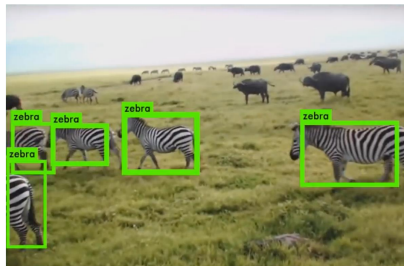
YOLO – Loss function

$$\mathcal{L} = \mathcal{L}_{Localization Loss} + \mathcal{L}_{Confidence Loss} + \mathcal{L}_{Classification Loss}$$

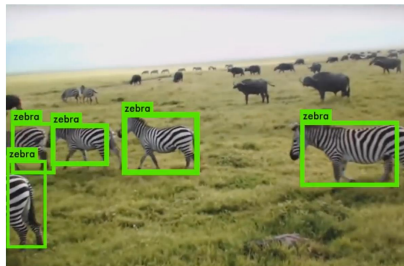


- ▶ Fast. Good for real-time processing
- ▶ End-to-end training

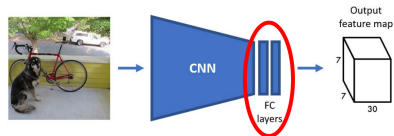




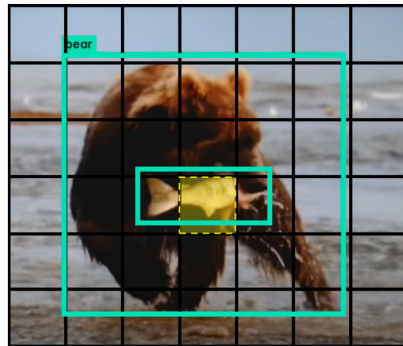
- ▶ Difficult to detect small objects
- ▶ Coarse predictions



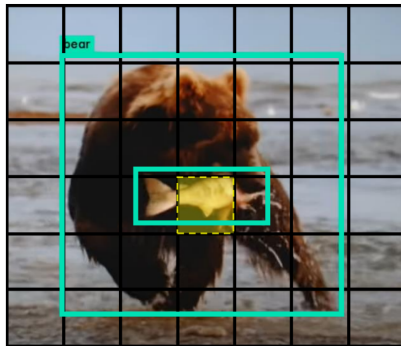
- ▶ Difficult to detect small objects
- ▶ Coarse predictions
- ▶ Fixed input size



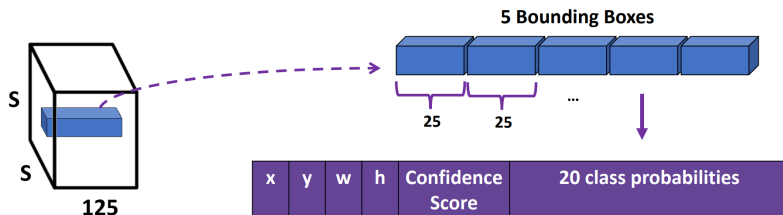
- ▶ Difficult to detect small objects
- ▶ Coarse predictions
- ▶ Fixed input size
- ▶ A grid cell can predict only one class



- ▶ Difficult to detect small objects
 - ▶ Coarse predictions
 - ▶ Fixed input size
 - ▶ A grid cell can predict only one class
- ▶ **Solutions:**
- Remove fc layers!
 - Predict class per bbox (not per cell)



- ▶ Removed fully connected layers
- ▶ A grid cell predicts class probabilities for each box



► YOLOv3

- J. Redmon, A. Farhadi. Yolov3: An incremental improvement, 2018

► YOLOv4

- A. Bochkovskiy, C. Wang, H. Liao. Yolov4: Optimal speed and accuracy of object detection (Feb. 2020)

► YOLOv5

- YOLOv5 by ultralytics (June 2020)

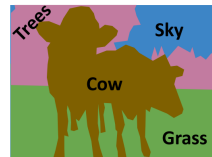
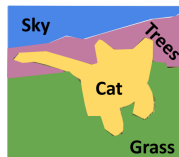
► PP-YOLO

- X. Long, K. Deng, G. Wang, Y. Zhang, Q. Dang, Y. Gao, H. Shen, J. Ren, S. Han, E. Ding, S. Wen. Pp-yolo: An effective and efficient implementation of object detector (June 2020)

► PP-YOLOv2 (2021)

- J. X. Huang, X. Wang, W. Lv, X. Bai, X. Long, K. Deng, Q. Dang, S. Han, Q. Liu, X. Hu, D. Yu, Y. Ma, O. Yoshie. PP-YOLOv2: A Practical Object Detector (2021)

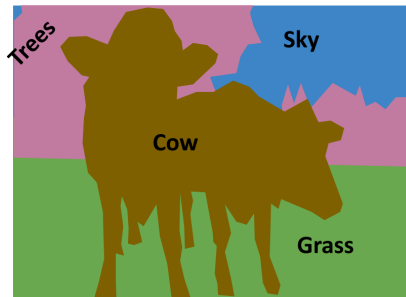
- **Things:** Object categories that can be separated into object instances (e.g. cats, cars, person)
- **Stuff:** Object categories that cannot be separated into instances (e.g. sky, grass, water, trees)



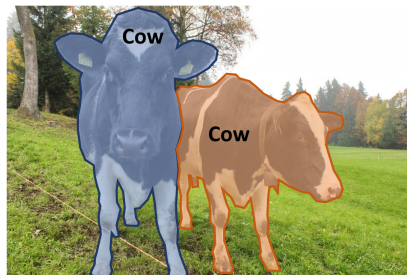
- **Object Detection:** Detects individual object instances, but only gives box(Only things!)



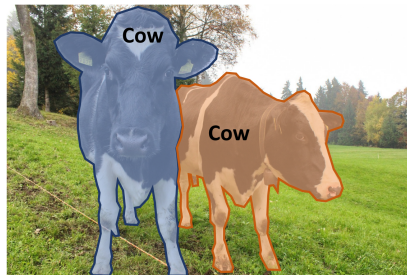
- **Semantic Segmentation:**
Gives per-pixel labels, but merges instances (Both things and stuff)

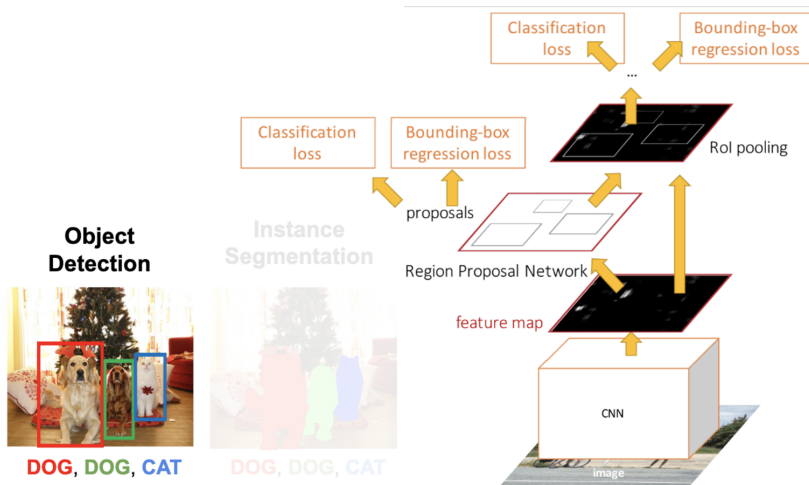


- Detect all objects in the image, and identify the pixels that belong to each object (Only things!)

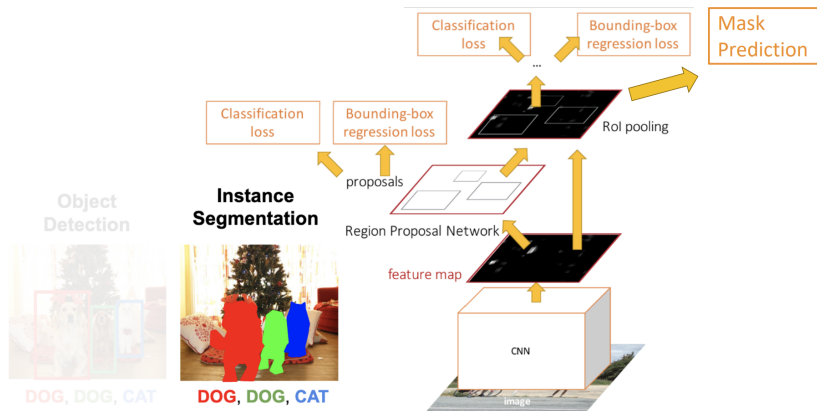


- ▶ Detect all objects in the image, and identify the pixels that belong to each object (Only things!)
- ▶ **Approach:** Perform object detection, then predict a segmentation mask for each object!



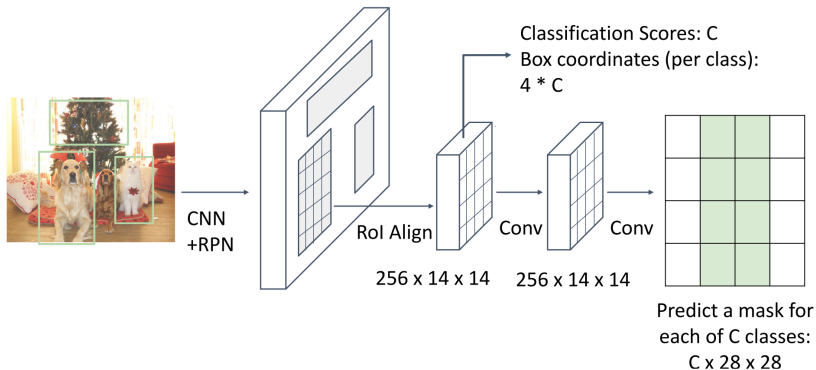


Instance Segmentation: Mask R-CNN

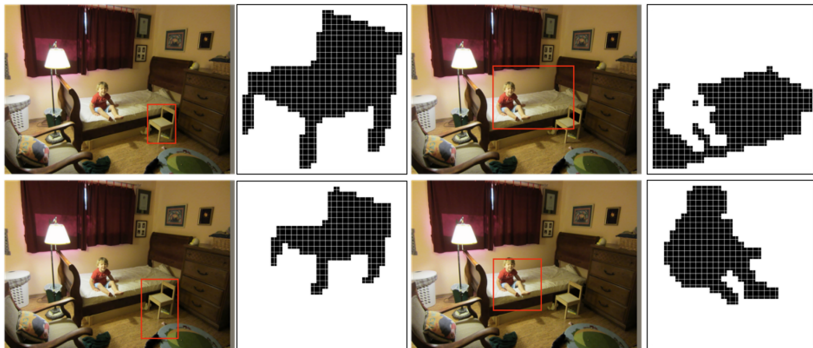


⁰He et al, "Mask R-CNN", ICCV 2017

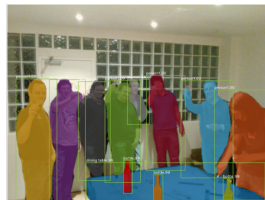
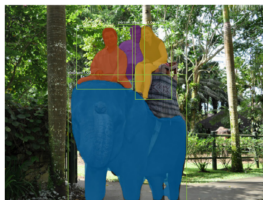
Instance Segmentation: Mask R-CNN



Mask R-CNN: Example Training Targets

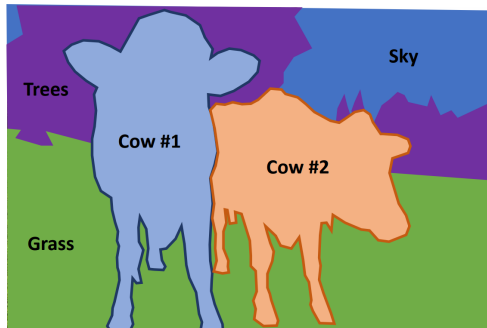


Mask R-CNN: Very Good Results!

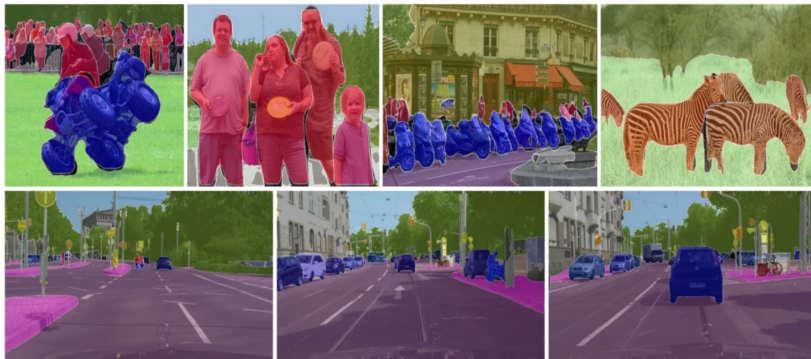


Beyond Instance Segmentation: Panoptic Segmentation

- ▶ Label all pixels in the image (both things and stuff)
- ▶ For "thing" categories also separate into instances



Beyond Instance Segmentation: Panoptic Segmentation

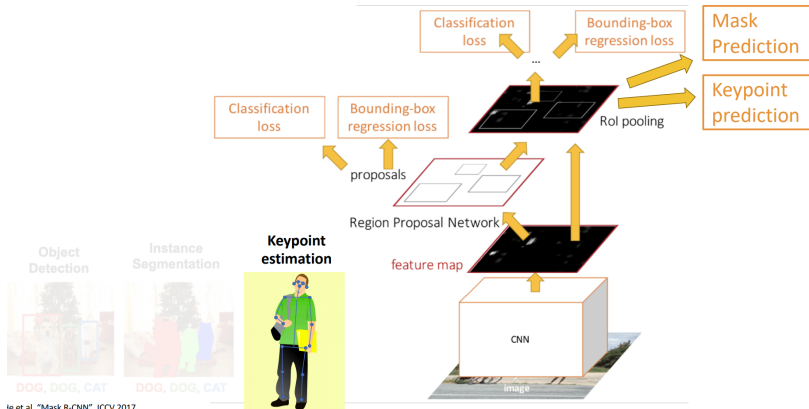


⁰Kirillov et al, "Panoptic Feature Pyramid Networks", CVPR 2019

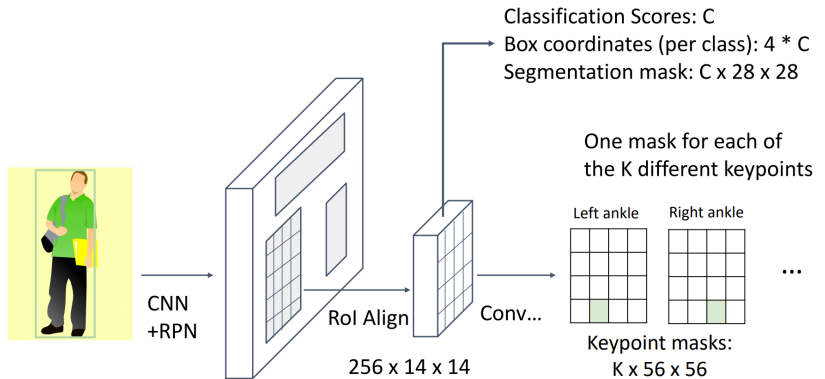
- ▶ Represent the pose of a human by locating a set of keypoint se.g. 17 keypoints:
- ▶ Nose
- ▶ Left / Right eye
- ▶ Left / Right earLeft / Right shoulder
- ▶ Left / Right elbow
- ▶ Left / Right wrist



Mask R-CNN: Keypoint Estimation



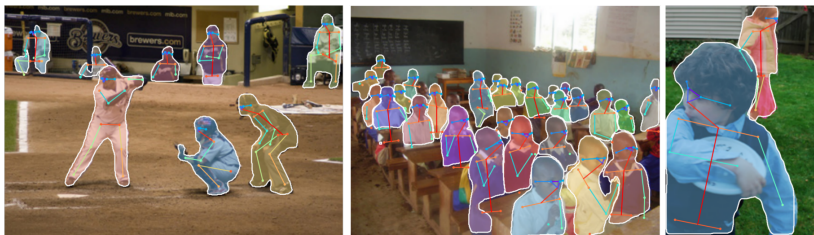
Mask R-CNN: Keypoint Estimation



Do et al. "Mask R-CNN" ICCV 2017

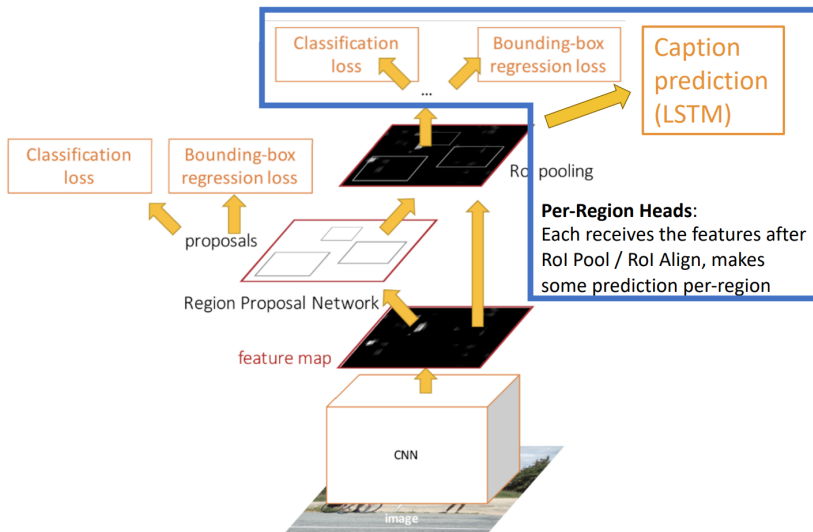
Ground-truth has one "pixel" turned on per keypoint. Train with softmax loss

Joint Instance Segmentation and Pose Estimation

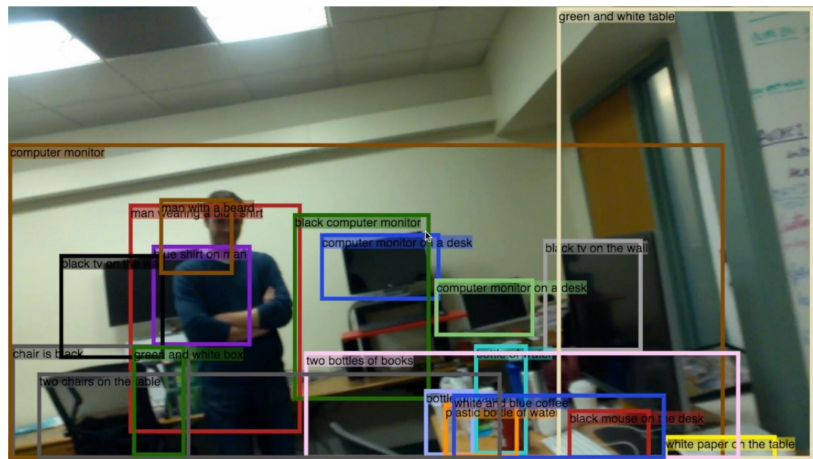


⁰He et al, "Mask R-CNN", ICCV 2017

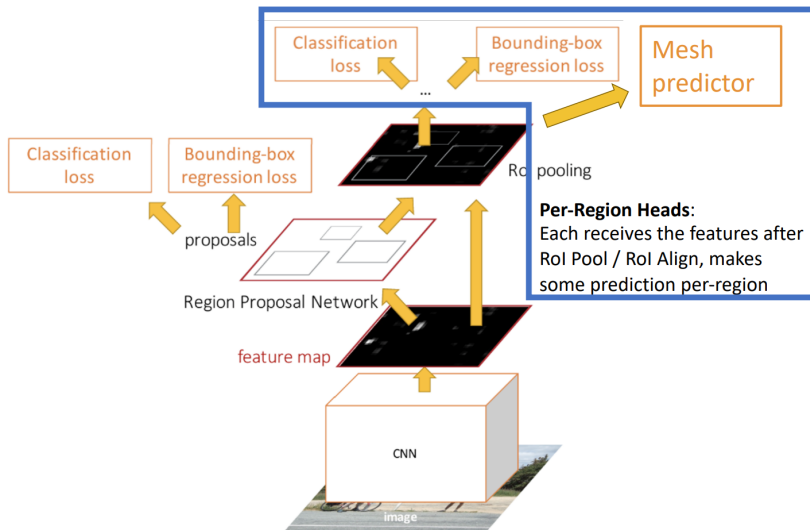
Captioning: Predict a caption per region!



Captioning: Predict a caption per region!

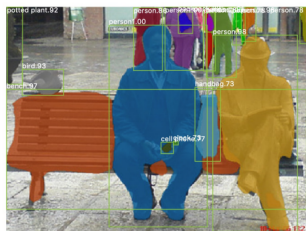


Johnson, Karpathy, and Fei-Fei, "DenseCap: Fully Convolutional Localization Networks for Dense Captioning", CVPR 2016



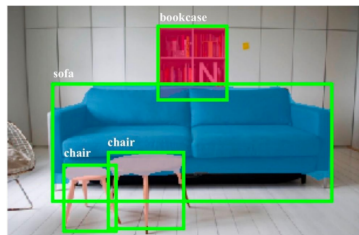
Mask R-CNN:

2D Image -> 2D shapes



Mesh R-CNN:

2D Image -> **3D** shapes



Gkioxari, Malik, and Johnson, "Mesh R-CNN", ICCV 2019

- ▶ **Goal:** Track objects over a sequence of photos or a video
- ▶ Exceedingly challenging in multi-object tracking scenarios
- ▶ Need to take care of not mixing up or losing objects midway
- ▶ **One Solution:** Perform object detection and assign IDs to each object and store its feature vector. Then track the objects based on its ID and feature vector

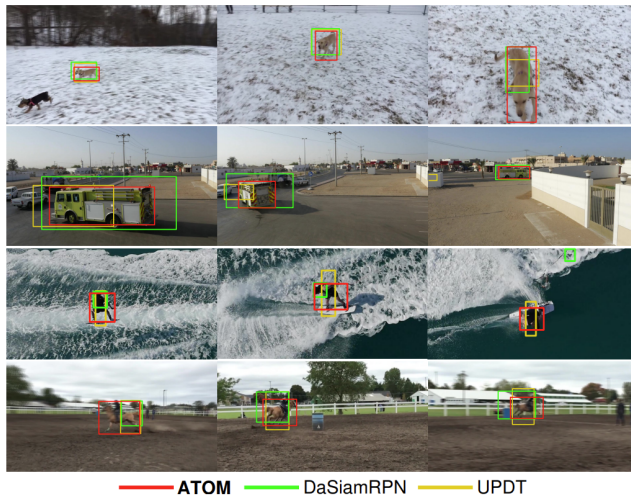


Figure 2: Comparison of 3 approaches for object tracking

Danelljan et al.

► Architectures:

- Improved YOLOv5 (with CBAM attention, dilated convolution, SIOU loss)
- EFE-SSD (with RFB module for small defects)
- Cycle-GAN + YOLOv5 (for data augmentation and detection)

► Use Case:

- Underground drainage pipeline defect detection (gravel intrusion, obstacles, foreign objects).
- Internal pipeline wall defect detection with image stitching.
- Automatic defect detection in CCTV inspection videos.

► Benefits:

- YOLOv5 with CBAM attention: **5.27% mAP improvement**.
- EFE-SSD with RFB module for small defect detection.
- Cycle-GAN enables **5.5×** sample augmentation from limited data.

► Research Papers:

- **Improved YOLOv5 (Dec 2024)**: CBAM attention, dilated convolution, SIOU loss.
- **EFE-SSD (Jun 2023)**: Skip Densely Connected Module (SDCM) for small targets.
- **Cycle-GAN + YOLOv5**: transfer learning from steel defect dataset, attention mechanism.

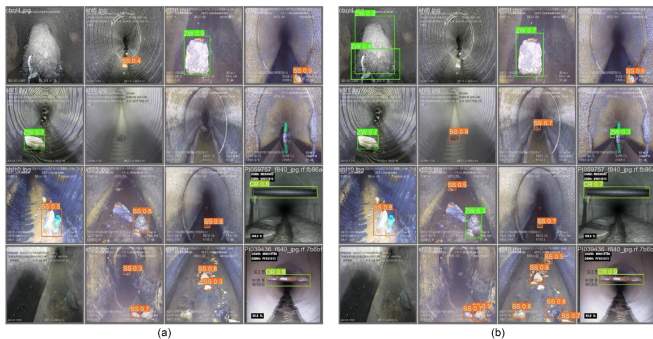


Figure 3: YOLOv5 for pipeline defects

These slides have been adapted from

- ▶ Fei-Fei Li, Yunzhu Li & Ruohan Gao, Stanford CS231n: [Deep Learning for Computer Vision](#)
- ▶ Assaf Shocher, Shai Bagon, Meirav Galun & Tali Dekel, WAIC DL4CV [Deep Learning for Computer Vision: Fundamentals and Applications](#)
- ▶ Justin Johnson, UMich EECS 498.008/598.008: [Deep Learning for Computer Vision](#)